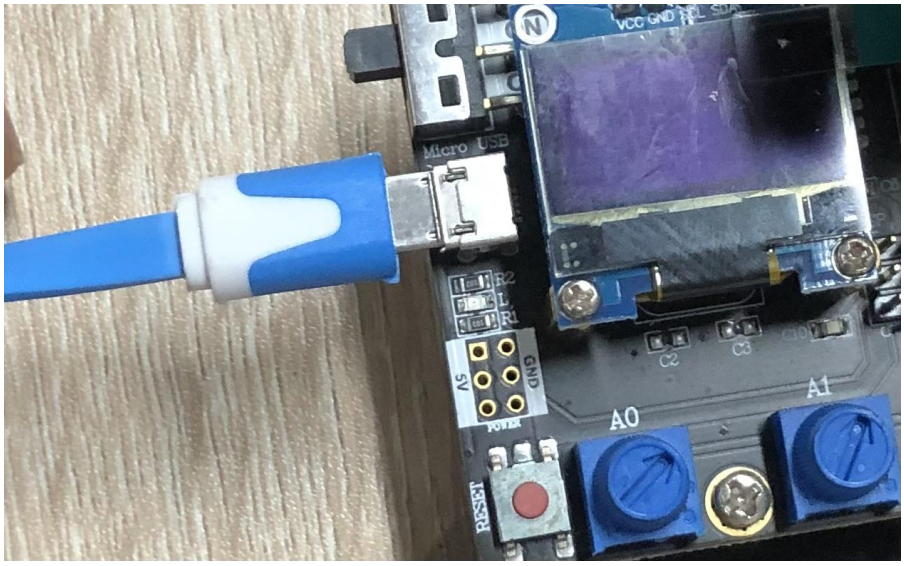
Test Adeept Arm Drive Board, Servo and etc.

1. Refer to the assembly of the base plate in the "assembly of the robotic arm" and assemble pedestals (including fixed drive plate and battery box).

2. Connect the junction port of the battery box to the drive board, as shown in the figure:

3. For Windows computer users, please find the "ch341ser_windows. Exe" file under the file path: ".\ 01 software package \ adeept driver \", and double-click to run and install the serial port driver. Then open the installed Arduino IDE (software).
(For the installation of non-Windows systems, please refer to the corresponding installation instructions in the package provided by us, for details, refer to "(3) install ch341ser driver" in Section 2.5 of this document)

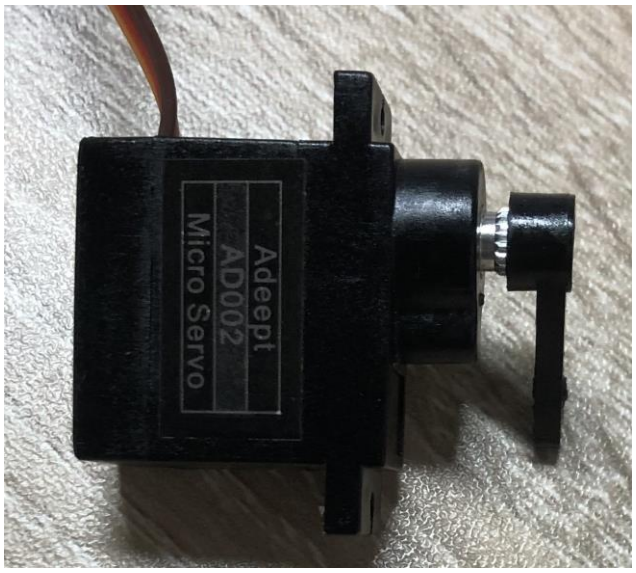
4. Click the menu bar of Arduino IDE interface: Tools - > port, check the existing port of the computer and write it down. Then, the USB end of micro USB cable is connected to the USB interface of the computer, and the micro interface is connected to the driver board, as shown in the figure:



At this time, please click the menu bar of Arduino IDE interface again: Tools - > port to check whether the computer adds a new port to insert the device. If a new port appears, proceed to step 3.5.

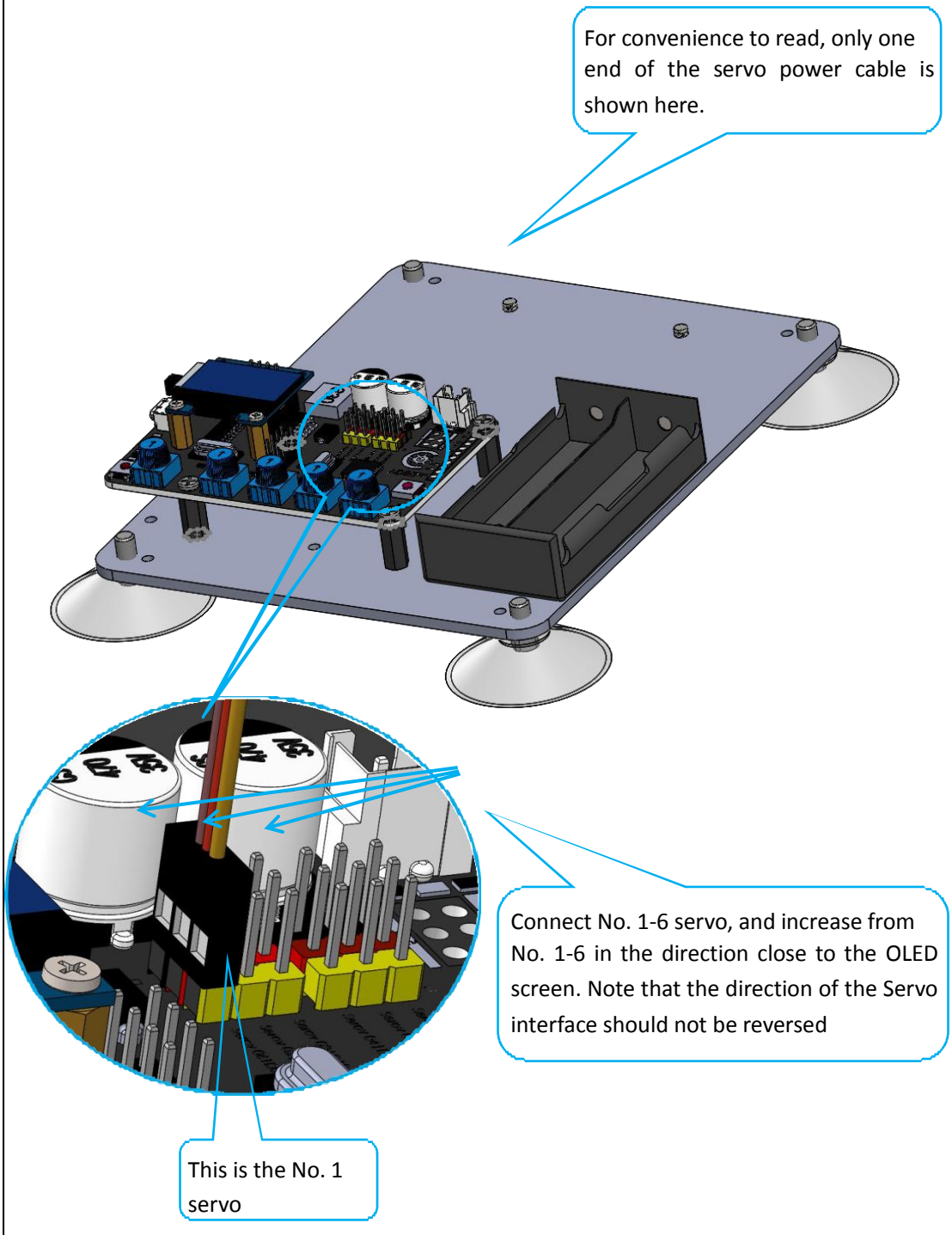
If there is no new port (except the existing port), please plug and unplug the micro USB cable again. If there is no new port, please contact the merchant to help you confirm whether the driver board hardware is damaged during transportation or due to other non-user reasons, and replace the product for you.

5. Unplug the USB end of the micro USB cable from the USB interface of the computer, and simply fix any rudder disc of each steering gear to the anti-skid teeth of the steering gear output shaft (the rudder disc cap has teeth connected with the anti-skid teeth, which can be easily connected to one after rotating and aligning), as shown in the figure:



Then, connect the connecting wire connectors of all 6 steering gears (including one spare steering gear) to the drive board (pay attention to the correct connection method, as shown in the steering gear connecting wire in the figure below) as shown in the figure:

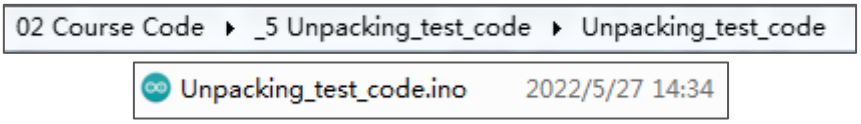
Connect five servos to the Adeept Arm Drive Board.



(please remember to disconnect the micro USB cable from the computer first to prevent damage to the driver board caused by possible short circuit operation)

You can see the right side of the connection position, such as "D11 / servo5", where 11 represents pin 11 of the drive board, corresponding to "myservo.attach(11);" in the Arduino code to be tested later Pin 11 in.

6. Find the Package of Documentation (Reference: Chapter 4, near Page 12 of this section, subsection 5, step (4)) that we provide to the user. Open the directory in sequence: “02 Course Code” -> “_5 Unpacking_test_code” -> “Unpacking_test_code”. Then select the code file "Unpacking_test_code" and Double click with the left mouse button or right click to select “Open”.



7. Click the menu bar of the Arduino IDE interface: "Tools" -> "development board" -> "Arduino AVR boards" -> "Arduino uno", "Tools" -> "port" -> select and click the port of the corresponding drive board.

8. Then click the "Upload" button on the Arduino IDE interface. After the upload is completed, the test can be carried out.

Test code description:

Servo test:

- There are two control modes in the test: 0, separate control; 1. Full control.

- By clicking the button marked on the drive board, you can switch the next pin load steering gear to be tested.

- Please refer to the code Notes for details.

OLED test:

- After the program is uploaded, the OLED on the driver board displays "OLED OK!" Then the OLED is normal. (The content of the test displayed here can be changed)