DTI INVERTER CAN MANUAL

FOR HV-500/HV-550/HV-850

Version 2.5

For developers and integrators

For inverter related informations and CAN Pinout please refer to the inverter Technical description. Upon any concerns or questions, please contact us at info@drivetraininnovation.com

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1. HISTORY AND RELATED DOCUMENTS

1.1 Document history

07/2018	**V1.0** Document created; basic specifications added.
01/2019	**V1.1** Fixed typos
03/2019	**V1.2** Fixed typos
04/2019	**V1.3** Fixed typos
08/2020	**V2.0** Major revision and actualizing for firmware version 4.1
10/2020	**V2.1** Modified IDs for commands.
10/2020	**V2.11** Fixed MSB / LSB order
10/2020	**V2.2** Updated document according to bugfix in the HV-500 regarding Standard CAN ID addressing
08/2021	**V2.3** Added new messages and drive enable control
10/2022	**V2.4** Rearranged packet IDs, added “set Digital out” command
02/2023	**V2.4 REV2** Wrong transmitted signal packet IDs fixed
04/2023	**V2.4 REV3** Added operation range for signals
05/2023	**V2.5** Added 3 new messages for support multi-controller config.

1.2 Related documents

- HV-500/HV-550/HV-850 Manual
- DTI CAN Tool manual (to be released)
- DTI Firmware upgrade manual

2. OVERVIEW

The scope of this manual is the CAN2 of DTI Inverters. The CAN1 is reserved for DTI Can Tool, Firmware updates and DTI devices.

The motor controller includes a software timeout. If the controller does not receive control command for the set time interval (in DTI CAN Tool: APP Settings / General / Timeout), the motor will be in free running and the control will stop until the next command. Therefore, CAN control messages should be sent faster (at least half period of the timeout) than the set time interval for continuous control.

DTI Inverters are CAN 2.0B Compliant.

2.1 CAN Speed

The default CAN Speed is 500Kbit/s. This can be adjusted in DTI Can Tool under APP Settings / CAN. This parameter can be adjusted individually for CAN1 and CAN2.

Available speeds:

- 125 Kbit/s
- 250 Kbit/s
- 500 Kbit/s
- 1Mbit/s

2.2 Controller ID (Node ID)

The Controller ID can be set via the DTI CAN tool in APP Settings / CAN.

By default, this ID is the last two digits of the inverter serial number in decimal.

2.3 ID Ranges

The inverter supports both Standard ID and Extended ID CAN message ID formats. The integrator must choose according to their requirement which method is used for addressing. Both addressing method executes the same functions.

2.3.1 Standard ID operation

With Standard CAN ID configuration the available ID range is between 1 and 30. The ID 31 is reserved for broadcast messages. Messages with node ID 0 will be rejected. This operation uses 5 bits to address nodes on the bus.

For more information, refer to 2.4 chapter.

2.3.2 Extended ID operation

When using Extended CAN ID, the settable ID range is between 1-254. The ID 255 is reserved for broadcast messages. Messages with node ID 0 will be rejected. In that mode 8 bit is used for addressing nodes on the bus.

For more information, refer to 2.4 chapter.

2.4 General message overview

The messages should contain the data in **BIG ENDIAN** (Motorola) byte order format. Every message has a **fixed length of 8 bytes**. Bytes which are not used filled with 0xFF.

2.4.1 CAN message ID

The standard CAN message ID is represented as below:

Standard ID (11 bits) **MSB:LSB**	
Packet ID	Node ID
0x 21	4
10:5 bits (6 bits)	4:0 bits (5 bits)
It can represent a transmitted “AC Current, DC Current” frame by the inverter with node ID 8.	

The extended CAN message ID is represented as below:

Extended ID (29 bits) **MSB:LSB**	
Packet ID	Node ID
0x 00 00 21	4
28:8 bits (21 bits)	7:0 bits (8 bits)
It can represent a transmitted “AC Current, DC Current” frame by the inverter with node ID 34.	

The following tables represents a general CAN bus message with standard and extended formats:

Table 1 Standard ID example message

	Message ID		**Data bytes**							
Position	10:5 bits	4:0 bits	0	1	2	3	4	5	6	7
Message	0x 00	4	00	00	24	5E	FF	FF	FF	FF
Desc.	Packet ID	Node ID	ERPM bytes [3:0] MSB:LSB (9310d)				Not used, filled with FF			

In case of standard ID you must shift the CAN ID by 5 to get the packet id:

Packet ID = (CANID >> 5)

To get the Node ID you must mask it by 0x1F:

Node ID = CANID & 0x1F

Table 2 Extended ID example message

	Message ID		**Data bytes**							
Position	28:8 bits	7:0 bits	0	1	2	3	4	5	6	7
Message	0x 00 00 00	4	00	00	24	5E	FF	FF	FF	FF
Desc.	Packet ID	Node ID	ERPM bytes [3:0] MSB:LSB (9310d)				Not used, filled with FF			

In case of extended ID you must shift the CAN ID by 8 to get the packet id:

Packet ID = (CANID >> 8)

To get the Node ID you must mask it by 0xFF:

Node ID = CANID & 0xFF

3. TRANSMITTED DATA BY INVERTER

In order to enable the transmission from the inverter, the following parameters should be enabled in the DTI CAN Tool:

- Enable CAN2: *Enabled*
- Send CAN2 Status: *Enabled*
- CAN2 map version: *V24*
- Specify each message broadcasting period

3.1 Packet IDs

Packet IDs are identifying the information content of each message. In the table below you can find which kind of information available on the CAN bus:

Table 3: Transmitted messages

Packet ID	Message description
0x1F	Control mode, Target Iq, motor position, isMotorStill
0x20	ERPM, Duty, Input Voltage
0x21	AC Current, DC Current
0x22	Controller Temp., Motor Temp., Fault code
0x23	Id, Iq values
0x24	Throttle signal, Brake signal, Digital I/Os, Drive enable, Limit status bits, CAN map version
0x25	configured max AC current, available max AC current, configured min AC current, available min AC current
0x26	configured max DC current, available max DC current, configured min DC current, available min DC current

3.2 Description of transmitted signals by the inverter

Table 4 Transmitted CAN bus messages

Packet ID	Byte	Bit start	Msg name	Message description	Min/Max data range (post-scale)	Min/Max operational range	Scale	Unit
0x1F	Length: 8 bytes		General data 6					
	0	0	Control mode	Describes the control mode of the inverter: **1: CONTROL_MODE_SPEED** **2: CONTROL_MODE_CURRENT** **3: CONTROL_MODE_CURRENT_BRAKE** **4: CONTROL_MODE_POS** **7: CONTROL_MODE_NONE** **0, 5, 6: NOT USED** Mainly used in multi-controller configurations for internal communication.	0 - 7	0 - 7	1	#
	1 - 2	8	Target Iq	The value represent how much Iq current the inverter is targeted to reach. This value excludes limits. For ex. if the target Iq is 50 A and temperature limit is hit, the values keep 50 A in any case, not including the deration of the temp. limit. This is useful in multi-inverter configuration to let know the secondary inverter the target Iq.	-3276,8 - 3276,7	-850 - 850	10	A_{pk}
	3 – 4	24	Motor position	Motor position expressed in degrees.	0 - 359	0 - 359	10	degree
	5	40	isMotorStill	Represents if the motor in still position or not. **1: still, 0: rotating**	0 - 1	0 - 1	1	#

	6 - 7	48	RESERVED	Filled with FF's. For future use.	-	-	-	-
0x20	Length: 8 bytes		General data 1					
	0 – 3	0	ERPM	Electrical RPM Equation: ERPM = Motor RPM * number of the motor pole pairs.	-2147483648-2147483647	-120 000 – 120 000	1	ERPM
	4 - 5	32	Duty cycle	The controller duty cycle. The sign of this value will represent whether the motor is running(positive) current or regenerating (negative) current.	-3276,8 - 3276,7	-100 – 100	10	%
	6 - 7	48	Input voltage	Input voltage is the DC voltage.	-32768 - 3276,7	0 – 1000	1	V
0x21	Length: 8 bytes		General data 2					
	0 - 1	0	AC current	The motor current. The sign of this value represents whether the motor is running(positive) current or regenerating (negative) current.	-3276,8 - 3276,7	-850 - 850	10	A_{pk}
	2 – 3	16	DC current	DC Current: Current on DC side. The sign of this value represents whether the motor is running(positive) current or regenerating (negative) current.	-3276,8 - 3276,7	-850 - 850	10	A_{dc}
	4 - 7	32	RESERVED	Filled with FF's. For future use.	-	-	-	-

Packet ID	Byte	Bit start	Msg name	Message description	Min/max data range (post-scale)	Min/max operational range	Scale	Unit
0x22	Length: 8 bytes		General data 3					
	0 – 1	0	Controller temperature	Temperature of the inverter semiconductors.	-3276,8 - 3276,7	-55 - 200	10	°C
	2 – 3	16	Motor temperature	Temperature of the motor measured by the inverter	-3276,8 - 3276,7	-55 - 200	10	°C
	4	32	Fault code	**0x00 : NO FAULTS** **0x01 : Overvoltage** - The input voltage is higher than the set maximum. **0x02 : Undervoltage** - The input voltage is lower than the set minimum. **0x03 : DRV** - Transistor or transistor drive error **0x04 : ABS. Overcurrent** - The AC current is higher than the set absolute maximum current. **0x05 : CTLR Overtemp.** - The controller temperature is higher than the set maximum. **0x06 : Motor Overtemp.** - The motor temperature is higher than the set maximum. **0x07 : Sensor wire fault** - Something went wrong with the sensor differential signals. **0x08 : Sensor general fault** - An error occurred while processing the sensor signals **0x09 : CAN Command error** - CAN message received contains parameter out of boundaries	0	255	1	#

				0x0A : Analog input error – Redundant output out of range				
	5-7	40	RESERVED	Filled with FF's. For future use.	-	-	-	-
0x23	Length: 8 bytes		General data 4					
	0 – 3	0	Id	FOC algorithm component Id.	-2147483,648 - 2147483,647	-850 – 850	100	A_{pk}
	4 – 7	32	Iq	FOC algorithm component Iq	-2147483,648 - 2147483,647	-850 – 850	100	A_{pk}

Packet ID	Byte	Bit start	Msg name	Message description	Min/max data range (post-scale)	Min/max operational range	Scale	Unit
0x24	Length: 8 bytes		General data 5					
	0	0	Throttle signal	Throttle signal derived from analog inputs or CAN2	-128 – 127	0 - 100	1	%
	1	8	Brake signal	Brake signal derived from analog inputs or CAN2	-128 - 127	0 - 100	1	%
	2	16	Digital input 1	1: Digital input is active 0: Digital input is inactive	0	1	1	#
		17	Digital input 2		0	1	1	#
		18	Digital input 3		0	1	1	#
		19	Digital input 4		0	1	1	#
		20	Digital output 1	1: Digital output is active 0: Digital output is inactive	0	1	1	#
		21	Digital output 2		0	1	1	#
		22	Digital output 3		0	1	1	#
		23	Digital output 4		0	1	1	#
	3	24	Drive enable	1: Drive enabled 0: Drive disabled Drive can be enabled/disbled by the digital input or/and via CAN2 interface	0	1	1	#

	4	32	Capacitor temp limit	1: Capacitor temperature limit active 0: Capacitor temperature limit inactive The inverter can limit the output power to not to overheat the internal capacitors. (only valid HW version 3.6 or newer)	0	1	1	#
		33	DC current limit	1: DC current limit active 0: DC current limit inactive	0	1	1	#
		34	Drive enable limit	1: Drive enable limit active 0: Drive enable limit inactive Indicates whether the drive enable limitation is active or inactive. Used for software development purposes. **For true indication of the drive state please use byte 3, bit 24 of this message.**	0	1	1	#
		35	IGBT acceleration temperature limit	1: IGBT acceleration limit active 0: IGBT acceleration limit inactive	0	1	1	#
		36	IGBT temperature limit	1: IGBT temperature limit active 0: IGBT temperature limit inactive	0	1	1	#
		37	Input voltage limit	1: Input voltage limit active 0: Input voltage limit inactive	0	1	1	#
		38	Motor acceleration temperature limit	1: Motor acceleration temperature limit active 0: Motor acceleration temperature limit inactive	0	1	1	#
		39	Motor temperature limit	1: Motor temperature limit active 0: Motor temperature limit inactive	0	1	1	#
	5	40	RPM min limit	1: RPM min limit active 0: RPM min limit inactive	0	1	1	#

	5	41	RPM max limit	1: RPM max limit active 0: RPM max limit inactive	0	1	1	#
		42	Power limit	1: Power limit by configuration active 0: Power limit by configuration inactive	0	1	1	#
		43 - 47	RESERVED	Set to 0.	0	1	1	#
	6	48	RESERVED	Filled with FF's. For future use.	-	-	-	-
	7	56	CAN map version	Indicates the CAN map version. For ex: 25 -> 2,5 (V2,5)	0	255	1	#
0x25	Length: 8 bytes		Configured and available AC currents					
	0 – 1	0	Max AC current	Max AC current configured with the DTI CAN tool.	-3276,8 - 3276,7	0 - 850	10	A_{pk}
	2 – 3	16	Av. Max AC current	Available max AC current. This value affected by the limitation functions (igbt temp, motortemp etc.) Defines how much current available from the configured one.	-3276,8 - 3276,7	0 - 850	10	A_{pk}
	4 – 5	32	Min AC current	Min AC current configured with the DTI CAN tool.	-3276,8 - 3276,7	-850 – 0	10	A_{pk}
	6- 7	48	Av. Min AC current	Available min AC current. This value affected by the limitation functions (igbt temp, motortemp etc.) Defines how much current available from the configured one.	-3276,8 - 3276,7	-850 - 0	10	A_{pk}

0x26	Length: 8 bytes		Configured and available DC currents					
	0 – 1	0	Max DC current	Max DC current configured with the DTI CAN tool.	-3276,8 - 3276,7	0 - 850	10	A_{dc}
	2 – 3	16	Av. Max DC current	Available max DC current. This value affected by the limitation functions (igbt temp, motortemp etc.) Defines how much current available from the configured one.	-3276,8 - 3276,7	0 - 850	10	A_{dc}
	4 – 5	32	Min DC current	Min DC current configured with the DTI CAN tool.	-3276,8 - 3276,7	-850 - 0	10	A_{dc}
	6- 7	48	Av. Min DC current	Available min DC current. This value affected by the limitation functions (igbt temp, motortemp etc.) Defines how much current available from the configured one.	-3276,8 - 3276,7	-850 - 0	10	A_{dc}

3.6 Example messages for transmitted data by inverter

Table 5: Example message: ERPM, Duty, Input Voltage (0x20)

Can message: ERPM, Duty, Input Voltage **(0x20)**

	Message ID		**Data segment**		
Message	0x 00 00 20	22	00 00 24 5E	00 71	01 86
Data	PID	Node ID	ERPM [3:0]	Duty Cycle [1:0]	Input voltage [1:0]
Length			4- byte	2- byte	2- byte
Scale			1	10	1
HEX Value			0x0000245E	0x0071	0x0186
DEC Value			9310	113	390
Real value			9310 RPM	11.3%	390 V
Raw MSG:	00 00 20 22 00 00 24 5E 00 71 01 86 (hexadecimal)				

Table 6: Example message: AC Current, DC Current, (0x21)

Can message: AC Current, DC Current **(0x21)**

	Message ID		**Data segment**	
Message	0x 00 00 21	22	00 5C	00 11
Data	PID	Node ID	AC Current [1:0]	DC Current [1:0]
Length			2- byte	2- byte
Scale			10	10
HEX Value			0x005C	0x0011
DEC Value			92	17
Real value			9.2 A_{AC}	1.7 A_{DC}
Raw MSG:	00 00 21 22 00 5C 00 11 FF FF FF FF (hexadecimal)			

Table 7: Example message: CTLR Temp, Motor Temp, Fault code (0x22)

Can message: Controller Temp, Motor Temp, Fault code **(0x22)**

	Message ID		**Data segment**		
Message	0x 00 00 22	22	01 53	01 17	00
Data	PID	Node ID	CTLR Temp [1:0]	Motor Temp [1:0]	Fault Code
Length			2- byte	2- byte	1- byte
Scale			10	10	1
HEX Value			0x0153	0x0117	0x00
DEC Value			339	279	0
Real value			33.9 °C	27.9 °C	None.
Raw MSG:	00 00 22 22 01 53 01 17 00 FF FF FF (hexadecimal)				

Table 8: Example message: Id, Iq Values (0x23)

Can message: Id, Iq Values **(0x23)**

	Message ID		**Data segment**	
Message	0x 00 00 23	22	00 00 00 64	00 00 02 92
Data	PID	Node ID	Id [3:0]	Iq [3:0]
Length			4- byte	4- byte
Scale			100	100
HEX Value			0x00000064	0x00000292
DEC Value			100	658
Real value			1	6.58
Raw MSG:	00 00 23 22 00 00 00 64 00 00 02 92 (hexadecimal)			

4. COMMANDS TO THE INVERTER

The inverter can receive commutation related and limiting commands on the CAN2. The following overview shows the possible methods for commutating via CAN and setting limits.

4.1 Command overview

The following commands can be sent to the inverter:

Table 9: Control commands

Packet ID	Command	Function
0x01	Set Current	
0x02	Set Brake current	
0x03	Set ERPM	
0x04	Set Position	
0x05	Set Relative current	
0x06	Set relative brake current	
0x07	Set digital output	Sets an output to HIGH or LOW
0x08	Set maximum AC current	
0x09	Set maximum AC brake current	
0x0A	Set maximum DC current	Limiting command
0x0B	Set maximum DC brake current	
0x0C	Drive enable	

4.2 Commands can be sent to the inverter

Table 10 Description of inverter commands

Packet ID	Byte	Bit start	Msg name	Message description	Min/max data range (post-scale)	Min/max operational range	Scale	Unit
0x01	Length: 8 bytes		Set AC current					
	0 – 1	0	AC current	This command sets the target motor AC current (peak, not RMS). When the controller receives this message, it automatically switches to current control mode. This value must not be above the limits of the inverter and must be multiplied by 10 before sending. This is a signed parameter, and the sign represents the direction of the torque which correlates with the motor AC current. (For the correlation, please refer to the motor parameters)	-3276,8 - 3276,7	-850 - 850	10	A_{pk}
	2 - 7	16	NOT USED	Not relevant to the command. Fill with FFs or use 2-byte DLC.	-	-	-	-
0x02	Length: 8 bytes		Set Brake current					
	0 - 1	0	Target brake current	Targets the brake current of the motor. It will result negative torque relatively to the forward direction of the motor. This value must be multiplied by 10 before sending, **only positive currents are accepted.**	-3276,8 - 3276,7	0 - 850	10	A_{pk}
	2 - 7	16	NOT USED	Not relevant to the command. Fill with FFs or use 2-byte DLC.	-	-	-	-

Packet ID	Byte	Bit start	Msg name	Message description	Min/max data range (post-scale)	Min/max operational range	Scale	Unit
0x03	Length: 8 bytes		Set speed (ERPM)					
	0 – 3	0	Target ERPM	This command enables the speed control of the motor with a target ERPM. This is a signed parameter, and the sign represents the direction of the spinning. For better operation you need to tune the PID of speed control. Equation: ERPM = Motor RPM * number of the motor pole pairs.	-2147483648 - 2147483647	-100 000 – 100 000	1	ERPM
	4 – 7	32	NOT USED	Not relevant to the command. Fill with FFs or use 4-byte DLC.	-	-	-	-
0x04	Length: 8 bytes		Set position					
	0 - 1	0	Target position	This value targets the desired position of the motor in degrees. This command is used to hold a position of the motor. This feature is enabled only if encoder is used as position sensor. The value has to be multiplied by 10 before sending.	-3276,8 - 3276,7	0 - 359	10	degree
	2 - 7	16	NOT USED	Not relevant to the command. Fill with FFs or use 2-byte DLC.	-	-	-	-

Packet ID	Byte	Bit start	Msg name	Message description	Min/max data range (post-scale)	Min/max operational range	Scale	Unit
0x05	Length: 8 bytes		Set relative current					
	0 – 1	0	Target relative AC current	This command sets a relative AC current to the minimum and maximum limits set by configuration. This achieves the same function as the “Set AC current” command. Gives you a freedom to send values between -100,0% and 100,0%. You do not need to know the motor limit parameters. This value **must be between -100 and 100** and must be multiplied by 10 before sending.	-3276,8 - 3276,7	-100 - 100	10	%
	2 – 7	32	NOT USED	Not relevant to the command. Fill with FFs or use 2-byte DLC.	-	-	-	-
0x06	Length: 8 bytes		Set relative brake current					
	0 - 1	0	Target relative brake AC current	Targets the relative brake current of the motor. It will result negative torque relatively to the forward direction of the motor. This value must be between 0 and 100 and must be multiplied by 10 before sending Gives you a freedom to send values between 0% and 100,0%. You do not need to know the motor limit parameters. This value must be between 0 and 100 and has to be multiplied by 10 before sending	-3276,8 - 3276,7	0 - 100	10	%
	2 - 7	16	NOT USED	Not relevant to the command. Fill with FFs or use 2-byte DLC.	-	-	-	-

Packet ID	Byte	Bit start	Msg name	Message description	Min/max data range (post-scale)	Min/max operational range	Scale	Unit
0x07	Length: 8 bytes		Set digital output	Sets a digital output to a desired state				
	0	0	Digital output 1	Sets the digital output 1 to HIGH (1) or LOW (0) state	0	1	1	#
	0	1	Digital output 2	Sets the digital output 2 to HIGH (1) or LOW (0) state	0	1	1	#
	0	2	Digital output 3	Sets the digital output 3 to HIGH (1) or LOW (0) state	0	1	1	#
	0	3	Digital output 4	Sets the digital output 4 to HIGH (1) or LOW (0) state	0	1	1	#
0x08	Length: 8 bytes		Set max. AC current					
	0 – 1	0	Maximum AC current	This value determines the maximum allowable drive current on the AC side. With this function you are able maximize the maximum torque on the motor. The value must be multiplied by 10 before sending.	-3276,8 - 3276,7	0 - 850	10	A_{pk}
	2 – 7	32	NOT USED	Not relevant to the command. Fill with FFs or use 2-byte DLC.	-	-	-	-

0x09	Length: 8 bytes		Set max brake current					
	0 - 1	0	Maximum brake AC current	This value sets the maximum allowable brake current on the AC side. This value must be multiplied by 10 before sending, **only negative currents are accepted.**	-3276,8 - 3276,7	-850 - 0	10	A_{pk}
	2 - 7	16	NOT USED	Not relevant to the command. Fill with FFs or use 2-byte DLC.	-	-	-	-

Packet ID	Byte	Bit start	Msg name	Message description	Min/max data range (post-scale)	Min/max operational range	Scale	Unit
0x0A	Length: 8 bytes		Set max. DC current					
	0 – 1	0	Maximum DC current limit	This value determines the maximum allowable drive current on the DC side. With this command the BMS can limit the maximum allowable battery discharge current. The value has to be multiplied by 10 before sending.	-3276,8 - 3276,7	0 - 850	10	A
	2 – 7	32	NOT USED	Not relevant to the command. Fill with FFs or use 2-byte DLC.	-	-	-	-
0x0B	Length: 8 bytes		Set max. DC brake current					
	0 - 1	0	Maximum brake DC current	This value determines the maximum allowable brake current on the DC side. With this command the BMS can limit the maximum allowable battery charge current. The value has to be multiplied by 10 before sending. **Only negative currents are accepted.**	-3276,8 - 3276,7	-850 - 0	10	%
	2 - 7	16	NOT USED	Not relevant to the command. Fill with FFs or use 2-byte DLC.	-	-	-	-

0x0C	Length: 8 bytes		Drive enable					
	0	0	Drive enable	0: Drive not allowed 1: Drive allowed Only 0 and 1 values are accepted. Must be sent periodically to be enabled. **Refer to chapter 4.3**	0	255	1	#
	1 - 7	8	NOT USED	Not relevant to the command. Fill with FFs or use 1-byte DLC.	-	-	-	-

4.3 Drive enable command

The drive enable command let you allow the drive of the inverter, even if analogue inputs are used for control.

To activate this function, you should check / APP settings / CAN / “Drive enable via CAN2” button. If the function is not activated, then commands via CAN2 interface will be not accepted.

4.3.1 Operation when analogue inputs are used for control

The drive enable signal will be “FALSE” by default, thus not allowing drive until the command message (0x24) not received periodically. If you use analogue control, you will not be able to drive the motor without sending the drive enable command periodically.

The sending period must be at least half of the value set in the configuration / App settings / General / Timeout.

For example:

> If the timeout is 1000 ms, you should send at least 500 ms or quicker (250 ms recommended) to avoid unexpected timeouts.

4.3.2 Operation when CAN2 interface used for control

The drive enable signal will be “FALSE” by default, thus not allowing drive until the command message (0x24) not received periodically. When you are using CAN2 interface for control the inverter, the drive enable message can be sent periodically, but not mandatory. It is enough to send a drive enable message at first and keep sending a control command (like AC current, speed control, brake etc.) which will reset timeout. That means that when a control message not received periodically, a timeout will happen, which will disable the drive enable state. After that event, the drive enable message should be sent again, to allow the drive.

4.4 Broadcast message

Broadcast messages can be sent to all the inverters on the same bus in order to set a common limit or commutation request.

- With Standard CAN message, the **node ID** should be replaced with **0x1F**
- With Extended CAN message, the **node ID** should be **0xFF**.

4.5 Example messages for commands

Table 11: Example message: Set AC Current (0x01)

Can message: Set AC Current **(0x01)**

	Message ID		**Data segment**
Message	0x 00 00 01	22	00 64
Data	PID	Node ID	Set AC Current [1:0]
Length			2- byte
Scale			10
Real (Target) value			10A
Scaled value			100
Hex value			0x0064
Raw MSG:	00 00 01 22 00 64 00 00 00 00 00 00 (hexadecimal)		

Table 12: Example message: Set Brake Current (0x02)

Can message: Set Brake Current **(0x02)**

	Message ID		**Data segment**
Message	0x 00 00 02	22	00 64
Data	PID	Node ID	Set Brake AC Current [1:0]
Length			2- byte
Scale			10
Real (Target) value			10A
Scaled value			100
Hex value			0x0064
Raw MSG:	00 00 02 22 00 64 00 00 00 00 00 00 (hexadecimal)		

Table 13: Example message: Set Brake Current (0x03)

Can message: Set ERPM **(0x03)**

	Message ID		**Data segment**
Message	0x 00 00 03	22	00 00 01 F4
Data	PID	Node ID	Set ERPM [3:0]
Length			4- byte
Scale			1
Real (Target) value			500 ERPM
Scaled value			500
Hex value			0x000001F4
Raw MSG:	00 00 03 22 00 00 01 F4 00 00 00 00 (hexadecimal)		

Table 14: Example message: Set position (0x04)

Can message: Set Position **(0x04)**

	Message ID		**Data segment**
Message	0x 00 00 04	22	03 E8
Data	PID	Node ID	Set position [1:0]
Length			2- byte
Scale			10
Real (Target) value			100°
Scaled value			1000
Hex value			0x03E8
Raw MSG:	00 00 04 22 03 E8 00 00 00 00 00 00 (hexadecimal)		

Table 15: Example message: Set Relative current (0x05)

Can message: Set Relative Current (**0x05)**

	Message ID		**Data segment**
Message	0x 00 00 05	22	00 64
Data	PID	Node ID	Set relative AC Current [1:0]
Length			2- byte
Scale			10
Real (Target) value			10%
Scaled value			100
Hex value			0x0064
Raw MSG:	00 00 05 22 00 64 00 00 00 00 00 00 (hexadecimal)		

Table 16: Example message: Set relative brake current (0x06)

Can message: Set Relative brake current **(0x06)**

	Message ID		**Data segment**
Message	0x 00 00 06	22	00 64
Data	PID	Node ID	Set relative brake Current [1:0]
Length			2- byte
Scale			10
Real (Target) value			10%
Scaled value			100
Hex value			0x0064
Raw MSG:	00 00 06 22 00 64 00 00 00 00 00 00 (hexadecimal)		

Table 17: Example message: Set maximum AC current (0x08)

Can message: Set maximum AC current (**0x08)**

	Message ID		**Data segment**
Message	0x 00 00 08	22	03 E8
Data	PID	Node ID	Set maximum AC Current [1:0]
Length			2- byte
Scale			10
Real (Target) value			100 A_{AC}
Scaled value			1000
Hex value			0x03E8
Raw MSG:	00 00 08 22 03 E8 00 00 00 00 00 00 (hexadecimal)		

Table 18: Example message: Set maximum AC brake current (0x09)

Can message: Set maximum AC Brake current **(0x09)**

	Message ID		**Data segment**
Message	0x 00 00 09	22	FC 18
Data	PID	Node ID	Set maximum AC Brake Current [1:0]
Length			2- byte
Scale			10
Real (Target) value			-100A_{AC}
Scaled value			-1000
Hex value			0xFC18
Raw MSG:	00 00 09 22 FC 18 00 00 00 00 00 00 (hexadecimal)		

Table 19: Example message: Set maximum DC current (0x0A)

Can message: Set maximum DC current **(0x0A)**

	Message ID		**Data segment**
Message	0x 00 00 0A	22	00 C8
Data	PID	Node ID	Set maximum AC Current [1:0]
Length			2- byte
Scale			10
Real (Target) value			20A_{DC}
Scaled value			200
Hex value			0x00C8
Raw MSG:	00 00 0A 22 00 C8 00 00 00 00 00 00 (hexadecimal)		

Table 20: Example message: Set maximum DC brake current (0x0B)

Can message: Set maximum DC brake current **(0x0B)**

	Message ID		**Data segment**
Message	0x 00 00 0B	22	FF 38
Data	PID	Node ID	Set maximum AC Current [1:0]
Length			2- byte
Scale			10
Real (Target) value			-20 A_{DC}
Scaled value			-200
Hex value			0xFF38
Raw MSG:	00 00 0B 22 FF 38 00 00 00 00 00 00 (hexadecimal)		

Table 21 Example message: Drive enable command (0x0C)

Can message: Drive enable **(0x0C)**

	Message ID		**Data segment**
Message	0x 00 00 0C	22	01
Data	PID	Node ID	Drive enable
Length			1- byte
Scale			1
Real (Target) value			1: TRUE enables drive 0: FALSE disables drive
Scaled value			1
Hex value			0xFF38
Raw MSG:	00 00 0C 22 01 00 00 00 00 00 00 00 (hexadecimal)		

5. LIST OF TABLES