# Performances

## One servo

### setPosition

Command

ID = 2

Length = 9 (ok)

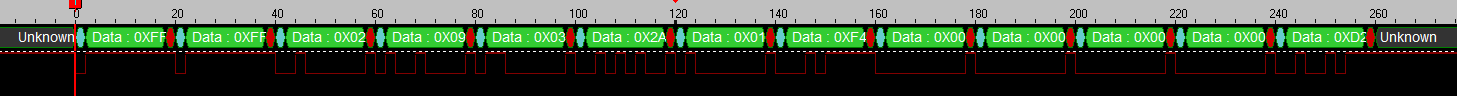
Write = 03h (ok)

Address = 2Ah = 42 = SCSCL\_GOAL\_POSITION\_L (ok)

Position = 1F4h = 500 (ok)

Time = 0000h (fixed)

Speed = 0000h



Timing = 260µs

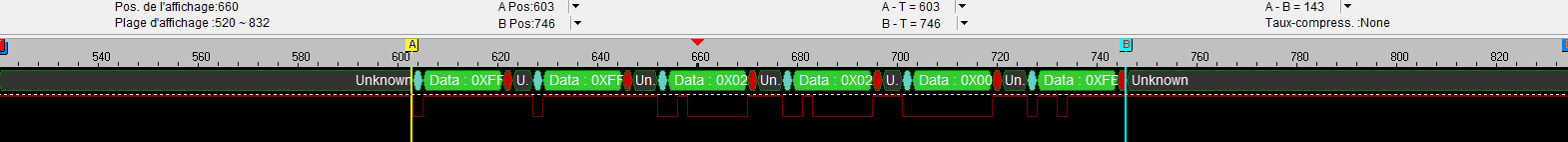
Ack :

ACK delay = 345µs

ID = 2

Length = 2 (ok)

Working Condition = 00h (ok)



Timing = 140µs

**Total serial timing = 575 to 745µs**

Total sw ESP32 timing = 844us < 880us < 1075us

### setPositionFast

Command

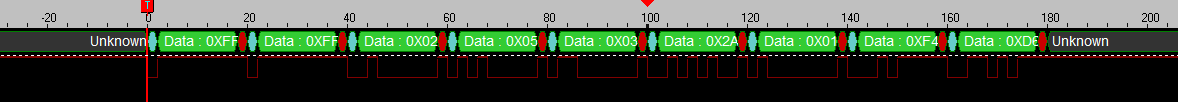
ID = 2

Length = 5 (ok)

Write = 03h (ok)

Address = 2Ah = 42 = SCSCL\_GOAL\_POSITION\_L (ok)

Position = 1F4h = 500 (ok)



Timing = 180µs

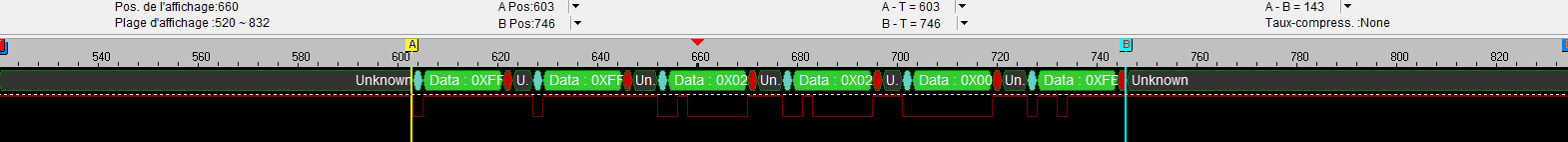
Ack :

ACK delay = 300µs

ID = 2

Length = 2 (ok)

Working Condition = 00h (ok)



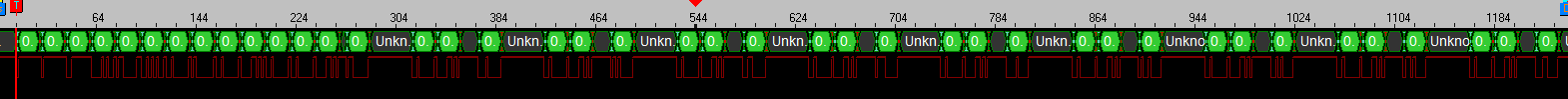
Timing = 140µs

**Total serial timing < 625µs**

Total sw ESP32 timing = 716us < 751us < 941us

## Twelve servo

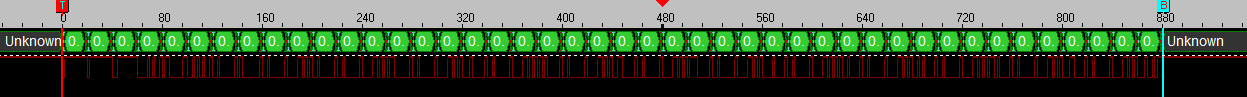
### setPosition12 with SCSCL API sync write



**Total serial timing < 1345µs**

Total sw ESP32 timing = 1395us < 1392us < 1414us

### setPosition12 custom implementation



**Total serial timing < 880µs (=theorical timing)**

Total sw ESP32 timing = 77us < 78us < 81us