

	signal, #byte, range [0...7]	signal, #bit, range [0...7]	signal length[bit]	signal name	signal function	value table	VCU	MCU	BMS	Charger	physical range	binary range	scaling / resolution	offset	unit	fault/initial value	Data type	comment
CAN_version_0.1																		
VCU_transmit																		
VCU to MCU_1 ID = 0x0800A7A6 cycle time=10ms DLC=8	0	0	2	S_motor_running_mode	Motor state operating mode given	0h-reserve 1h-traction 2h-brake 3h-reserve	T	R			0...3	0...3	1	0		0	unsigned	Do not use
	0	2	2	S_motor_control_mode	Motor control mode	0-reserve 1-torque mode 2-speed mode 3-reserve	T	R			0...3	0...3	1	0		0	unsigned	Generally, torque control mode is used unless otherwise specified
	0	4	2	S_motor_run_stop	Motor control instructions	0-reserve 1-run 2-stop 3-reserve	T	R			0...3	0...3	1	0		0	unsigned	The motor controller can drive the motor only after receiving the run command
	0	6	2	S_motor_direction	Motor direction control	0-N or P shift 1-CCW 2-CW 3-reserve	T	R			0...3	0...3	1	0		0	unsigned	CCW counterclockwise direction, forward command. CW clockwise direction, reverse command. Do not use.
	2	16	16	S_motor_torque	Motor torque control command	TorqueObj	T	R			-15000~15000	0...65535	1	-15000	Nm	0	signed	Only in the torque control mode, the torque control command is sent. In speed control mode, this command sends 0
	4	32	16	S_motor_speed	Motor speed control command	SpeedObj	R				-15000~15000	0...65535	1	-15000	rpm	0	signed	Only in the speed control mode, the speed control command is sent. In speed control mode, this command sends 0
MCU_transmit																		
MCU_State_1 电机状态1 ID = 0x0C08A6A7 cycle time=10ms DLC=8	0	0	16	N_motorTorqueLim	Motor torque limit value	MotorMaxTor	R	T			-15000~15000	0...65535	1	-15000	Nm	0	unsigned	
	2	16	16	N_motorTorque	Motor torque	MotorTor	R	T			-15000~15000	0...65535	1	-15000	Nm	0	unsigned	
	4	32	16	N_motorSpeed	Motor speed	MotorSpd	R	T			-15000~15000	0...65535	1	-15000	rpm	0	unsigned	
	6	48	2	St_motorDirection	Motor rotation direction	0h=stop 1h=ccw 2h=cw 3h=reserve	R	T			0...3	0...3	1	0		0	unsigned	
	6	50	2	St_motorMode	Motor operation mode	0h=stop 1h=torque mode 2h=speed mode 3h=slope slip	R	T			0...3	0...15	1	0		0	unsigned	
	6	52	2	St_motor	Total motor fault status	0h= reserve 1h= Warning 2h= Limit Power 3h= Fault	R	T			0...3	0...15	1	0		0	unsigned	

[illegible]

6	48	4	Motor Quantity	Number of motors		R	T			0...15	0...15	1	0		0	unsigned	
6	52	4	Motor Num	Motor number		R	T			0...15	0...15	1	0		0	unsigned	
7	56	8	MCU Number	MCU manufacturer number		R	T			0...255	0...255	1	0		0	unsigned	

Note: The protocol meets the CAN 2.0B standard and uses extended frames, the communication baud rate is 500Kbps, and the CAN message uses intel format.