OmG
Outstanding Model Gear

舵机编程卡
软件使用手册

1 工作电压：USB（5V/500mA）
2 操作系统：Windows XP/Windows Vista/Windows 7/Windows 8/ windows10（32/64bit）
3 适用舵机：OMG-D4/R4/R5/A3系列。

软件中间部分为信息显示窗口，当进行配置卡插拔、舵机参数读写时都有信息进行提示。

参数功能说明

串口号：连接USB及电脑的端口
检测串口：电脑会自动检测到USB的端口
打开串口：确认舵机通过USB编程卡已经连接到电脑

最小角度：可以设置舵机左右最小角度，参考值为1-150
最大角度：可以设置舵机左右最小角度，参考值为2-300
中点角度：参考范围值：SFR窄频参考值为500，SR及SSR窄频
参考值为750，铁心马达宽频参考值为1000，无刷马达
宽频参考值为1000

> 当舵机在遥控器中点位时没有在对应位置上，可以修改此值，
> 使舵机摆臂偏移，相当于遥控器通道的微调。

最小脉宽：SFR窄频参考值为250，SR及SSR窄频参考值为500,铁
心马达宽频参考值为500，无刷马达宽频参考值为900
最大脉宽：SFR窄频参考值为750，SR及SSR窄频参考值为1000，
铁心马达宽频参考值2500，无刷马达宽频参考值2100
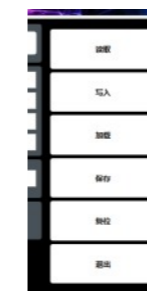死区范围：调整舵机死区（灵敏度），参考值：1-4

增益：参考值为5-40
阻尼：设置舵机阻尼，参考值为5-40
输出功率：参考范围值为950-1150（75%-96%）
堵转保护：
　时长：参考值范围500-6000（1000=3秒）
　功率：参考值范围400-600，调整舵机的输出功率。
　　功率越大，舵机的扭力越大，消耗电流也大。
反转：设置舵机旋转正反向。
锁舵：丢失信号后，保持舵机当前信号
缓启动：舵机上电慢复位功能。
　通电后舵机会缓慢转到当前输入信号位置上。
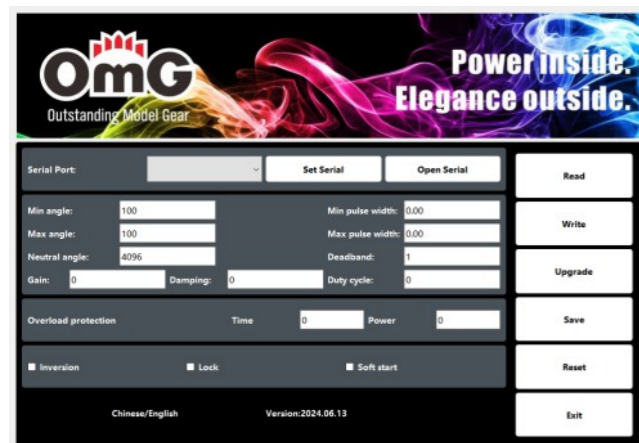
> 注：上电慢复位功能是防止舵机安装位置不正确，
> 上电时快速摆动造成设备损伤。

读取：把舵机的参数读出到软件界面。
写入：把当前参数写入舵机。
加载：打开电脑保存的舵机参数文件。
保存：保存当前舵机参数到电脑。
复位：恢复到默认出厂设置
退出：退出并关闭调参软件。

使用说明

1 插入USB配置卡到电脑端口,本配置卡为免安装驱动,等待系统自动适配驱动程序（大约5-10秒钟）。

2 如果电脑没有检测到驱动程序，需要在文件夹中点击CH34x_Install_Windows_v3_4程序，进行安装。

3 打开软件程序 📖 YiQuDa

4 插入舵机，检测串口，打开串口，然后再读取舵机参数，
读取完成后，可进行修改参数，然后点击写入，即可完成

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Servo Programming Card
software user manual

Working voltage: USB (5V/500mA)
Operating system: Windows XP/Windows Vista/Windows 7
/Windows 8/ Windows10 (32/64bit)
Applicable servos: OMG-D4/R4/R5/A3 series.

The middle part of the software is the information display window. The information will be prompted when the programming card is inserted and removed, and the servo parameters are read and written.

Programming items Instructions

Serial port: connecting USB and computer
Set serial: The computer will automatically detect the USB port
Open serial: Confirm that the servo is connected to the computer through the USB programming card

Min angle: Set the low pulse width or high pulse width angle of the servo, the reference value is 50-150
Max angle: Set the low pulse width or high pulse width angle of the servo, the reference value is 50-150
Neutral angle: Servo neutral angle offset error

> If the servo is not at the neutral position when the transmitter is at the neutral position, you can modify this value to offset the servo arm, which is equivalent to fine-tuning of the transmitter channel.

Min pulse width: Set the minimum pulse width signal of the servo, reference value is 500-1000
Max pulse width: Set the maximum pulse width signal of the servo, reference value is 2000-2500
Deadband: adjust the servo deadband (sensitivity), reference value is 1-4

Gain: reference value is 5-40
Damping: Set the servo damping, the reference value is 5-60
Output power: reference value is 950-1150 (75%-96%)
Stall protection:
Time: Reference value is 500-6000 (1000=3 seconds)
Power: Reference value is 400-600. Adjust the output power of the servo. The greater the power, the greater the torque and the greater the current consumption.
Inversion: Set the forward and reverse direction of the servo.
Lock: Keep the current signal of the servo after losing the signal.
Soft start: After powering on, the servo will slowly move to the current input signal position.

> Note: The power-on slow start function is to prevent the servo from damage causing by rapid swinging under an incorrect position during power-on.

Read: Read the parameters of the servo to the software interface.
Write: Write the current parameters into the servo.
Load: Open the servo parameter file saved on the computer.
Save: Save the current servo parameters to the computer.
Reset: Restore to default factory settings
Exit: Exit and close the programming software.

Using instruction

1 Insert the USB programming card into the computer port. This programming card is driver-free. Wait for the system to automatically adapt the driver (about 5-10 seconds).

2 If the computer does not detect the driver, please click the Ch34x _ Install _ Windows _ v3 _ 4 program in the folder to install it.

3 Open the software program 📖 YiQuDa

4 Insert the servo, click the Set Serial, Open Serial, and the Read. After reading, you can modify the parameters, and then click Write to complete the setting.