CANID\_CMD\_LEVELWIND

payload layout

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Initiator of command:

CANID\_CMD\_LEVELWIND**\_Is**

Where ‘s’ is instance number: 1,2,3,4

Responder of command:

CANID\_CMD\_LEVELWIND**\_Rd**

where ‘d’ is instance number (drum): 1,2,3,4,5,6,7

DLC: 3 or 7

PAYLOAD\_TYPE: U8\_U8\_U8\_X4

Functions that initiate command (“**I**”): GENCMD (general, and varied, e.g PC)

Function that sends response (“**R**”): Levelwind

payload[0] U8

Drum bits (Levelwind instances)

0 = Ignore command

1 = Act upon command; respond if necessary

bit 7 – spare

bit 6 – Drum #7

… #2-#6

bit 0 – Drum #1

payload[1] U8

Command code (widely applicable to functions)

(See: GliderWinchCommons//embed/svn\_common/trunk/db/CMD\_CODES\_INSERT.sql)

payload[2] U8

Sub-command code, (applicable to Levelwind function)

payload[3-6] X4

Four byte value:

Interpretation depends on sub-command code

Types: int32\_t, uint32\_t, float

**Sub-commands**

**If** – payload[1] (See CMD\_CODES\_INSERT.sql)

CMD\_GET\_READING, 36, 'Send a reading for the code in following payload byte’

**Then**--

payload[2] sub-command codes:

**0** = Levelwind switches (uint32\_t)

payload[3-7] = Port E switches, right justified: (PE14-PE7) >> 7

**1** = CAN bus voltage (float)

**2** = Stepper Controller voltage (float)

3 = Position accumulator at motor-side limit sw closure

4 = Position accumulator at not-motor-side limit sw closure

5 = Position accumulator at center