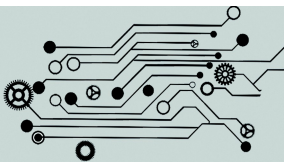

ARM BLDC MOTOR WHEEL CONTROL LIST

OP CODE	CANBUS ID	CANBUS DATA INFO									DATA LIMITS
		D0	D1	D2	D3	D4	D5	D6	D7	DATA TYPE	Min / Max / Unit
TARGET VELOCITY / TARGET VELOCITY- DİSTANCE	0Xuuu00020	Velocity				* Distance				FLOAT / FLOAT	0 / 100 / Rpm - / - / cm
INFORMATION 1 REQUEST	0X00000200	REMOTE ID								-	-
INFORMATION 2 REQUEST	0X00000201	REMOTE ID								-	-
INFORMATION 1 INFO 1	0Xuuu00000	Motor Max. Rpm (rpm)				-	-	-	-	FLOAT	d/dk
INFORMATION 1 INFO 2	0Xuuu00001	Position Tolerance(cm)				Max. Current (amper)				FLOAT / FLOAT	0 / - / cm 0 / 7 / A
INFORMATION 1 INFO 3	0Xuuu00002	Software Version	-	-	-	-	-	-	-	Unsigned Char	-
INFORMATION 2 INFO 1	0Xuuu00010	Motor Direction	Motor Positioned Status	Motor Velocity (rpm)				Slave Number	-	Unsigned Char / Unsigned Char / F LOAT / Unsigned Char	-
INFORMATION 2 INFO 2	0Xuuu00011	-	-	-	-	** Torque (0-1)(e.g. : 0,2)				FLOAT	-
INFORMATION 2 INFO 3	0Xuuu00012	Total Distance (cm)				Encoder Pulse (0-65535) (1024 ppr)				FLOAT / INT	-
INFORMATION 2 INFO 4	0Xuuu00013	Motor Current (Amper)				Motor Positioned Statsus	Motor Direction	-	-	FLOAT / Unsigned Char / Unsigned Char	-
INFORMATION 2 INFO 5	0Xuuu00014	-	Hall Sensor 1 Error	Hall Sensor 2 Error	Hall Sensor 3 Error	Hall Sensor State Error	Motor Socket Error	Motor Direction Error	-	All Unsigned Char	0 / 1 / -
INFORMATION 2 INFO 6	0Xuuu00015	Rpm Calculate Error	-	-	-	-	Motor Over Current Error	Motor 24V Input Error	Eeprom Error	All Unsigned Char	0 / 1 / -
INFORMATION 2 INFO 7	0Xuuu00016	-	-	-	-	Motor Hard Current Error	-	-	-	Unsigned Char	0 / 1 / -
INFORMATION 2 INFO 8	0Xuuu00017	Motor Step Counter				Position Tolerance				Unsigned Int / FLOAT	0 / - / - 0 / - / cm
TARGET TORQUE	0Xuuu0002E	Motor Torque				-	-	-	-	FLOAT	0 / 1 / -
ACCELERATION START – STOP	0Xuuu00031	*** Accelation (1-Motor Max. Rpm)				-	-	-	-	FLOAT	0 / V / -
SYSTEM RESET	0Xuuu00029	-	-	-	-	-	-	-	-	-	-
MOTION MODE	0Xuuu00033	**** Motion Mode (0 or 1) (For Target Velocity: 0 or For Targer Velocity-Distance : 1)				-	-	-	-	INT	0 / 1 / -
TARGET POSITION TOLERANCE	0Xuuu00023	Position Tolerance(cm)				-	-	-	-	FLOAT	0 / - / cm

* This value is used when the motion mode is 1.

** This value must be between zero and one. The percentage value is defined as a decimal number.

*** This value sets the acceleration time of the movement.

**** This value controls the distance or no distance mode of the movement.

NOTE1: Canbus communication speed is 1Mbit/s.

NOTE2: Canbus Extended Id structure is shown below:

ID Structure: 0X**uuu**000**dd** **(ID: 0X011000dd – 0XFFF000dd.)**

uuu: Unit Number, this specifies the unit itself to gather related data from Bus.

dd: Data type, this block specifies the types of data like speed, angle or torque, received by the related unit. (dd, shown in the table.)

Example ID :

0X01100020 Slave 1; 0X01200020 Slave 2; 0X01300020 Slave 3; ...

0X02100020 Slave 1; 0X02200020 Slave 2; 0X02300020 Slave 3; ...