

The address of the IIC slave is:0x26						
Register Address	R/W	Type	Value/Length	Explanation		
0x01	W	uint8_t	1: 520 motor 2: 310 motor 3: TT motor (with encoder) 4: TT motor (without encoder)	Write motor type		
0x02	W	uint16_t	0-3600	Configuring motor deadband		
0x03	w	uint16_t	0-65535	Write the pulse line of the motor (number of magnetic ring lines)According to the parameter table		
0x04	w	uint16_t	0-65535	Write the motor reduction ratio derived from the parameter table		
0x05	w	float	4 char bytes	Enter the wheel diameter, unit:mm		
0x06	w	int16_t	-1000~1000	Speed control with encoder	Each speed occupies 2 bits. For uint8_t, For example, the speed of the motor m1 is 200, the speed of the motor m2 is -200, the speed of the motor m3 is 0, and the speed of the motor m4 is 500. That is, [0x00 0xC8 0xFF 0x38 0x00 0x00 0x01 0xf4]	
0x07	w	int16_t	-3600~3600	Control pwm speed	The calculation of PWM is the same as above	
0x10	R	int16_t		Read M1 encoder real-time pulse data - 10ms	data = buf[0]<<8 buf[1]	
0x11	R	int16_t		Read M2 encoder real-time pulse data - 10ms	data = buf[0]<<8 buf[1]	
0x12	R	int16_t		Read M3 encoder real-time pulse data - 10ms	data = buf[0]<<8 buf[1]	
0x13	R	int16_t		Read M4 encoder real-time pulse data - 10ms	data = buf[0]<<8 buf[1]	
0x20	R	uint16_t	2 byte	Read the total pulse data of the M1 motor encoder	High	The acquired data needs to be shifted to get the correct data High bit represents: buf[0] buf[1] Low bit represents: bf[0] bf[1] data =buf[0]<<24 buf[1]<<16 bf[0]<<8 bf[1]
0x21	R	uint16_t	2 byte	Read the total pulse data of the M1 motor encoder	Low	
0x22	R	uint16_t	2 byte	Read the total pulse data of the M2 motor encoder	High	The acquired data needs to be shifted to get the correct data High bit represents: buf[0] buf[1] Low bit represents: bf[0] bf[1] data = buf[0]<<24 buf[1]<<16 bf[0]<<8 bf[1]
0x23	R	uint16_t	2 byte	Read the total pulse data of the M2 motor encoder	Low	
0x24	R	uint16_t	2 byte	Read the total pulse data of the M3 motor encoder	High	The acquired data needs to be shifted to get the correct data High bit represents:buf[0] buf[1] Low bit represents:bf[0] bf[1] data = buf[0]<<24 buf[1]<<16 bf[0]<<8 bf[1]
0x25	R	uint16_t	2 byte	Read the total pulse data of the M3 motor encoder	Low	
0x26	R	uint16_t	2 byte	Read the total pulse data of the M4 motor encoder	High	The acquired data needs to be shifted to get the correct data High bit represents:buf[0] buf[1] Low bit represents:bf[0] bf[1] data = buf[0]<<24 buf[1]<<16 bf[0]<<8 bf[1]
0x27	R	uint16_t	2 byte	Read the total pulse data of the M4 motor encoder	Low	