SIKO Encoder CAN BUS Commands

Open Terminal

First Terminal (Compulsory) Initialisation of can0

sudo ip link set can0 type can bitrate 500000

sudo ip link set can0 up

2nd Terminal

candump can0

3rd Terminal (Compulsory to run for all address) This is to make the encoder publish data

cansend can0 601#2300180510000 %601 = 600 + Node ID

cansend can0 000#01 %Operation Mode

If there are no values in Candump can0, check kernel version.

https://ubuntuhandbook.org/index.php/2020/12/install-linux-kernel-5-10-ubuntu-linux-mint/ %Verified to work

4th Terminal

python can\_reader.py

Set Address Commands (In this example ID = 4) (Connect only 1 encoder at a time)

cansend can0 7E5#0401 %Set to LSS Configuration Mode

cansend can0 7E5#11NID %NID is Node-ID

cansend can0 7E5#1104 %NID is Node-ID = 4

cansend can0 7E5#17 %Save Configuration cansend can0 7E5#0400 %Set to LSS Waiting Mode

cansend can0 000#82 % Reset Communication

Extra Commands

cansend can0 601#40046000 %Read Position for address 1

Run Ros Package

rosrun can\_encoder\_pub can\_encoder\_ros\_pub.py