

CAN Protocol (Lifting Platform)

Enable command				
Sender	Receiver	CAN ID	DLC	Period[ms]
Controller	Lifting Platform	0x03020103	4	/
data	function	data type	description	
byte[0]	/	uint8	Fixed value 0x03	
byte[1]	/	uint8	Fixed value 0x02	
byte[2]	/	uint8	Fixed value 0x01	
byte[3]	enable	uint8	0-disable 1-enable	

Heartbeat feedback				
Sender	Receiver	CAN ID	DLC	Period[ms]
Lifting Platform	Controller	0x030201B0	1	500ms
data	function	data type	description	
byte[0]	enable	uint8	0-disable 1-enable	

Status command				
Sender	Receiver	CAN ID	DLC	Period[ms]
Controller	Lifting Platform	0x03020111	3	/
data	function	data type	description	

byte[0]	return to zero point	uint8	1-start
byte[1]	max move velocity[0:7]	uint16	unit: mm/s
byte[2]	max move velocity[8:15]		

Status feedback				
Sender	Receiver	CAN ID	DLC	Period[ms]
Lifting Platform	Controller	0x030201B1	6	100ms
data	function	data type	description	
byte[0]	status	uint8	0:normal 1:abnormal	
byte[1]	return to zero point status	uint8	0-finished 1-calibrating	
byte[2]	errorcode [0:7]	uint16		
byte[3]	errorcode[8:15]			
byte[4]	max move velocity [0:7]	uint16		
byte[5]	max move velocity[8:15]			

Request move range command				
Sender	Receiver	CAN ID	DLC	Period[ms]
Controller	Lifting Platform	0x03020112	0	/
data	function	data type	description	
/	/	/	/	

Request move range feedback				
Sender	Receiver	CAN ID	DLC	Period[ms]

Lifting Platform	Controller	0x030201B2	6	/
data	function	data type	description	
byte[0]	move range[0:7]	uint16	unit: mm	
byte[1]	move range[8:15]			
byte[2]-byte[5]	reverse	uint8	0	

Move velocity feedback				
Sender	Receiver	CAN ID	DLC	Period[ms]
Lifting Platform	Controller	0x030201B3	6	50ms
data	function	data type	description	
byte[0]	velocity[0:7]	uint16	unit: mm/s	
byte[1]	velocity[8:15]			
byte[2]-byte[5]	reverse	uint8	0	

Position setting command				
Sender	Receiver	CAN ID	DLC	Period[ms]
Controller	Lifting Platform	0x03020114	6	/
data	function	data type	description	
byte[0]	position[0:7]	uint16	unit: mm	
byte[1]	position[8:15]			
byte[2]-byte[5]	reverse	uint8	0	

Move position feedback				
Sender	Receiver	CAN ID	DLC	Period[ms]
Lifting Platform	Controller	0x030201B4	6	50ms
data	function	data type	description	

byte[0]	real position[0:7]	uint16	unit: mm
byte[1]	real position[8:15]		
byte[2]-byte[5]	reverse	uint8	0

Example

1. Enable device

CAN ID: 0x03020103, Data: 03 02 01 01

2. Set position 100mm

CAN ID: 0x03020114, Data: 64 00 00 00 00 00