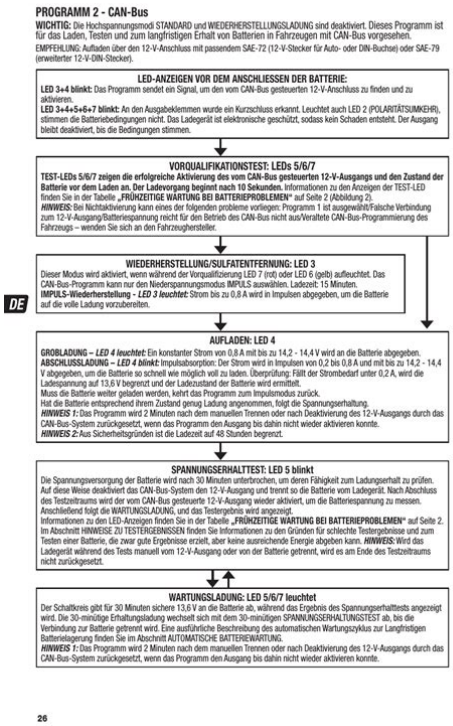
can bus manual


PROGRAMM 2 - CAN-Bus

WICHTIG: Die Hochspannungsmodi STANDARD und WIEDERHERSTELLUNGSLADUNG sind deaktiviert. Dieses Programm ist für das Laden, Testen und zum langfristigen Erhalt von Batterien in Fahrzeugen mit CAN-Bus vorgesehen.
EMPFEHLUNG: Aufladen über den 12-V-Anschluss mit passendem SAE-72 (12-V-Stecker für Auto- oder DIN-Buchse) oder SAE-79 (erweiterter 12-V-DIN-Stecker).

LED-ANZEIGEN VOR DEM ANSCHLIESSEN DER BATTERIE:
LED 3+4 blinkt: Das Programm sendet ein Signal, um den vom CAN-Bus gesteuerten 12-V-Anschluss zu finden und zu aktivieren.
LED 3+4+5+6+7 blinkt: An den Ausgabeklemmen wurde ein Kurzschluss erkannt. Leuchtet auch LED 2 (POLARITÄTSUMKEHR), stimmen die Batteriebedingungen nicht. Das Ladegerät ist elektronische geschützt, sodass kein Schaden entsteht. Der Ausgang bleibt deaktiviert, bis die Bedingungen stimmen.

VORQUALIFIKATIONSTEST: LEDs 5/6/7
TEST-LEDs 5/6/7 zeigen die erfolgreiche Aktivierung des vom CAN-Bus gesteuerten 12-V-Ausgangs und den Zustand der Batterie vor dem Laden an. Der Ladevorgang beginnt nach 10 Sekunden. Informationen zu den Anzeigen der TEST-LED finden Sie in der Tabelle **„FRÜHZEITIGE WARTUNG BEI BATTERIEPROBLEMEN"** auf Seite 2 (Abbildung 2).
HINWEIS: Bei Nichtaktivierung kann eines der folgenden probleme vorliegen: Programm 1 ist ausgewählt/Falsche Verbindung zum 12-V-Ausgang/Batteriespannung reicht für den Betrieb des CAN-Bus nicht aus/Veraltete CAN-Bus-Programmierung des Fahrzeugs – wenden Sie sich an den Fahrzeughersteller.

WIEDERHERSTELLUNG/SULFATENTFERNUNG: LED 3
Dieser Modus wird aktiviert, wenn während der Vorqualifizierung LED 7 (rot) oder LED 6 (gelb) aufleuchtet. Das CAN-Bus-Programm kann nur den Niederspannungsmodus IMPULS auswählen. Ladezeit: 15 Minuten.
IMPULS-Wiederherstellung - ***LED 3 leuchtet:*** Strom bis zu 0,8 A wird in Impulsen abgegeben, um die Batterie auf die volle Ladung vorzubereiten.

DE

AUFLADEN: LED 4
GROBLADUNG – ***LED 4 leuchtet:*** Ein konstanter Strom von 0,8 A mit bis zu 14,2 - 14,4 V wird an die Batterie abgegeben.
ABSCHLUSSLADUNG – ***LED 4 blinkt:*** Impulsabsorption: Der Strom wird in Impulsen von 0,2 bis 0,8 A und mit bis zu 14,2 - 14,4 V abgegeben, um die Batterie so schnell wie möglich voll zu laden. Überprüfung: Fällt der Strombedarf unter 0,2 A, wird die Ladespannung auf 13,6 V begrenzt und der Ladezustand der Batterie wird ermittelt.
Muss die Batterie weiter geladen werden, kehrt das Programm zum Impulsmodus zurück.
Hat die Batterie entsprechend ihrem Zustand genug Ladung angenommen, folgt die Spannungserhaltung.
HINWEIS 1: Das Programm wird 2 Minuten nach dem manuellen Trennen oder nach Deaktivierung des 12-V-Ausgangs durch das CAN-Bus-System zurückgesetzt, wenn das Programm den Ausgang bis dahin nicht wieder aktivieren konnte.
HINWEIS 2: Aus Sicherheitsgründen ist die Ladezeit auf 48 Stunden begrenzt.

SPANNUNGSERHALTTEST: LED 5 blinkt
Die Spannungsversorgung der Batterie wird nach 30 Minuten unterbrochen, um deren Fähigkeit zum Ladungserhalt zu prüfen. Auf diese Weise deaktiviert das CAN-Bus-System den 12-V-Ausgang und trennt so die Batterie vom Ladegerät. Nach Abschluss des Testzeitraums wird der vom CAN-Bus gesteuerte 12-V-Ausgang wieder aktiviert, um die Batteriespannung zu messen. Anschließend folgt die WARTUNGSLADUNG, und das Testergebnis wird angezeigt.
Informationen zu den LED-Anzeigen finden Sie in der Tabelle **„FRÜHZEITIGE WARTUNG BEI BATTERIEPROBLEMEN"** auf Seite 2.
Im Abschnitt HINWEISE ZU TESTERGEBNISSEN finden Sie Informationen zu den Gründen für schlechte Testergebnisse und zum Testen einer Batterie, die zwar gute Ergebnisse erzielt, aber keine ausreichende Energie abgeben kann. ***HINWEIS:*** Wird das Ladegerät während des Tests manuell vom 12-V-Ausgang oder von der Batterie getrennt, wird es am Ende des Testzeitraums nicht zurückgesetzt.

WARTUNGSLADUNG: LED 5/6/7 leuchtet
Der Schaltkreis gibt für 30 Minuten sichere 13,6 V an die Batterie ab, während das Ergebnis des Spannungserhalttests angezeigt wird. Die 30-minütige Erhaltungsladung wechselt sich mit dem 30-minütigen SPANNUNGSERHALTUNGSTEST ab, bis die Verbindung zur Batterie getrennt wird. Eine ausführliche Beschreibung des automatischen Wartungszyklus zur Langfristigen Batterielagerung finden Sie im Abschnitt AUTOMATISCHE BATTERIEWARTUNG.
HINWEIS 7: Das Programm wird 2 Minuten nach dem manuellen Trennen oder nach Deaktivierung des 12-V-Ausgangs durch das CAN-Bus-System zurückgesetzt, wenn das Programm den Ausgang bis dahin nicht wieder aktivieren konnte.

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Book Descriptions:

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Information sensed by one part can be shared withA modern car may have up to 70 ECUs and each ofThe broadcasted data isTo support this, CAN FD Flexible Data Rate has been designed as the next generation CAN bus.This will also drive an increasing need for IoT CAN FD data loggers. The extended 29bit identifier frame CAN 2.0B is identical except theIt also contains the 4 bit Data Length Code DLCReach out for free sparring! This lets you log timestamped CAN data to an SD card. In someNotice that the CAN IDs and data bytes are in hexadecimal format Simply connect it to e.g. a car or truck toFor example, a CAN frame with a specific CAN ID may carrySo, if you e.g. want to convert raw CAN protocol data from your car, you need to reverse engineer the CAN bus data. However, in some casesTo make this practical,Here, the CAN database DBC With this, you can get quickly from raw J1939 data to humanreadable form. Therefore a set of standardizedFurther, these higherlayer protocols will increasingly be based on the next generation of CAN, CAN FDOBD2 specifies diagnostic troubleIt is based on CAN, meaning that a CAN bus data logger is also able to log CANopen data. This is key in e.g. machine diagnostics or optimizingIt increases the payload from 8 to 64 bytes and allows for a higher dataThis enables increasingly dataintensive use cases like EVs. Administration Guide Omnicomm Online. Release notes Omnicomm LLS 20230 Fuel Tankers Installation. Installation, Launch, Setup and Control Guide Remote Configuration Server. User Manual Omnicomm Online. Integration Manual Conversion Server. User Manual Omnicomm 3.0 Terminals. User Manual. Omnicomm Configurator 6 Omnicomm OKO 3.0 Video Terminal. User Manual Omnicomm OKO Video Terminal. User Manual Omnicomm 3.1 Terminals. User Manual Omnicomm LLS Fuel Level Sensor. Integration manual Omnicomm OBDII Terminal. User Manual Omnicomm LLSAF 4 Fuel Level Sensor. User Manual. Omnicomm Configurator 6 Omnicomm LLS 30160, LLSAF 4 Fuel Level Sensors.https://ecatts.com/userfiles/case-1290-service-manual.xml

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User Manual. Omnicomm Configurator 6 Omnicomm LLS 4 Fuel Level Sensors. User Manual Omnicomm LLS 5 Fuel Level Sensor. User Manual Omnicomm LLSEx 5 Fuel Level Sensor and BISMX Intrinsic Safety Unit. User Manual Fuel Volume Indicator Omnicomm LLDHD. User manual Omnicomm ICON Display. User Manual Fuel Level Sensor Omnicomm LLSHD User manual Third party terminals connection Galvanic Isolation Unit BR15. Datasheet Omnicomm LLD fuel volume indicator.If you need to add parameter readings from the CAN bus that are missing from this list, go to Omnicomm Configurator and click on Add. You will be taken to the following screenHere are the available options 1, 2, 3, or 4 bits; 1, 2, or 4 bytes.You can choose a number from 1 to 262,143.You can choose values from 0 to 63.You can choose between values from 0 to 4,294,967,295. It was designed specifically for automotive applications but is now also used in other areas. Based on the same architecture FMS protocol dedicated to telematics systems is available. It has certain standardized parameters available, such as fuel consumption, engine workhours, etc. Please visit for more information and message structure.Supported information is dependent upon vehicle equipment. For the full information set, additional Electronic Control Units ECU may be required. Please contact the manufacturer or your dealer for more details.If your vehicle supports J1939 and

J1708 both protocols then you must disable J1708 in configuration to receive fuel data. This parameter is used to configure hardware message filter.They consist of 4 identifier bytes and 8 data bytes. Below you will find a sample configuration for fuel consumption parameter. Messages use 4 bytes, but the first and last bytes may differ in different vehicle models while the middle four bytes are the same for all vehicles. The first and last bytes may have any value. Because of this reason it is recommended to write FF in the first byte and the same in the last byte.http://completeframers.com/uploadimage/case-1150b-dozer-manual.xml

All Mercedes Benz Actros 2 models with Vehicle Identification Number VIN starting with WDB93 have a possibility to connect FM6300 module to CAN bus. This can be done by connecting to special PSM module which may or may not be included in the truck or ground module of the vehicle. For CAN signal to be available, parameter 520 must be enabled in “kommunikationsschnittstelle” in the vehicle with Mercedes Stardiagnose. CAN wires can be found on X5 connector located in the fuse box. Pin 5 CAN Low signal yellow wire. Pin 2 CAN High signal blue wireSo in order to prevent data loss, set Averaging constant parameter to 1.Data parsing is preceded by selecting correct message from all available on CAN bus. FMS standard interface description indicates that fuel consumption is parameter with ID FEE9Document indicates that 58 bytes are used in FMS standard.Note, that configurator has them listed starting with MSB. After message is filtered it is attached to the data packet and sent to the server.If you continue to use this site we will assume that you are happy with it. Ok Read more. Depending on the used CAN system, different car data is available like temperature, revolution, acceleration, and many more. There are three ways to create them To select the port simply click on appropriate CAN port tab. In fact, some vehicle operation can be interrupted if we connect to the bus with the wrong baud rate set. Available are all common values from 5 to 1000 kBaud. Under the baud rate edit box we have also a notification of how many messages came through the bus and how many of them were corrupted red. This information shows if the baud rate is correct and also if the bus has any problems due to a bad connection or bus overload. You can import messages and channels from DBC and ARXML files or from XML files in Dewesoft specific format. ARXML version 3 and 4 are supported. You can either choose to just add the signals to the existing ones or to merge them by name or bit positions.

Export to ARXML is not supported. So now we can see message IDs, the speed of messages and raw binary values coming from the bus. We choose the Setup button and the empty message setup screen Can channel setup window will appear see below. If you want to select all channels from all messages, it is easiest to use channel view and then Select all. All messages will be enabled as soon as there is a channel within that message set to Used. Arb ID is always extended in this case. This is most widely used on trucks. Please make sure that the bus type is really J1939 before enabling this option. It also serves as a Gateway from any connected QuantumX module to Ethernet, but also from any QuantumX module to CAN bus or CAN2CAN. For this all signals can be acquired as raw signal stream and decoded in PC or recorder software. All the acquired signals can also be decoded in realtime and transferred to analog voltage output MX878B or for instance to an Ethernet based fieldbus CX27C for bench integration. The module’s powerful CAN gateway mode allows you up to transmit up to 200 analog inputs signals to your automation system and thus an easy way integrating new equipment in your existing bench test or in any mobile recorder or test equipment. For this all signals can be encoded in realtime which allows lowest latencies MX471C also operates as Ethernet gateway. So any signal from directly connected MX modules can be transferred to Ethernet and to a PC or recorder. Additionally, messages can be split up, as required, and reassembled, for instance, to setting up a CAN2CAN gateway is possible. QuantumX BrochureHBM Common API User ManualTECH NOTE IEEE15882008 Precision Time Protocol in Data Acquisition and Testing. EnglishEnglishQuantumX CX22BWQuantumX Universal and distributable DAQHBM are suppliers of this system. Simply connect the sensors of your choice to each of the connections, and off you go. QuantumX AccessoriesCables, connectors, software, and more from one supplier.

With branches in 30 countries, customers worldwide receive results they can trust. High resistance to disturbance, highspeed data transfer, ease of use and deterministic realtime behavior are among the reasons for this success. As a fieldbus, CAN bus reaches its limits when dealing with larger and more complex machines. For these applications, however, POWERLINK is the ideal expansion into the higher performance range. By continuing to browse the site you are agreeing to our use of cookies. Please find more information about cookies in our Privacy Policy. Features of device, settings, installation Control relay Setting Galileosky Base Block WiFi Tracking Devices with Retranslator Function Data transmission settings for Galileosky 7.0 and Base Block tracking devices Connection and setting Connection and setting Connection and setting Connection and setting Connection and setup Connection and setting Connection and Setup Connection and Setting. Discover what CAN bus actuators can do for your industrial machinery. Using Modbus makes it easy to integrate and maintain many devices on the same network. Actuators with Modbus can be used for industrial automation, solar tracking etc. If you need more detailed information about electric actuators and BUS communication, please do not hesitate to contact your local LINAK office. Built to last, built for hard work and built for work in harsh environments.Learn how in this guide.The will to listen and engage with customers, each other, and people in general, runs deep with us. So come meet us on social media too. We use cookies to let us know when you visit our websites, how you interact with us, to enrich your user experience, and to customize your relationship with our website. Click on the different category headings to find out more. You can also change some of your preferences. Note that blocking some types of cookies may impact your experience on our websites and the services we are able to offer.

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If you at a later stage connect more gensets, the controller automatically identifies and connects them via CAN bus, and application configuration is possible via the display. Only buttons relevant for a function are visible to the user. Get easy access to the most common functions with configurable shortcuts. Configure parameters for each level and have only relevant parameters displayed. The controller is made of robust materials and is built to last. It has undergone several tests showing that it stands wear and tear in all types of harsh environments. Also, the controller is suitable for PVDiesel hybrid solutions and also meets Tier 4 Final requirements In total, DEIF’s power management system can handle eight bus tie breakers. It stands out for its reliability and operatorfriendliness. It is optimized for sending small amounts of data between multiple nodes. CAN

is not a fast bus by todays standards, with a maximum data rate of only 1 Megabit per second. However, operating at low data rates makes CAN quite robust to noise and allows buses to span long distances. The most common CAN physical layer standard is ISO 118981, but others are also used. Instead, each CAN node may operate as a transmitter or receiver at any time. A messages identifier also represents the priority and allows for automatic arbitration when multiple nodes try to transmit at the same time. If one node sends a dominant bit and another sends a recessive bit, the result will be dominant as shown in Table 1 . Automatic arbitration is built in to the CAN protocol as all nodes must monitor the bus state during transmission and cease transmission if a dominant bit is seen when sending a recessive bit. For more information about the Komodo interfaces compatibilities, please refer to Section 2. Applications other than this, such as reading from a large memory device, would not use CAN. The plug includes screw terminals so it can be used easily with wires. Please see Section 2.

3 for descriptions of the CAN signals. Please see the API section of this document for more information on how to configure and use these pins. Table 2 shows the pinout for the DIN9 connector on the Komodo interface along with corresponding color and label on the cable. This port connects to the analysis computer that runs the software or a custom application.Whenever the state of an enabled digital input changes, an event will be sent to the analysis PC. These pins can be set to activate on various conditions that are described more thoroughly in Section 5. A common use for this feature is to trigger an oscilloscope or logic analyzer to capture data. Input pins can be configured to have a pullup, pulldown, or no resistor enabled. The internal pullup resistors have a nominal value of 1.5 k. Additional GPIO pin specifications are listed in Table 3. For connector pinout information, please see Section 2.1.1. Two pins on the DB9 are connected to ground to provide a solid ground path, though it is only necessary to connect to one of these. When configured as an input, Voltage may range from 12 V to 12 V. See Section 2.5.1 for more details. If enabled, the Komodo CAN Interfaces will provide approximately 4.8 V out on this pin and can source up to 73mA per CAN channel. The Komodo will illuminate the CAN power LED if power is detected on this pin. Internally, these pins are floating. See Section 2.7 for more details. It illuminates when the Komodo interface is correctly connected to an analysis computer and is receiving power over USB. The power LEDs will be off if power is neither observed nor sourced. If no data is being sent on an active CAN channel, the activity LED will simply remain on without blinking. Drawing more than this may damage the hardware. Not all bitrates are supported. When an attempt is made to set the bitrate, the Komodo interface will be set to the closest supported value less than or equal to the requested value.

The Komodo interface should be plugged directly into the host PCs USB host port or a selfpowered hub. The Komodo interface should not be connected to a buspowered hub because these are only specified to supply 100 mA per port. The specific compatibility for each operating system is discussed below. Be sure the device driver has been installed before plugging in the Komodo interface. When using the 32bit library on a 64bit distribution, the appropriate 32bit system libraries are also required. The driver installer can be found either on the CDROM use the HTML based guide that is opened when the CD is first loaded to locate the Windows installer, or in the Downloads section of the Komodo interface product page on the Total Phase website. The following steps describe the feedback the user should receive from Windows after a Komodo interface is plugged into a system for the first time Instructions for using this utility can be found below. Alternatively, the Uninstall option found in the driver installer can also be used to remove the driver from the system. It is critical that all Total Phase devices have been disconnected from your system before removing the USB drivers. This differs from previous versions that required the user to ensure independently that the libusb library was installed on the system. See the README.txt in the API package for more details. This is the preferred way to support access to the Komodo interface such that the device is accessible by all of the users on the system upon device plugin. This file is

99totalphase.rules. Please follow the following steps to enable the appropriate permissions for the Komodo interface. These files are komodo and komodo.usermap. Please follow the following steps to enable hotplugging. The following procedure is not necessary if you were able to exercise the steps in the previous subsections. The following steps can help setup the correct permissions.

Please note that these steps will make the entire USB filesystem world writable. Both Mac OS X 10.5 Leopard and 10.6 Snow Leopard are supported. It is typically necessary to ensure that the user running the software is currently logged into the desktop. No further user configuration should be necessary. The Komodo CAN Solo Interface consists of one CAN channel and presents one port to the computer when connected. For example, one connected Komodo CAN Duo Interface would be assigned ports 0 and 1, and a second Komodo CAN Solo Interface would be assigned port 2. With n Komodo interfaces attached, the allocated ports will be numbered from 0 to 2n1. For example, take the case of a graphical application that is written to communicate CAN through a Komodo interface. The user can simply replace the old Komodo DLL with the newer one. How does this work The application contains only a stub which in turn dynamically loads the DLL on the first invocation of any Komodo API function. If the DLL is replaced, the application simply loads the new one, thereby utilizing all of the improvements present in the replaced DLL. The default behavior of locating the Komodo DLL is dependent on the operating system platform and specific programming language environment.Each DLL revision is tagged as being compatible with firmware revisions greater than or equal to a certain version number. Likewise, each firmware version is tagged as being compatible with DLL revisions greater than or equal to a specific version number. If there is a version mismatch, the API calls to open the device will fail. See the API documentation for further details. Accessing Komodo functionality simply requires function calls to the Komodo API. This API is easy to understand, much like the ANSI C library functions, e.g. there is no unnecessary entanglement with the Windows messaging subsystem like development kits for some other embedded tools.

Different Rosetta bindings are included with the software distribution on the distribution CD. They can also be found in the software download package available on the Total Phase website. As an example, the integration for the C language bindings is described below. For more information on how to integrate the bindings for other languages, please see the example code included on the distribution CD and also available for download on the Total Phase website. Ensure that the include path for compilation also lists the directory in which komodo.h is located if the two files are not placed in the same directory. A system similar to the one employed for the DLLFirmware crossvalidation is used for the binding and DLL compatibility check. Here is an example The compatibility check is performed within the binding.See the comments in komodo.c for more details. Take the case of the Komodo interface receiving CAN messages asynchronously. If the application calls the function to change the state of a GPIO while some unprocessed asynchronous messages are pending, the Komodo interface will modify the GPIO pin but also save any pending CAN messages internally. The messages will be held until the appropriate API function is called. A CAN channel can receive messages asynchronously with respect to the host PC software. Between calls to the Komodo API, these messages must be buffered somewhere in memory. This is accomplished on the PC host, courtesy of the operating system. Naturally, the buffer is limited in size and once this buffer is full, bytes will be dropped. This condition can affect other synchronous communication with the Komodo interface. The obvious solution is to reduce the amount of traffic that is sent by all CAN nodes between calls to the Komodo API. This will require the ability to reconfigure the offending CAN devices. The other option is to poll the CAN channel to collect pending messages more frequently.

If the application design requires multithreaded use of the Komodo functionality for a single port, each Komodo API call can be wrapped with a threadsafe locking mechanism before and after invocation. For more details, please see the API section. This is caused by the inherent design of the USB architecture. The operating system will queue any outgoing USB transfer request on the host

until the next USB frame period. The frame period is 1 ms. Thus, if the application attempts to execute several transactions in rapid sequence there can be 12 ms delay between each transaction plus any additional process scheduling delays introduced by the operating system. The upgrade procedure is performed via USB and has several error checking facilities to ensure that the Komodo interface is not rendered permanently unusable by a bad firmware update. In the worst case scenario, a corruption can cause the Komodo interface to be locked until a subsequent clean update is executed. It contains the kmflash utility. This utility contains the necessary information to perform the entire firmware update. If the selected devices hardware is not suitable to accept the new firmware, an error will be printed and the utility will be reinvoked. The process should take a few seconds, with a progress bar displayed during the procedure. Try the update again, since the Komodo interface has most likely become locked due to a corruption in the upgrade process. If the update still does not take effect, it is best to revert back to the previous firmware. This can be done by running a previous version of kmflash that contains an earlier firmware version. Check the Total Phase website or the distribution CD that was included with your Komodo interface for previous versions of the firmware. The set of API functions and their functionality is identical regardless of which Rosetta language binding is utilized. The only differences are in the calling convention of the functions.

For further information on such differences, please refer to the documentation that accompanies each language bindings in the Komodo software distribution. The Komodo API provides both signed and unsigned data types. The complete list of status codes is provided at the end of this chapter. All of the error codes are assigned values less than 0, separating these responses from any numerical values returned by certain API functions. If these status codes are received, refer to the previous sections in this datasheet that discuss the DLL and API integration of the Komodo software. If this error is encountered, there is likely a serious version incompatibility that was not caught by the automatic version checking system. Next, ensure that the Rosetta language binding e.g., komodo.c and komodo.h are from the same release as the Komodo DLL. If all of these versions are synchronized and there are still problems, please contact Total Phase support for assistance. This means that while the Komodo handle is valid and the communication channel is open, there was an error receiving the acknowledgment response from the Komodo interface. The error signifies that it was not possible to guarantee that the connected Komodo interface has processed the host PC request, though it is likely that the requested action has been communicated to the Komodo interface and the response was simply lost. Komodo CAN bus and GPIO data functions require that a Komodo handle be in an enabled state.Only the error codes that are specific to each API function are described below. With multiprocess access comes the possibility of two separate processes interfering with one another in a number of ways. That is, a software process attempting to manipulate the CAN or GPIO interfaces through a port must first acquire certain feature resources from the Komodo CAN Duo device. These features are as follows The CONFIG features, however, can only be possessed by one port at a time.

Thus, it is possible for both ports to have simultaneous access to the CAN and GPIO interfaces, but it is not possible for one port to change certain vital configuration parameters the other port relies on. Each port represents a single element in the ports array. The ports from a single Komodo device always appear sequentially in the ports array. Both ports from device 0 are inuse. Both ports from the device 1 are free. The first port from device 2 is inuse and second port is free.The IDs are guaranteed to be nonzero if valid. However, if either array is NULL, the length passed in for the other array is used asis, and the NULL array is not populated. If both arrays are NULL, neither array is populated, but the number of devices found is still returned. The DLL is not of a sufficient version for interoperability with the firmware version or vice versa.The DLL is not of a sufficient version for interoperability with the firmware version or vice versa.It can be used to determine which component caused an incompatibility error. The lower 16 bits gives the. The lower 16 bits gives theIt

is filled with whatever information is available. For example, if the firmware version is not filled, then the device could not be queried for its version number. This will usually be 1. The total number of Komodo ports closed is returned by the function. Bitmask values are as defined in Table 6. The bitmask value only indicates the features that are supported by the port. The IDs are guaranteed to be nonzero if valid. The ID is the unsigned integer representation of the 10digit serial number. If the code is not valid, it returns a NULL string. This function will return the number of milliseconds that were actually slept. Instead, the returned feature mask will indicate which features are currently acquired. The CONFIG features can only be possessed by one port at a time. Instead, the returned feature mask will indicate which features are currently acquired.

Only once one of these individual buffers is filled, does the read function return. Therefore, in order to fulfill shorter latency requirements, these individual buffers are set to a smaller size. If a larger latency is requested, then the individual buffers will be set to a larger size. It is important to keep in mind that there is a fixed cost to processing each individual buffer that is independent of buffer size. Therefore, the tradeoff is that using a small latency will increase the overhead per byte buffered. A large latency setting decreases that overhead, but increases the amount of time that the library must wait for each buffer to fill before the library can process their contents. The latency time should be set to a value shorter than the timeout. This enumerated type is described in Table 8. If this buffer is filled, the Komodo will not report new packets or events, and it will stop transmitted packes on the CAN bus. To decrease the possibility of this buffer filling, the following steps may be taken This is the default behavior. This function returns the actual timeout value in milliseconds. It will attempt each bitrate in order for up to 500 ms before attempting a new bitrate. If a successfully completed packet is perceived by the channel, then that bitrate is deemed a success, and the bitrate is returned. The maximum allowable bitrate is 1 MHz. The configuration will be described by the same values as in the table above. An exception to this exists if info is a NULL pointer.This same struct is used for the CAN transmit functions. Do not retransmit. As an asynchrnonous call, this function will not block. Only one attempt will be made to transmit the packet on the CAN bus in this case. Any attempts to set a pin configured as either an input or as a nonsoftwarecontrolled output will be silently ignored. Distribution rights do not include public posting or mirroring on Internet websites.