<<NegativeValues>>

+NegativeValuesTwoBytes(int Value):int

<<AngleVelocity>>

+ProcessAngleVelocity(unsigned char*, int MSByte, int LSByte):int

<<Torque>>

+ProcessTorque(unsigned char* CAN_DATA, int MSByte, int LSByte):int

<<Angle>>

+ProcessAngle(unsigned char* CAN_DATA, int MSByte, int LSByte):int

MotorPosInfo

-MotorAngle:int
-MotorSpeed:int
-ElectricalOutFreq:int
-DeltaResolverFiltered:int

+MotorPosInfo(unsigned char*);
+MotorPosInfo();
+GetMotorAngle():int
+GetMotorSpeed():int
+GetElectricalOutFreq():int
+GetDeltaResolverFiltered():int

TorqueTimerInfo

-CommandedTorque:int
-TorqueFeedback:int
-PowerOnTime:int

+TorqueTimerInfo(unsigned char*);
+TorqueTimerInfo();
+GetCommandedTorque():int
+GetTorqueFeedback():int
+GetPowerOnTime():int

CommandMessage

-TorqueCommand:int
-SpeedCommand:int
-DirectionCommand:bool
-InverterEnable:bool
-InverterDischarge:bool
-SpeedMode:bool
-CommandedTorqueLimit:int
-struct can_frame frame;

+CommandMessage(int TorqueCommand, int SpeedCommand, bool Direction, bool InverterEnable, bool InverterDischarge, bool SpeedMode, int CommandedTorqueLimit);
+SetParameter(int, signed short int):void