

TITLE: CAN AIO (All In One) UI – Write Param

TARGET MODEL: CAN-AT Servos (FW Ver $\geq$ 1.7, Not include ST version)

DATE: 2025_11_13

1: Edit CAN-UI.ini

Add the following to the My Documents/CAN-UI.ini file.

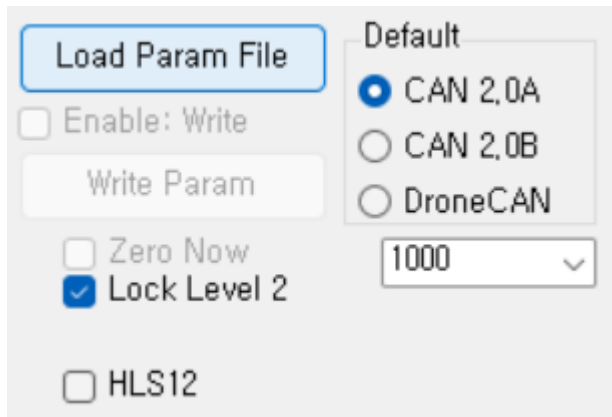
If the file doesn't exist, run the AIO UI exe once and then quit it.

[SPECIAL]

PARAM = Yes

2: Run AIO exe

The following will be added to the screen:



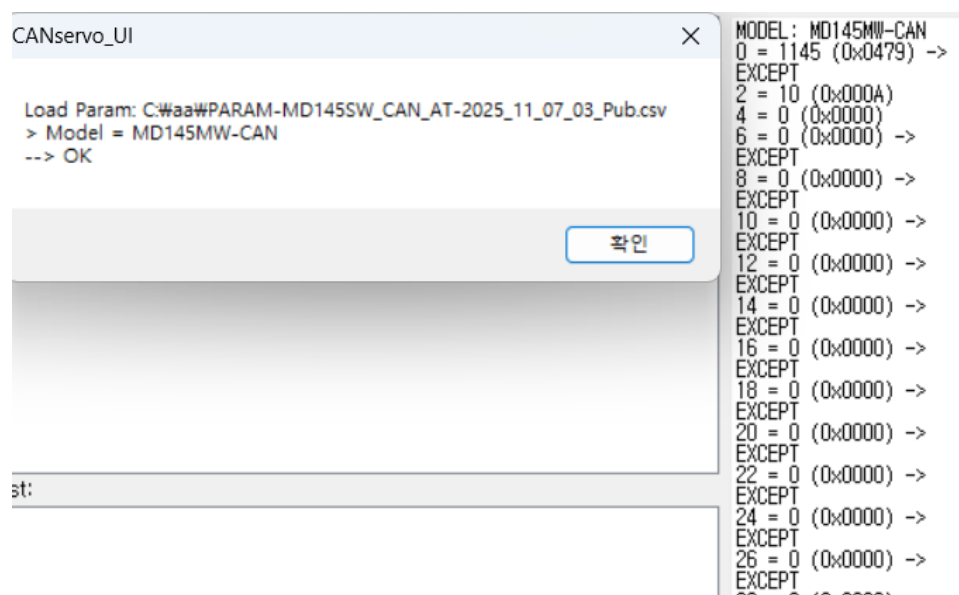
The screenshot shows a software interface for configuring a servo motor. It includes a 'Load Param File' button, a 'Write Param' button, and several checkboxes: 'Enable: Write', 'Zero Now', 'Lock Level 2' (which is checked), and 'HLS12'. On the right, there is a 'Default' section with three radio buttons: 'CAN 2.0A' (selected), 'CAN 2.0B', and 'DroneCAN'. Below these is a dropdown menu currently set to '1000'.

3: Load Param File

Open the parameter file by clicking the button "Load Param File".

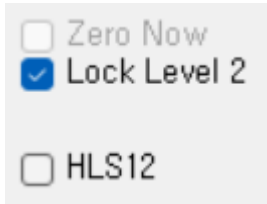
Ex: PARAM-MD145SW_CAN_AT-2025_11_07_03_Pub.csv

If there is no problem with the file, it will appear like this:



3: preparatory work

3.1: Manipulate the check boxes as follows:

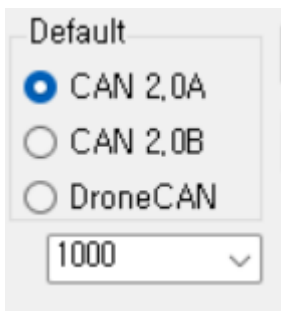


☐ Zero Now
☒ Lock Level 2
☐ HLS12

3.2: Setting default servo communication speed and mode

Selecting CAN 2.0A in the Default box will default to 2.0A.

Select the desired default setting and communication speed.



Default
☒ CAN 2.0A
☐ CAN 2.0B
☐ DroneCAN
1000 ▾

4: Connect one servo and click the "Scan" button.

Port: COM7 (dropdown) Open Close

Baudrate: 115200 (dropdown)

COM7: 3.1 B3T3

Protocol: ☒ CAN 2.0A ☐ CAN 2.0B ☐ DroneCAN ☐ Use Stream Off

Speed: (kbps) 1000 (dropdown)

Scan

Left Center Right

CAN ID for FW Update via bootloader 7F0 (HEX, 1~7FF)

Idx	Type	SID	NID	Count
1	CAN 2.0A	0	0	1

5: Select Servo in Servo List

Port: COM7 (dropdown) Open Close

Baudrate: 115200 (dropdown)

COM7: 3.1 B3T3

Protocol: ☒ CAN 2.0A ☐ CAN 2.0B ☐ DroneCAN ☐ Use Stream Off

Speed: (kbps) 1000 (dropdown)

Scan

Left Center Right

CAN ID for FW Update via bootloader 7F0 (HEX, 1~7FF)

Servo List:

Idx	Type	SID	NID	Count	Connect
1+	CAN 2.0A	0	0	1	OK: Only One

Load Param File

☒ Enable: Write

Write Param

☐ Zero Now

☒ Lock Level 2

☐ HLS12

Select a servo from the Servo List. The "Enable: Write" checkbox will become active.

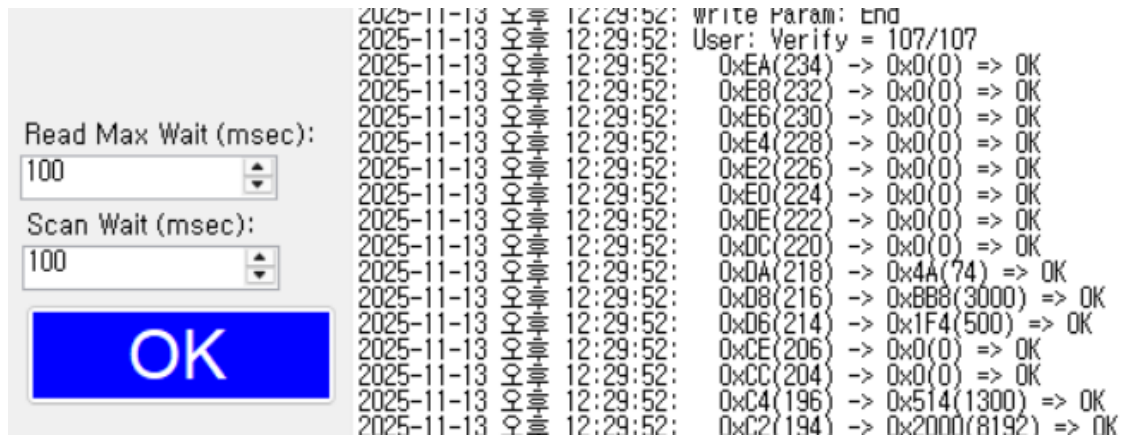
Checking the "Enable: Write" checkbox will activate the "Write Param" button.

☒ Enable: Write

Write Param

Now, click the Write Param button and wait for the result.

If successful, an OK box will appear.



If it fails, press the Write Param button again to try again.

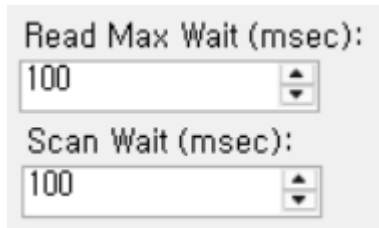
6. Repeat

Remove the servo and repeat step 4.

Note 1:

If a communication error occurs, adjust the Read Wait and Scan Wait values as shown below.

If communication is problematic, try increasing them gradually.



The image shows a screenshot of a configuration window with two settings. The first setting is 'Read Max Wait (msec):' with a value of '100'. The second setting is 'Scan Wait (msec):' with a value of '100'. Both settings have a small up/down arrow icon to the right of the text input field.

Read Max Wait (msec):	100
Scan Wait (msec):	100

END