----------Instructions----------

1. Welcome to watch the "HitBotStudio Software Installation and Uninstall.Mp4" video tutorial;

2.setup.exe:Starting installation, please follow the default instructions to install, the installation path can be modified.

3.RemoveHIiBotStudio.msi: Starting repair and uninstall, which can be removed from the computer (Kindly notes that please close the "Server.exe" software with the white logo opened in the lower right corner of the computer taskbar before uninstalling)

4. After the software is successfully installed, please run it as an administrator or use right-click the property - compatibility - check the program to run the program as the administrator. Please allow the software to run on the private network/shared network at the first time you open it; please Turn off the firewall to avoid intercept, otherwise the robot arm cannot be connected normally.

5. Setting the static IP of the local Ethernet to "192.168.0.100" (mechanical arm host IP), subnet mask: 255.255.255.0; others do not need to be set; if you need to modify the network segment , the last position of the robot arm ip must be 100, then you should set the robot arm IP through the Android mobile APP, and ensure that the host and the robot arm are in the same network segment.

6. The PC is connected to the mechanical arm network port through the network cable. The green light will always on after the power is turned on, indicating that the line is connected. Opening the HitBotStudio software and pull down the directory in the Robot arm IP controls, then the ID of the current arm will be displayed; selecting the ID, click the “Initialize” button, and the “Initialization Successful” will pop up. After that, the arm can be controlled.

7. Please watch the "HitBStudio Basic Tutorial.Mp4" before using the software, the project administrator password: hitbot (must be lowercase).

--Hi19.2.1 version software update ----------------

1. Optimize the running speed of the process in order to improve work efficiency;

2. Add a client module which can receive the coordinates transmitted by the server and modify the value of the variable;

3. The point module adds client function to request compensation value from the server, the specific operation: point module attribute --> check point compensation ---> right mouse button "guest" module to view and modify the client attributes;

4. The tray module adds the client function to request the compensation value from the server. The specific operation: tray module attribute-->check the tray compensation---> right mouse button "guest" module to view and modify the client attributes;

5. The project path is specified by default. The opened software can automatically load the process file. The specific operation: the upper right corner of the interface --> Settings --> Project default path --> Browse and save;

6. After the communication line is normally connected, the arm can be powered on, and the system input signal can be used to initialize the arm and start the process;