Command	Explanation	Example	Remark
$mtype:x#	Motor model	$mtype:1#	x: is the type of motor Different values represent the type of motor 1: 520 motor 2: 310 motor 3: TT motor (with encoder) 4: TT motor (without encoder)
$deadzone:xxxx#	Configure the motor pwm pulse dead zone	$deadzone:1650#	xxxx: is the dead zone value, which needs to be measured. By changing this value, the minimum vibration of the motor can be eliminated. The dead zone value range is (0-3600)
$mline:xx#	Configure the motor phase lines	$mline:13#	xx: This is the motor's reduction ratio parameter. This value can be obtained by looking up the seller motor parameter table.
$wdiameter:xx#	Configure the wheel diameter	$wdiameter:50#	xx: This is the diameter of the wheel. This value can be measured or obtained based on the seller information.
$MPID:x.xx,x.xx,x.xx#	Configure PID parameters	$MPID:1.5,0.03,0.1#	x.xx,x.xx,x.xx: These are the parameters for controlling the motors p, i, and d respectively. Each time a pair of values is changed, the chip will restart and the motor will stop moving. This is normal.
$flash_reset#	Reset default		
$spd:0,0,0,0#	Control speed of 4 motors	$spd:100,-100,0,50#	0,0,0,0: represents M1,M2,M3,M4 on the board screen. The speed range is (-1000~1000) and will be invalid if it exceeds the range.
$pwm:0,0,0,0#	Control 4 motors with PWM output	$spd:0,520,300,800#	0,0,0,0: represents M1,M2,M3,M4 on the board screen. The speed range is (-3600~3600) and will be invalid if it exceeds the range
$upload:0,0,0#	Receive encoder data	$upload:1,0,0#	$upload:0,0,0# The first 0 represents: the total encoder data of the wheel rotation The second 0 represents: the real-time encoder data of the wheel rotation (10ms) The third 0 represents: the speed of the wheel
$read_flash#	Query flash variables		
$read_vol#	Check battery level		