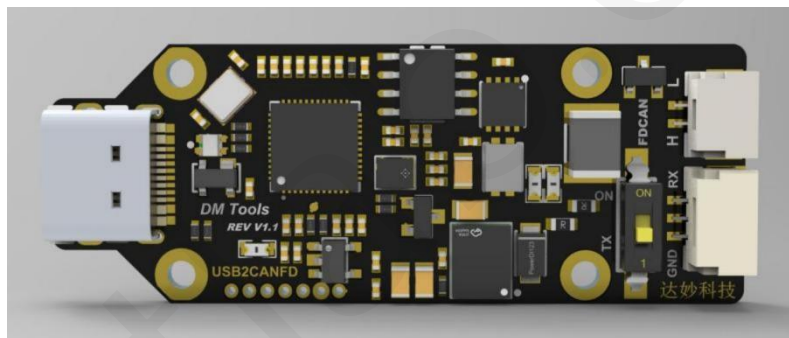


DAMIAO

USB to CANFD Module

USB to CANFD Module V1.0 2025.07.28



Disclaimer

Thank you for purchasing the DAMIAO USB to CANFD Module (hereinafter referred to as the "Module"). Before using this product, please carefully read and follow all safety guidelines provided in this document and by DAMIAO Technology. Failure to do so may cause harm to you and surrounding homo sapiens, damage this product, or other surrounding items. Once you use this product, it is deemed that you have carefully read this document, understood, acknowledged, and accepted all terms and contents of this document and all related documentation of this product. You commit to using this product solely for legitimate purposes. You commit to bearing full responsibility for the use of this product and any potential consequences. DAMIAO Technology shall not be held liable for any damage, injury, or legal liability arising directly or indirectly from the use of this product.

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Precautions

1. Ensure all cables are correctly connected according to the manual before use to prevent damage to interfaces and modules.
2. Operate within the recommended voltage, current, temperature, and other environmental conditions specified in the manual to avoid damaging the module and affecting its service life.
3. Inspect all components for integrity before use. If any parts are missing, aged, or damaged, discontinue use immediately.
4. Take protective measures during use. Do not touch components on the module directly with hands to prevent electrostatic discharge and physical damage. Keep the module clean to avoid short circuits or performance degradation caused by foreign objects.
5. If abnormalities such as sparking, smoke, or a burning smell occur during power-up or operation, immediately turn off the power supply.
6. The USB to CANFD module does not support host computers with versions below V2.0.0.0. Please use it with a newer version of the host computer software.

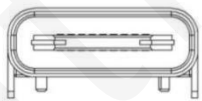
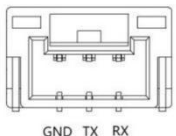
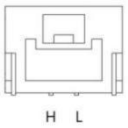
7. The USB to CANFD module supports FDCAN data frames and a maximum baud rate of 5Mbps.

8. The product's communication protocol is not open. Secondary development is supported using the official SDK.。

Packing List

1. USB to CANFD Module × 1
2. Power Cable: Type-C Data Cable × 1
3. Debugging Serial Cable: GH1.25 Connector Cable - 3pin (Different Planes, 300mm) × 1
4. Debugging CAN Cable: GH1.25 Connector Cable - 2pin (Different Planes, 300mm) × 1

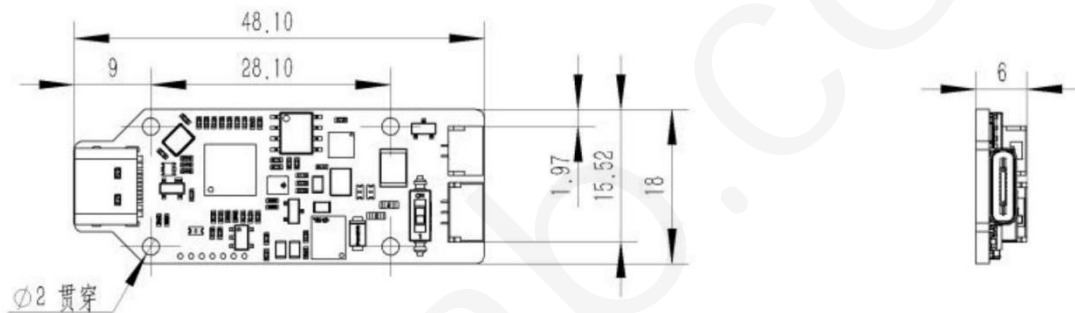
Interface and Pin Definition

Specific Name-Serial No.	Interface Marking	Interface Type	Description
Power & Communication Interface		Type-C	Used to power the module and communicate with the host computer.
UART Interface		GH1.25 3P	Used to connect other serial devices
CAN Interface		GH1.25 2P	Used to connect to CAN network bus, transmit and receive CAN messages

Terminal Resistor Switch		-	CAN bus 120Ω terminal resistor switch, toggle down to ON to enable (default ON)
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Dimensions and Installation

Please install the product to the corresponding equipment referring to the mounting hole dimensions and positions.



Indicator Light Status

Indicator Light Status	Status Description
Blue slow flashing	Not connected to host computer
Green slow flashing	Connected to host computer
Green fast flashing	CAN bus passive error
Red fast flashing	CAN bus-off error

Module Usage Instructions

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❖ Connecting to Host Computer

The device connection process is as follows:

1. Insert the device: Connect the device to the PC and open the host computer software;
2. View the device: Press the F2 shortcut key to open the device view window;
3. Close the device view window;
4. Open serial port: Click the [Open Serial Port] button at number 3 to complete the connection port number;
5. Status confirmation: After successful connection, the device indicator light changes from blue slow flashing to green slow flashing.

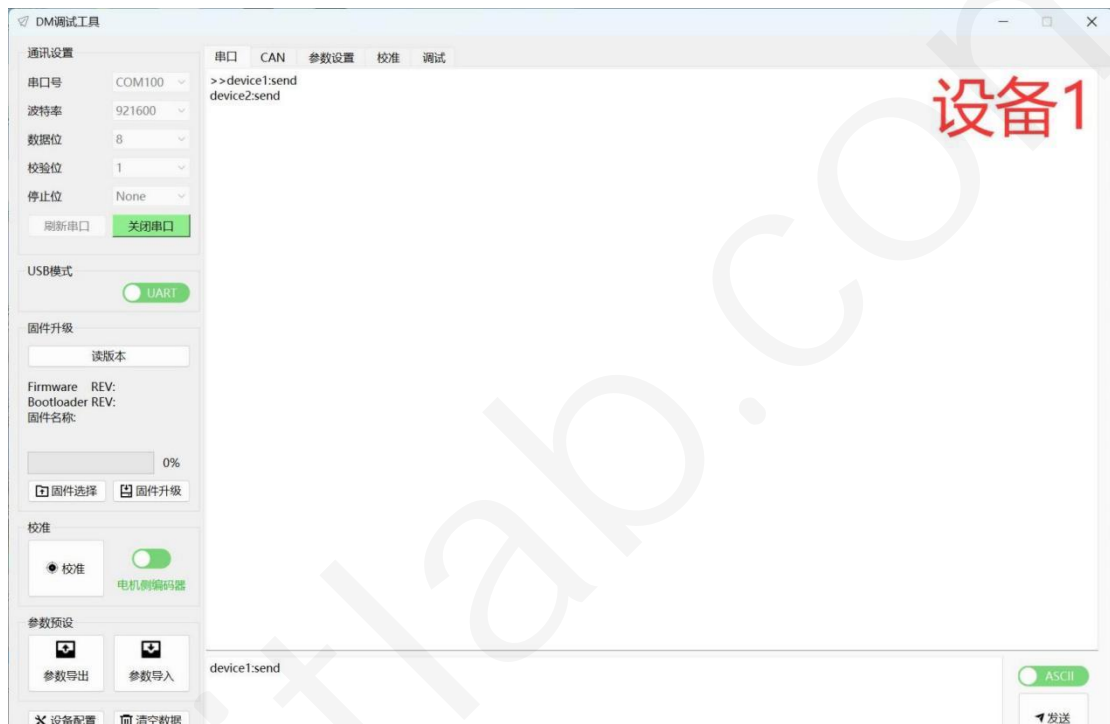


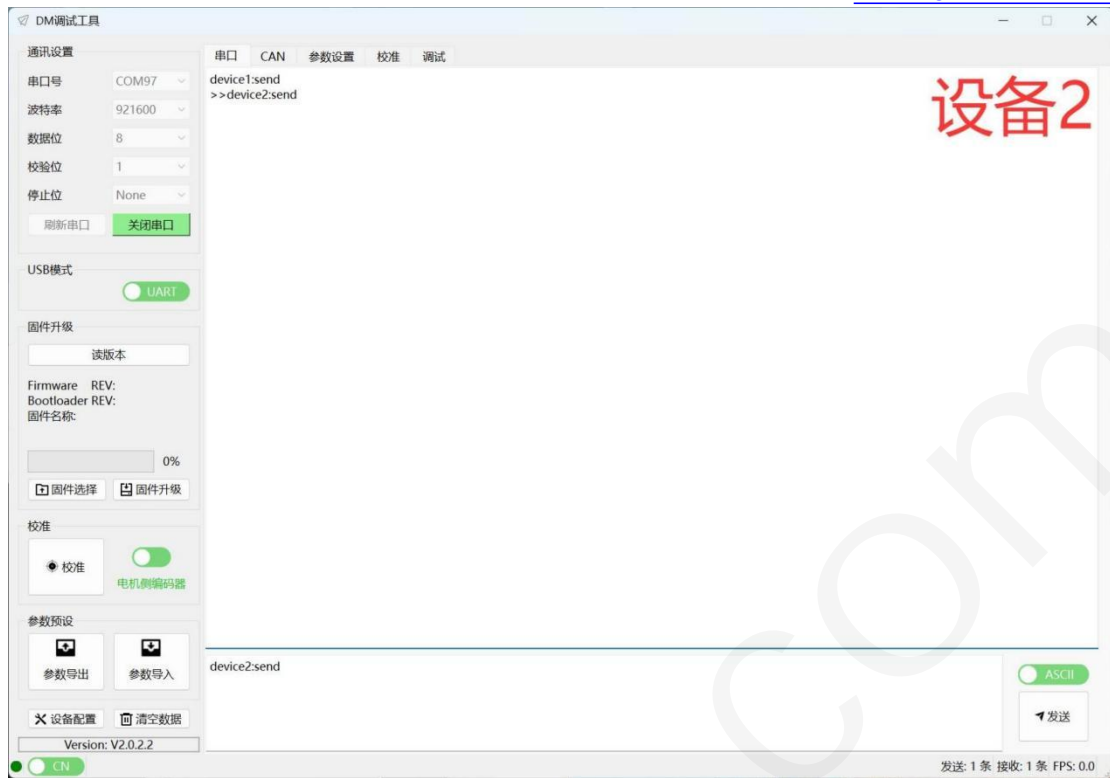
❖ USB to UART Function

This module provides USB to UART function. Data sent and received via USB are directly forwarded to the UART interface without any protocol processing.

When both devices are at the same baud rate, data can be received normally using the host computer's serial assistant. If the baud rates are different, data cannot be received properly.

This function of the module supports other serial assistants.





❖ Configuring CAN Baud Rate

1. Configuring CAN2.0 Baud Rate

The steps to configure the CAN2.0 baud rate are as follows:

- ① Press the F2 shortcut key on the main interface to open the device configuration window;
- ② Switch the working mode: Set the device communication type to CAN2.0;
- ③ Configure the baud rate: Select the CAN baud rate (supports common baud rates such as 1Mbps, 500kbps, 250kbps, 200kbps, 125kbps, 100kbps, etc.);
- ④ Apply the configuration: Click the Update Configuration button (the configuration will be saved to the module and will not be lost after power off)



2. Configuring CANFD Baud Rate

The steps to configure the CANFD baud rate are as follows:

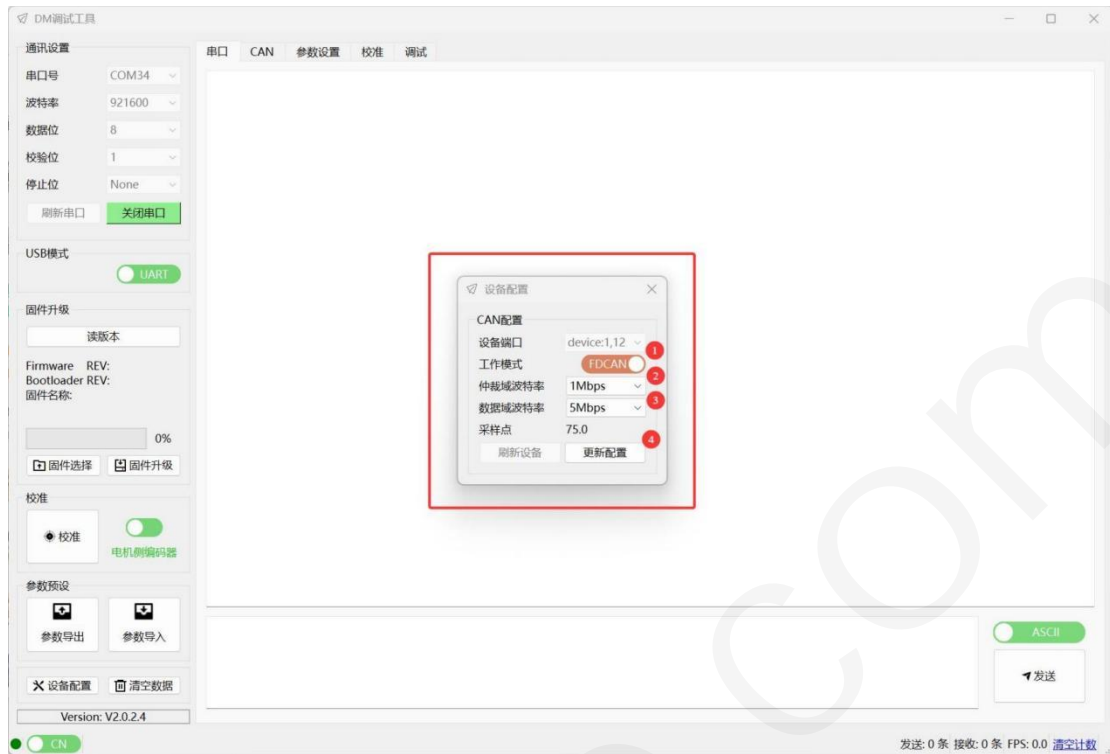
- ① Press the F2 shortcut key on the main interface to open the device configuration window;
- ② Switch the working mode: Set the device working mode to FDCAN;
- ③ Configure the baud rate:

Arbitration domain baud rate: Maximum support 1Mbps (optional 1Mbps/500kbps/250kbps/200kbps/125kbps/100kbps, etc.);

Data domain baud rate: Maximum support 5Mbps (optional 5Mbps/4Mbps/2.5Mbps/2Mbps/1Mbps, etc.);

④ Apply the configuration: Click the Update Configuration button (the configuration has power-off memory function).

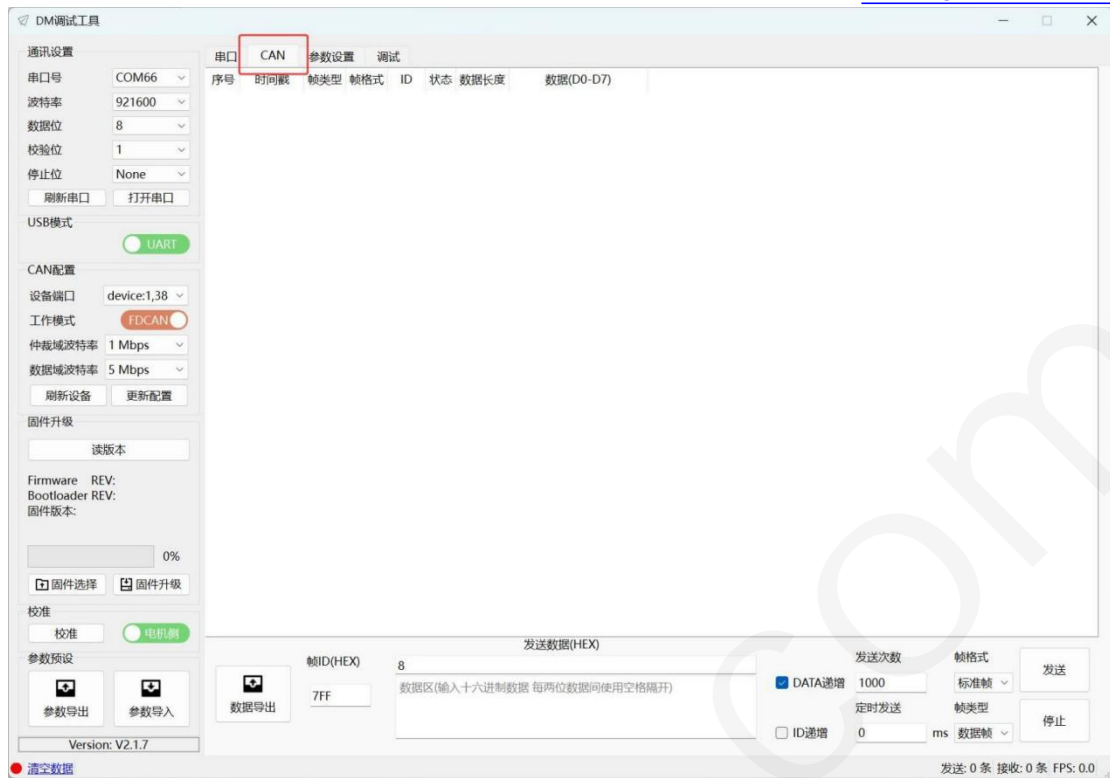
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❖ Sending/Receiving Messages

1. Sending CAN Messages

Connect the device to the target device via the CAN bus (connect the device to the CAN network where the target device is located).



Click the CAN tab in the host computer to jump to the CAN message sending and receiving monitoring page.



As shown in the figure above:

Number 1: Frame data length configuration box;

Number 2: Frame data configuration box (input hexadecimal data, Chinese input is prohibited, spaces will be automatically filled after every two digits);

Number 3: Frame ID configuration box, standard frame maximum 7FF (11 bits), extended frame maximum 1FFFFFFF (29 bits);

Number 4: Data increment check box, when checked, the low byte of data will increment by 1 when sending messages;

Number 5: ID increment check box, when checked, the ID will increment by 1 when sending messages;

Number 6: Transmission count configuration box, when -1 is entered, it sends infinitely, and you need to manually click the stop button to stop sending;

Number 7: Periodic sending time configuration box, when set to 0, it sends without interval, and CAN messages will be sent at the fastest speed;;

Number 8: Frame format check box, supports selecting standard frame and extended frame;

Number 9: Frame type check box, supports selecting data frame and remote frame. It is worth noting that there is no remote frame under FDCAN;

Number 10: CAN message send button;

Number 11: Stop sending button, this button can interrupt the current sending task;

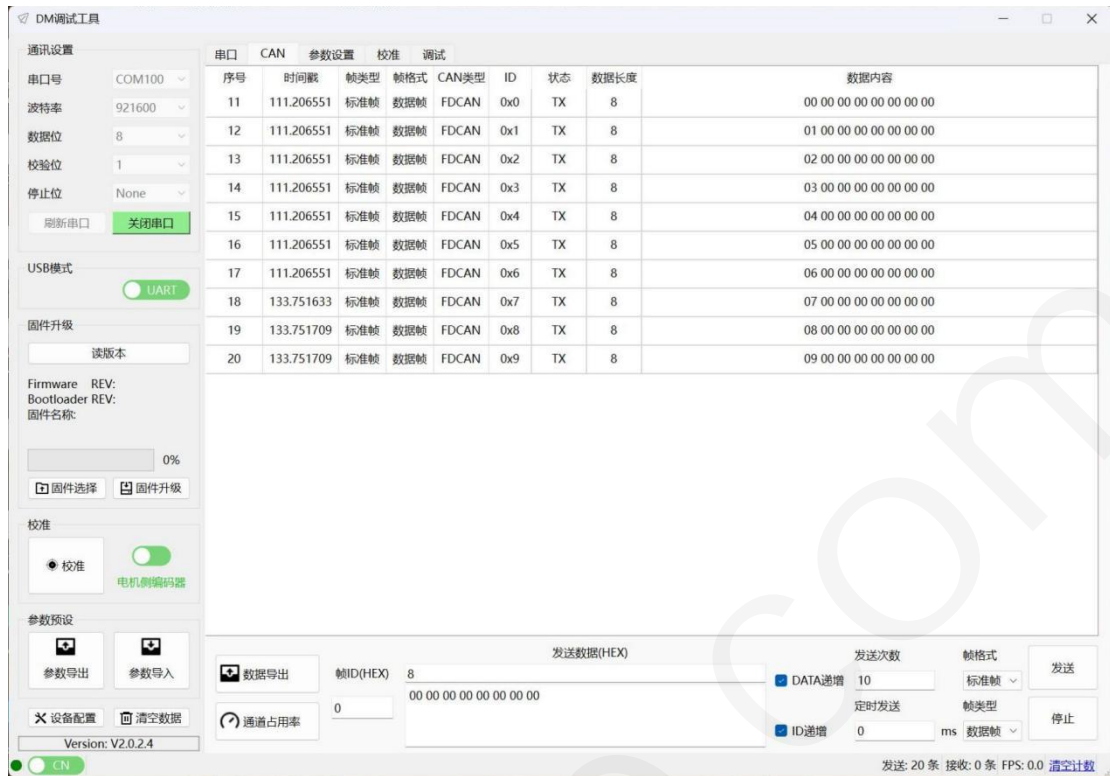
Number 12: Export data button, supports exporting received and sent CAN messages in CSV format;

Number 13: Channel occupancy rate view button.

The figure below shows the effect of continuously sending 10 standard frame messages while performing data increment and ID increment. The host computer can

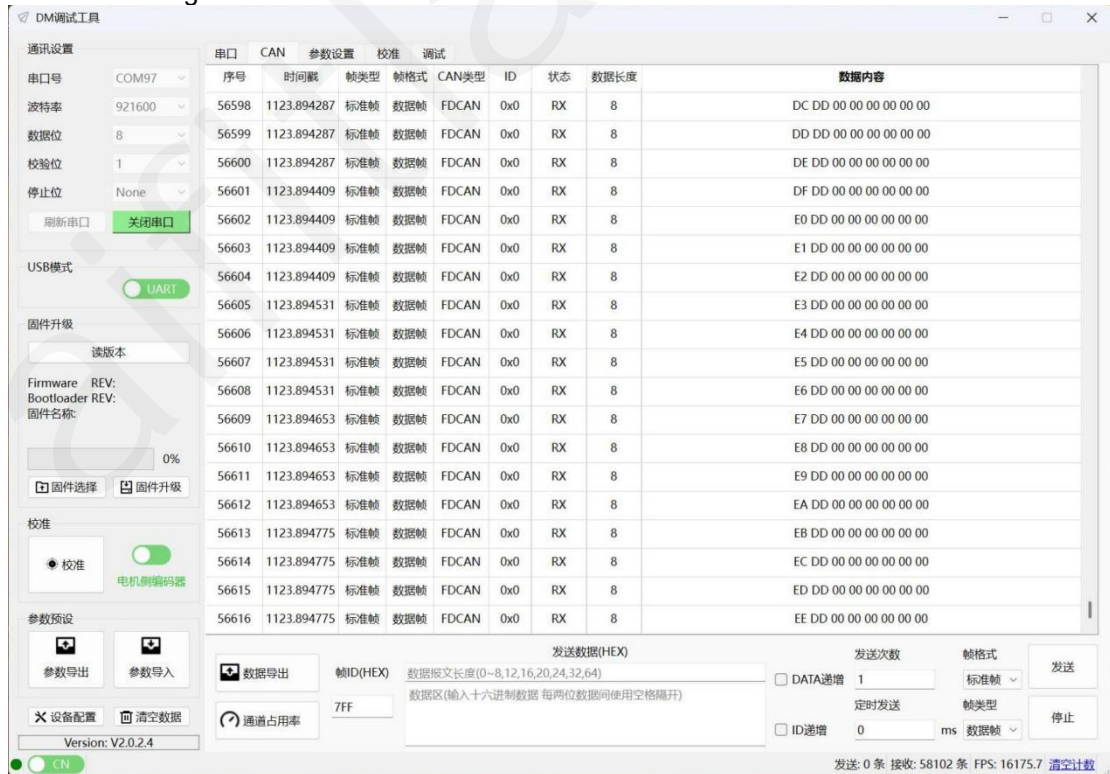
monitor the sent message type, timestamp, format, ID, sending direction, data length, and content.

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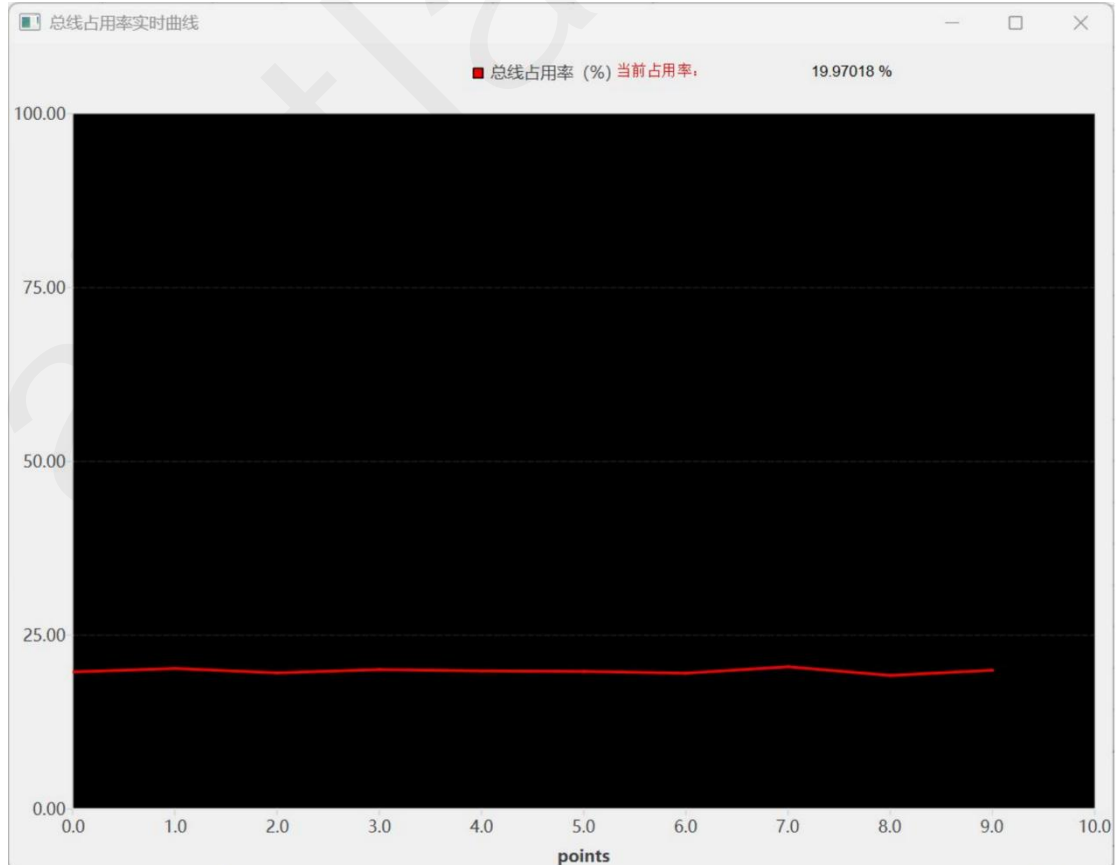
2. Receiving CAN Messages

Connect the device to the target device via the CAN bus (connect the device's CAN interface to the CAN network where the target device is located), and you can receive and monitor messages on the CAN bus. The figure below shows the effect of another device sending to the module.



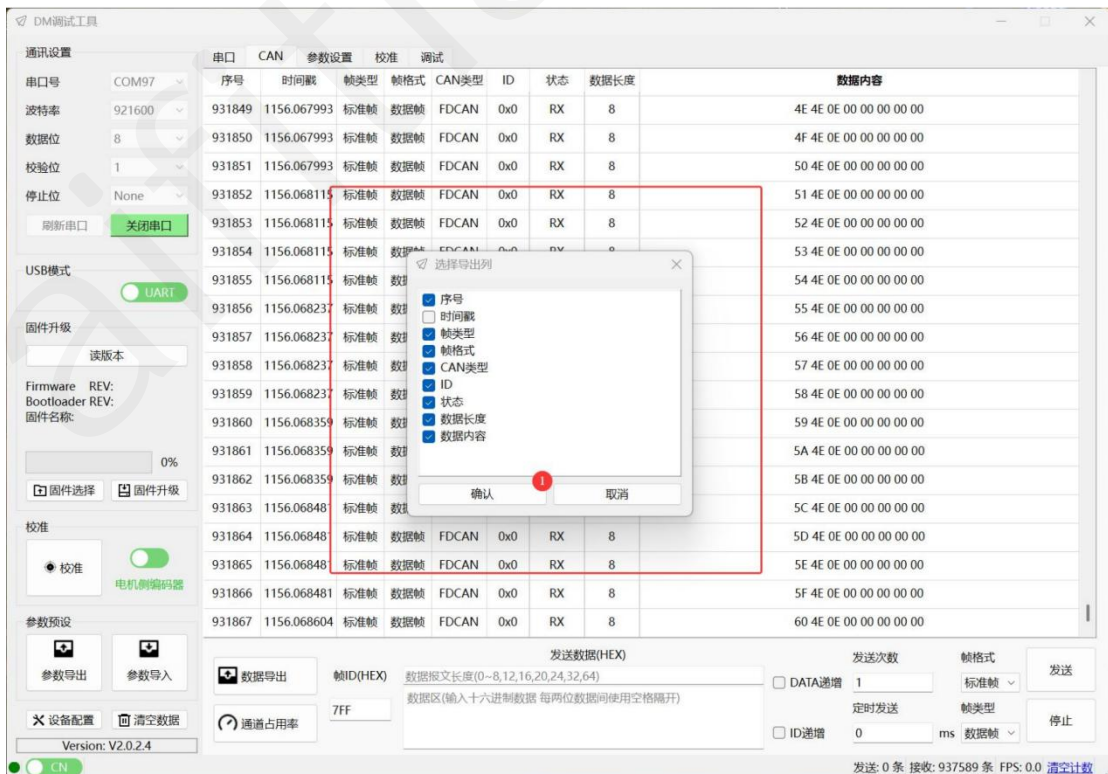
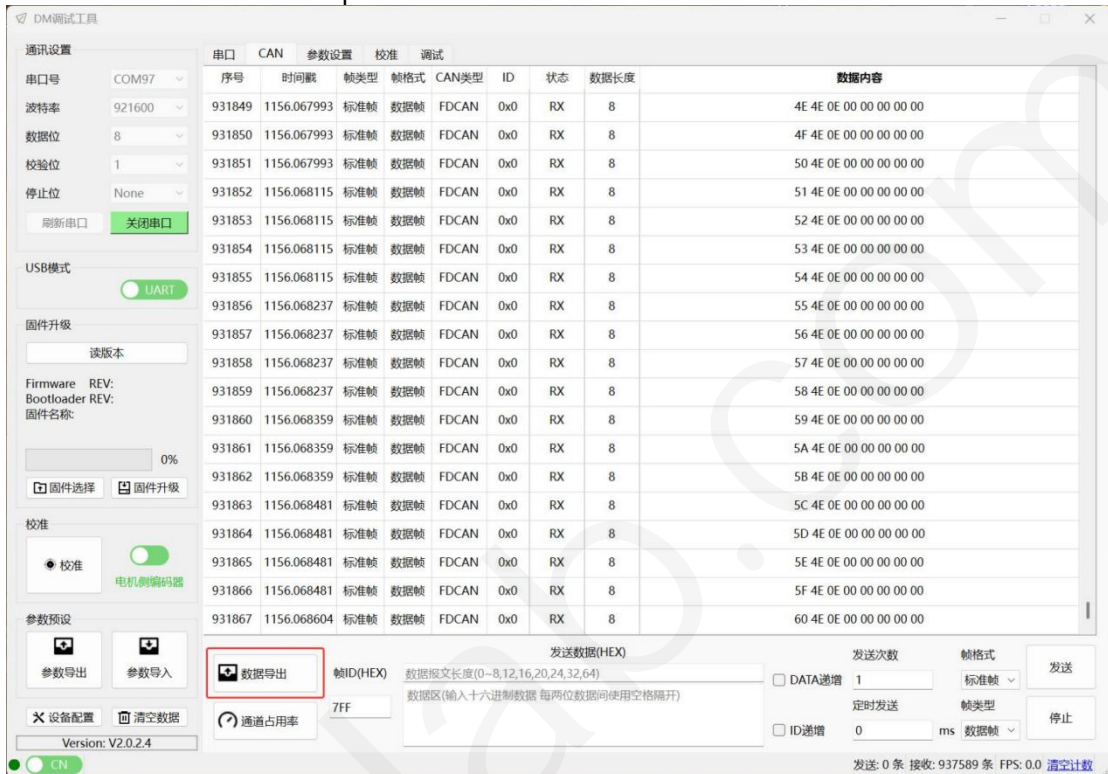
❖ Bus Utilization Monitoring

The device can monitor bus utilization. Switch to the CAN tab, and click the channel occupancy button in the red box as shown in the figure below to bring up the occupancy curve chart.



❖ Custom Data Export

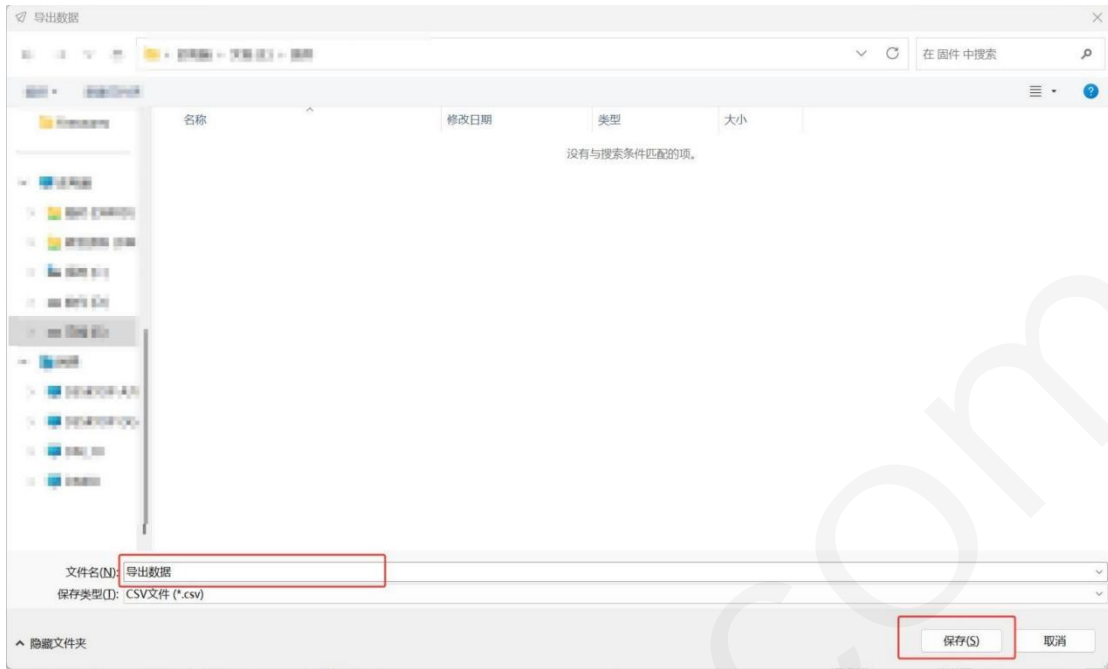
The host computer supports CAN message data export function. Click the data export button in the red box as shown in the figure below to bring up the data export function page. It supports optional data content export. If timestamp data is not needed, you can uncheck the timestamp item box.



[DAMIAO Motor Products](#)

Click the Confirm button, enter the file name, and then click the Save button to export CAN message data in CSV format.

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序号	帧类型	帧格式	CAN类型	ID	状态	数据长度	数据内容
2	832513	标准帧	数据帧	FDCAN	0x0	RX	8 32 C7 0C 00 00 00 00 00
3	832514	标准帧	数据帧	FDCAN	0x0	RX	8 E9 C7 0C 00 00 00 00 00
4	832515	标准帧	数据帧	FDCAN	0x0	RX	8 3A C9 0C 00 00 00 00 00
5	832516	标准帧	数据帧	FDCAN	0x0	RX	8 9F C8 0C 00 00 00 00 00
6	832517	标准帧	数据帧	FDCAN	0x0	RX	8 7B C6 0C 00 00 00 00 00
7	832518	标准帧	数据帧	FDCAN	0x0	RX	8 33 C7 0C 00 00 00 00 00
8	832519	标准帧	数据帧	FDCAN	0x0	RX	8 EA C7 0C 00 00 00 00 00
9	832520	标准帧	数据帧	FDCAN	0x0	RX	8 3B C9 0C 00 00 00 00 00
10	832521	标准帧	数据帧	FDCAN	0x0	RX	8 7C C6 0C 00 00 00 00 00
11	832522	标准帧	数据帧	FDCAN	0x0	RX	8 34 C7 0C 00 00 00 00 00
12	832523	标准帧	数据帧	FDCAN	0x0	RX	8 A0 C8 0C 00 00 00 00 00
13	832524	标准帧	数据帧	FDCAN	0x0	RX	8 EB C7 0C 00 00 00 00 00
14	832525	标准帧	数据帧	FDCAN	0x0	RX	8 3C C9 0C 00 00 00 00 00
15	832526	标准帧	数据帧	FDCAN	0x0	RX	8 7D C6 0C 00 00 00 00 00
16	832527	标准帧	数据帧	FDCAN	0x0	RX	8 A1 C8 0C 00 00 00 00 00
17	832529	标准帧	数据帧	FDCAN	0x0	RX	8 EC C7 0C 00 00 00 00 00
18	832528	标准帧	数据帧	FDCAN	0x0	RX	8 35 C7 0C 00 00 00 00 00
19	832530	标准帧	数据帧	FDCAN	0x0	RX	8 3D C9 0C 00 00 00 00 00
20	832531	标准帧	数据帧	FDCAN	0x0	RX	8 7E C6 0C 00 00 00 00 00
21	832532	标准帧	数据帧	FDCAN	0x0	RX	8 A2 C8 0C 00 00 00 00 00
22	832533	标准帧	数据帧	FDCAN	0x0	RX	8 ED C7 0C 00 00 00 00 00
23	832534	标准帧	数据帧	FDCAN	0x0	RX	8 7F C6 0C 00 00 00 00 00
24	832535	标准帧	数据帧	FDCAN	0x0	RX	8 36 C7 0C 00 00 00 00 00
25	832537	标准帧	数据帧	FDCAN	0x0	RX	8 A3 C8 0C 00 00 00 00 00
26	832536	标准帧	数据帧	FDCAN	0x0	RX	8 3E C9 0C 00 00 00 00 00
27	832538	标准帧	数据帧	FDCAN	0x0	RX	8 EE C7 0C 00 00 00 00 00
28	832539	标准帧	数据帧	FDCAN	0x0	RX	8 EF C7 0C 00 00 00 00 00
29	832540	标准帧	数据帧	FDCAN	0x0	RX	8 F0 C7 0C 00 00 00 00 00
30	832541	标准帧	数据帧	FDCAN	0x0	RX	8 80 C6 0C 00 00 00 00 00
31	832542	标准帧	数据帧	FDCAN	0x0	RX	8 37 C7 0C 00 00 00 00 00
32	832543	标准帧	数据帧	FDCAN	0x0	RX	8 38 C7 0C 00 00 00 00 00
33	832545	标准帧	数据帧	FDCAN	0x0	RX	8 39 C7 0C 00 00 00 00 00
34	832546	标准帧	数据帧	FDCAN	0x0	RX	8 81 C6 0C 00 00 00 00 00
35	832544	标准帧	数据帧	FDCAN	0x0	RX	8 3F C9 0C 00 00 00 00 00
36	832547	标准帧	数据帧	FDCAN	0x0	RX	8 3A C7 0C 00 00 00 00 00

❖ Reading Device Version

To read the device firmware version, press F9 to bring up the module firmware upgrade interface, click the Read Version button in the red box as shown in the figure below, and you can see the device version information below.



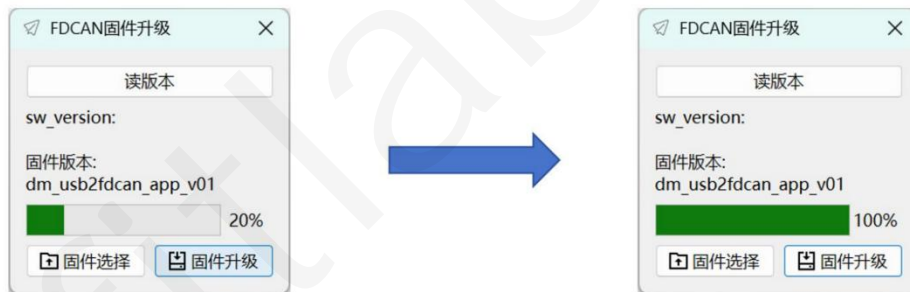
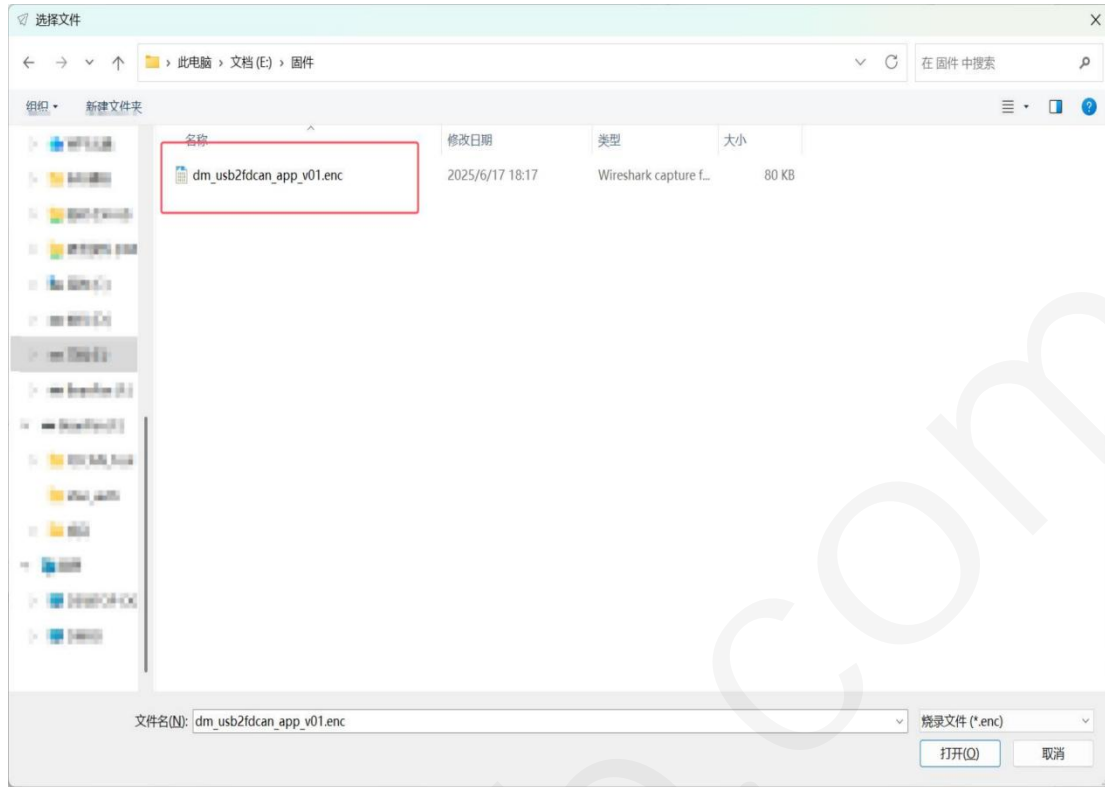
❖ Device Firmware Upgrade

The steps for module firmware upgrade are as follows:

- 1 Press the F9 shortcut key on the main interface to bring up the firmware upgrade window;
- 2 Click the Firmware Selection button to select the firmware version to upgrade;
- 3 Click the Firmware Upgrade button and wait for the upgrade progress bar to complete;
- 4 After successful upgrade, the module will automatically restart. You can open the window again to check if the module version has been successfully upgraded;



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Application Example: Debugging DAMIAO Motor Instructions

❖ Modifying Motor Baud Rate

All parameter modification operations must be performed when the motor is in a disabled state. The new version of the host computer optimizes the motor baud rate modification process. The operation steps are as follows:



① Enter the parameter setting interface: Click the Parameter Settings button on the main interface to jump to the parameter setting page;

② Read current parameters: Click the Read Parameters button to obtain the motor's current configuration parameters; (If CAN reading fails, please retry the read operation)

③ Modify baud rate setting: Select the target baud rate (such as 5Mbps) in the CAN Baud dropdown menu;

④ Save configuration: Click the Write Parameters button to complete the setting (this operation can be written via UART communication mode or CAN communication mode, with power-off memory function);

【Precautions】

- Ensure the baud rate modification matches other devices in the communication system;
- After writing, it is recommended to read the parameters again to confirm the settings have taken effect;

❖ Reading/Writing Parameters in CAN Mode

Before reading/writing parameters in CAN mode, you first need to determine the motor's CAN ID. In UART mode, switch to the parameter setting page and click Read

Parameters to read the motor's CAN ID. If UART mode cannot be used, jump to the Debug tab and click the Read ID button on the right. After obtaining the motor ID, the

software will automatically synchronize and update it to the ID box on the left. Then, click the switch button in the red box on the left to switch to CAN mode, and the input box next to it is for the motor ID (this input box will be automatically filled by the software after reading parameters in UART mode). Finally, click the Read Parameters button in CAN mode to read all motor parameters (if acquisition fails, try clicking the Read Parameters button again).

1. Obtaining Motor CAN ID

UART mode acquisition:

Enter the parameter setting page

Click the Read Parameters button to read the motor's current parameters (including CAN ID)

After successful reading, the CAN ID will be automatically filled into the ID input box on the left

Switch to the Debug tab

Click the Read ID button on the right to obtain the motor ID

Manually fill the obtained ID into the ID input box on the left

2. Switching to CAN Mode

Click the switch button on the left to change the communication mode to CAN

Confirm that the motor ID input box has been correctly filled (it will be automatically filled after reading parameters in UART mode)

3. Reading/Writing Parameters in CAN Mode

Reading parameters:

Click the Read Parameters button and wait for the reading to complete

If it fails, check the CAN connection and retry

Writing parameters:

Modify the target parameters (such as baud rate, ID, etc.)

Click the Write Parameters button to save (with power-off memory function)

【Precautions】

- Ensure the CAN bus terminal resistors are matched to avoid communication abnormalities;
- When writing parameters, the motor should be in disabled mode.

DM测试工具

通讯设置

串口号: COM97

波特率: 921600

数据位: 8

校验位: 1

停止位: None

USB模式

CAN ID: 1

固件升级

Firmware REV:
 Bootloader REV:
 固件名称:
 DM8009(V3)_V6417_02

0%

校准

校准 电机编码器

参数预设

Version: V2.0.2.4

串口 CAN **参数设置** 校准 测试

电机参数

相电阻 (R): 203.144 mR

相电感 (L): 66.0936 uH

磁链 (λ): 0.0041645 Wb

粘滞系数: 0.00167515

转动惯量: 0.000201941 kg*m2

控制限值

PMAX: 12.5

VMAX: 45

TMAX: 54

KT_OUT: 0

齿轮系数: 1

阻尼因子: 4

控制设置

控制模式: 1:MIT模式

电流带宽: 1000

速度 KP: 0.0068

速度 KI: 0.002

位置 KP: 54

位置 KI: 0

驱动参数

极对数: 21 欠压: 15 加速度: 2 Ki_current: 100

减速比: 9 过压: 54 减速度: -2 Ki_speed: 2500

过流: 0.8 过温: 100 限速: 600 fbw: 40

通讯参数

CAN ID: 0x01 Master ID: 0x00 CAN Timeout: 1 CAN Baud: 5M 子版本号: 2

反馈报文	D[0]	D[1]	D[2]	D[3]	D[4]	D[5]	D[6]	D[7]
MST_ID	IDERR<<64	POS[15:8]	POS[7:0]	VEL[11:4]	VEL[3:0][T[11:8]	T[7:0]	T_MOS	T_Rotor

控制报文	D[0]	D[1]	D[2]	D[3]	D[4]	D[5]	D[6]	D[7]
ID	p_des [15:8]	p_des [7:0]	v_des [11:4]	v_des[3:0] Kp [11:8]	Kp [7:0]	Kd [3:0]	t_m[11:8]	t_0[7:0]

ID 表示控制器的 ID, 取 CAN_ID 的低 8 位
ERR 表示故障, 对应故障类型为:
 P——过压; C——电机线圈过温
 U——欠压; D——通讯丢失; T——电机温度报警
 A——过电流; E——过流;
 POS 表示电机的位置信息
 VEL 表示电机的速度信息
 T 表示电机的扭矩信息
 T_MOS 表示驱动上 MOS 的平均温度, 单位 °C
 T_Rotor 表示电机内部线圈的平均温度, 单位 °C
 位置、速度和扭矩采用线性映射的关系将浮点型数据转换成有符号的定点数据, 其中位置采用 16 位数据, 速度和扭矩均使用 12 位。

After modifying the parameters, click the Write Parameters button to write the new parameters into the motor driver. For example, if you need to modify the motor control mode, change the control mode (MIT mode) to speed mode in the red box at the lower left corner of the parameter setting interface, then click the Write Parameters button.



After successful modification, read the parameters again, and you can see that the motor mode has been successfully changed.

DM测试工具

通讯设置

串口号: COM97

波特率: 921600

数据位: 8

校验位: 1

停止位: None

刷新串口 关闭串口

USB模式

CAN ID: 1 CAN

固件升级

读版本

Firmware REV: 0%

固件选择 固件升级

校准

校准 电机编码器

参数预设

参数导出 参数导入

设备配置 清空数据

Version: V2.0.2.4

电机参数

相电阻 (R): 203.144 mR 参数标定

相电感 (L): 66.0936 uH

磁链 (λ): 0.0041645 Wb

粘滞系数: 0.00167515

转动惯量: 0.000201941 kg*m2

控制限值

PMAX: 12.5

VMAX: 45

TMAX: 54

KT_OUT: 0

齿轮系数: 1

阻尼因子: 4

控制设置

控制模式: 3:速度模式

电流带宽: 1000

速度 KP: 0.0068

速度 KI: 0.002

位置 KP: 54

位置 KI: 0

驱动参数

极对数: 21 欠压: 15 加速度: 2 Ki_current: 100 读参数

减速比: 9 过压: 54 减速度: -2 Ki_speed: 2500

过流: 0.8 过温: 100 限速: 600 fbw: 40 写参数

通讯参数

CAN ID: 0x01 Master ID: 0x00 CAN Timeout: 1 CAN Baud: 5M 子版本号: 2

反馈报文	D[0]	D[1]	D[2]	D[3]	D[4]	D[5]	D[6]	D[7]
MST_ID	IDERR<<4	POS[15:8]	POS[7:0]	VEL[11:4]	VEL[3:0][11:8]	T[7:0]	T_MOS	T_Rotor

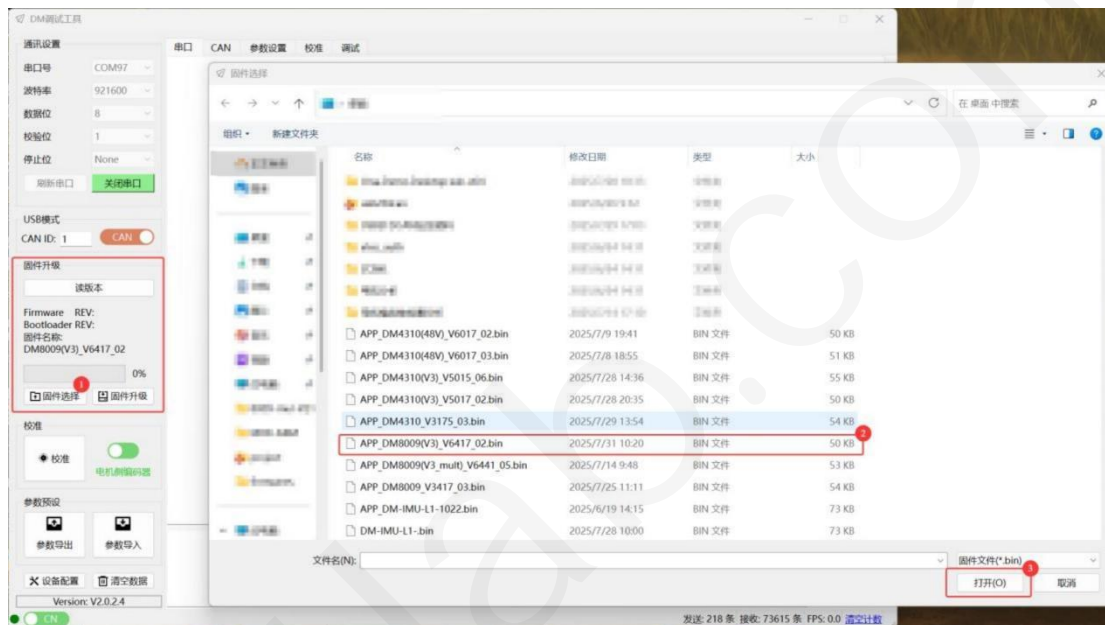
控制报文	D[0]	D[1]	D[2]	D[3]
0x200+ID	v_des			

ID 表示控制器的 ID, 取 CAN_ID 的低 8 位
ERR 表示故障, 对应故障类型为:
 B——超压; C——电机线圈过温
 G——欠压; A——过电流; D——通讯丢失; E——过载
 H——MOS 过温
 POS 表示电机的位置信息
 VEL 表示电机的速度信息
 T 表示电机的温度信息
 T_MOS 表示驱动上 MOS 的平均温度, 单位℃
 T_Rotor 表示电机内部线圈的平均温度, 单位℃
 位置、速度和扭矩采用线性映射的关系将浮点型数据转换成符号的定点数据, 其中位置采用 16 位数据, 速度和扭矩均使用 12 位。

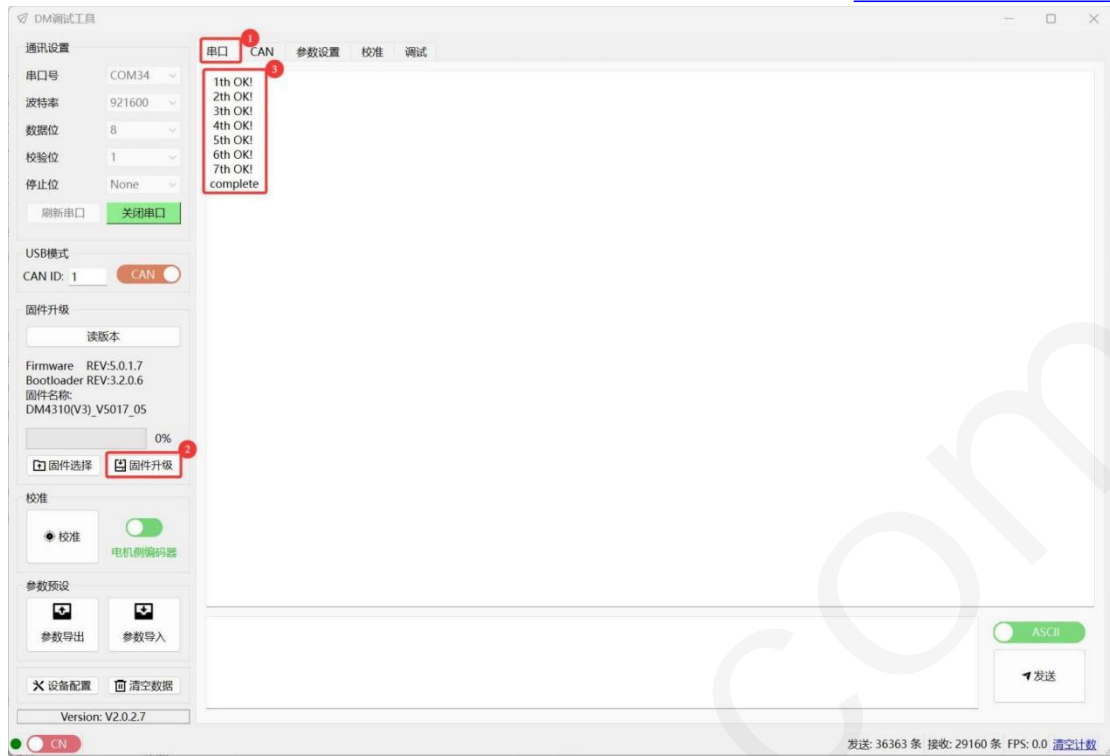
发送: 218 条 接收: 73615 条 FPS: 0.0 清空计数

❖ Motor Firmware Upgrade via CAN Channel

When you need to use the CAN channel for motor firmware upgrade, ensure the motor firmware version supports this function, then you can use the module for CAN mode upgrade. First, obtain the motor ID number. The method to obtain it can be found in the CAN mode motor parameter reading/writing section. Then click the Firmware Selection button in the red box at the lower left corner to open the file selection dialog and select the firmware to upgrade.



Finally, click the Firmware Upgrade button and wait for the firmware upgrade progress bar to complete, then the firmware upgrade is finished. At the same time, you can see the upgrade process prompts on the serial port interface.



❖ Motor Debugging

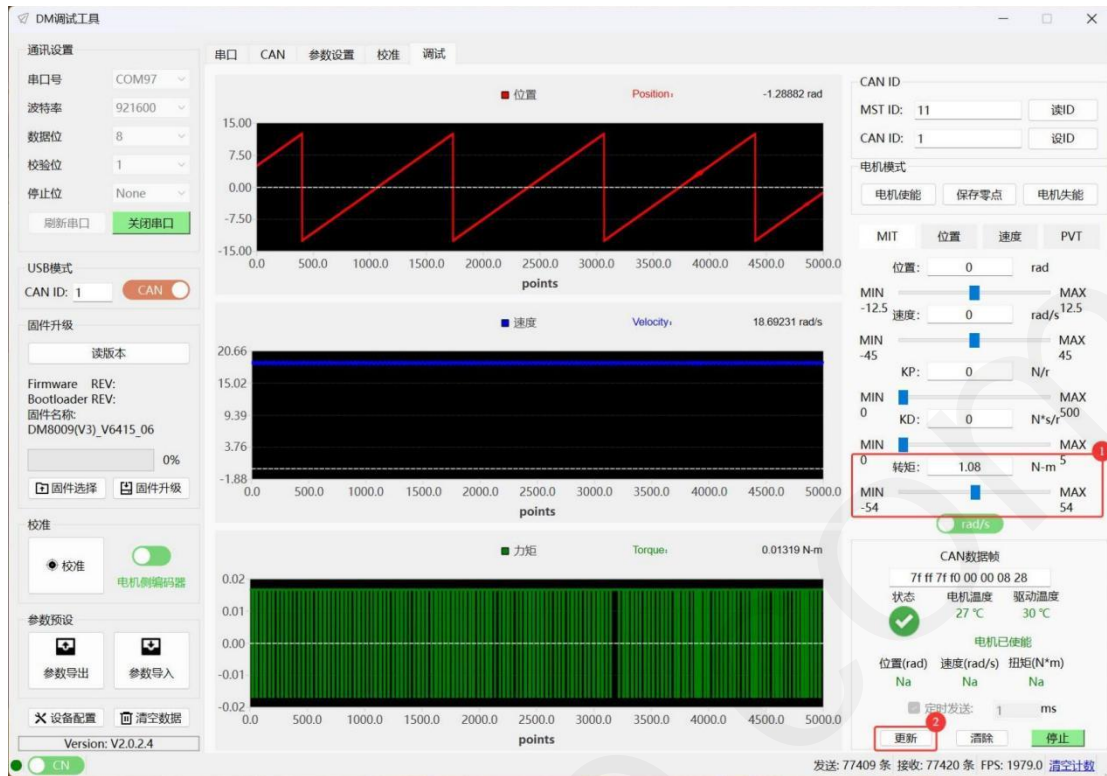
Before debugging the motor, be sure to confirm the current motor's CAN baud rate and configure the USB to CANFD to the same baud rate. The baud rate configuration process is described in the previous sections. The following takes a 5Mbps motor in MIT mode as an example.

To view the motor status waveform in real-time, click the Debug tab to jump to the debug page, then click the Send button in the red box at the lower right corner to obtain the motor's feedback frame in real-time and parse the data (when you no longer need to update the status waveform, click the Stop button at the same position).

The screenshot displays the DM Debugging Tool interface, which is used for monitoring and controlling a motor. The interface is divided into several sections:

- Left Panel (Configuration):** Contains settings for communication (Serial Port: COM97, Baud Rate: 921600, Data Bits: 8, Parity: 1, Stop Bits: None), USB Mode (CAN), and Firmware Upgrade (Firmware REV: Bootloader REV: DM8009(V3)_V6415_06).
- Top Tab Bar:** Includes '串口', 'CAN', '参数设置', '校准', and '调试' (Debug). The '调试' tab is currently selected and highlighted with a red box.
- Central Waveform Area:** Displays three real-time waveforms:
 - Position (red):** Shows a constant value of -1.94839 rad over 5000 points.
 - Velocity (blue):** Shows a constant value of -0.01099 rad/s over 5000 points.
 - Torque (green):** Shows a constant value of -0.03956 N·m over 5000 points.
- Right Panel (Control Parameters):** Includes fields for CAN ID (MST ID: 11, CAN ID: 1), Motor Mode (电机使能, 保存零点, 电机失能), and various control parameters (MIT, 位置, 速度, PVT) with sliders and input boxes for MIN, MAX, KP, and KD values.
- Bottom Right Panel (CAN Data Frame):** A red box highlights this section, showing the CAN data frame '7f ff 7f 00 00 07 ff'. It displays the motor status (电机未使能), temperature (电机温度: 27 °C, 驱动温度: 30 °C), and position/velocity/torque (位置(rad): Na, 速度(rad/s): Na, 扭矩(N*m): Na). A '停止' (Stop) button is highlighted with a red box.

When torque control is needed, modify the torque input box to the target torque or drag the slider below to the target torque, then click the Update button to send the corresponding torque control command (be sure to confirm the motor is in enabled state before clicking the Update button).



For more other motor debugging instructions, please refer to the Debugging Assistant User Manual (DAMIAO Drive Control Protocol) V1.4.pdf. Download link:

<https://gitee.com/kit-miao/damiao-document/blob/master/%E8%B0%83%E8%AF%95%E5%8A%A9%E6%89%8B%E4%BD%BF%E7%94%A8%E8%AF%B4%E6%98%8E%E4%B9%A6%EF%BC%88%E8%BE%BE%E5%A6%99%E9%A9%B1%E5%8A%A8%E6%8E%A7%E5%88%B6%E5%8D%8F%E8%AE%AE%EF%BC%89V1.4.pdf>

❖ Motor Feedback Frame Parsing

1. Transmitted Frame Parsing

Following motor debugging, when clicking the Update button, the CAN data frame content box below will parse the torque instruction into the data content of the CAN control message.

CAN数据帧

08 00 80 00 00 00 08 0e

状态	电机温度	驱动温度
	-25 °C	-5 °C

电机已使能

位置	速度	扭矩
-12.5	-10	-28

定时发送: 1 ms

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2. Received Frame Parsing

When you need to parse the motor feedback message received at a certain moment, click the CAN tab, copy the message content to be parsed, paste this content into the input box in the CAN data frame content box on the debug interface, and press the Enter key to parse the position, speed, and torque data of this motor message.

