



USER MANUAL UMAX130540

ISOLATED DUAL CHANNEL UNIVERSAL SIGNAL CONVERTER WITH CAN, SAE J1939

USER MANUAL

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3.00	October 19, 2020	Ilona Korpelainen	Updated to match firmware V3.00 (Auto baud rate)

ACCRONYMS

ACK	Positive Acknowledgement (from SAE J1939 standard)
BATT +/-	Battery positive (a.k.a. Vps) or Battery Negative (a.k.a. GND)
DIN	Digital Input used to measure active high or low signals
DM	Diagnostic Message (from SAE J1939 standard)
DTC	Diagnostic Trouble Code (from SAE J1939 standard)
EA	Electronic Assistant, p/n AX070502 (A Service Tool for Axiomatic ECUs)
ECU	Electronic Control Unit (from SAE J1939 standard)
GND	Ground reference (a.k.a. BATT-)
I/O	Inputs and Outputs
MAP	Memory Access Protocol
NAK	Negative Acknowledgement (from SAE J1939 standard)
PDU1	A format for messages that are to be sent to a destination address, either specific or global (from SAE J1939 standard)
PDU2	A format used to send information that has been labeled using the Group Extension technique, and does not contain a destination address.
PGN	Parameter Group Number (from SAE J1939 standard)
PropA	Message that uses the Proprietary A PGN for peer-to-peer communication
PropB	Message that uses a Proprietary B PGN for broadcast communication
PWM	Pulse Width Modulation
RPM	Rotations per Minute
SPN	Suspect Parameter Number (from SAE J1939 standard)
TP	Transport Protocol
UIN	Universal input used to measure voltage, current, frequency or digital inputs
Vps	Voltage Power Supply (a.k.a. BATT+)
%dc	Percent Duty Cycle (Measured from a PWM input)

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J1939/21	Data Link Layer, SAE, December 2010
J1939/71	Vehicle Application Layer, SAE, March 2011
J1939/73	Application Layer-Diagnostics, SAE, February 2010
J1939/81	Network Management, SAE, May 2003
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This document assumes the reader is familiar with the SAE J1939 standard. Terminology from the standard is used, but not described in this document.



NOTE: This product is supported by Electronic Assistant V5.15.117.0 and higher

1. OVERVIEW OF CONTROLLER

The isolated dual channel universal signal converter (2In2Out) is designed for extremely versatile control of up to two signal level outputs. Its flexible circuit design gives the user a wide range of configurable input and output types. The sophisticated control algorithms allow the user to program the controller for a wide range of applications without the need for customer software.

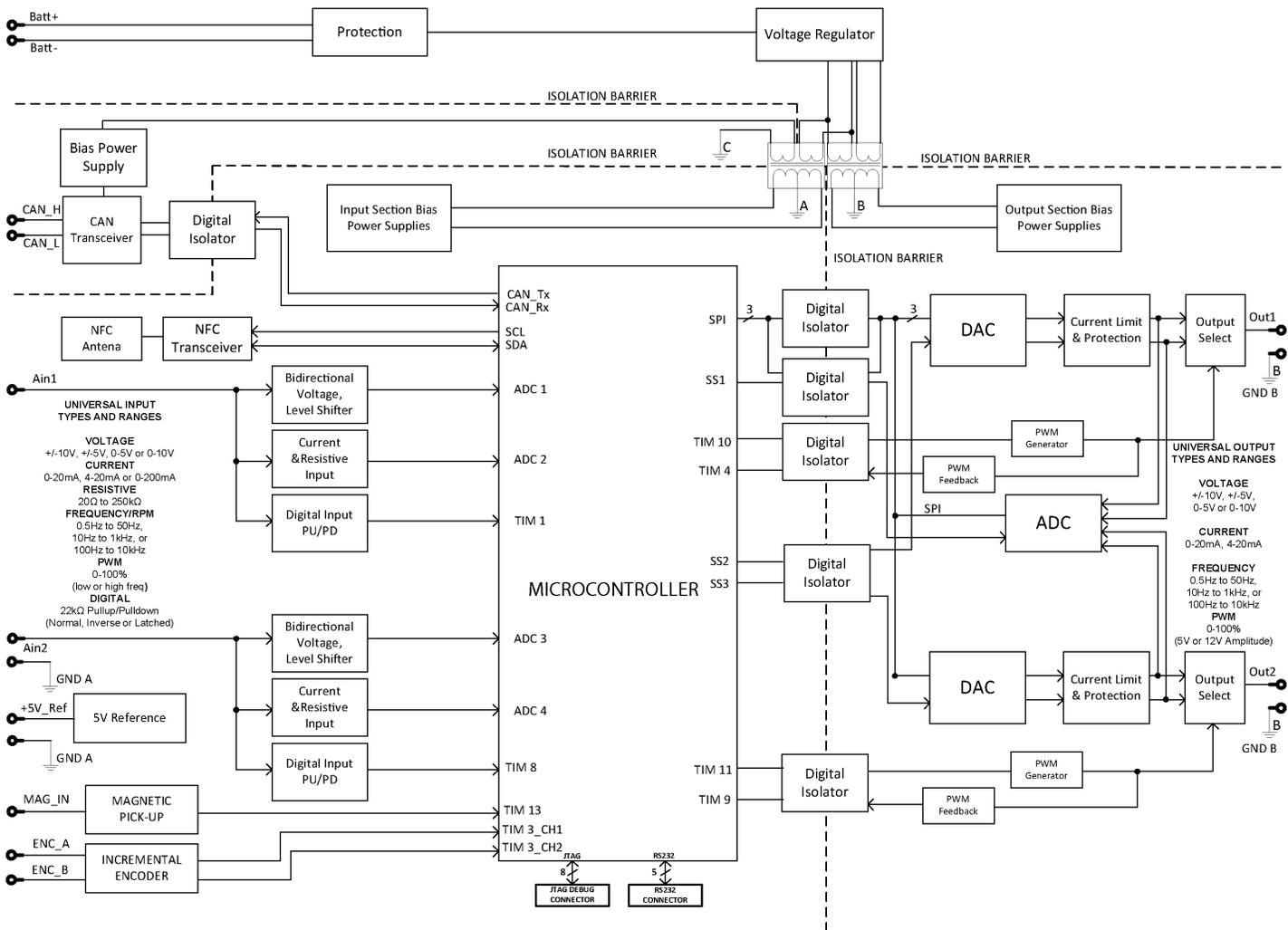


Figure 1 – Hardware Functional Block Diagram

The controller has two fully programmable universal signal inputs that can be setup to read: voltage, current, resistive, frequency or digital input signals. In addition, there is a magnetic input for reading magnetic pick up sensor and an encoder input.

The two universal signal outputs can be setup to output: voltage (0-5V, 0-10V, +/-5V or +/-10V), current (0-20mA or 4-20mA), PWM (fixed frequency), Frequency (fixed duty cycle), variable PWM and Freq, and Digital On/Off. All I/O ports on the unit are fully independent from another.

The controller has four-way digital isolation between inputs, outputs, power and CAN bus.

The Axiomatic Electronic Assistant is used to configure the isolated dual channel universal signal converter. Configurable properties, EA setpoints, are listed in chapter 3. Setpoint configuration can be saved in a file which can then be utilized to program the same configuration to another isolated dual channel universal signal converter. Throughout this document, EA setpoint names are referred with bolded text in double-quotes and the setpoint option is referred with italicized text in single-quotes. For example, “**Input Sensor Type**” setpoint set to option ‘*Voltage 0 to 5V*’.

In addition, to configuring the controller with EA and USB-CAN device, the reduced amount of setpoints are available as parameters to be configured through near field communication (NFC) by using the mobile E-Write NFC tool available on the Google Play Store. Controllers NFC feature and available parameters are described in chapter 4.

In this document the configurable properties of the ECU are divided into function blocks, namely Input Function Block, Output Function Block, Diagnostic Function Block, PID Control Function Block, Lookup Table Function Block, Programmable Logic Function Block, Math Function Block, DTC React Function Block, CAN Transmit Message Function Block, CAN Receive Message Function Block and Inching Control Block. These function blocks are presented in detail in next subchapters.

1.1. Input Function Blocks

The controller has two universal signal inputs (Input1 and Input2), which can be configured to measure voltage, current, resistance, frequency, pulse width (PWM) or digital signal. In addition, there is a Magnetic input (Input3) and an Encoder Input (Input4).

Universal Signal Input setpoint group has the “**Input Sensor Type**” setpoint, which is used to configure input type. Selecting input type effects on other setpoints and how they are interpreted and should thus be selected first on this block. The input sensor types are listed in Table 1.

0	<i>Disabled</i>
10	<i>Voltage 0 to 5 V</i>
11	<i>Voltage 0 to 10V</i>
12	<i>Voltage -5 to 5 V</i>
13	<i>Voltage -10 to 10 V</i>
20	<i>Current 0 to 20 mA</i>
21	<i>Current 4 to 20 mA</i>
22	<i>Current 0 to 200 mA</i>
30	<i>Resistive 20 Ω to 250 kΩ</i>
40	<i>Frequency 0.5 to 50 Hz</i>
41	<i>Frequency 10 Hz to 1 kHz</i>
42	<i>Frequency 100 Hz to 20 kHz</i>
50	<i>PWM Low Frequency (<1kHz)</i>
51	<i>PWM High Frequency (>100Hz)</i>
60	<i>Digital (normal)</i>
61	<i>Digital (inverse)</i>
62	<i>Digital (latched)</i>

Table 1 – Universal Input Sensor Type Options

With Universal Inputs voltage (i.e. 0-5V, 0-10V, +/-5V, +/-10V) or current (0-20mA, 4-20mA, 0-200mA) sensor types the input signals go directly to a 12-bit analog-to-digital converter (ADC) on the processor. The voltage input is a high impedance input protected against shorts to GND or Vps. In current mode, a current sense resistor (249Ω, for 0-20mA and 5Ω for 0-200mA) is used to measure the input signal.

Resistive inputs can accurately read a resistive value connected between the input pin and INGND. The 2In2Out controller multiplexes a configurable current source (10uA, 100uA, 1mA, 10mA) to the input pin set up as resistive input, and measures voltage created across the input. Depending on the value of the resistive load, the input will self-calibrate to the appropriate sourcing current.

0	<i>None</i>
1	<i>111ns</i>
2	<i>1.78us</i>
3	<i>14.22us</i>

Table 2 – Debounce Time Options

Frequency/RPM or Pulse Width Modulated (PWM) “**Input Sensor Type**” options connect an input to 16-bit timer pin on the processor. “**Debounce Time**” setpoint is used to select an input capture filter for the timer pin in question. “**Pulse Per Revolution**” setpoint is only associated with the frequency input type. If the setpoint is configured to be different from 0, then the input data will be reported as in rotations-per-minute (RPM). Otherwise, frequency inputs are measured in Hertz.

Universal Inputs have available three Digital “**Input Sensor Type**” options: Normal, Inverse and Latched. With digital input sensor types, the input measurement is given, either 1 (ON) or 0 (OFF). The Universal Inputs measure digital voltage with 1.8.V ON threshold and 1.2V OFF threshold.

On Frequency, PWM and digital input modes 10kΩ pull-up or pull-down resistors can be enabled or disabled by setting the value of the “**Pullup/Pulldown Resistor**” setpoint. Setpoint options are given in Table 3. By default, pull-down resistors are enabled for all inputs.

0	<i>Pullup/down Off</i>
1	<i>10 kΩ Pullup</i>
2	<i>10 kΩ Pulldown</i>

Table 3 – Pullup/Pulldown Resistor Options

“**Active High/Active Low**” setpoint is used to configure how signal high and low are interpreted. Setpoint options are given in Table 4. By default, all inputs are selected to be Active High, which means that signal high is interpreted as 1(ON) and signal low as 0(OFF).

0	<i>Active High</i>
---	--------------------

1	Active Low
---	------------

Table 4 – Active High/Low Options

Table 5 shows the effect of different digital input types on input signal measurement interpretation with recommended “**Pullup/Pulldown Resistor**” and “**Active High/Low**” combinations.

Input Sensor Type		Pulldown Active High	Pullup Active Low	Input measured (state)
6	<i>Digital (normal)</i>	High	Low or Open	1 (ON)
		Low or Open	High	0 (OFF)
61	<i>Digital (inverse)</i>	High or Open	Low	1 (ON)
		Low	High or Open	0 (OFF)
62	<i>Digital (latched)</i>	High to Low	Low to High	0 (no change)
		Low to High	High to Low	1 (state change)

Table 5 – Digital Input Sensor Type versus Input State

The “**Minimum Range**” and “**Maximum Range**” setpoints are used to define range of the signal input outputs as a control source. For example, if “**Maximum Range**” is set to 4V for an input, the control signal is saturated at 4V if input signal rises above 4V. The “**Minimum Range**” and “**Maximum Range**” setpoints are interpreted in input types units, thus they should be re-adjusted after editing “**Input Sensor Type**”.

Software filters can be applied to the measured input signal. Setpoints “**Software Filter Type**” and “**Software Filter Constant**” are used to configure the software filter. By default, no filter is applied to the signal. Software filtering is described in detail in section below.

The rest of the setpoints in the Input setpoint group are used to configure input related fault diagnostics and are described in section 1.4.

1.2. Input filtering

Measured input data from universal inputs can be filtered to form desired CAN message data. Input filters are configured with “**Filter Type**” and “**Filter Constant**” setpoints. Filters are configured for each input individually.

“**Filter Type**” setpoint defines the type of software filter used. Setpoint options are ‘*No Filtering*’, ‘*Moving Average*’ and ‘*Repeating Average*’. The ‘*No Filtering*’ option applies no filtering to the measured input data. The ‘*Moving Average*’ option applies the transfer function below to the measured input data, where $Value_N$ is the current value of the CAN message data, $Value_{N-1}$ is the previous CAN message data and Filter Constant is the value of the “**Filter Constant setpoint**”.

Equation 1 - Moving Average Transfer Function:

$$Value_N = Value_{N-1} + \frac{(Input - Value_{N-1})}{Filter\ Constant}$$

Equation 2 - Repeating Average Transfer Function:

$$Value = \frac{\sum_0^N Input_N}{N}$$

The ‘*Repeating Average*’ option applies the transfer function above to the measured input data, where N is value of the “**Filter Constant**” setpoint. At every reading of the input value, the value is added to the sum. At every Nth read, the sum is divided by N, and the result is new CAN message data. The sum is set to zero for the next read and summing is started again.

1.3. Universal Signal Output Function Blocks

The controller has two fully isolated signal outputs. “**Output Type**” setpoint determines what kind of signal the output produces. Changing this setpoint causes other setpoints in the group to update to match selected type, thus the “**Output Type**” should be selected before configuring other setpoints within the setpoint group. “**Output Type**” setpoint options are listed in Table 6.

0	<i>Disabled</i>
12	<i>Voltage 0 to 5V</i>
13	<i>Voltage 0 to 10V</i>
14	<i>Voltage -5 to 5V</i>
15	<i>Voltage -10 to 10V</i>
20	<i>Current 0 to 20mA</i>
21	<i>Current 4 to 20mA</i>
40	<i>Frequency 0 to 20kHz</i>
50	<i>PWM</i>
60	<i>Digital On/Off</i>
70	<i>Mixed PWM and Frequency</i>

Table 6 – Output Type Options for Universal Signal Output

Voltage and current outputs are generated with fully isolated onboard digital to analog converters (DAC). Frequency, PWM, Digital and Mixed outputs are produced with controller’s timer outputs. Signal amplitude can be selected to be either 5V or 12V with “**Frequency/PWM Amplitude**” setpoint.

Output signal minimum and maximum values are configured with “**Output At Minimum Command**” and “**Output At Maximum Command**” setpoints. Value ranges for both setpoints are limited by selected “**Output Type**”.

With linear output types (all output types except ‘*Digital On/Off*’), regardless of what type of control input is selected, the output will always respond in a linear fashion to changes in the input per Equation 3.

$$y = mx + a$$

$$m = \frac{Y_{max} - Y_{min}}{X_{max} - X_{min}}$$

$$a = Y_{min} - m * X_{min}$$

Equation 3 - Linear Slope Calculations

In the case of the Output Control Logic function block, X and Y are defined as

Xmin = Control Input Minimum Ymin = “**Output at Minimum Command**”

Xmax = Control Input Maximum Ymax = “**Output at Maximum Command**”

In all cases, while X-axis has the constraint that $X_{min} < X_{max}$, there is no such limitation on the Y-axis. Thus configuring “**Output At Minimum Command**” to be greater than “**Output At Maximum Command**” allows output to follow control signal inversely.

To prevent abrupt changes at the output due to sudden changes in the command input, the user can choose to use the independent up or down ramps to smooth out the response. The “**Ramp Up**” and “**Ramp Down**” setpoints are in milliseconds, and the step size of the output change will be determined by taking the absolute value of the output range and dividing it by the ramp time.

“**Fixed Output Frequency/PWM Duty Cycle**” setpoint is used to select output signal duty cycle with ‘*Frequency 0 to 20kHz*’ output type and frequency with ‘*PWM*’ output type. The value of this setpoint defaults when “**Output Type**” setpoint is changed.

With the ‘*Digital On/Off*’ output type, in OFF state output is 0V and in ON state 5V or 12V depending on selected amplitude. The ‘*Digital On/Off*’ output type has several associated setpoints. The “**Digital Response**” setpoint is used to select digital response, setpoint options are listed in Table 7.

0	<i>Normal On/Off</i>
1	<i>Inverse Logic</i>
2	<i>Latched Logic</i>
3	<i>Blinking Logic</i>

Table 7 – Digital Response Options

In a ‘*Normal*’ response, when the Control input commands the output ON, then the output will be turned ON. However, in an ‘*Inverse*’ response, the output will be ON unless the input commands the output ON, in which case it turns OFF.

The “**Digital Out Delay**” and “**Delay Polarity**” setpoints are associated with ‘*Normal*’ “**Digital Response**”. The “**Digital Out Delay**” defines output state change delay in milliseconds. Setting “**Digital Out Delay**” to 0ms applies no state change delay. The “**Delay Polarity**” setpoint defines which edge the state change delay will be applied. For example, selecting ‘*Rising Edge*’ for “**Delay Polarity**” and setting “**Digital Out Delay**” value >0ms, applies defined delay when driving output signal state changes from OFF to ON.

0	<i>Rising Edge</i>
1	<i>Falling Edge</i>

Table 8 – Delay Polarity

If a ‘*Latched*’ response is selected, the output will change state, when the input commands the state from OFF to ON.

If a ‘*Blinking*’ response is selected, the output will blink at the rate of the “**Digital Blink Rate**” setpoint while the input commands the output ON. When commanded OFF, the output will stay off.

The “**Control Source**” setpoint together with “**Control Number**” setpoint determine which signal is used to drive the output. For example, setting “**Control Source**” to ‘*Universal Input Measured*’ and “**Control Number**” to ‘1’, connects signal measured from Universal Input1 to the output in question. The input signal is scaled per input type range between 0 and 1 to form control signal. Outputs respond in a linear fashion to changes in control signal. If a non-digital signal is selected to

drive digital output the command state will be 0 (OFF) at or below the “**Output At Minimum Command**”, 1 (ON) at or above “**Output At Maximum Command**” and will not change in between those points.

The ‘*Mixed PWM and Frequency*’ output type has second control input which is selected with “**Frequency Control Source**” and “**Frequency Control Number**” setpoints. Associated “**Mixed Output Frequency Min**” and “**Mixed Output Frequency Max**” setpoints determine minimum and maximum values for the frequency control signal.

In addition to the Control input, outputs also support Enable and Override inputs.

The “**Enable Source**” setpoint together with “**Enable Number**” setpoint determine the enable signal for the output in question. The “**Enable Response**” setpoint is used to select how output will respond to the selected Enable signal. “**Enable Response**” setpoint options for the proportional output are listed in Table 9. If “**Enable Source**” is set to ‘*Control not used*’, the Enable signal is interpreted to be ON. If a non-digital signal is selected as Enable signal the signal is interpreted as shown in Figure 3.

0	<i>Enable When On, Else Shutoff</i>
1	<i>Enable When On, Else Ramp off</i>
2	<i>Enable When Off, Else Shutoff</i>
3	<i>Enable When Off, Else Ramp off</i>
4	<i>Enable When On, Else Ramp To Min</i>
5	<i>Enable When On, Else Ramp To Max</i>

Table 9 – Enable Response Options

Override input allows the output drive to be configured to go to a default value in the case of the override input being engaged/disengaged, depending on the logic selected in “**Override Response**”, presented on Table 10. When active, the output will be driven to the value in “**Output at Override Command**” regardless of the value of the Control input. The “**Override Source**” and “**Override Number**” together determine the Override input signal.

0	<i>Override When On</i>
1	<i>Override When Off</i>

Table 10 – Override Response Options

If a fault is detected in any of the active inputs (Control/Enable/Override) the output will respond per “**Control Fault Response**” setpoint as outlined in Table 11. Fault Value is defined by “**Output in Fault Mode**” setpoint value, which is interpreted in selected output units.

0	<i>Shutoff Output</i>
1	<i>Apply Fault Value</i>
2	<i>Hold Last Value</i>

Table 11 – Fault Response Options

It is also possible to set ALL outputs to be turned off in case of power supply, controller temperature or CAN bus fault as described in section 1.4.

Actual output value is measured internally from output feedback connection. With voltage and current output type, fully isolated onboard analog to digital converter (ADC) is utilized to measure the feedback signal. With frequency, PWM and mixed output types, 16-bit processor timer pin measures the output signal. Output feedback value is available as control source as shown in section 1.12. and can thus be used in fault detection presented in section 1.4.

1.4. Diagnostic Function Blocks

The 2In2Out controller supports diagnostic messaging. DM1 message is a message, containing Active Diagnostic Trouble Codes (DTC) that is sent to the J1939 network in case a fault has been detected. A Diagnostic Trouble Code is defined by the J1939 standard as a four-byte value which is a combination of:

SPN	Suspect Parameter Number	(user defined)
FMI	Failure Mode Identifier	(see Table 13 and Table 14)
CM	Conversion Method	(always set to 0)
OC	Occurrence Count	(number of times the fault has happened)

In addition to supporting the DM1 message, 2In2Out Input also supports:

DM2	Previously Active Diagnostic Trouble Codes	Sent only on request
DM3	Diagnostic Data Clear/Reset of Previously Active DTCs	Done only on request
DM11	Diagnostic Data Clear/Reset for Active DTCs	Done only on request

Fault detection and reaction is a standalone functionality that can be configured to monitor and report diagnostics of various controller parameters. The 2In2Out controller supports 16 Diagnostics Definitions, each freely configurable by the user.

By default, the monitoring of operating voltage, CPU temperature and receive message timeouts is configured to diagnostics blocks 1, 2 and 3., In case any of these three diagnostics blocks are needed for some other use, the default settings can be adjusted by the user to suit the application.

There are 4 fault types that can be used, “**Minimum and maximum error**”, “**Absolute value error**”, “**State error**” and “**Double minimum and maximum error**”.

Minimum and maximum error has two thresholds, “MIN Shutdown” and “MAX Shutdown” that have configurable, independent diagnostics parameters (SPN, FMI, Generate DTCs, delay before flagging status). In case the parameter to monitor stays between these two thresholds, the diagnostic is not flagged.

Absolute value error has one configurable threshold with configurable parameters. In case the parameter to monitor stays below this threshold, the diagnostic is not flagged.

State error is like the Absolute value error, the only difference is that State error does not allow the user to specify specific threshold values; thresholds ‘1’ and ‘0’ are used instead. This is ideal for monitoring state information, such as received message timeouts.

Double minimum and maximum error lets user to specify four thresholds, each with independent diagnostic parameters. The diagnostic status and threshold values is determined and expected as show in Figure 2 below.

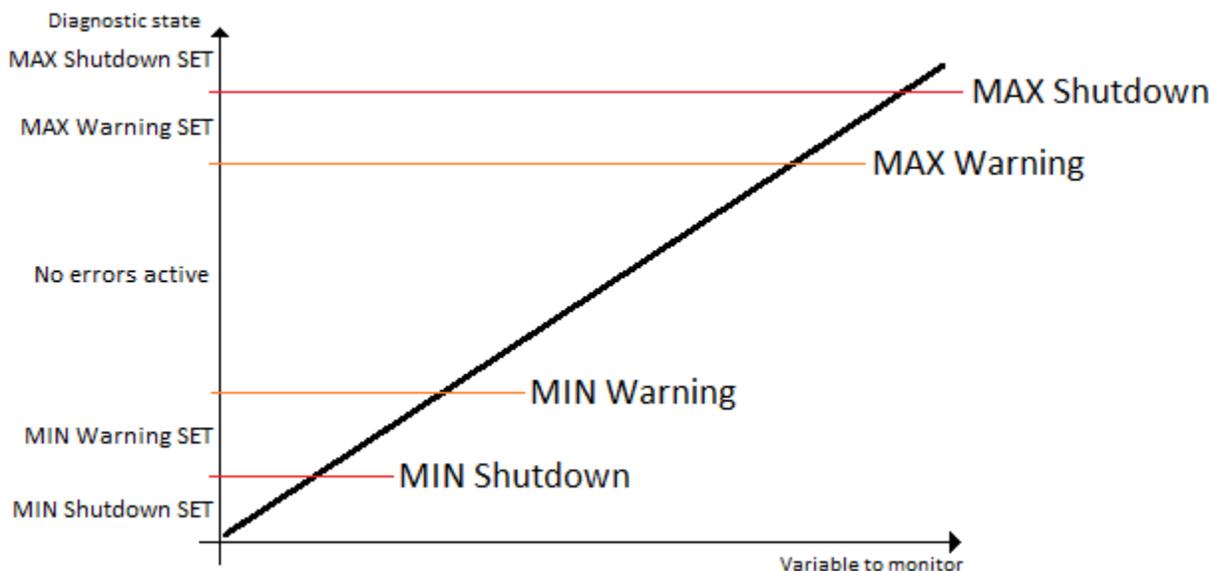


Figure 2 – Double Minimum and Maximum Error Thresholds

In case any of the Diagnostics blocks is configured to monitor Output Feedback, there is an internal error status flag maintained automatically for that output. This internal flag can be used for driving the output to a specified state in case of diagnostic event using Signal Output setpoints “Output Fault Response”, “Output in Fault Mode” and “Fault Detection Enabled”.

There is also built in error status flags for power supply and CPU temperature monitoring. In case any of the diagnostics blocks is measuring these two parameters, the corresponding internal error status flags can be used for shutting down the unit in case of failure. The setpoints “**Power Fault Disables Outputs**” and “**Over Temperature Shutdown**” can be used for enabling the shutdown of the unit (shutdown == output driving is turned off).

While there are no active DTCs, the 2In2Out controller will send “No Active Faults” message. If a previously inactive DTC becomes active, a DM1 will be sent immediately to reflect this. As soon as the last active DTC goes inactive, a DM1 indicating that there are no more active DTCs will be sent.

If there is more than one active DTC at any given time, the regular DM1 message will be sent using a multipacket message to the Requester Address using the Transport Protocol (TP).



At power up, the DM1 message will not be broadcasted until after 5 second delay. This is done to prevent any power up or initialization conditions from being flagged as an active error on the network.

When the fault is linked to a DTC, a non-volatile log of the occurrence count (OC) is kept. As soon as the controller detects a new (previously inactive) fault, it will start decrementing the “**Delay**

before Event is flagged” timer for that Diagnostic function block. If the fault has remained present during the delay time, then the controller will set the DTC to active, and will increment the OC in the log. A DM1 will immediately be generated that includes the new DTC. The timer is provided so that intermittent faults do not overwhelm the network as the fault comes and goes, since a DM1 message would be sent every time the fault shows up or goes away.

By default, the fault flag is cleared when error condition that has caused it goes away. The DTC is made Previously Active and is it is no longer included in the DM1 message. To identify a fault having happened, even if the condition that has caused is one away, the **“Event Cleared only by DM11”** setpoint can be set to ‘True’. This configuration enables DTC to stay Active, even after the fault flag has been cleared, and be included in DM1 message until a Diagnostic Data Clear/Reset for Active DTCs (DM11) has been requested.

As defined by J1939 Standard the first byte of the DM1 message reflects the Lamp status. **“Lamp Set by Event”** setpoint determines the lamp type set in this byte of DTC. **“Lamp Set by Event”** setpoint options are listed in Table 12. By default, the ‘Amber, Warning’ lamp is typically the one set be any active fault.

0	<i>Protect</i>
1	<i>Amber Warning</i>
2	<i>Red Stop</i>
3	<i>Malfunction</i>

Table 12 – Lamp Set by Event in DM1 Options

“SPN for Event” defines suspect parameter number used as part of DTC. The default value zero is not allowed by the standard, thus no DM will be sent unless **“SPN for Event”** in is configured to be different from zero. **It is user’s responsibility to select SPN that will not violate J1939 standard.** When the **“SPN for Event”** is changed, the OC of the associated error log is automatically reset to zero.

0	<i>Data Valid But Above Normal Operational Range - Most Severe Level</i>
1	<i>Data Valid But Below Normal Operational Range - Most Severe Level</i>
2	<i>Data Intermittent</i>
3	<i>Voltage Above Normal, Or Shorted To High Source</i>
4	<i>Voltage Below Normal, Or Shorted To Low Source</i>
5	<i>Current Below Normal Or Open Circuit</i>
6	<i>Current Above Normal Or Grounded Circuit</i>
7	<i>Mechanical Error</i>
8	<i>Abnormal Frequency Or Pulse Width Or Period</i>
9	<i>Abnormal Update Rate</i>
10	<i>Abnormal Rate Of Change</i>
11	<i>Root Cause Not Known</i>
12	<i>Bad Component</i>
13	<i>Out Of Calibration</i>
14	<i>Special Instructions</i>
15	<i>Data Valid But Above Normal Operating Range – Least Severe Level</i>
16	<i>Data Valid But Above Normal Operating Range – Moderately Severe Level</i>
17	<i>Data Valid But Below Normal Operating Range – Least Severe Level</i>

18	<i>Data Valid But Below Normal Operating Range – Moderately Severe Level</i>
19	<i>Network Error</i>
20	<i>Data Drifted High</i>
21	<i>Data Drifted Low</i>
31	<i>Condition Exists</i>

Table 13 – FMI for Event Options

Every fault has associated a default FMI with them. The used FMI can be configured with “**FMI for Event**” setpoint, presented in Table 13. When an FMI is selected from Low Fault FMIs in Table 14 for a fault that can be flagged either high or low occurrence, it is recommended that the user would select the high occurrence FMI from the right column of Table 14. There is no automatic setting of High and Low FMIs in the firmware, the user can configure these freely.

Low Fault FMIs	High Fault FMIs
<i>FMI=1, Data Valid But Below Normal Operation Range – Most Severe Level</i>	<i>FMI=0, Data Valid But Above Normal Operational Range – Most Severe Level</i>
<i>FMI=4, Voltage Below Normal, Or Shorted to Low Source</i>	<i>FMI=3, Voltage Above Normal, Or Shorted To High Source</i>
<i>FMI=5, Current Below Normal Or Open Circuit</i>	<i>FMI=6, Current Above Normal Or Grounded Circuit</i>
<i>FMI=17, Data Valid But Below Normal Operating Range – Least Severe Level</i>	<i>FMI=15, Data Valid But Above Normal Operating Range – Least Severe Level</i>
<i>FMI=18, Data Valid But Below Normal Operating Level – Moderately Severe Level</i>	<i>FMI=16, Data Valid But Above Normal Operating Range – Moderately Severe Level</i>
<i>FMI=21, Data Drifted Low</i>	<i>FMI=20, Data Drifted High</i>

Table 14 – Low Fault FMIs and corresponding High Fault FMIs

1.5. PID Control Function Block

The PID Control function block is an independent logic block, but it is normally intended to be associated with proportional output control blocks described earlier. When the “**Control Source**” for an output has been setup as a ‘*PID Function Block*’, the command from the selected PID block drives the physical output on the 2In2Out Controller.

The “**PID Target Command Source**” and “**PID Target Command Number**” setpoints determine control input and the “**PID Feedback Input Source**” and “**PID Feedback Input Number**” setpoints determine the established the feedback signal to the PID function block. The “**PID Response Profile**” will use the selected inputs as per the options listed in Table 15. When active, the PID algorithm will be called every “**PID Loop Update Rate**” in milliseconds.

0	<i>Single Output</i>
1	<i>Setpoint Control</i>
2	<i>On When Over Target</i>
3	<i>On When Below Target</i>

Table 15 – PID Response Options

When a ‘*Single Output*’ response is selected, the Target and Feedback inputs do not have to share the same units. In both cases, the signals are converted to a percentage values based on the minimum and maximum values associated with the source function block.

For example, a CAN command could be used to set the target value, in which case it would be converted to a percentage value using “**Receive Data Min**” and “**Receive Data Max**” setpoints in the appropriate ‘*CAN Receive X*’ function block. The closed-loop feedback signal (i.e. a 0-5V input) could be connected to ‘*Universal Input 1*’ and selected as the feedback source. In this case the value of the input would be converted to a percentage based on the “**Minimum Range**” and “**Maximum Range**” setpoints in the input block. The output of the PID function would depend on the difference between the commanded target and the measured feedback as a percentage of each signals range. In this mode, the output of the block would be a value from -100% to 100%.

When a ‘*Setpoint Control*’ response is selected, the “**PID Target Command Source**” automatically gets updated to ‘*Control Constant Data*’ and cannot be changed. The value set in the associated constant in the Constant Data List function block becomes the desired target value. In this case, both the target and the feedback values are assumed to be in same units and range. The minimum and maximum values for the feedback automatically become the constraints on the constant target. In this mode, the output of the block would be a value from 0% to 100%.

For example, if the feedback was setup as a 4-20mA input, a “**Constant Value X**” setpoint set to 14.2 would automatically be converted to 63.75%. The PID function would adjust the output as needed to have the measured feedback to maintain that target value.

The last two response options, ‘*On When Over Target*’ and ‘*On When Under Target*’, are designed to allow the user to combine the two proportional outputs as a push-pull drive for a system. Both outputs must be setup to use the same control input (linear response) and feedback signal in order to get the expected output response. In this mode, the output would be between 0% to 100%.

In Order to allow the output to stabilize, the user can select a non-zero value for “**PID Delta Tolerance**”. If the absolute value of $Error_k$ is less than this value, $Error_k$ in the formula below will be set to zero.

The PID algorithm used is shown below, where **G**, **Ki**, **Ti**, **Kd**, **Td** and **Loop_Update_Rate** are configurable parameters.

$$PIDOutput_k = P_k + I_k + D_k$$

$$P_k = P_Gain * Error_k$$

$$I_k = I_Gain * ErrorSum_k$$

$$D_k = D_Gain * (Error_k - Error_{k-1})$$

$$Error_k = Target - Feedback$$

$$ErrorSum_k = ErrorSum_{k-1} + Error_k$$

$$P_Gain = G$$

$$I_Gain = G * Ki * T/Ti \text{ (Note: If Ti is zero, I_Gain = 0)}$$

$$D_Gain = G * Kd * Td / T$$

$$T = Loop_Update_Rate * 0.001$$

Equation 4 – PID Control Algorithm

Each system will have to be turned for the optimum output response. Response times, overshoots and other variables will have to be decided by the customer using an appropriate PID tuning strategy. Axiomatic is not responsible for tuning the control system.

1.6. Lookup Table Function Block

Lookup Tables are used to give output response up to 10 slopes per input. If more than 10 slopes are required, A Programmable Logic Block can be used to combine up to three tables to get 30 slopes as described in Section 1.7.

Lookup tables have three differing modes defined by “**X-Axis Type**” setpoint, given in Table 16. Option ‘0 – Data Response’ is the normal mode where block input signal is selected with the “**X-Axis Source**” and “**X-Axis Number**” setpoints and X values present directly input signal values. With option ‘1 – Time Response’ the input signal is time and X values present time in milliseconds. And selected input signal is used as digital enable. Option ‘2 – Enabled Data Response’ works like the Data Response option with a configurable threshold for the input signal to enable and disable the output. The output value in ‘disabled’ mode can be defined by the user with “**Output value when disabled**” setpoint.

The Enabled Data Response X-Axis type is targeted for joystick applications, where it is needed to disable the output drive when joystick position exceeds a certain threshold and can be enabled only when the joystick is returned to neutral position.

0	<i>Data Response</i>
1	<i>Time Response</i>
2	<i>Enabled Data Response</i>

Table 16 – X-Axis Type Options

The slopes are defined with (x, y) points and associated point response. X value presents input signal value and Y value corresponding Lookup Table output value. “PointN – Response” setpoint defines type of the slope from preceding point to the point in question. Response options are given in Table 17. ‘Ramp To’ gives a linearized slope between points, whereas ‘Jump to’ gives a point to point response, where any input value between X_{N-1} and X_N will result Lookup Table output being Y_N . “Point0 – Response” is always ‘Jump To’ and cannot be edited. Choosing ‘Ignored’ response causes associated point and all the following points to be ignored.

0	<i>Ignore</i>
1	<i>Ramp To</i>
2	<i>Jump To</i>

Table 17 – PointN – Response Options

In case Time Response is used, the “**Autocycle**” setpoint can be used for generating a repeating, cyclic output while the selected control source enables the time response output of the particular lookup table.

The X values are limited by minimum and maximum range of the selected input source if the source is one of the Input Blocks or a Math Function Block. For the fore mentioned sources X-Axis data will be redefined when ranges are changed, therefore inputs should be adjusted before changing X-Axis values. For other sources Xmin and Xmax are 0 and 10,000. The X-Axis is constraint to be in rising order, thus value of the next index is greater than or equal to preceding

one. Therefore, when adjusting the X-Axis data, it is recommended that X_{10} is changed first, then lower indexes in descending order.

$$X_{min} \leq X_0 \leq X_1 \leq X_2 \leq X_3 \leq X_4 \leq X_5 \leq X_6 \leq X_7 \leq X_8 \leq X_9 \leq X_{10} \leq X_{max}$$

The Y-Axis has no constraints on the data it presents, thus inverse, decreasing, increasing or other response can be easily established. The Smallest of the Y-Axis values is used as Lookup Table output min and the largest of the Y-Axis values is used as Lookup Table output max (i.e. used as X_{min} and X_{max} values in linear calculation, Section 1.3). Ignored points are not considered for min and max values.

1.7. Programmable Logic Function Block

The Programmable Logic Function Block is very powerful tool. A Programmable Logic can be linked to up to three Lookup Tables, any of which would be selected only under given conditions. Thus, output of a Programmable Logic at any given time will be the output of the Lookup Table selected by defined logic. Therefore, up to three different responses to the same input, or three different responses to different inputs, can become the input to another function block.

To enable any one of the Programmable Logic blocks, the “**Programmable Logic Enabled**” setpoint must be set to ‘*True*’. By default, all Logic blocks are disabled.

The three associated tables are selected by setting “**Table X – Lookup Table Block Number**” setpoint to desired Lookup Table number, for example selecting 1 would set Lookup Table 1 as TableX.

For each TableX there are three conditions that define the logic to select the associated Lookup Table as Logic output. Each condition implements function *Argument1 Operator Argument2* where Operator is logical operator defined by setpoint “**Table X – Condition Y, Operator**”. Setpoint options are listed in Table 18. Condition arguments are selected with “**Table x – Condition Y, Argument Z Source**” and “**Table x – Condition Y, Argument Z Number**” setpoints. If ‘0 – Control not Used’ option is selected as “**Table x – Condition Y, Argument Z Source**” the argument is interpreted as 0.

0	<i>=, Equal</i>
1	<i>!=, Not Equal</i>
2	<i>>, Greater Than</i>
3	<i>>=, Greater Than or Equal</i>
4	<i><, Less Than</i>
5	<i><=, Less Than or Equal</i>

Table 18 – Table X – Condition Y, Operator Options

The three conditions are evaluated and if the result satisfies logical operation defined with “**Table X – Conditions Logical Operator**” setpoint, given in Table 19, the associated Lookup Table is selected as output of the Logical block. Option ‘0 – Default Table’ selects associated Lookup Table in all conditions.

0	<i>Default Table (Table1)</i>
1	<i>Cnd1 And Cnd2 And Cnd3</i>
2	<i>Cnd1 Or Cnd2 Or Cnd3</i>
3	<i>(Cnd1 And Cnd2) Or Cnd3</i>
4	<i>(Cnd1 Or Cnd2) And Cnd3</i>

Table 19 – Table X – Conditions Logical Operator Options

The three logical operations are evaluated in order and the first to satisfy gets selected, thus if Table1 logical operation is satisfied, the Lookup Table associated with Table1 gets selected regardless of two other logical operations. In addition, if none of the logical operations is satisfied the Lookup Table associated with Table1 gets selected.

1.8. Math Function Block

There are four mathematical function blocks that allow the user to define basic algorithms. A math function block can take up to five input signals. Each input is then scaled according to the associated limit and scaling setpoints.

Inputs are converted into percentage value based on the “**Function X Input Y Minimum**” and “**Function X Input Y Maximum**” values selected. For additional control the user can also adjust the “**Function X Input Y Scaler**”. By default, each input has a scaling ‘weight’ of 1.0 However, each input can be scaled from -1.0 to 1.0 as necessary before it is applied in the function.

For example, in the case where the user may want to combine two inputs such that a joystick (Input 1) is the primary control of an output, but the speed can be incremented or decremented based on a potentiometer (Input 2), it may be desired that 75% of the scale is controlled by the joystick position, while the potentiometer can increase or decrease the min/max output by up to 25%. In this case, Input 1 would be scaled with 0.75, while Input 2 uses 0.25. The resulting addition will give a command from 0 to 100% based on the combined positions of both inputs.

A mathematical function block includes four selectable functions, which each implements equation $A \text{ operator } B$, where A and B are function inputs and operator is function selected with setpoint “**Math function X Operator**”. Setpoint options are presented in Table 20. The functions are connected, so that result of the preceding function goes into Input A of the next function. Thus Function 1 has both Input A and Input B selectable with setpoints, where Functions 2 to 4 have only Input B selectable. Input is selected by setting “**Function X Input Y Source**” and “**Function X Input Y Number**”. If “**Function X Input B Source**” is set to 0 ‘Control not used’ signal goes through function unchanged.

$$\text{Math Block Output} = (((A1 \text{ op1 } B1) \text{ op2 } B2) \text{ op3 } B3) \text{ op4 } B4$$

0	=, True when InA equals InB
1	!=, True when InA not equal InB
2	>, True when InA greater than InB
3	>=, True when InA greater than or equal InB
4	<, True when InA less than InB
5	<=, True when InA less than or equal InB
6	OR, True when InA or InB is True
7	AND, True when InA and InB are True
8	XOR, True when either InA or InB is True, but not both
9	+, Result = InA plus InB
10	-, Result = InA minus InB
11	x, Result = InA times InB
12	/, Result = InA divided by InB
13	MIN, Result = Smallest of InA and InB
14	MAX, Result = Largest of InA and InB

Table 20 – Math function X Operator Options

For logic operations (6, 7, 8) scaled input greater or equal to 1 is treated as TRUE. For logic operations (0 to 8), the result of the function will always be 0 (FALSE) or 1 (TRUE). For the

arithmetic functions (9 to 14), it is recommended to scale the data such that the resulting operation will not exceed full scale (0 to 100%) and saturate the output result.

When dividing, a zero divider will always result in a 100% output value for the associated function.

Lastly the resulting mathematical calculation, presented as a percentage value, can be scaled into the appropriate physical units using the “**Math Output Minimum Range**” and “**Math Output Maximum Range**” setpoints. These values are also used as the limits when the Math Function I selected as the input source for another function block.

1.9. DTC React

The DTC React function block is a very simple function which will allow a received DTC, sent from another ECU on a DM1 message, to disable an output or be used as input to another type of logic block. Up to five SPN/FMI combinations can be selected.

Should a DM1 message be received with the SPN/FMI combination defined, the corresponding DTC State will be set to ON. Once ON, if the same SPN/FMI combination has not been received again after 3 seconds, the DTC State will be reset to OFF.

The DTC could be used as a digital input for any function block as appropriate.

1.10. CAN Transmit Message Function Block

The CAN Transmit function block is used to send any output from another function block (i.e. input, CAN receive) to the J1939 network. The 2In2Out Controller has eight CAN Transmit Messages and each message has four completely user defined signals.

1.10.1. CAN Transmit Message Setpoints

Each CAN Transmit Message setpoint group includes setpoints that effect the whole message and are thus mutual for all signals of the message. These setpoints are presented in this section. The setpoints that configure an individual signal are presented in next section.

The “**Transmit PGN**” setpoint sets PGN used with the message. **User should be familiar with the SAE J1939 standard, and select values for PGN/SPN combinations as appropriate from section J1939/71.**

“**Repetition Rate**” setpoint defines the interval used to send the message to the J1939 network. If the “**Repetition Rate**” is set to zero, the message is disabled unless it shares its PGN with another message. In case of a shared PGN repetition rate of the LOWEST numbered message are used to send the message ‘bundle’.



At power up, transmitted message will not be broadcasted until after a 5 second delay. This is done to prevent any power up or initialization conditions from creating problems on the network.

By default, all messages are sent on Proprietary B PGNs as broadcast messages. Thus “**Transmit Message Priority**” is always initialized to 6 (low priority) and the “**Destination Address**” setpoint is not used. This setpoint is only valid when a PDU1 PGN has been selected, and it can be set either to the Global Address (0xFF) for broadcasts, or sent to a specific address as setup by the user.

1.10.2. CAN Transmit Signal Setpoints

Each CAN transmit message has four associated signals, which define data inside the Transmit message. “**Control Source**” setpoint together with “**Control Number**” setpoint define the signal source of the message. “**Control Source**” and “**Control Number**” options are listed in Table 21. Setting “**Control Source**” to ‘*Control Not Used*’ disables the signal.

“**Transmit Data Size**” setpoint determines how many bits signal reserves from the message. “**Transmit Data Index in Array**” determines in which of 8 bytes of the CAN message LSB of the signal is located. Similarly, “**Transmit Bit Index in Byte**” determines in which of 8 bits of a byte the LSB is located. These setpoints are freely configurable, thus **it is the User’s responsibility to ensure that signals do not overlap and mask each other.**

“**Transmit Data Resolution**” setpoint determines the scaling done on the signal data before it is sent to the bus. “**Transmit Data Offset**” setpoint determines the value that is subtracted from the signal data before it is scaled. Offset and Resolution are interpreted in units of the selected source signal.

1.11. CAN Receive Function Block

The CAN Receive function block is designed to take any SPN from the J1939 network, and use it as an input to another function block (i.e. Outputs).

The “**Receive Message Enabled**” is the most important setpoint associated with this function block and it should be selected first. Changing it will result in other setpoints being enabled/disabled as appropriate. By default, ALL receive messages are disabled.

Once a message has been enabled, a Lost Communication fault will be flagged if that message is not received off the bus within the “**Receive Message Timeout**” period. This could trigger a Lost Communication event as described in section 1.4. To avoid timeouts on a heavily saturated network, it is recommended to set the period at least three times longer than the expected update rate. To disable the timeout feature, simply set this value to zero, in which case the received message will never trigger a Lost Communication fault.

By default, all control messages are expected to be sent to the 2 Input 2 Output Controller on Proprietary B PGNs. However, should a PDU1 message be selected, the 2 Input 2 Output Controller can be setup to receive it from any ECU by setting the “**Specific Address that sends the PGN**” to the Global Address (0xFF). If a specific address is selected instead, then any other ECU data on the PGN will be ignored.

The “**Receive Data Size**”, “**Receive Data Index in Array (LSB)**”, “**Receive Bit Index in Byte (LSB)**”, “**Receive Resolution**” and “**Receive Offset**” can all be used to map any SPN supported by the J1939 standard to the output data of the Received function block.

As mentioned earlier, a CAN receive function clock can be selected as the source of the control input for the output function blocks. When this is case, the “**Received Data Min (Off Threshold)**” and “**Received Data Max (On Threshold)**” setpoints determine the minimum and maximum values of the control signal. As the names imply, they are also used as the On/Off thresholds for digital output types. These values are in whatever units the data is AFTER the resolution and offset is applied to CAN receive signal.

The 2 Input 2 Output Controller I/O supports up to five unique CAN Receive Messages. Defaults setpoint values are listed in section 3.12.

1.12. Available Control Sources

Many of the Function Blocks have selectable input signals, which are determined with “[Name] Source” and “[Name] Number” setpoints. Together, these setpoints uniquely select how the I/O of the various function blocks are linked together. “[Name] Source” setpoint determines the type of the source and “[Name] Number” selects the actual source if there is more than one of the same type. Available “[Name] Source” options and associated “[Name] Number” ranges are listed in Table 21. All sources, except “CAN message reception timeout”, are available for all blocks, including output control blocks and CAN Transmit messages. Thought input Sources are freely selectable, not all options would make sense for any input, and it is up to the user to program the controller in a logical and functional manner.

Sources	Number Range	Notes
<i>0: Control Not Used</i>	N/A	When this is selected, it disables all other setpoints associated with the signal in question.
<i>1: Received CAN Message</i>	1 to 8	User must enable the function block, as it is disabled by default.
<i>2: Input Measured</i>	1 to 4	1 – Universal Signal Input1 2 – Universal Signal Input2 3 – Magnetic Input (Input3) 4 – Encoder Input (Input4)
<i>3: PID Function Block</i>	1 to 2	User must enable the function block, as it is disabled by default.
<i>4: Lookup Table</i>	1 to 8	User must enable the function block, as it is disabled by default.
<i>5: Programmable Logic Block</i>	1 to 4	User must enable the function block, as it is disabled by default.
<i>6: Math Function Block</i>	1 to 4	User must enable the function block, as it is disabled by default.
<i>7: Control Constant Data</i>	1 to 15	1 = FALSE, 2 = TRUE, 3 to 15 = User Selectable
<i>8: Diagnostic Trouble Code</i>	1 to 5	Will only be valid if the corresponding DTC has a non-zero SPN
<i>9: Inching Control</i>	N/A	User must enable the function block, as it is disabled by default.
<i>10: Output Target Value</i>	1 to 4	1 – Universal Signal Output 1 2 – Universal Signal Output 2

		3 – Universal Signal Output 1 frequency with Mixed type 4 – Universal Signal Output 2 frequency with Mixed type used in Output Diagnostics, can be mapped to a CAN Transmit Message.
11: Output Feedback	1 to 4	1 – Universal Signal Output 1 2 – Universal Signal Output 2 3 – Universal Signal Output 1 frequency with Mixed type 4 – Universal Signal Output 2 frequency with Mixed type
12: Power Supply Measured	N/A	Measured power supply value in Volts, used in Power Supply Diagnostics, can be mapped to a CAN Transmit Message.
13: Processor Temperature Measured	N/A	Measured processor temperature in °C, used in Over Temperature Diagnostics, can be mapped to a CAN Transmit Message.
14: Receive Message Timeout	N/A	Only available in Diagnostic blocks.

Table 21 – Available Control Sources and Numbers

If a non-digital signal is selected to drive a digital input, the signal is interpreted to be OFF at or below the minimum of selected source and ON at or above the maximum of the selected source, and it will not change in between those points. Thus, analog to digital interpretation has a built-in hysteresis defined by minimum and maximum of the selected source, as shown in Figure 3. For example, Universal Input signal is interpreted to be ON at or above “Maximum Range” and OFF at or below “Minimum Range”.

Control Constant Data has no unit nor minimum and maximum assigned to it, thus user must assign appropriate constant values according to intended use.

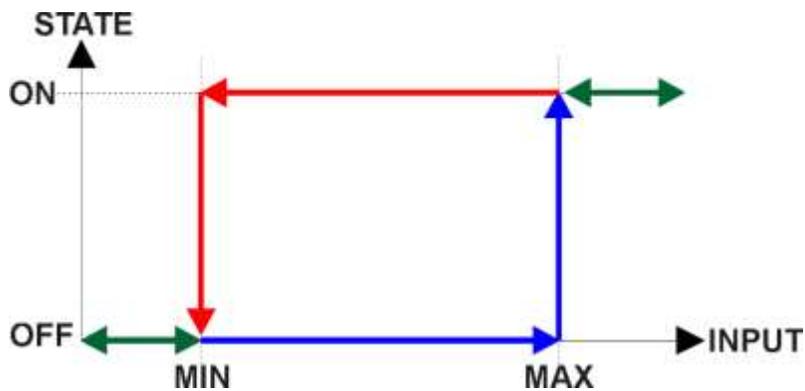


Figure 3 – Analog source to Digital input

1.13. Inching Control Block

The Inching Control Block provides fast and easy setup to control output with dual input. The Inching Control Block has two selectable inputs: Increasing Input, selected with “**IncInput Source**” and “**IncInput Number**” setpoints, and Decreasing Input, selected with “**DecInput Source**” and “**DecInput Number**” setpoints. Both inputs of the block are digital, thus when a non-digital signal is selected as an input it is interpreted in a manner described in section 1.12. The Control implements a xor logic, where output value increases when incrementing input is ON, decreases when decreasing input is ON and is held in current value while both inputs are ON or OFF, as shown in Table 22. Output of the control block is a value between 0 and 100 (%).

Increasing Input	Decreasing Input	Output
OFF	OFF	HOLD
ON	OFF	INCREASE
OFF	ON	DECREASE
ON	ON	HOLD

Table 22 – Inching Control Logic

Each input has a selectable mode that defines how the control block output responses when an input is ON. In ‘*Ramp*’ mode the output continuously ramps increasing towards maximum (100) or ramps decreasing towards minimum (0), while an input signal is ON. In ‘*Notch*’ mode the output increases by a set notch value, or decreases by a set notch value, when an input signal state changes from OFF to ON. The modes are selected with “**Inc Response**” and “**Dec Response**” setpoints. Ramp times are defined with setpoints “**Inc Ramp**” and “**Dec Ramp**”. And notch values are set with “**Inc Notch**” and “**Dec Notch**” setpoints.

0	<i>Ramp</i>
1	<i>Notch</i>

Table 23 – Inc Response and Dec Response Options

After a power cycle, enabled Inching Control Block output holds the value set with “**Start Value**” setpoint until input turns ON.

2. OVERVIEW OF J1939 FEATURES

The software was designed to provide flexibility to the user with respect to messages sent from the ECU by providing:

- Configurable ECU Instance in the NAME (to allow multiple ECUs on the same network)
- Configurable Input Parameters
- Configurable PGN and Data Parameters
- Configurable Diagnostic Messaging Parameters, as required
- Diagnostic Log, maintained in non-volatile memory

2.1. Introduction to Supported Messages

The ECU is compliant with the standard SAE J1939, and supports following PGNs from the standard.

From J1939-21 – Data Link Layer

- Request 59904 0x00EA00
- Acknowledgement 59392 0x00E800
- Transport Protocol – Connection Management 60416 0x00EC00
- Transport Protocol – Data Transfer Message 60160 0x00EB00
- Proprietary B from 65280 0x00FF00
to 65535 0x00FFFF
to 65535 0x00FFFF

From J1939-73 – Diagnostics

- DM1 – Active Diagnostic Trouble Codes 65226 0x00FECA
- DM2 – Previously Active Diagnostic Trouble Codes 65227 0x00FECB
- DM3 – Diagnostic Data Clear/Reset for Previously Active DTCs 65228 0x00FECC
- DM11 – Diagnostic Data Clear/Reset for Active DTCs 65235 0x00FED3
- DM14 – Memory Access Request 55552 0x00D900
- DM15 – Memory Access Response 55296 0x00D800
- DM16 – Binary Data Transfer 55040 0x00D700

From J1939-81 – Network Management

- Address Claimed/Cannot Claim 60928 0x00EE00
- Commanded Address 65240 0x00FED8

From J1939-71 – Vehicle Application Layer

- ECU Identification Information 64965 0x00FDC5
- Software Identification 65242 0x00FEDA
- Component Identification 65259 0x00FEEB

None of the application layer PGNs are supported as part of the default configurations, but they can be selected as desired for transmit function blocks.

Setpoints are accessed using standard Memory Access Protocol (MAP) with proprietary addresses. The Electronic Assistant (EA) allows for quick and easy configuration of the unit over CAN network.

2.2. NAME, Address and Identification Information

The 2In2Out Controller has the following default for the J1939 NAME. The user should refer to the SAE J1939/81 standard for more information on these parameters and their ranges.

Arbitrary Address Capable	Yes
Industry Group	0, Global
Vehicle System Instance	0
Vehicle System	0, Non-specific system
Function	126, I/O Controller
Function Instance	1, Axiomatic AX130540
ECU Instance	0, First Instance
Manufacture Code	162, Axiomatic Technologies
Identity Number	Variable, uniquely assigned during factory programming for each ECU

The ECU Instance is a configurable setpoint associated with the NAME. Changing this value will allow multiple ECUs of this type to be distinguishable from one another when they are connected on the same network.

The default value of the “ECU Address” setpoint is 128 (0x80), which is the preferred starting address for self-configurable ECUs as set by the SAE in J1939 tables B3 and B7. The EA will allow the selection of any address between 0 and 253. ***It is user’s responsibility to select an address that complies with the standard.*** The user must also be aware that since the unit is arbitrary address capable, if another ECU with a higher priority NAME contends for the selected address, the 2In2Out Controller will continue select the next highest address until it finds one that it can claim. See J1939/81 for more details about address claiming.

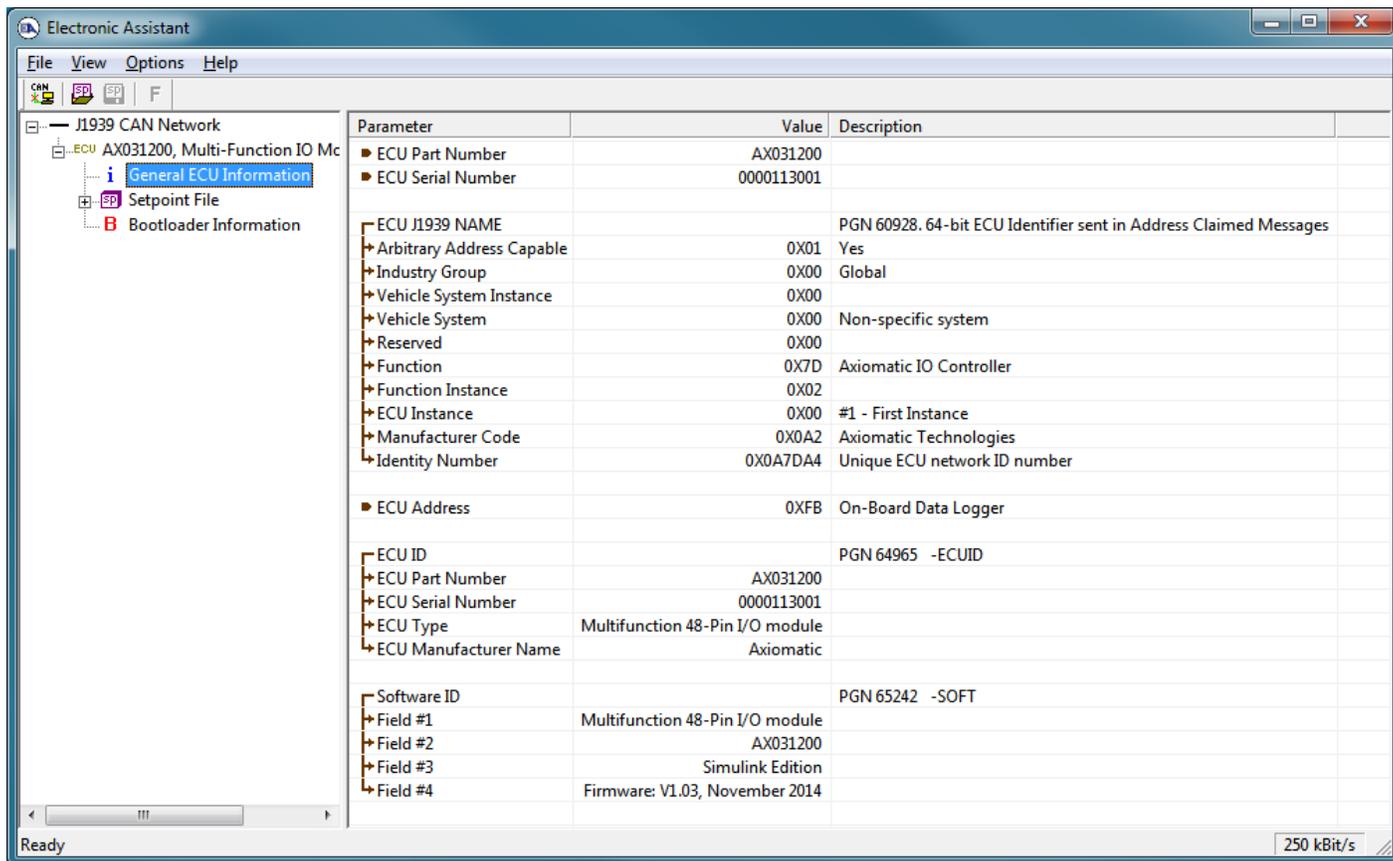


Figure 4 – General ECU Information

ECU Identification Information

PGN 64965	ECU Identification Information	-ECUID	
Transmission Repetition Rate:	On request		
Data Length:	Variable		
Extended Data Page:	0		
Data Page:	0		
PDU Format:	253		
PDU Specific:	197 PGN Supporting Information:		
Default Priority:	6		
Parameter Group Number:	64965 (0x00FDC5)		
Start Position	Length	Parameter Name	SPN
a	Variable	ECU Part Number, Delimiter (ASCII “*”)	2901
b	Variable	ECU Serial Number, Delimiter (ASCII “*”)	2902
c	Variable	ECU Location, Delimiter (ASCII “*”)	2903
d	Variable	ECU Type, Delimiter (ASCII “*”)	2904
e	Variable	ECU Manufacturer Name, Delimiter (ASCII “*”)	4304
(a)*(b)*(c)*(d)*(e)*			

Software Identifier

PGN 65242	Software Identification	-SOFT	
Transmission Repetition Rate:	On request		
Data Length:	Variable		
Extended Data Page:	0		
Data Page:	0		
PDU Format:	254		
PDU Specific:	218 PGN Supporting Information:		
Default Priority:	6		
Parameter Group Number:	65242 (0x00FEDA)		
Start Position	Length	Parameter Name	SPN
1	1 Byte	Number of software identification fields	965
2-n	Variable	Software identification(s), Delimiter (ASCII “*”)	234

Byte 1 is set to 5, and the identification fields are as follows.

(Part Number)*(Version)*(Date)*(Owner)*(Description)

The EA shows all this information in “General ECU Information”, as shown in Figure 4.

Note: The information provided in the Software ID is available for any J1939 service tool which supports the PGN -SOFT

Component Identification

PGN 65259	Component Identification	-CI	
Transmission Repetition Rate:	On request		
Data Length:	Variable		
Extended Data Page:	0		
Data Page:	0		
PDU Format:	254		
PDU Specific:	235 PGN Supporting Information:		
Default Priority:	6		
Parameter Group Number:	65259 (0x00FEED)		
Start Position	Length	Parameter Name	SPN
a	1-5 Byte	Make, Delimiter (ASCII “*”)	586
b	Variable	Model, Delimiter (ASCII “*”)	587
c	Variable	Serial Number, Delimiter (ASCII “*”)	588
d	Variable	Unit Number (Power Unit), Delimiter (ASCII “*”)	233
(a)*(b)*(c)*(d)*(e)*			

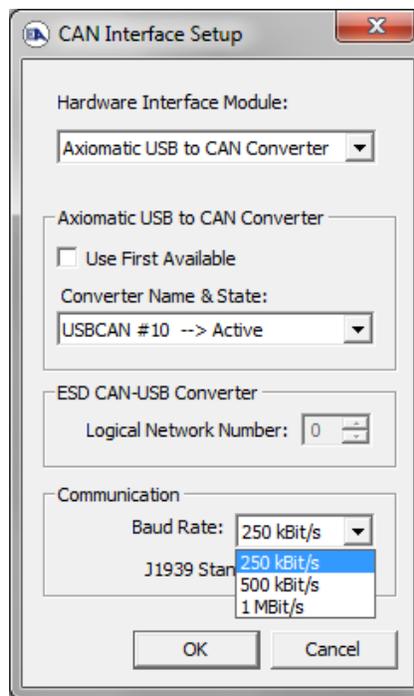
3. ECU SETPOINTS ACCESSED WITH ELECTRONIC ASSISTANT

This section describes in detail each setpoint, and their default and ranges. Default values presented in tables are values used when setpoint in question is active. Many of the setpoints are dependent on other setpoints and they may not be active by default. Associated Figures show screen capture of initial operation, however some of the setpoints are not in default condition as they are set differently to activate more setpoints for the image. The setpoints are divided into setpoint groups as they are shown in EA. For more information on how each setpoint is used by 6 Input 5 Output Valve controller, refer to the relevant section in this user manual.

3.1. Accessing the ECU Using EA

ECU P/N AX130540 is provided with Automatic Baud Rate Detection Process (Auto Baud Rate). AX130540 can be classified as Adjustable Baud Rate Only Temporarily Installed ECU with Silent Baud Discovery Mode, described in J1939/16. Each time ECU is powered on Silent Baud Discovery Mode is utilized to select the CAN bus baud rate. Supported baud rates are 250 kbit/s, 500 kbit/s and 1 Mbit/s.

The CAN Interface Setup can be found from “Options” menu in EA.



3.2. J1939 Network Parameters

“ECU Instance Number” and “ECU Address” setpoints and their effect are defined in Section 2.2.

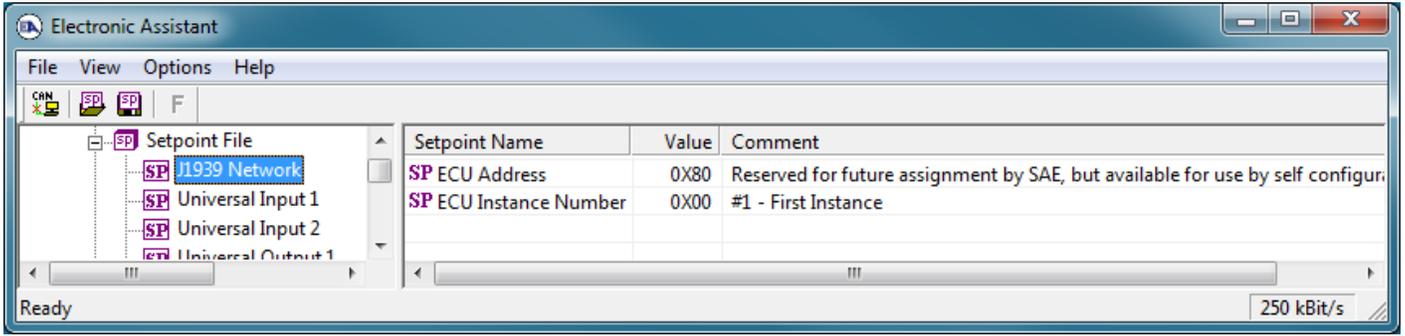


Figure 5 – Screen Capture of J1939 Setpoints

Name	Range	Default	Notes
ECU Address	0x80	0-253	Preferred address for a self-configurable ECU
ECU Instance	0-7	0x00	Per J1939-81

Table 24 – J1939 Network Setpoints

If non-default values for the “**ECU Instance Number**” or “**ECU Address**” are used, they will be mirrored during a setpoint file flashing, and will only take effect once the entire file has been downloaded to the unit. After the setpoint flashing is complete, the unit will claim the new address and/or re-claim the address with the new NAME. If these setpoints are changing, it is recommended to close and re-open the CAN connection on EA after the file is loaded so that only the new NAME and address are showing in the J1939 CAN Network ECU list.

3.3. Universal Signal Input Setpoints

The Universal Signal Inputs are defined in Section 1.1. Please refer there for detailed information about how all these setpoints are used.

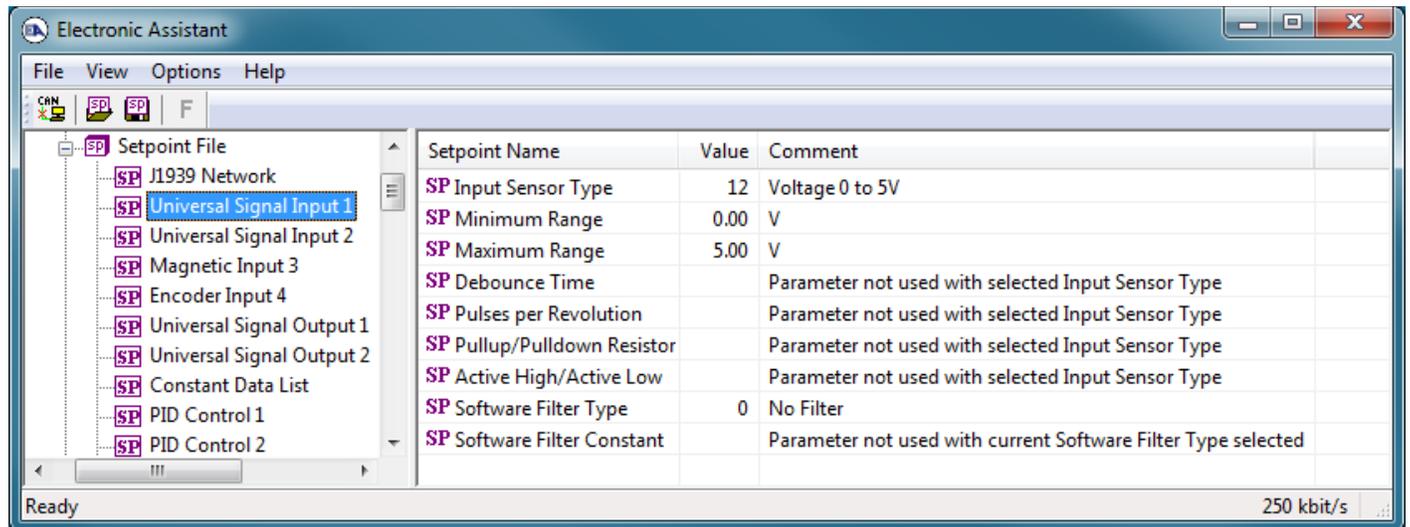


Figure 6 – Screen Capture of Universal Signal Input Setpoints

Name	Range	Default	Notes
Input Sensor Type	Drop List	Voltage 0 to 5V	See Table 1
Minimum Range	From Minimum Error to Maximum Range	Depends on Input Sensor Type	
Maximum Range	From Minimum Range to Maximum Error	Depends on Input Sensor Type	
Debounce Time	Drop List	None	See Table 2
Pulse per Revolution	0 to 1.00	1	See Section 1.1
Pullup/Pulldown Resistor	Drop List	10kΩ Pulldown	See Table 3
Active High/Active Low	Drop List	Active High	See Table 4
Software Filter Type	Drop List	No Filtering	See Section 1.2
Software Filter Constant	1..1000	1	

Table 25 – Universal Signal Input Setpoints

3.4. Magnetic Input and Encoder Input Setpoints

Magnetic Input and Encoder Input setpoints function similar as Universal Signal Input Setpoints above. Universal Signal Inputs are presented in Section 1.1. Please refer there for detailed information about how all these setpoints are used.

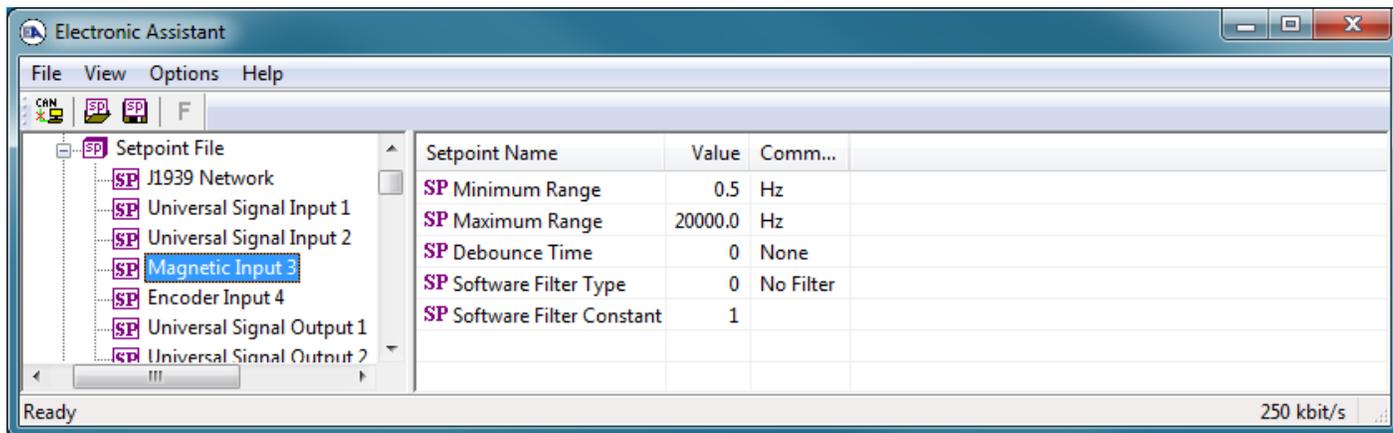


Figure 7 – Screen Capture of Universal Signal Input Setpoints

Name	Range	Default	Notes
Minimum Range	0.5 Hz to Maximum Range	0.5 Hz	
Maximum Range	From Minimum Range to 20000 Hz	20000 Hz	
Debounce Time	Drop List	None	See Table 2
Software Filter Type	Drop List	No Filtering	See Section 1.2
Software Filter Constant	1..1000	1	

Table 26 – Universal Signal Input Setpoints

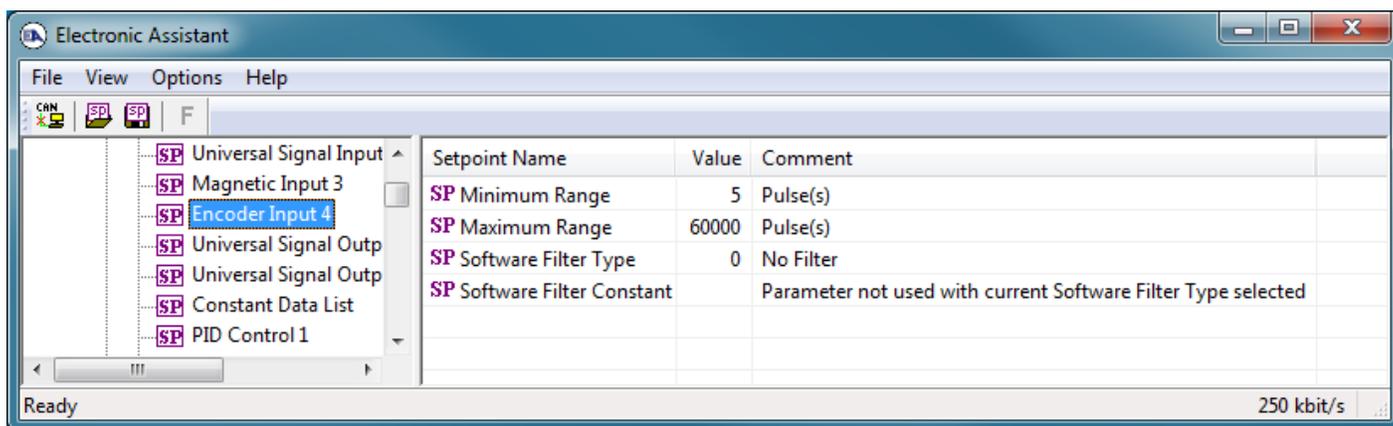


Figure 8 – Screen Capture of Universal Signal Input Setpoints

Name	Range	Default	Notes
Minimum Range	1 to Maximum Range	1 Pulse(s)	
Maximum Range	From Minimum Range to 600000	60000 Pulse(s)	
Active High/Active Low	Drop List	Active High	See Table 4
Software Filter Type	Drop List	No Filtering	See Section 1.2
Software Filter Constant	1..1000	1	

Table 27 – Universal Signal Input Setpoints

3.5. Universal Signal Output Setpoints

The Universal Signal Output Function Block is defined in Section 1.3. Please refer there for detailed information about how these setpoints are used. Outputs are disabled by default. To enable an output “**Output Type**” and “**Control Source**” must be chosen.

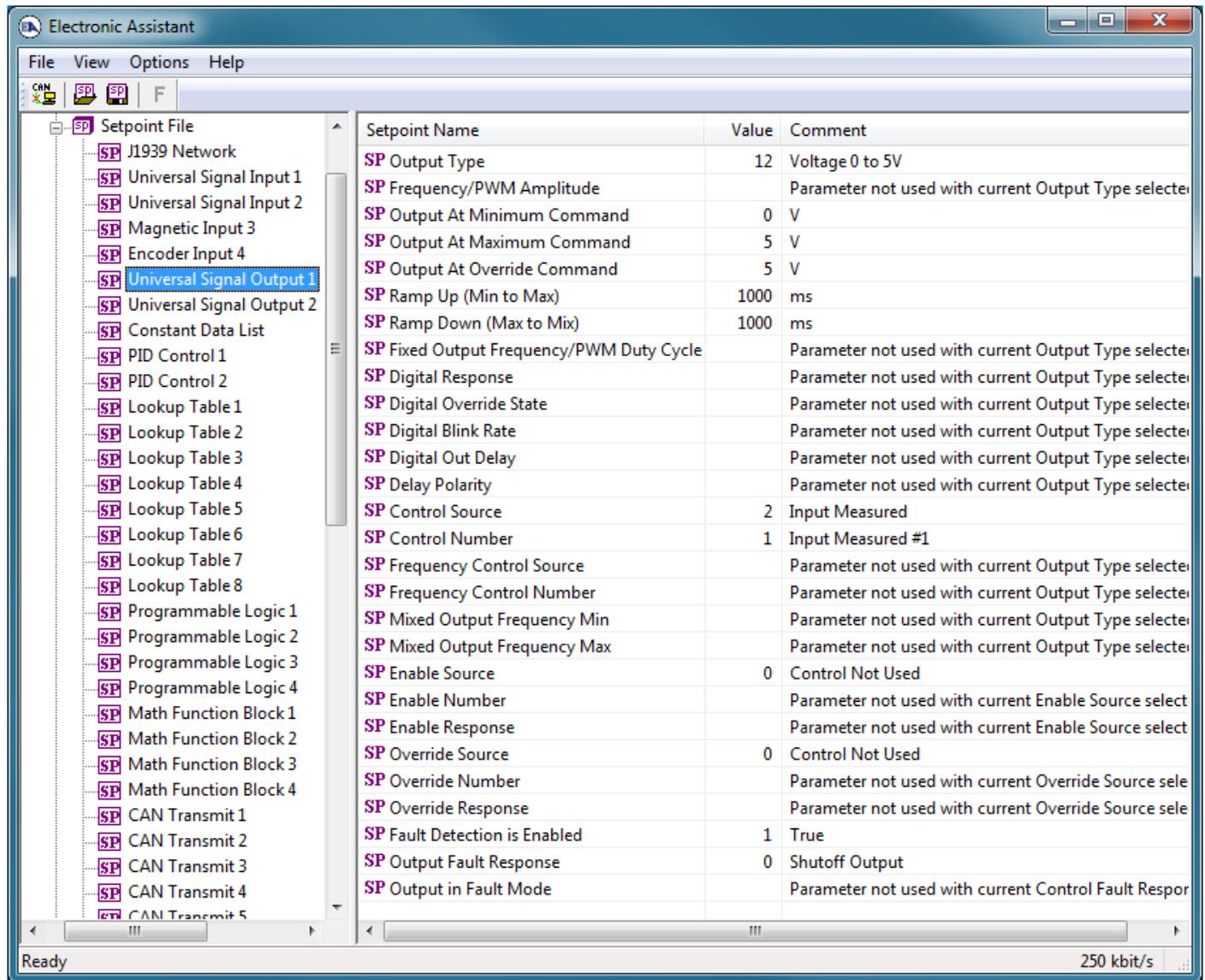


Figure 9 – Screen Capture of Universal Signal Output Setpoints

Name	Range	Default	Notes
Output Type	Drop List	Disabled	See Table 6
Frequency/PWM Amplitude	Drop List	0 to 5 V	
Output At Minimum Command	Limit to Limit	Depends on Output Type	
Output At Maximum Command	Limit to Limit	Depends on Output Type	
Output At Override Command	Limit to Limit	Depends on Output Type	
Ramp Up (Min to Max)	0 to 10 000ms	0ms	
Ramp Down (Max to Min)	0 to 10 000ms	0ms	
Fixed Output Frequency/PWM Duty Cycle	0.1 to 100 % 0.1 Hz to 50 000 Hz	50 % 250 Hz	
Digital Response	Drop List	Normal On/Off	See Table 7
Digital Override State	Drop List	ON	
Digital Blink Rate	100 to 5000 ms	1000ms	
Digital Out Delay	0 to 60000 ms	0ms	
Delay Polarity	Drop List	Rising Edge	See Table 8 Table 8 – Delay Polarity
Control Source	Drop List	Universal Input Measured	See Table 21
Control Number	Depends on control source	1	See Table 21
Frequency Control Source	Drop List	Control not used	See Table 21
Frequency Control Number	Depends on control source	1	See Table 21
Mixed Output Frequency Min	0.1 Hz to 50 000 Hz	50.0 Hz	
Mixed Output Frequency Max	0.1 Hz to 50 000 Hz	250.0 Hz	
Enable Source	Drop List	Control not used	See Table 21
Enable Number	Depends on enable source	1	See Table 21
Enable Response	Drop List	Enable When On, else Shutoff	See Table 9
Override Source	Drop List	Control not used	See Table 21
Override Number	Depends on override source	1	See Table 21
Override Response	Drop List	Override When On	See Table 10
Fault Detection is Enabled	Drop List	True	
Output Fault Response	Drop List	Shutoff Output	See Table 11
Output in Fault Mode	Limit to Limit	Depends on Output Type	

Table 28 – Universal Signal Output Setpoints

3.6. Constant Data List

The Constant Data List Function Block is provided to allow the user to select values as desired for various logic block functions.

The first two constants are fixed values of 0 (False) and signal1 (True) for use in binary logic. The remaining 13 constants are fully user programmable to any value between +/- 1 000 000. The default values (shown in Figure 10) are arbitrary and should be configured by the user as appropriate for their application.

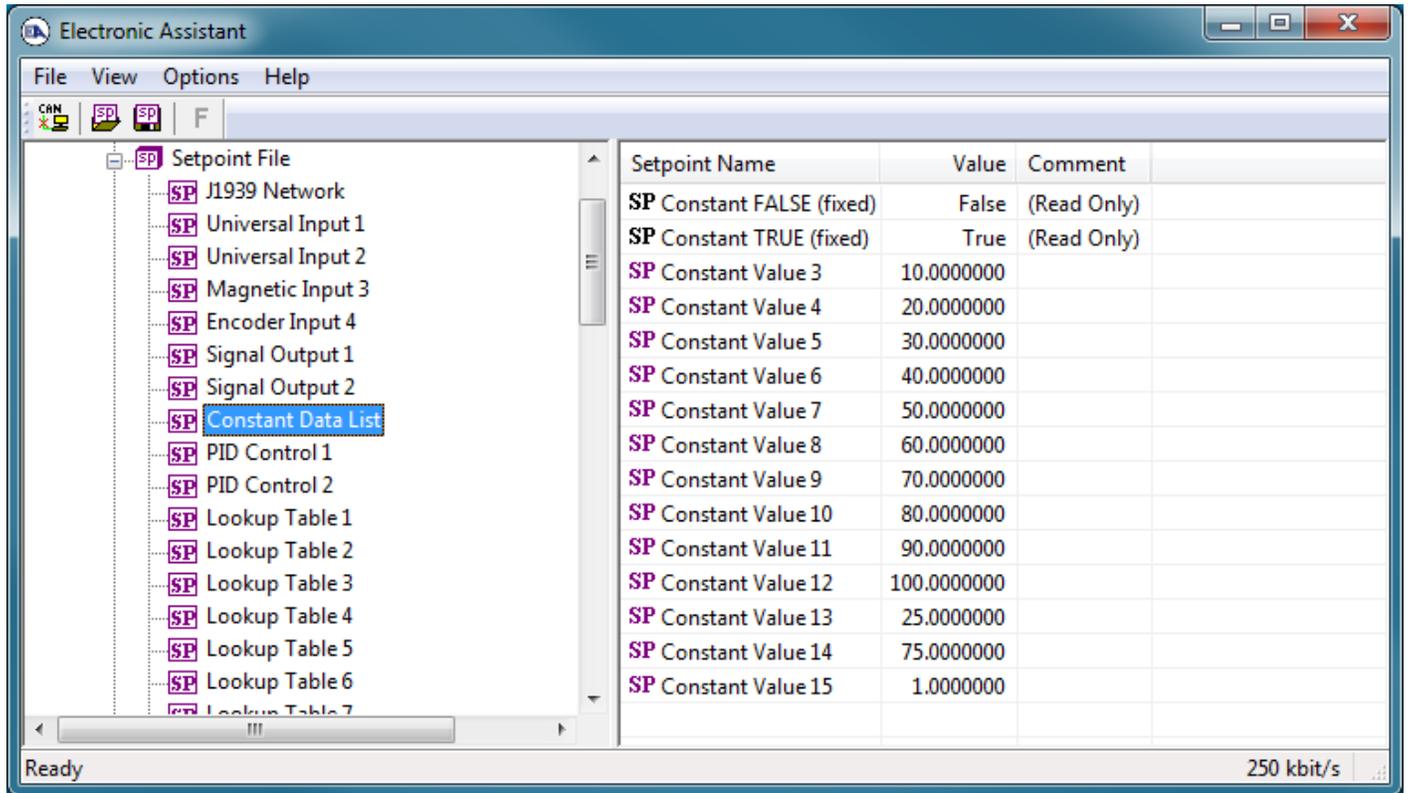


Figure 10 – Screen Capture of Constant Data List Setpoints

3.7. PID Control

The PID Control Function Block is defined in Section 1.5. Please refer there for detailed information about how all these setpoints are used.

Command Source is set to '*Control Not Used*' by default. To enable a PID Control, select appropriate "**PID Target Command Source**" and "**PID Feedback Input Source**".

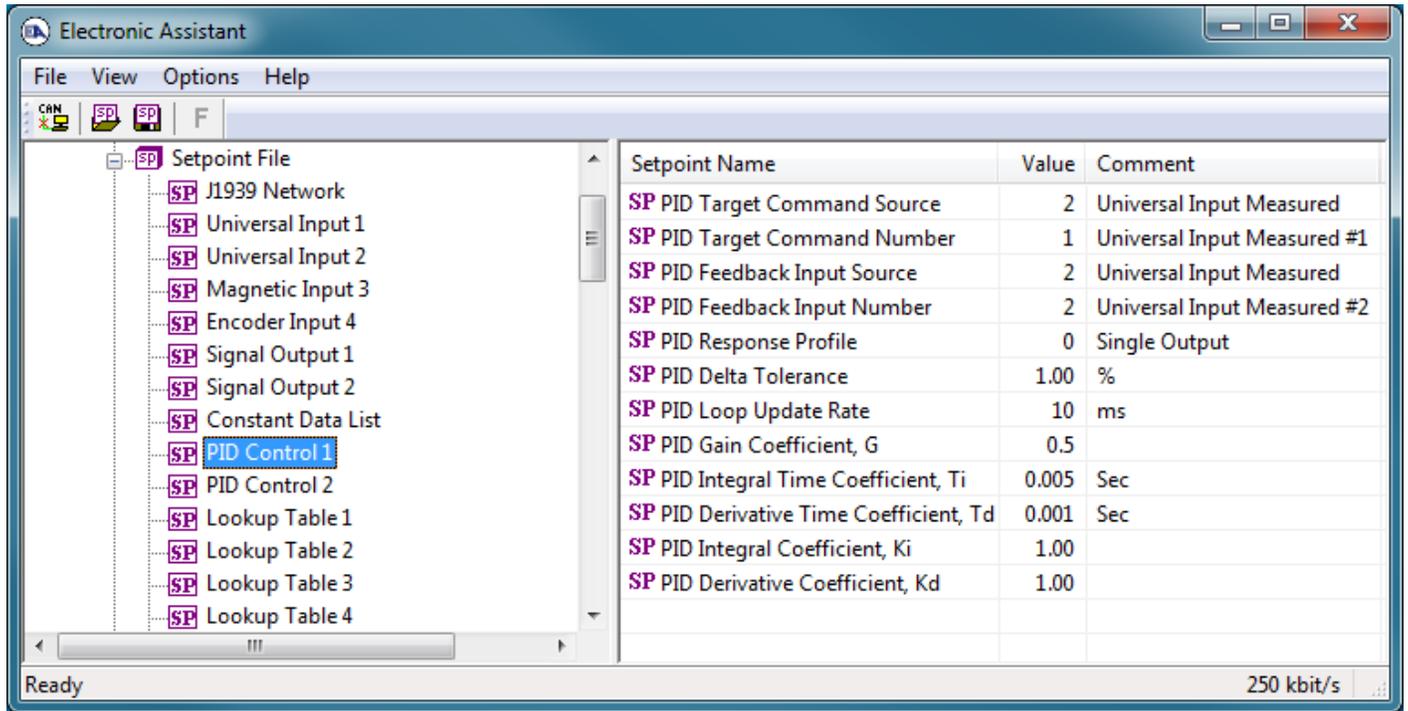


Figure 11 – Screen Capture of PID Control Setpoints

Name	Range	Default	Notes
PID Target Command Source	Drop List	Control Not Used	See Table 21
PID Target Command Number	Depends on control source	1	See Table 21
PID Feedback Input Source	Drop List	Control Not Used	See Table 21
PID Feedback Input Number	Depends on control source	1	See Table 21
PID Response Profile	Drop List	Single Output	See Table 15
PID Delta Tolerance	0 to 100	1.00 %	%
PID Loop Update Rate	1 to 60 000 ms	10ms	1 ms resolution
PID Gain Coefficient, G	0.1 to 10	0.5	See Equation 4
PID Integral Time Coefficient, Ti	0.001 to 10 Sec	0.005 Sec	0.001 Sec (1ms) resolution
PID Derivative Time Coefficient, Td	0.001 to 10 Sec	0.001 Sec	0.001 Sec (1ms) resolution
PID Integral Coefficient, Ki	0 to 10	1.00	0 disables integral, PD ctrl
PID Derivative Coefficient, Kd	0 to 10	1.00	0 disables derivative, PI ctrl

Table 29 – Programmable Logic Setpoints

3.8. Lookup Table

The Lookup Table Function Block is defined in Section 1.6 Please refer there for detailed information about how all these setpoints are used. “**X-Axis Source**” is set to ‘*Control Not Used*’ by default. To enable a Lookup Table select appropriate “**X-Axis Source**”.

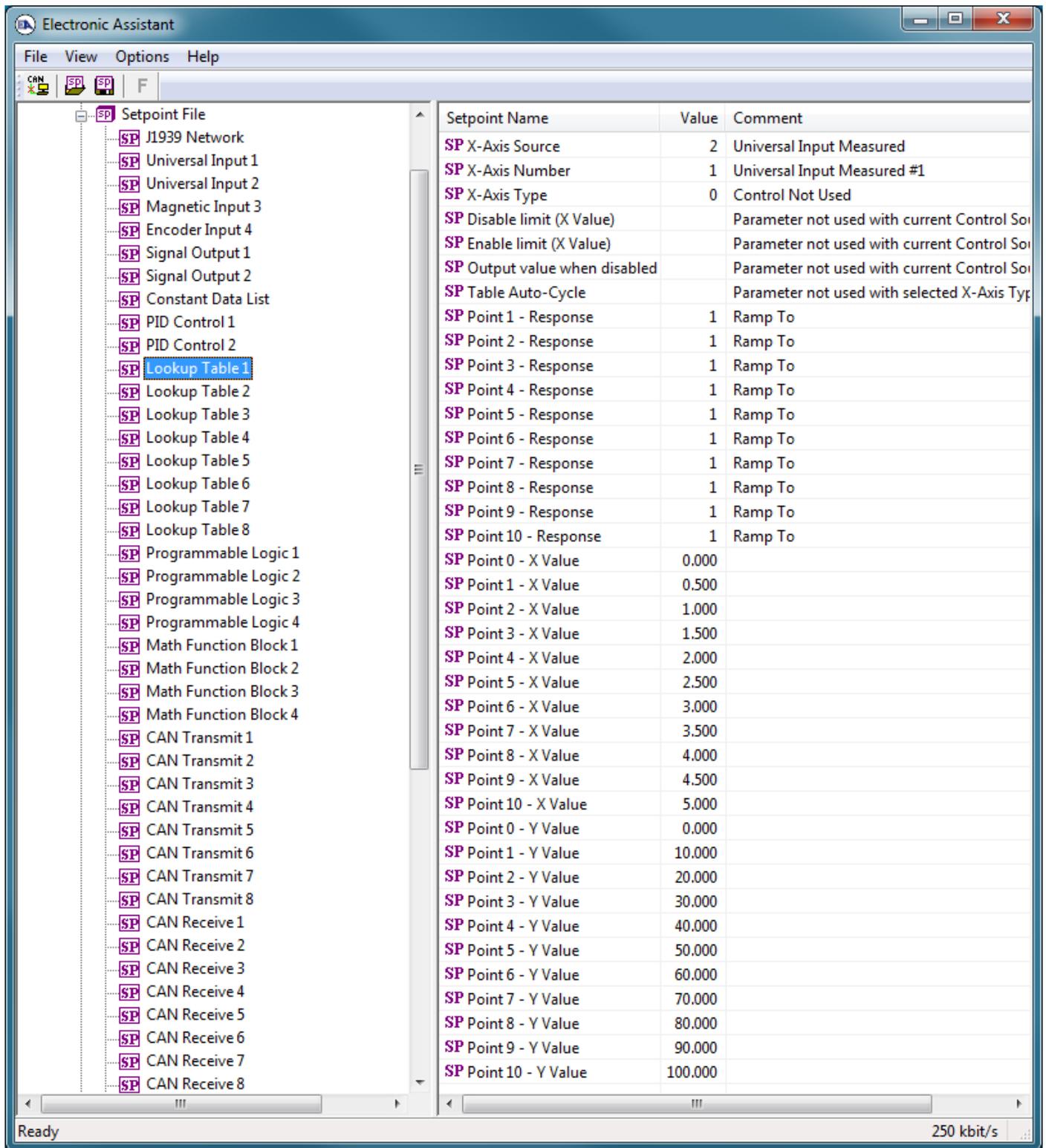


Figure 12 – Screen Capture of Lookup table Setpoints

Name	Range	Default	Notes
X-Axis Source	Drop List	Control Not Used	See Table 21
X-Axis Number	Depends on control source	1	See Table 21
X-Axis Type	Drop List	Data Response	See Table 16

Disable limit (X Value)	From X-Axis source minimum to X-Axis source maximum	X-Axis source maximum 5.000	See Section 1.6
Enable limit (X Value)	From X-Axis source minimum to X-Axis source maximum	2.500	See Section 1.6
Output value when disabled	-10 ⁶ to 10 ⁶	0.000	See Section 1.6
Table Auto-Cycle	Drop List	0	
Point 1 - Response	Drop List	Ramp To	See Table 17
Point 2 - Response	Drop List	Ramp To	See Table 17
Point 3 - Response	Drop List	Ramp To	See Table 17
Point 4 - Response	Drop List	Ramp To	See Table 17
Point 5 - Response	Drop List	Ramp To	See Table 17
Point 6 - Response	Drop List	Ramp To	See Table 17
Point 7 - Response	Drop List	Ramp To	See Table 17
Point 8 - Response	Drop List	Ramp To	See Table 17
Point 9 - Response	Drop List	Ramp To	See Table 17
Point 10 - Response	Drop List	Ramp To	See Table 17
Point 0 - X Value	From X-Axis source minimum to Point 1 - X Value	X-Axis source minimum 0.000	See Section 1.6
Point 1 - X Value	From Point 0 - X Value to Point 2 - X Value	0.500	See Section 1.6
Point 2 - X Value	From Point 1 - X Value to Point 3 - X Value	1.000	See Section 1.6
Point 3 - X Value	From Point 2 - X Value to Point 4 - X Value	1.500	See Section 1.6
Point 4 - X Value	From Point 3 - X Value to Point 5 - X Value source	2.000	See Section 1.6
Point 5 - X Value	From Point 4 - X Value to Point 6 - X Value	2.500	See Section 1.6
Point 6 - X Value	From Point 5 - X Value to Point 7 - X Value	3.000	See Section 1.6
Point 7 - X Value	From Point 6 - X Value to Point 8 - X Value	3.500	See Section 1.6
Point 8 - X Value	From Point 7 - X Value to Point 9 - X Value	4.000	See Section 1.6
Point 9 - X Value	From Point 8 - X Value to Point 10 - X Value	4.500	See Section 1.6
Point 10 - X Value	From Point 9 - X Value to X-Axis source maximum	X-Axis source maximum 5.000	See Section 1.6
Point 0 - Y Value	-10 ⁶ to 10 ⁶	0.000	
Point 1 - Y Value	-10 ⁶ to 10 ⁶	10.000	
Point 2 - Y Value	-10 ⁶ to 10 ⁶	20.000	
Point 3 - Y Value	-10 ⁶ to 10 ⁶	30.000	
Point 4 - Y Value	-10 ⁶ to 10 ⁶	40.000	
Point 5 - Y Value	-10 ⁶ to 10 ⁶	50.000	
Point 6 - Y Value	-10 ⁶ to 10 ⁶	60.000	
Point 7 - Y Value	-10 ⁶ to 10 ⁶	70.000	
Point 8 - Y Value	-10 ⁶ to 10 ⁶	80.000	
Point 9 - Y Value	-10 ⁶ to 10 ⁶	90.000	
Point 10 - Value	-10 ⁶ to 10 ⁶	100.000	

Table 30 – Lookup Table Setpoints

3.9. Programmable Logic

The Programmable Logic function block is defined in Section 1.7. Please refer there for detailed information about how all these setpoints are used. “**Programmable Logic Enabled**” is ‘*False*’ by default. To enable Logic set “**Programmable Logic Enabled**” to ‘*True*’ and select appropriate “**Argument Source**”.

Setpoint Name	Value	Comment
SP Programmable Logic Enabled	1	True
SP Table 1 - Lookup Table Block Number	1	Lookup Table 1
SP Table 1 - Conditions Logical Operator	1	Cnd1 And Cnd2 And Cnd3
SP Table 1 - Condition 1, Argument 1 Source	2	Universal Input Measured
SP Table 1 - Condition 1, Argument 1 Number	1	Universal Input Measured #1
SP Table 1 - Condition 1, Operator	0	=, Equal
SP Table 1 - Condition 1, Argument 2 Source	7	Control Constant Data
SP Table 1 - Condition 1, Argument 2 Number	3	Control Constant Data #3
SP Table 1 - Condition 2, Argument 1 Source	0	Control Not Used
SP Table 1 - Condition 2, Argument 1 Number		Parameter not used with current Control :
SP Table 1 - Condition 2, Operator		Parameter not used with current Control :
SP Table 1 - Condition 2, Argument 2 Source	0	Control Not Used
SP Table 1 - Condition 2, Argument 2 Number		Parameter not used with current Control :
SP Table 1 - Condition 3, Argument 1 Source	0	Control Not Used
SP Table 1 - Condition 3, Argument 1 Number		Parameter not used with current Control :
SP Table 1 - Condition 3, Operator		Parameter not used with current Control :
SP Table 1 - Condition 3, Argument 2 Source	0	Control Not Used
SP Table 1 - Condition 3, Argument 2 Number		Parameter not used with current Control :
SP Table 2 - Lookup Table Block Number	2	Lookup Table 2
SP Table 2 - Conditions Logical Operator	1	Cnd1 And Cnd2 And Cnd3
SP Table 2 - Condition 1, Argument 1 Source	0	Control Not Used
SP Table 2 - Condition 1, Argument 1 Number		Parameter not used with current Control :
SP Table 2 - Condition 1, Operator		Parameter not used with current Control :
SP Table 2 - Condition 1, Argument 2 Source	0	Control Not Used
SP Table 2 - Condition 1, Argument 2 Number		Parameter not used with current Control :
SP Table 2 - Condition 2, Argument 1 Source	0	Control Not Used
SP Table 2 - Condition 2, Argument 1 Number		Parameter not used with current Control :
SP Table 2 - Condition 2, Operator		Parameter not used with current Control :
SP Table 2 - Condition 2, Argument 2 Source	0	Control Not Used
SP Table 2 - Condition 2, Argument 2 Number		Parameter not used with current Control :
SP Table 2 - Condition 3, Argument 1 Source	0	Control Not Used
SP Table 2 - Condition 3, Argument 1 Number		Parameter not used with current Control :
SP Table 2 - Condition 3, Operator		Parameter not used with current Control :
SP Table 2 - Condition 3, Argument 2 Source	0	Control Not Used
SP Table 2 - Condition 3, Argument 2 Number		Parameter not used with current Control :
SP Table 3 - Lookup Table Block Number	3	Lookup Table 3
SP Table 3 - Conditions Logical Operator	1	Cnd1 And Cnd2 And Cnd3
SP Table 3 - Condition 1, Argument 1 Source	0	Control Not Used
SP Table 3 - Condition 1, Argument 1 Number		Parameter not used with current Control :

Figure 13 – Screen Capture of Programmable Logic Setpoints

Setpoint ranges and default values for Programmable Logic Blocs are listed in Table 31. Only “**Table1**” setpoint are listed, because other “**TableX**” setpoints are similar, except for the default value of the “**Lookup Table Block Number**” setpoint, which is X for “**TableX**”.

Name	Range	Default	Notes
Programmable Logic Enabled	Drop List	False	
Table1 - Lookup Table Block Number	1 to 8	Look up Table 1	
Table1 - Conditions Logical Operation	Drop List	Default Table	See Table 19
Table1 - Condition1, Argument 1 Source	Drop List	Control Not Used	See Table 21
Table1 - Condition1, Argument 1 Number	Depends on control source	1	See Table 21
Table1 - Condition1, Operator	Drop List	=, Equal	See Table 18
Table1 - Condition1, Argument 2 Source	Drop List	Control Not Used	See Table 21
Table1 - Condition1, Argument 2 Number	Depends on control source	1	See Table 21
Table1 - Condition2, Argument 1 Source	Drop List	Control Not Used	See Table 21
Table1 - Condition2, Argument 1 Number	Depends on control source	1	See Table 21
Table1 - Condition2, Operator	Drop List	=, Equal	See Table 18
Table1 - Condition2, Argument 2 Source	Drop List	Control Not Used	See Table 21
Table1 - Condition2, Argument 2 Number	Depends on control source	1	See Table 21
Table1 - Condition3, Argument 1 Source	Drop List	Control Not Used	See Table 21
Table1 - Condition3, Argument 1 Number	Depends on control source	1	See Table 21
Table1 - Condition3, Operator	Drop List	=, Equal	See Table 18
Table1 - Condition3, Argument 2 Source	Drop List	Control Not Used	See Table 21
Table1 - Condition3, Argument 2 Number	Depends on control source	1	See Table 21

Table 31 – Programmable Logic Setpoints

3.10. Math Function Block

The Math Function Block is defined in Section 1.8. Please refer there for detailed information about how all these setpoints are used. “**Math Function Enabled**” is ‘False’ by default. To enable a Math Function Block, set “**Math Function Enabled**” to ‘True’ and select appropriate “**Input Source**”.

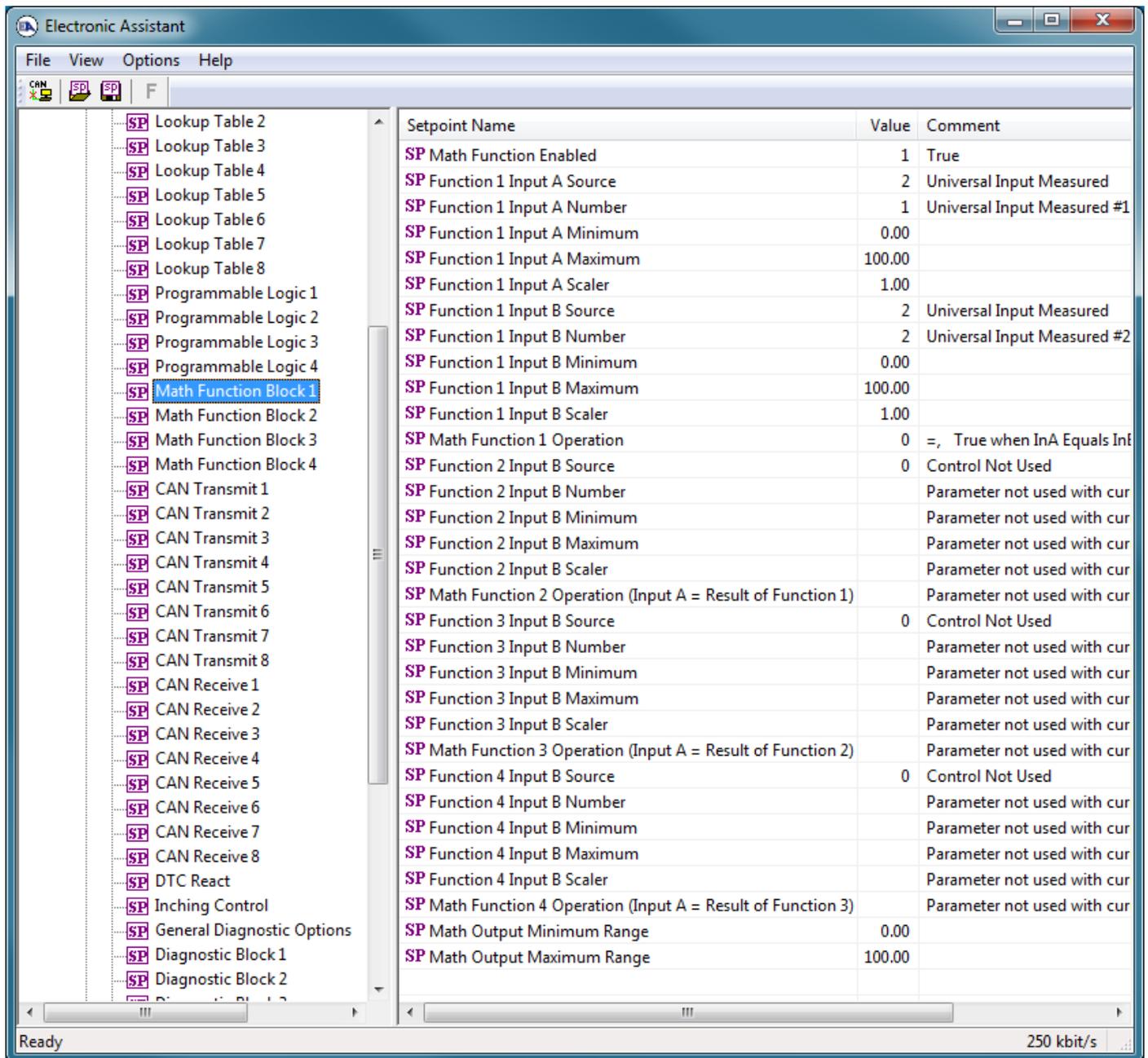


Figure 14 – Screen Capture of Math Function Block Setpoints

Name	Range	Default	Notes
Math Function Enabled	Drop List	False	
Function 1 Input A Source	Drop List	Control not used	See Table 21
Function 1 Input A Number	Depends on control source	1	See Table 21
Function 1 Input A Minimum	-10^6 to 10^6	0.0	
Function 1 Input A Maximum	-10^6 to 10^6	100.0	
Function 1 Input A Scaler	-1.00 to 1.00	1.00	
Function 1 Input B Source	Drop List	Control not used	See Table 21
Function 1 Input B Number	Depends on control source	1	See Table 21
Function 1 Input B Minimum	-10^6 to 10^6	0.0	
Function 1 Input B Maximum	-10^6 to 10^6	100.0	
Function 1 Input B Scaler	-1.00 to 1.00	1.00	
Math Function 1 Operation	Drop List	=, True when InA Equals InB	See Table 20
Function 2 Input B Source	Drop List	Control not used	See Table 21
Function 2 Input B Number	Depends on control source	1	See Table 21
Function 2 Input B Minimum	-10^6 to 10^6	0.0	
Function 2 Input B Maximum	-10^6 to 10^6	100.0	
Function 2 Input B Scaler	-1.00 to 1.00	1.00	
Math Function 3 Operation	Drop List	=, True when InA Equals InB	See Table 20
Function 3 Input B Source	Drop List	Control not used	See Table 21
Function 3 Input B Number	Depends on control source	1	See Table 21
Function 3 Input B Minimum	-10^6 to 10^6	0.0	
Function 3 Input B Maximum	-10^6 to 10^6	100.0	
Function 3 Input B Scaler	-1.00 to 1.00	1.00	
Math Function 3 Operation	Drop List	=, True when InA Equals InB	See Table 20
Function 4 Input B Source	Drop List	Control not used	See Table 21
Function 4 Input B Number	Depends on control source	1	See Table 21
Function 4 Input B Minimum	-10^6 to 10^6	0.0	
Function 4 Input B Maximum	-10^6 to 10^6	100.0	
Function 4 Input B Scaler	-1.00 to 1.00	1.00	
Math Function 4 Operation	Drop List	=, True when InA Equals InB	See Table 20
Math Output Minimum Range	-10^6 to 10^6	0.0	
Math Output Maximum Range	-10^6 to 10^6	100.0	

Table 32 – Math Function Setpoints

3.11. CAN Transmit Setpoints

CAN Transmit Message Function Block is presented in Section 1.10. Please refer there for detailed information how these setpoints are used. “**Transmit Repetition Rate**” is 0ms by default, thus no message will be sent.

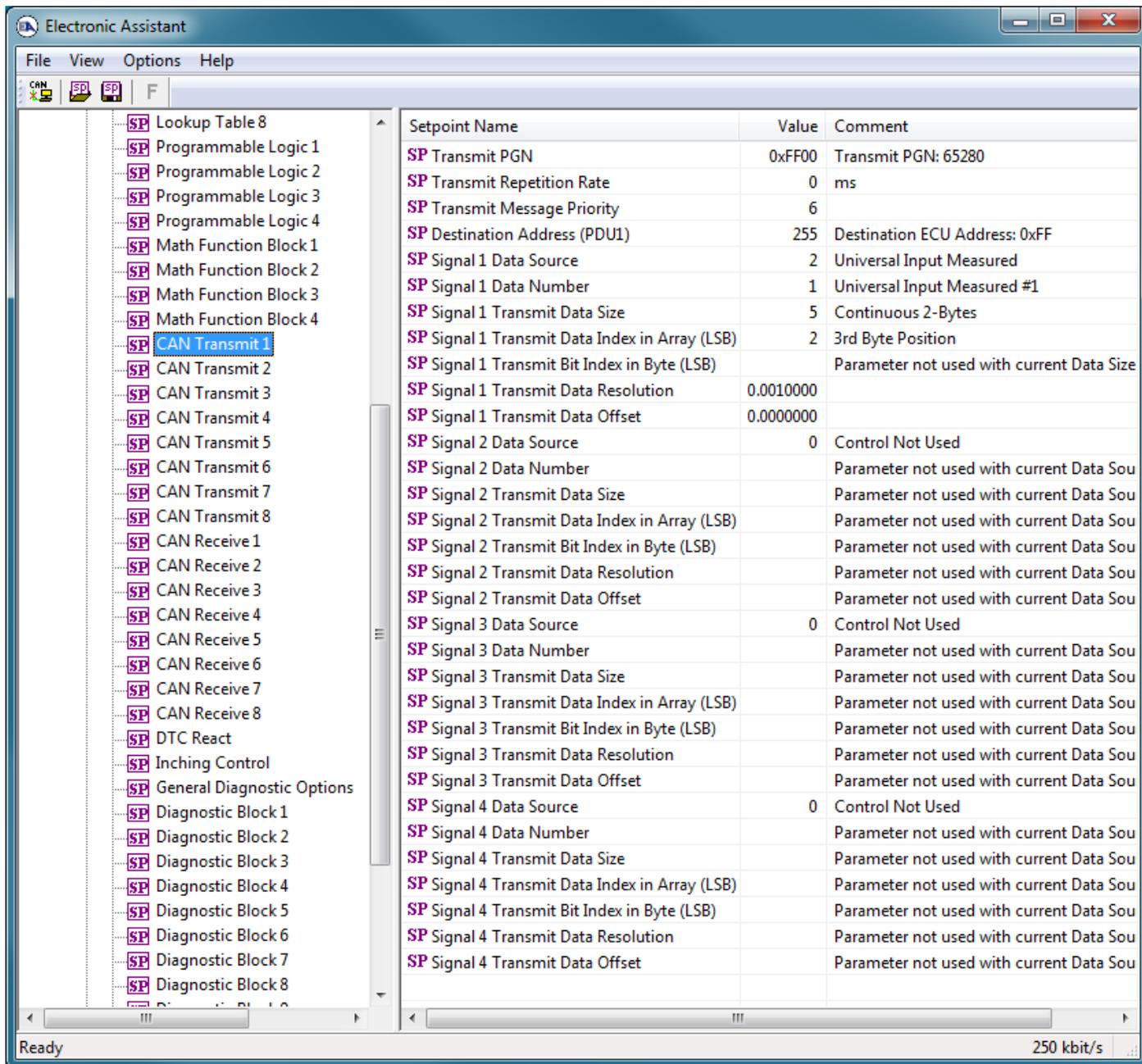


Figure 15 – Screen Capture of CAN Transmit Message Setpoints

Name	Range	Default	Notes
Transmit PGN	0xff00 ... 0xffff	Different for each	See Section 1.10.1
Transmit Repetition Rate	0 ... 65000 ms	0ms	0ms disables transmit
Transmit Message Priority	0...7	6	Proprietary B Priority
Destination Address	0...255	255	Not used by default
Signal 1 Control Source	Drop List	Different for each	See Table 21
Signal 1 Control Number	Drop List	Different for each	See 1.10.2
Signal 1 Transmit Data Size	Drop List	2 bytes	
Signal 1 Transmit Data Index in Array	0-7	2	
Signal 1 Transmit Bit Index In Byte	0-7	0	
Signal 1 Transmit Data Resolution	-100000.0 to 100000	0.001	
Signal 1 Transmit Data Offset	-10000 to 10000	0.0	
Signal 2 Control Source	Drop List	Signal undefined	See Table 21
Signal 2 Control Number	Drop List	Signal undefined	See 1.10.2
Signal 2 Transmit Data Size	Drop List	2 bytes	
Signal 2 Transmit Data Index in Array	0-7	0	
Signal 2 Transmit Bit Index In Byte	0-7	0	
Signal 2 Transmit Data Resolution	-100000.0 to 100000	0.001	
Signal 2 Transmit Data Offset	-10000 to 10000	0.0	
Signal 3 Control Source	Drop List	Signal undefined	See Table 21
Signal 3 Control Number	Drop List	Signal undefined	See 1.10.2
Signal 3 Transmit Data Size	Drop List	2 bytes	
Signal 3 Transmit Data Index in Array	0-7	0	
Signal 3 Transmit Bit Index In Byte	0-7	0	
Signal 3 Transmit Data Resolution	-100000.0 to 100000	0.001	
Signal 3 Transmit Data Offset	-10000 to 10000	0.0	
Signal 4 Control Source	Drop List	Signal undefined	See Table 21
Signal 4 Control Number	Drop List	Signal undefined	See 1.10.2
Signal 4 Transmit Data Size	Drop List	2 bytes	
Signal 4 Transmit Data Index in Array	0-7	0	
Signal 4 Transmit Bit Index In Byte	0-7	0	
Signal 4 Transmit Data Resolution	-100000.0 to 100000	0.001	
Signal 4 Transmit Data Offset	-10000 to 10000	0.0	

Table 33 – CAN Transmit Message Setpoints

3.12. CAN Receive Setpoints

The Math Function Block is defined in Section 1.11. Please refer there for detailed information about how these setpoints are used. **“Receive Message Timeout”** is set to 0ms by default. To enable Receive message set **“Receive Message Timeout”** that differs from zero.

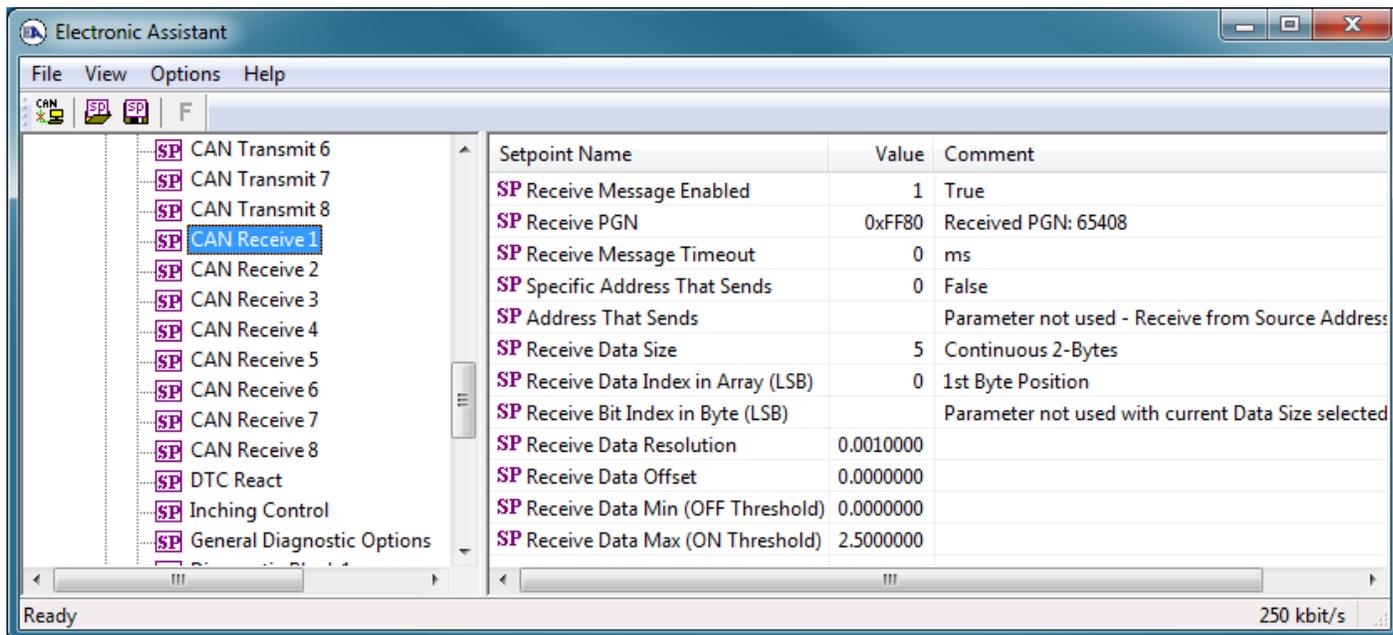


Figure 16 – Screen Capture of CAN Receive Message Setpoints

Name	Range	Default	Notes
Received Message Enabled	Drop List	False	
Received PGN	0 to 65536	Different for each	
Received Message Timeout	0 to 60 000 ms	0ms	
Specific Address that sends PGN	Drop List	False	
Address That Sends	0 to 255	254 (0xFE, Null Addr)	
Receive Transmit Data Size	Drop List	2 bytes	
Receive Transmit Data Index in Array	0-7	0	
Receive Transmit Bit Index In Byte	0-7	0	
Receive Transmit Data Resolution	-100000.0 to 100000	0.001	
Receive Transmit Data Offset	-10000 to 10000	0.0	
Receive Data Min (Off Threshold)	-1000000 to Max	0.0	
Receive Data Max (On Threshold)	-100000 to 100000	2.0	

Table 34 – CAN Receive Setpoints

3.13. DTC React

The DTC React Function Block is defined in Section 1.9. Please refer there for detailed information about how these setpoints are used.

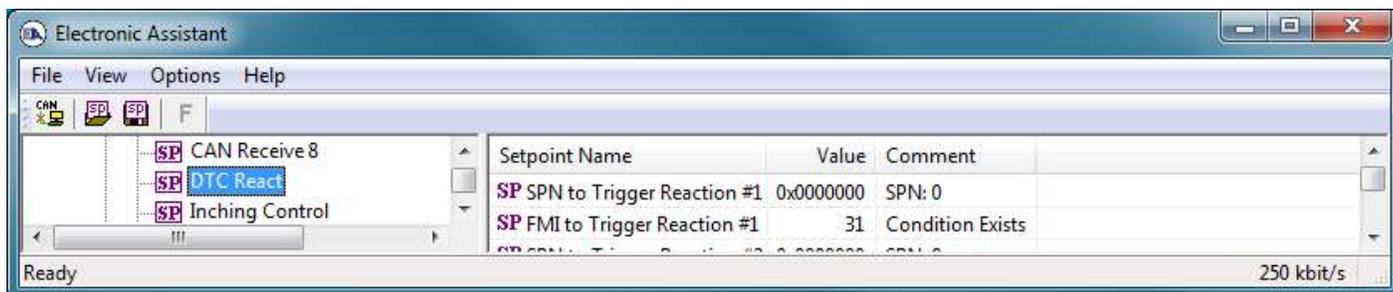


Figure 17 – Screen Capture of DTC React Setpoints

Name	Range	Default	Notes
SPN to Trigger Reaction #1	0 to 524287	0	0 is an illegal value, and disables the DTC
FMI to Trigger Reaction #X	Drop List	31, Condition Exists	Supports all FMIs in the J1939 standard

Table 35 – DTC React Setpoints

3.14. Inching Control

The Inching Control Block is defined in Section 1.13 Please refer there for detailed information about how these setpoints are used.

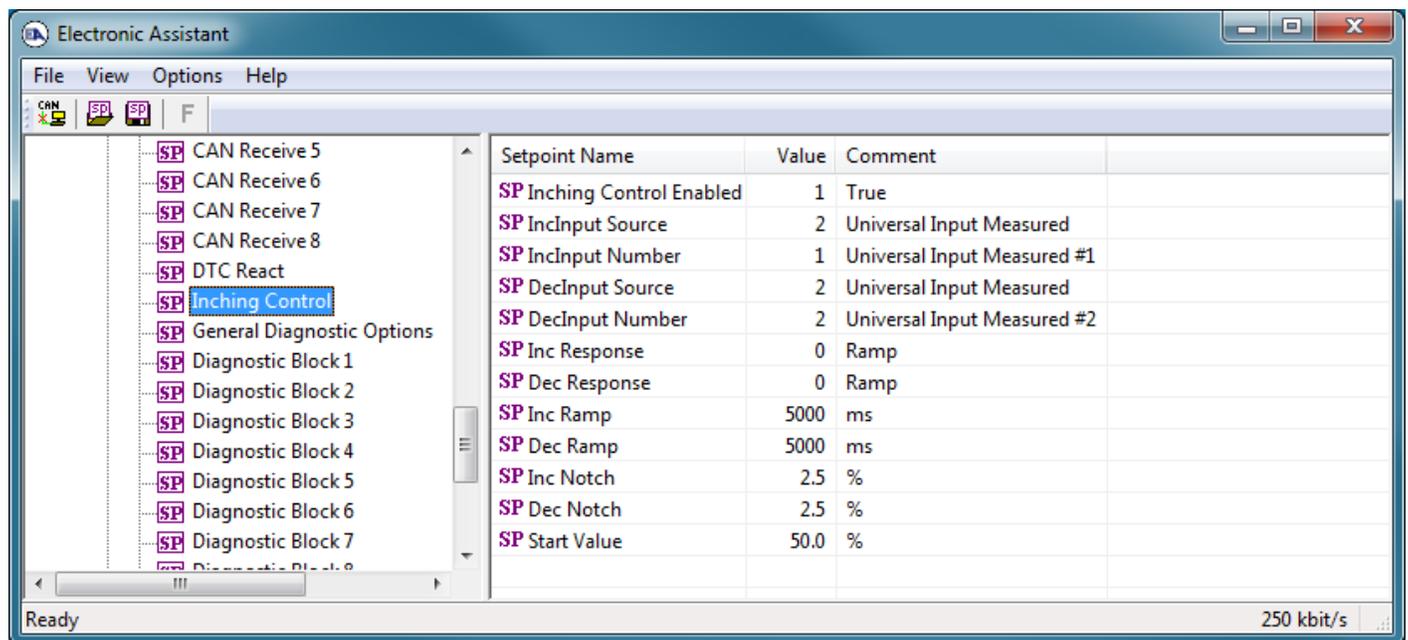


Figure 18 – Screen Capture of Inching Control Setpoints

Name	Range	Default	Notes
Inching Control Enabled	Drop List	False	
IncInput Source	Drop List	Universal Input Measured	See Table 21
IncInput Number	Depends on IncInput source	1	See Table 21
DecInput Source	Drop List	Universal Input Measured	See Table 21
DecInput Number	Depends on DecInput source	2	See Table 21
Inc Response	Drop List	Ramp	See Table 23
Dec Response	Drop List	Ramp	See Table 23
Inc Ramp	0 to 20 000 ms	5000 ms	
Dec Ramp	0 to 20 000 ms	5000 ms	
Inc Notch	0 to 100 %	2.5 %	
Dec Notch	0 to 100 %	2.5 %	
Start Value	0 to 100 %	50.0 %	

Table 36 – Inching Control Setpoints

3.15. General Diagnostic Options Setpoints

These setpoints control the shutdown of the ECU in case of a power supply, CPU temperature or CAN bus related errors. Diagnostics are defined in 1.3. Please refer there for detailed information how these setpoints are used.

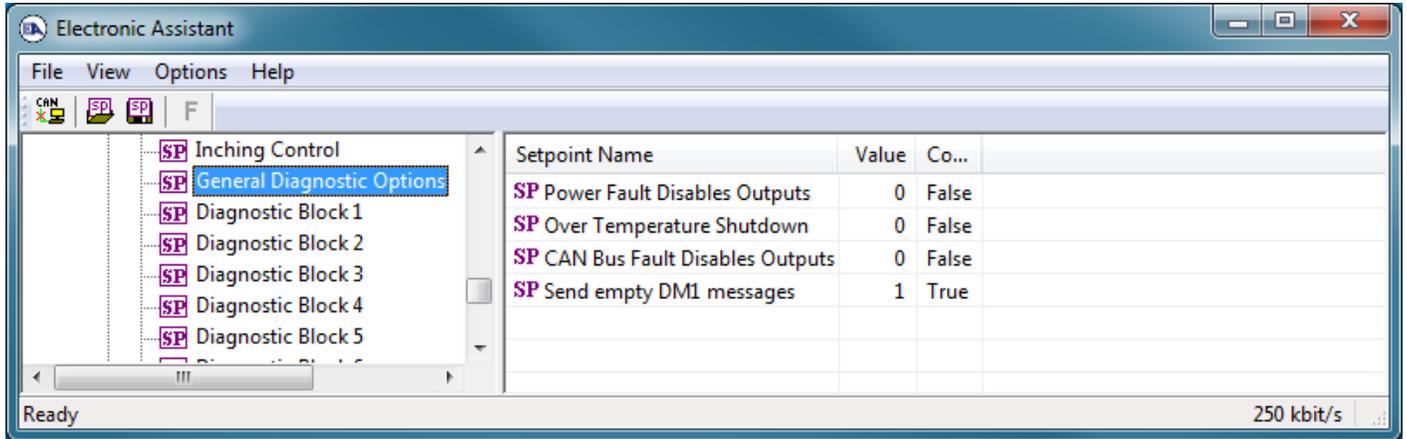


Figure 19 – Screen Capture of General Diagnostic Options Setpoints

Name	Range	Default	Notes
Power Fault Disables Outputs	Drop List	False	
Over Temperature Shutdown	Drop List	False	
CAN Bus Fault Disables Outputs	Drop List	False	
Send empty DM1 messages	Drop List	True	

Table 37 – General Diagnostic Setpoints

3.16. Diagnostic Block Setpoints

There are 16 Diagnostics blocks that can be configured to monitor various parameters of the Controller. The Diagnostic Function Block is defined in section 1.4. Please refer there for detailed information how these setpoints are used.

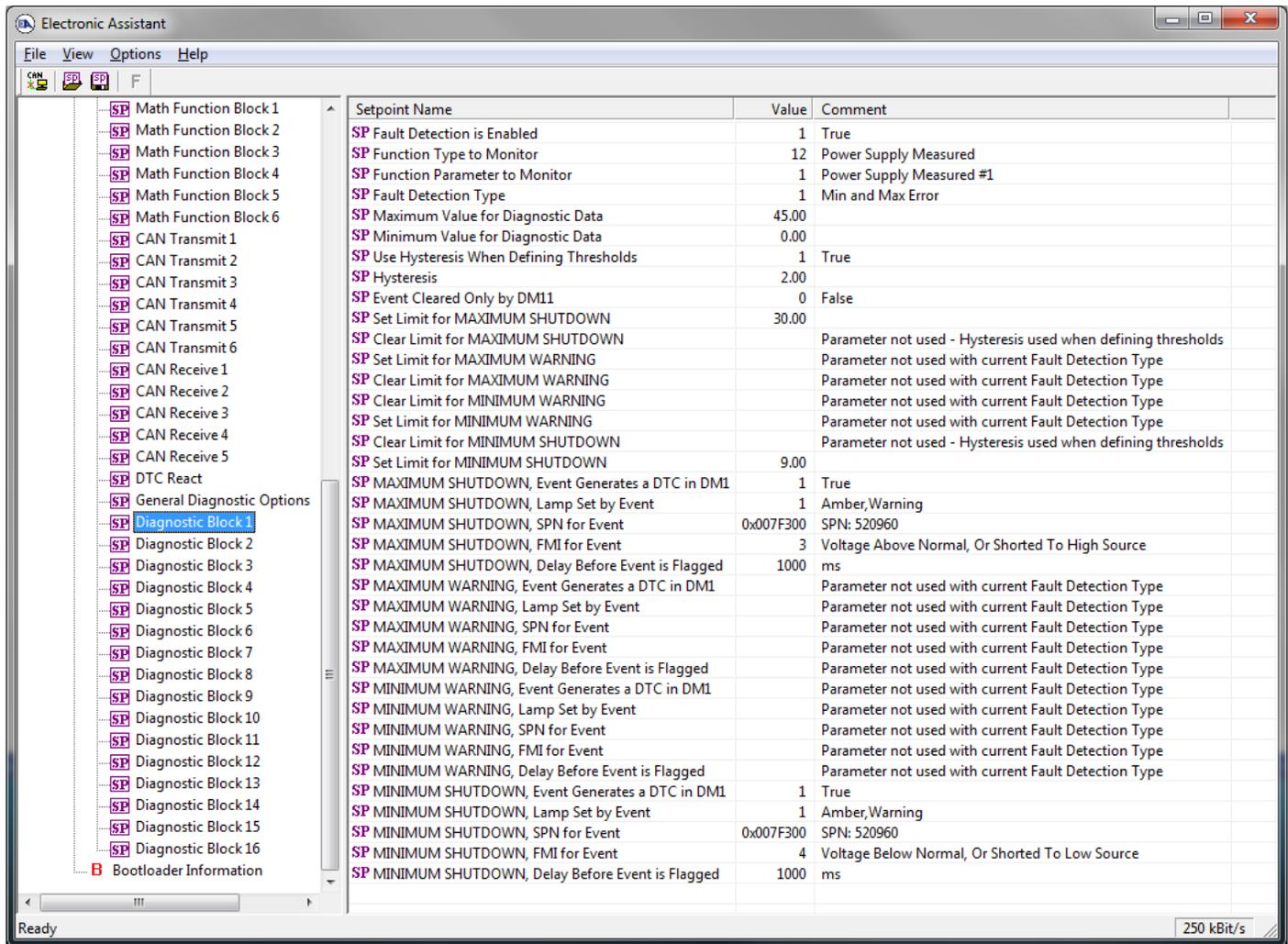


Figure 20 – Screen Capture of Diagnostic Block Setpoints

Name	Range	Default	Notes
Fault Detection is Enabled	Drop List	False	
Function Type to Monitor	Drop List	0 – Control not used	
Function parameter to Monitor	Drop List	0 – No selection	
Fault Detection Type	Drop List	1 – Min and Max Error	See section 1.4
Maximum Value for Diagnostic Data	Minimum Value for Diagnostic Data ... 4.28e ⁹	5.0	
Minimum Value for Diagnostic Data	0.0 ... Maximum Value for Diagnostic Data	0.0	
Use Hysteresis When Defining Thresholds	Drop List	False	
Hysteresis	0.0 ... Maximum Value for Diagnostic Data	0.0	
Event Cleared only by DM11	Drop List	False	
Set Limit for MAXIMUM SHUTDOWN	Minimum Value for Diagnostic Data ... Maximum Value for Diagnostics Data	4.8	
Clear Limit for MAXIMUM SHUTDOWN	Minimum Value for Diagnostic Data ... Maximum Value for Diagnostics Data	4.6	
Set Limit for MAXIMUM WARNING	Minimum Value for Diagnostic Data ... Maximum Value for Diagnostics Data	0.0	
Clear Limit for MAXIMUM WARNING	Minimum Value for Diagnostic Data ... Maximum Value for Diagnostics Data	0.0	
Clear Limit for MINIMUM WARNING	Minimum Value for Diagnostic Data ... Maximum Value for Diagnostics Data	0.0	
Set Limit for MINIMUM WARNING	Minimum Value for Diagnostic Data ... Maximum Value for Diagnostics Data	0.0	
Clear Limit for MINIMUM SHUTDOWN	Minimum Value for Diagnostic Data ... Maximum Value for Diagnostics Data	0.4	
Set Limit for MINIMUM SHUTDOWN	Minimum Value for Diagnostic Data ... Maximum Value for Diagnostics Data	0.2	
MAXIMUM SHUTDOWN, Event Generates a DTC in DM1	Drop List	True	
MAXIMUM SHUTDOWN, Lamp Set by Event	Drop List	0 – Protect	See Table 12
MAXIMUM SHUTDOWN, SPN for Event	0...524287	520448 (\$7F100)	It is the user's responsibility to select an SPN that will not violate the J1939 standard.

MAXIMUM SHUTDOWN, FMI for Event	Drop List	3, Voltage Above Normal	See Table 13
MAXIMUM SHUTDOWN, Delay Before Event is Flagged	0...60000 ms	1000	
MAXIMUM WARNING, Event Generates a DTC in DM1	Drop List	True	
MAXIMUM WARNING, Lamp Set by Event	Drop List	0 – Protect	See Table 12
MAXIMUM WARNING, SPN for Event	0...524287	520704 (\$7F200)	It is the user's responsibility to select an SPN that will not violate the J1939 standard.
MAXIMUM WARNING, FMI for Event	Drop List	3, Voltage Above Normal	See Table 13
MAXIMUM WARNING, Delay Before Event is Flagged	0...60000 ms	1000	
MINIMUM WARNING, Event Generates a DTC in DM1	Drop List	True	
MINIMUM WARNING, Lamp Set by Event	Drop List	0 – Protect	See Table 12
MAXIMUM WARNING, SPN for Event	0...524287	520960 (\$7F300)	It is the user's responsibility to select an SPN that will not violate the J1939 standard.
MINIMUM WARNING, FMI for Event	Drop List	4, Voltage Below Normal	See Table 13
MINIMUM WARNING, Delay Before Event is Flagged	0...60000 ms	1000	
MINIMUM SHUTDOWN, Event Generates a DTC in DM1	Drop List	True	
MINIMUM SHUTDOWN, Lamp Set by Event	Drop List	Amber Warning	See Table 12
MINIMUM SHUTDOWN, SPN for Event	0...524287	521216 (\$7F400)	It is the user's responsibility to select an SPN that will not violate the J1939 standard.
MINIMUM SHUTDOWN, FMI for Event	Drop List	4, Voltage Below Normal	See Table 13
MINIMUM SHUTDOWN, Delay Before Event is Flagged	0...60000 ms	1000	

Table 38 – Diagnostic Block Setpoints

4. CONTROLLER PARAMETERS ACCESSED WITH E-WRITE NFC

The controller's NFC technology provides users the ability to configure the controllers without the need to be powered on. A set of parameters can be configured with the mobile E-Write NFC configuration tool, which is available for download at Google Play Store. E-Write NFC application allows the user to configure the module as well as to assign each of the AX022420 controllers a unique alias to easily distinguish between the controllers with a large system. To ensure prompt and easy use of the NFC only most essential setpoints can be configured through NFC. Available setpoint are presented in next subchapters.

4.1. Controller Information

The Controller Information provides information such as current version of firmware and date, serial number, as well as a configurable parameter to identify various AX022420 controllers within an application system, Controller Alias.

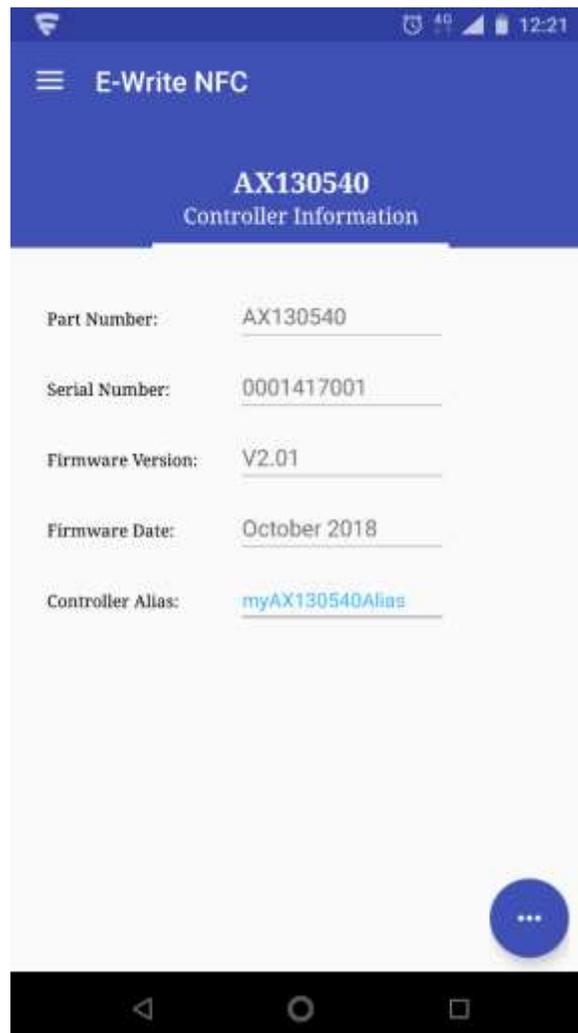


Figure 21 – Screen Capture of Controller Information Parameters

4.2. Universal Input

All the setpoints of Universal Input Blocks are available to be configured through the NFC. The Universal Input block is defined in section 1.1. Please refer there for information how these parameters are used.



Figure 22 – Screen Capture of Universal Input Parameters

Name	Range	Default	Notes
Input Sensor Type	Drop List	VOLTAGE_0_TO_5V	See Table 1
Pulses per Revolution	Drop List	FALSE	See Section 1.1
Minimum Range	From Minimum Error to Maximum Range	Depends on Input Sensor Type	
Maximum Range	From Minimum Range to Maximum Error	Depends on Input Sensor Type	
Debounce Time	Drop List	None	See Table 2
Pullup/Pulldown Resistor	Drop List	10kΩ Pulldown	See Table 3
Active High/Active Low	Drop List	Active High	See Table 4
Software Filter Type	Drop List	No Filtering	See Section 1.2
Software Filter Constant	1..1000	1	

Table 39 – Universal Input Parameters

4.3. Encoder Input

All Encoder Input setpoints are available to be configured through the NFC. The Encoder Input is defined in section 1.1. Please refer there for information how these parameters are used.

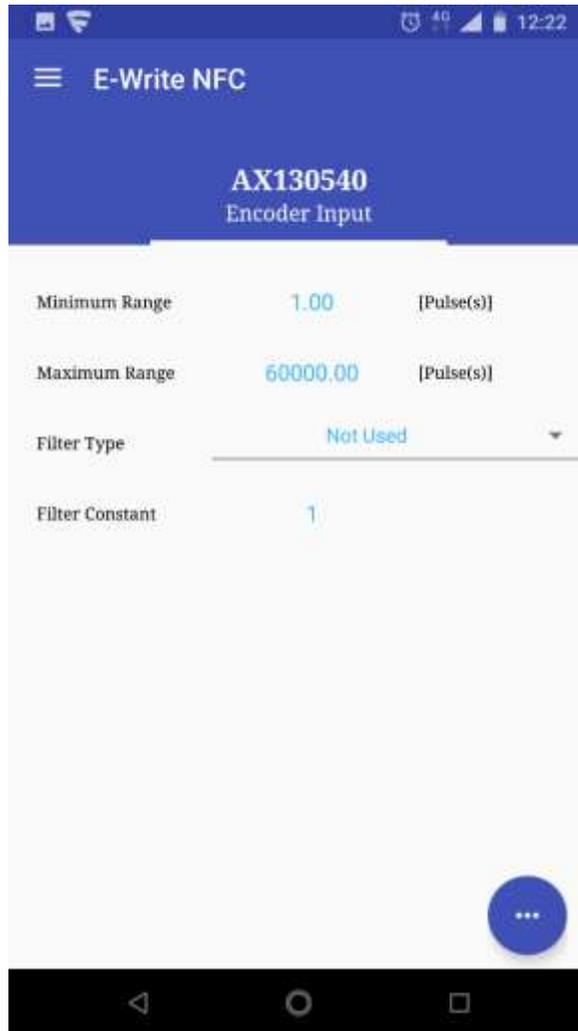


Figure 23 – Screen Capture of Encoder Input Parameters

Name	Range	Default	Notes
Minimum Range	1 to Maximum Range	1 Pulse(s)	
Maximum Range	From Minimum Range to 600000	60000 Pulse(s)	
Software Filter Type	Drop List	No Filtering	See Section 1.1
Software Filter Constant	1..1000	1	

Table 40 – Encoder Input Parameters

4.4. Magnetic Input

All Magnetic Input setpoints are available to be configured through the NFC. The Magnetic Input is defined in section 1.1. Please refer there for information how these parameters are used.

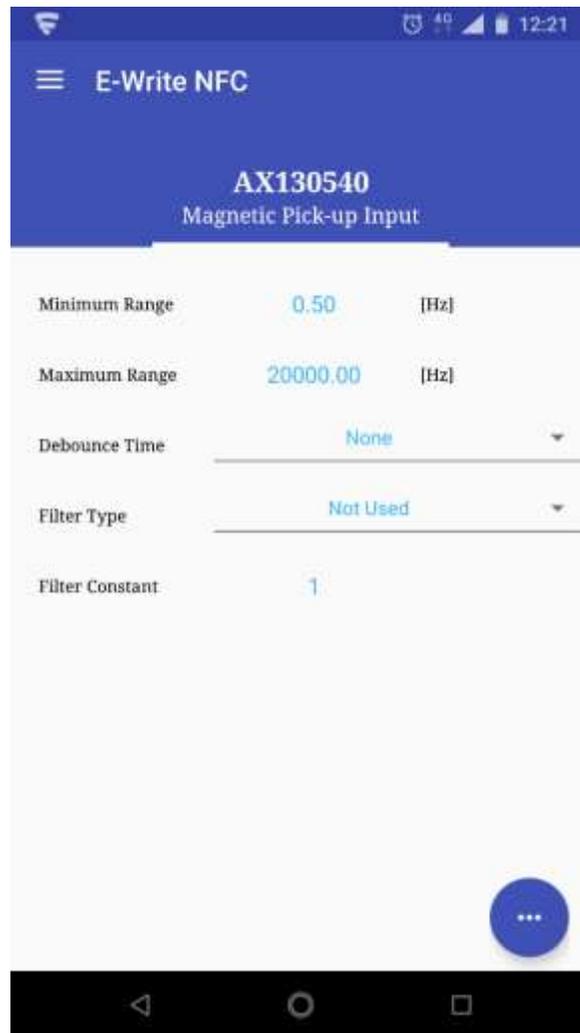


Figure 24 – Screen Capture of Magnetic Input Parameters

Name	Range	Default	Notes
Minimum Range	0.5 Hz to Maximum Range	0.5 Hz	
Maximum Range	From Minimum Range to 20000 Hz	20000 Hz	
Debounce Time	Drop List	None	See Table 2
Software Filter Type	Drop List	No Filtering	See Section 1.1
Software Filter Constant	1..1000	1	

Table 41 – Magnetic Input Parameters

4.5. Proportional Output

Most Proportional Output setpoints are available to be configured through the NFC. Instead of Source and Number pairs used in EA to select inputs of the output block, NFC has single list of available inputs, namely 'Not Used', 'Universal Input 1 Measured', 'Universal Input 2 Measured', 'Magnetic Pick-up Input Measured' and 'Encoder Input Measured'. Other input settings selected with EA are interpreted as 'Not Used'. The Proportional Output is defined in section 1.3. Please refer there for information how these parameters are used.

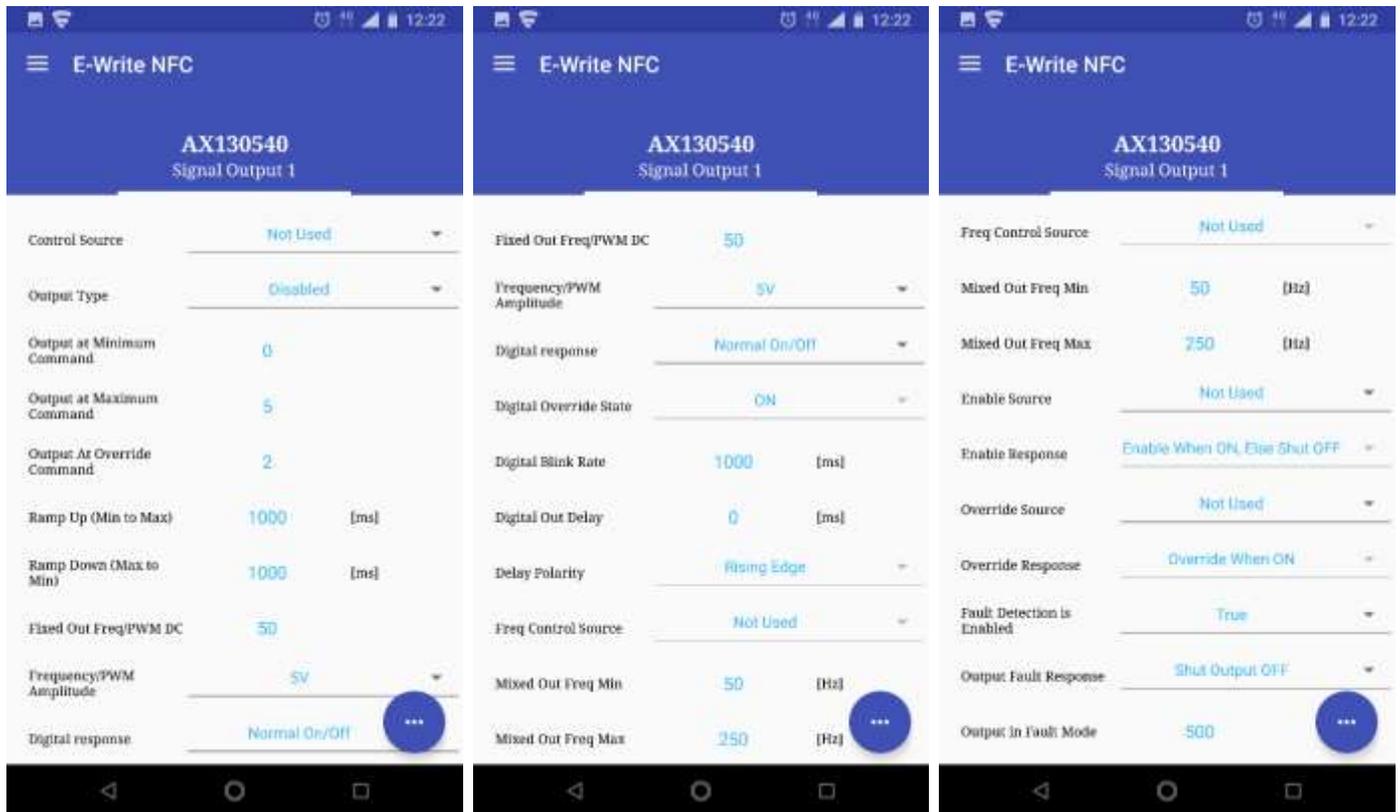


Figure 25 – Screen Capture of Proportional Output Parameters

Name	Range	Default	Notes
Control Source	Drop List	Not Used	See Section 4.5
Output Type	Drop List	Disabled	See Table 6
Output At Minimum Command	Limit to Limit	Depends on Output Type	
Output At Maximum Command	Limit to Limit	Depends on Output Type	
Output At Override Command	Limit to Limit	Depends on Output Type	
Ramp Up (Min to Max)	0 to 10 000ms	0ms	
Ramp Down (Max to Min)	0 to 10 000ms	0ms	
Fixed Output Frequency/PWM Duty Cycle	0.1 to 100 % 0.1 Hz to 50 000 Hz	50 % 250 Hz	
Frequency/PWM Amplitude	Drop List	0 to 5 V	
Digital Response	Drop List	Normal On/Off	See Table 7
Digital Override State	Drop List	ON	
Digital Blink Rate	100 to 5000 ms	1000ms	
Digital Out Delay	0 to 60000 ms	0ms	
Delay Polarity	Drop List	Rising Edge	See Table 8 Table 8 – Delay Polarity
Frequency Control Source	Drop List	Control not used	See Table 21
Mixed Output Frequency Min	0.1 Hz to 50 000 Hz	50.0 Hz	
Mixed Output Frequency Max	0.1 Hz to 50 000 Hz	250.0 Hz	
Enable Source	Drop List	Control not used	See Section 4.5
Enable Response	Drop List	Enable When On, else Shutoff	See Table 9
Override Source	Drop List	Control not used	See Section 4.5
Override Response	Drop List	Override When On	See Table 10
Fault Detection is Enabled	Drop List	True	
Output Fault Response	Drop List	Shutoff Output	See Table 11
Output in Fault Mode	Limit to Limit	Depends on Output Type	

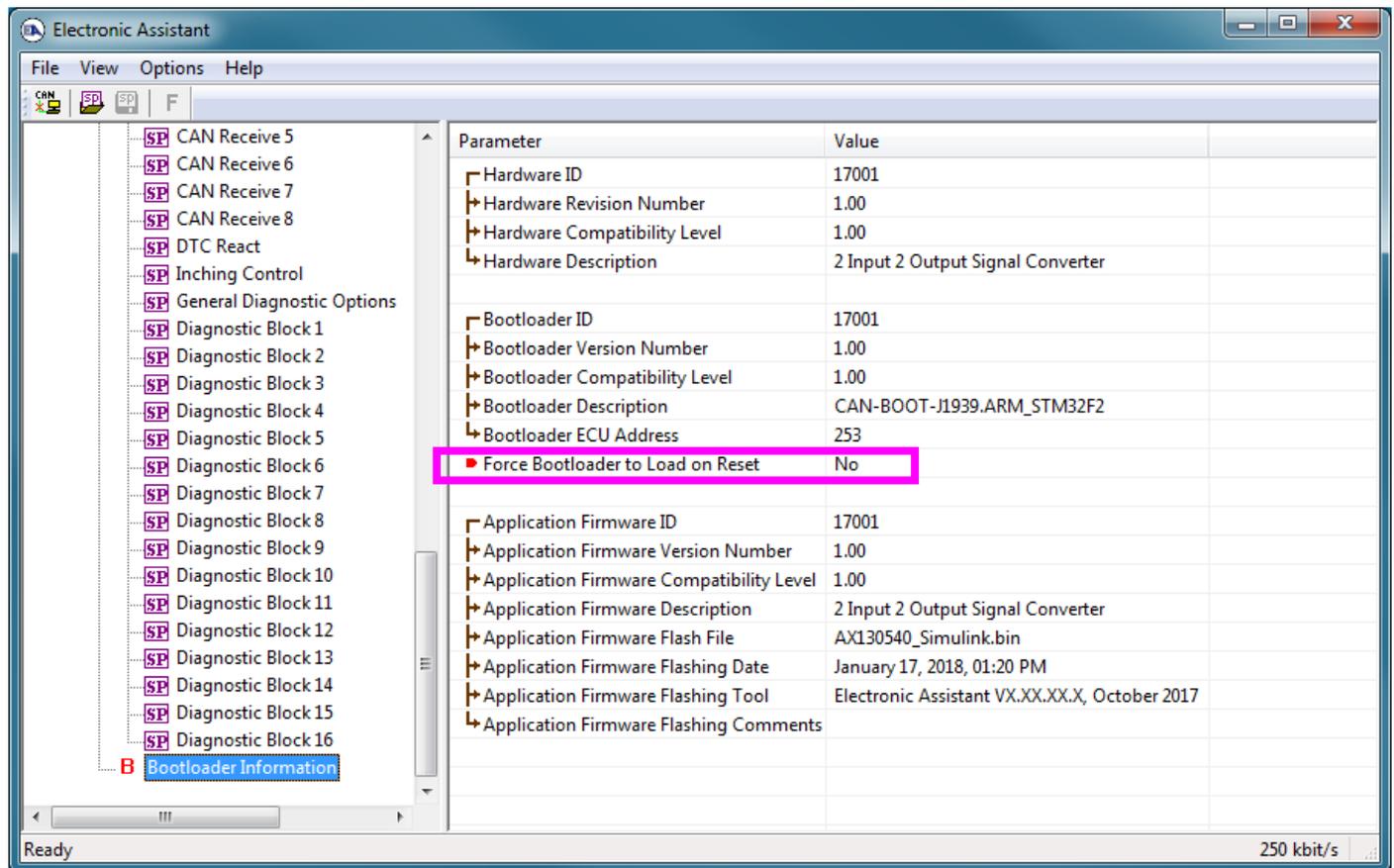
Table 42 – Proportional Output Parameters

5. REFLASHING OVER CAN WITH EA BOOTLOADER

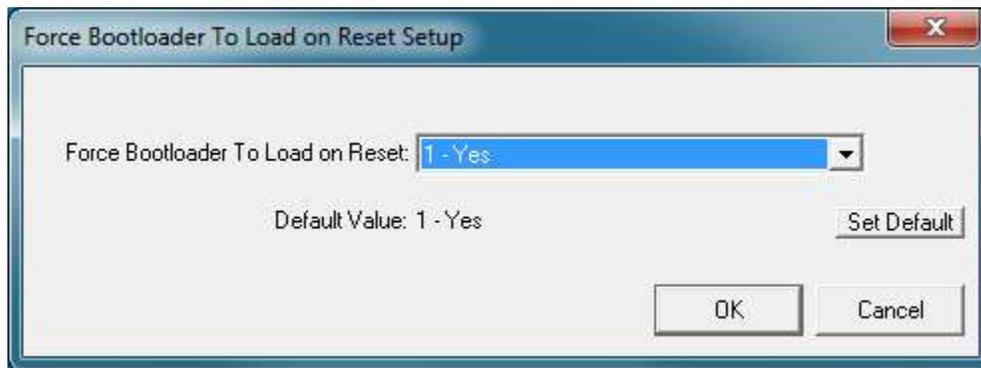
The AX130540 can be upgraded with new application firmware using the **Bootloader Information** section. This section details the simple step-by-step instructions to upload new firmware provided by Axiomatic onto the unit via CAN, without requiring it to be disconnected from the J1939 network.

Note: To upgrade the firmware use Electronic Assistant V4.5.53.0 or higher.

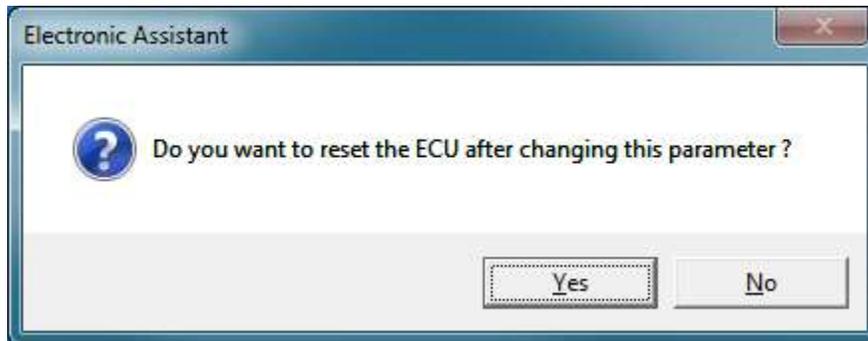
1. When EA first connects to the ECU, the **Bootloader Information** section will display the following information.



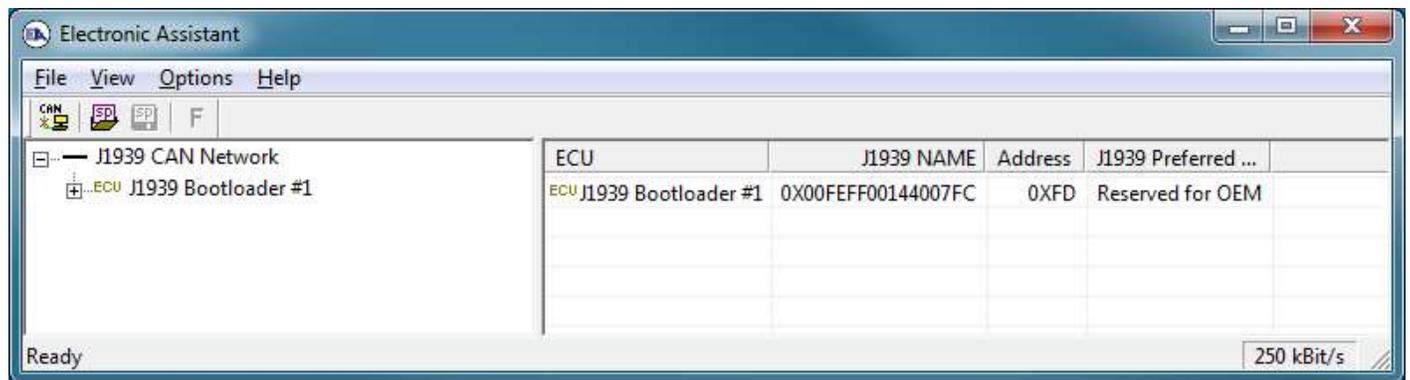
2. To use the bootloader to upgrade the firmware running on the ECU, change the variable “**Force Bootloader To Load on Reset**” to Yes.

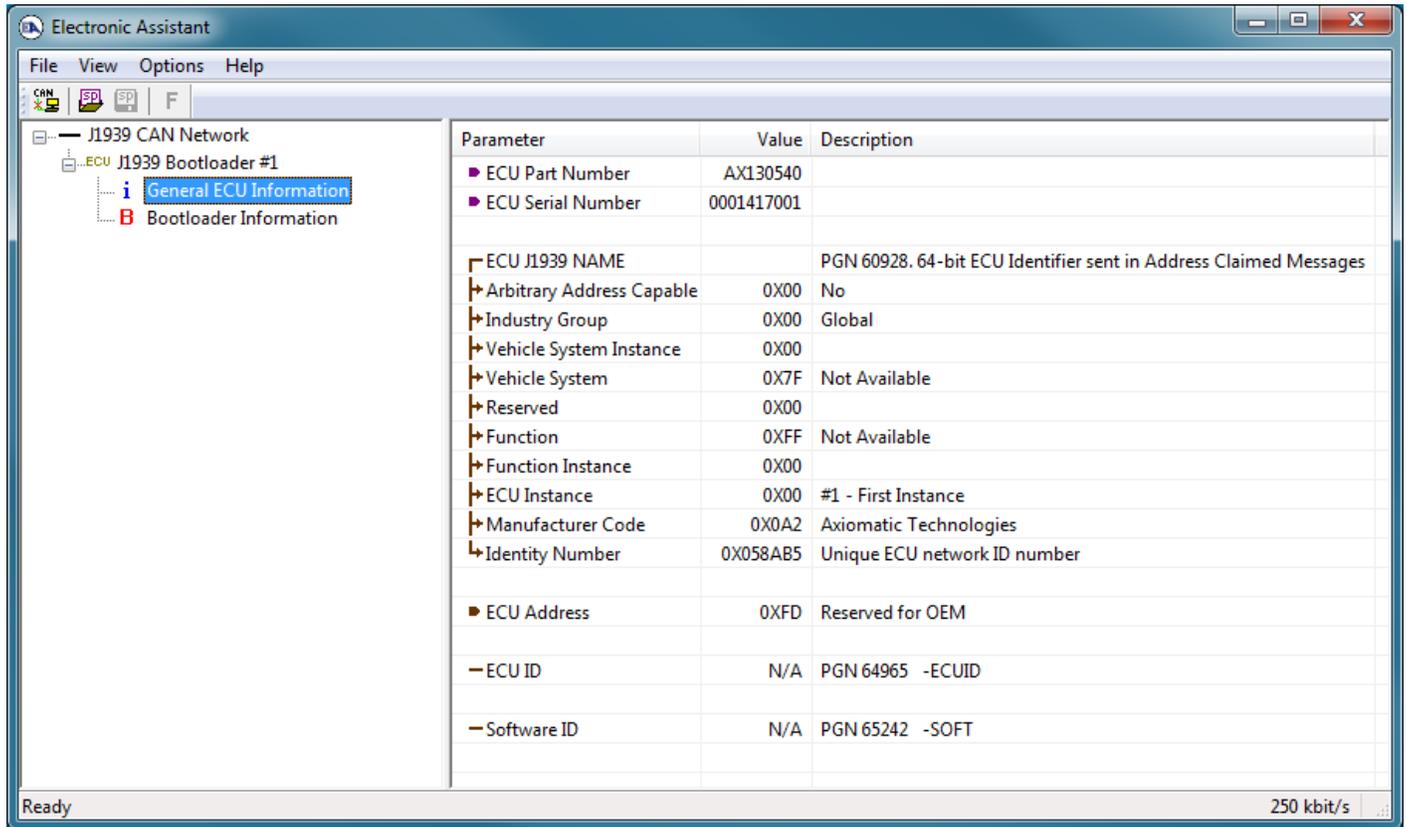


3. When the prompt box asks if you want to reset the ECU, select Yes.



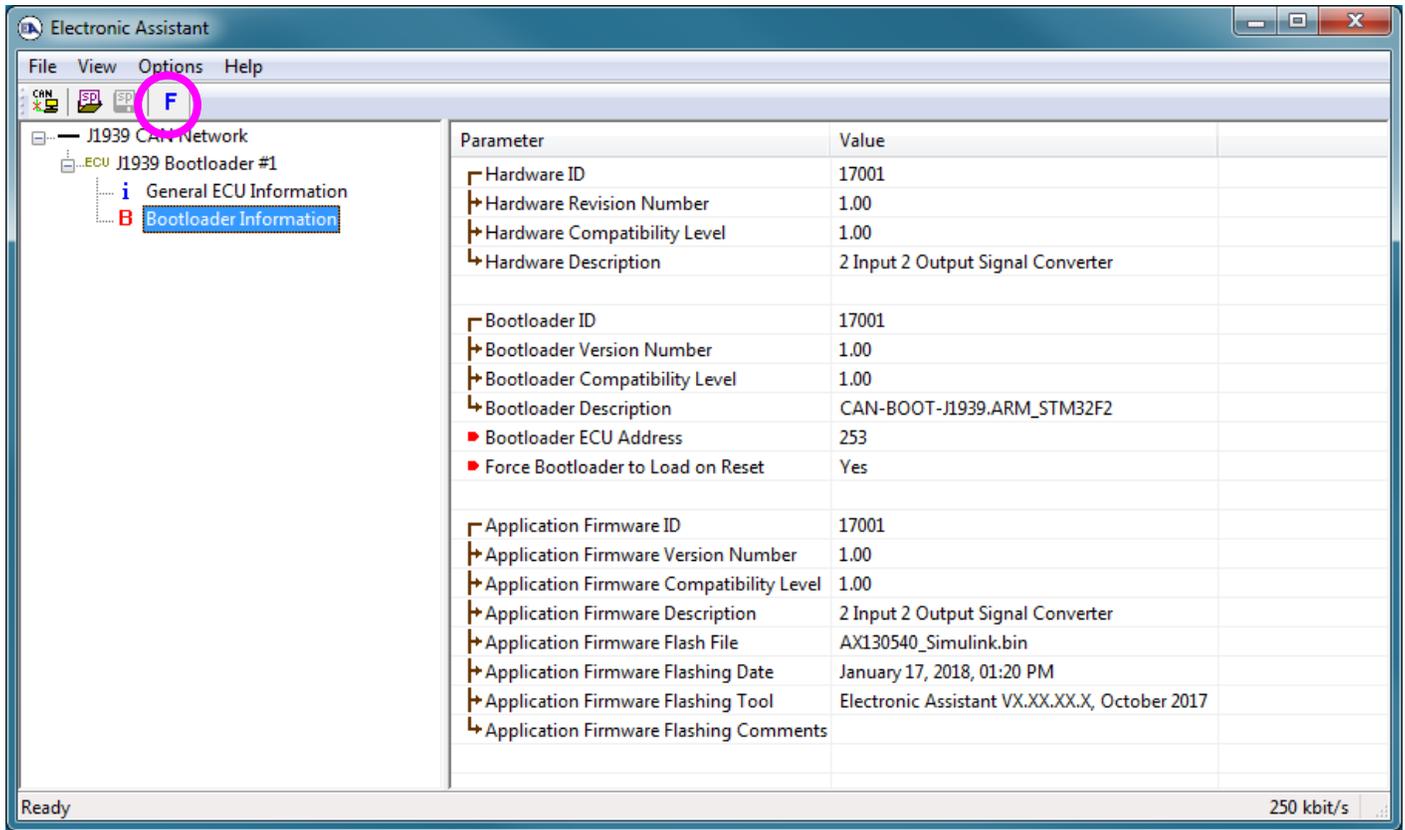
4. Upon reset, the ECU will no longer show up on the J1939 network as an AX130540 but rather as **J1939 Bootloader #1**.





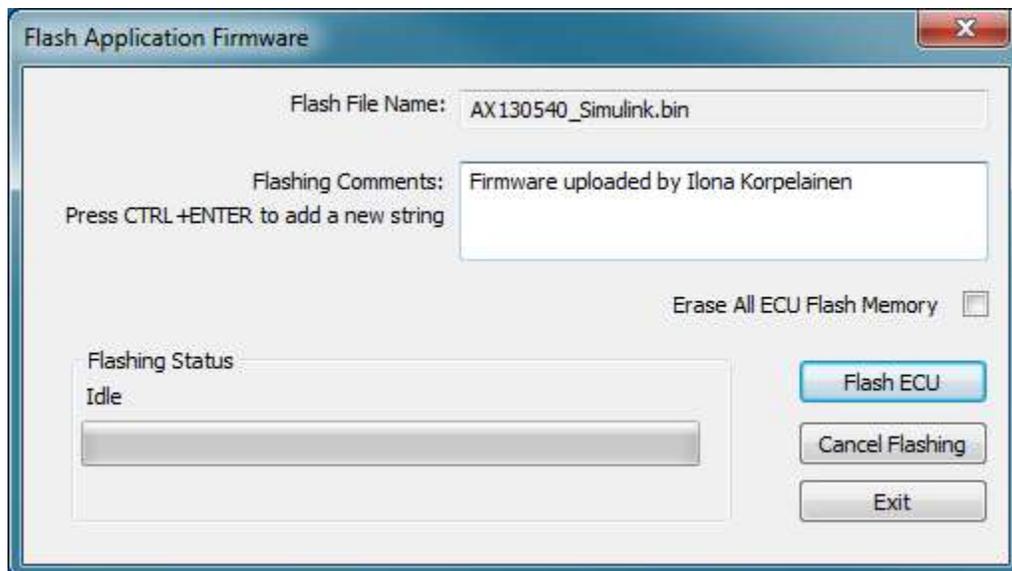
Note that the bootloader is NOT Arbitrary Address Capable. This means that if you want to have multiple bootloaders running simultaneously (not recommended) you would have to manually change the address for each one before activating the next, or there will be address conflicts. And only one ECU would show up as the bootloader. Once the 'active' bootloader returns to regular functionality, the other ECU(s) would have to be power cycled to re-activate the bootloader feature.

- When the **Bootloader Information** section is selected, the same information is shown as when it was running the AX130540 firmware, but in this case the **F**lashing feature has been enabled.



6. Select the **F**lashing button and navigate to where you had saved the **AX130540_Simulink.bin** file sent from Axiomatic. (Note: only binary (.bin) files can be flashed using the EA tool.)
7. Once the Flash Application Firmware window opens, you can enter comments such as “Firmware upgraded by [Name]” if you so desire. This is not required, and you can leave the field blank if you do not want to use it.

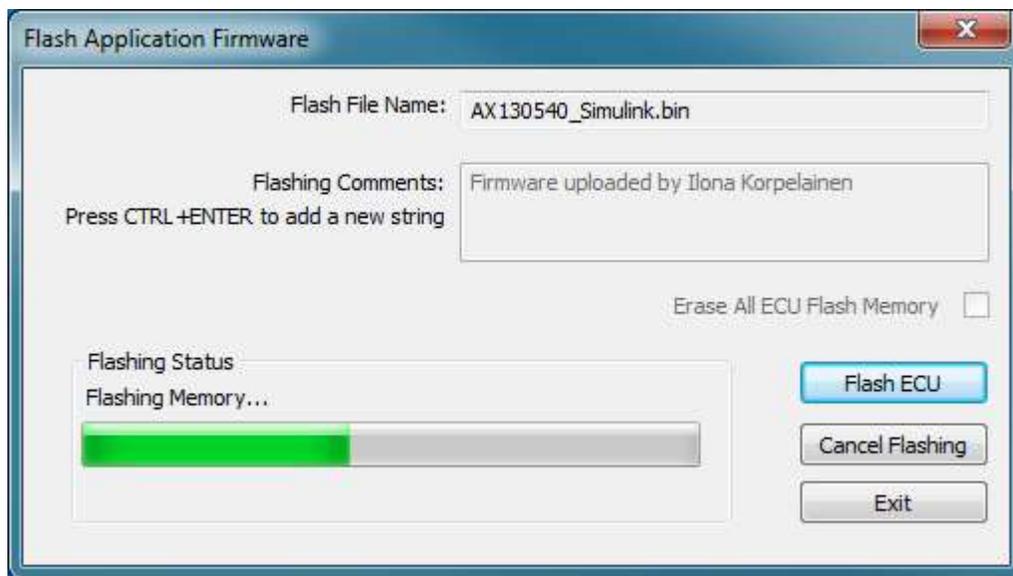
Note: You do not have to date/time-stamp the file, as this is done automatically by the EA tool when you upload the new firmware.





WARNING: Do not check the “Erase All ECU Flash Memory” box unless instructed to do so by your Axiomatic contact. Selecting this will erase ALL data stored in non-volatile flash including the calibration from Axiomatic factory testing. It will also erase any configuration of the setpoints that might have been done to the ECU and reset all setpoints to their factory defaults. By leaving this box unchecked, none of the setpoints will be changed when the new firmware is uploaded.

A progress bar will show how much of the firmware has been sent as the upload progresses. The more traffic there is on the J1939 network, the longer the upload process will take.



Once the firmware has finished uploading, a message will pop up indicating the successful operation. If you select to reset the ECU, the new version of the AX130540 application will start running, and the ECU will be identified as such by EA. Otherwise, the next time the ECU is power-cycled, the AX130540 application will run rather than the bootloader function.



Note: If at any time during the upload the process is interrupted, the data is corrupted



(bad checksum) or for any other reason the new firmware is not correct, i.e. bootloader detects that the file loaded was not designed to run on the hardware platform, the bad or corrupted application will not run. Rather, when the ECU is reset or power-cycled the **J1939 Bootloader** will continue to be the default application until valid firmware has been successfully uploaded into the unit.

APPENDIX A - TECHNICAL SPECIFICATION

Technical Specifications:

Specifications are indicative and subject to change. Actual performance will vary depending on the application and operating conditions. Users should satisfy themselves that the product is suitable for use in the intended application. All our products carry a limited warranty against defects in material and workmanship. Please refer to our Warranty, Application Approvals/Limitations and Return Materials Process as described on www.axiomatic.com/service.html.

Power Supply

Power Supply Input	12 Vdc or 24 Vdc nominal 9...36 Vdc power supply range Shutdown voltage is 8.0 Vdc.
Protection	Reverse polarity protection Overvoltage protection is up to 45 V.

Inputs

Inputs	2 Universal Signal Inputs User programmable as Voltage, Current, Resistive, Frequency, RPM, PWM or Digital signal inputs types. Refer to Table 1.0. 1 Magnetic Pick Up Sensor Input 1 Encoder Input																																																
Magnetic Pick Up Sensor Input	Range: 0.5 Hz to 20 kHz Amplitude: 100 mV to 60 Vrms																																																
Encoder Input	One 2 phase, phase A and B, incremental encoder input. Range: 0.5 Hz to 150 kHz Amplitude: up to +Vsupply																																																
Input Grounds	1 provided																																																
Protection	All inputs are protected against short to GND. All inputs, except current inputs, are protected against shorts to Nominal Vps (36Vdc).																																																
Input Accuracy and Resolution	<table border="1"> <thead> <tr> <th>Input Type</th> <th>Input Range</th> <th>Accuracy</th> <th>Resolution</th> </tr> </thead> <tbody> <tr> <td rowspan="4">Voltage</td> <td>0-5V</td> <td>+/- 0.5%</td> <td>1 mV</td> </tr> <tr> <td>0-10V</td> <td>+/- 0.5%</td> <td>1 mV</td> </tr> <tr> <td>-5V to 5V</td> <td>+/- 0.5%</td> <td>1 mV</td> </tr> <tr> <td>-10V to 10V</td> <td>+/- 0.5%</td> <td>1 mV</td> </tr> <tr> <td rowspan="2">Current</td> <td>0(4)-20mA</td> <td>+/-1%</td> <td>1 µA</td> </tr> <tr> <td>0-200mA</td> <td>+/-1%</td> <td>1 µA</td> </tr> <tr> <td>Resistive</td> <td>30-250kΩ</td> <td>+/-1%</td> <td>1 Ω for lower ranges 1 kΩ for higher ranges</td> </tr> <tr> <td rowspan="3">Frequency</td> <td>0.5Hz-50Hz</td> <td>+/-0.3%</td> <td>0.01 Hz</td> </tr> <tr> <td>10Hz-1kHz</td> <td>+/-0.3%</td> <td>0.1 Hz</td> </tr> <tr> <td>100Hz-20kHz</td> <td>+/-0.3%</td> <td>1 Hz</td> </tr> <tr> <td rowspan="2">PWM</td> <td>Low Frequency</td> <td>+/-0.1%</td> <td>0.01%</td> </tr> <tr> <td>High Frequency</td> <td>+/-0.1%</td> <td>0.01%</td> </tr> </tbody> </table>				Input Type	Input Range	Accuracy	Resolution	Voltage	0-5V	+/- 0.5%	1 mV	0-10V	+/- 0.5%	1 mV	-5V to 5V	+/- 0.5%	1 mV	-10V to 10V	+/- 0.5%	1 mV	Current	0(4)-20mA	+/-1%	1 µA	0-200mA	+/-1%	1 µA	Resistive	30-250kΩ	+/-1%	1 Ω for lower ranges 1 kΩ for higher ranges	Frequency	0.5Hz-50Hz	+/-0.3%	0.01 Hz	10Hz-1kHz	+/-0.3%	0.1 Hz	100Hz-20kHz	+/-0.3%	1 Hz	PWM	Low Frequency	+/-0.1%	0.01%	High Frequency	+/-0.1%	0.01%
Input Type	Input Range	Accuracy	Resolution																																														
Voltage	0-5V	+/- 0.5%	1 mV																																														
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	100Hz-20kHz	+/-0.3%	1 Hz																																														
PWM	Low Frequency	+/-0.1%	0.01%																																														
	High Frequency	+/-0.1%	0.01%																																														

Table 1.0 –User Programmable Universal Inputs																																																	
Analog & Digital Input Functions	Voltage Input, Current Input, Resistive Input or Digital Input																																																
Voltage Input	0-5 V (Impedance 110 kΩ) 0-10 V (Impedance 130 kΩ) +/- 5V (Impedance 110 kΩ) +/- 10V (Impedance 130 kΩ)																																																
Current Input	0-200 mA (Impedance 5 Ω); 1V max. 0-20 mA (Impedance 249 Ω) 4-20 mA (Impedance 249 Ω)																																																
Resistive	20 Ohms to 250 kOhms Self-calibrating																																																
Digital Input Level	Accepts 5 V TTL Accepts up to Vps Threshold: Low <1 V High >2.2 V																																																
Digital Input	1 M Ω Impedance or Active High or Active Low with 10 kOhm pull-up or pull-down																																																
Timer Input Functions	PWM Input, Frequency Input, RPM Input																																																
PWM Input	Low Frequency (0.50 Hz to 1 kHz) High Frequency (100 Hz to 10 kHz) 0 to 100% D.C.																																																
Frequency/RPM Input	0.5 Hz to 50 Hz; 10 Hz to 1 kHz; or 100 Hz to 20 kHz																																																
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Outputs

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Voltage Reference	<p>+5V, +/- 0.5%, 50 mA Ground is shared with Input Grounds.</p>																																																
Protection for Output Terminals	<p>Fully protected against short circuit to output ground. Unit will fail safe in the case of a short circuit condition, self-recovering when the short is removed.</p>																																																

General Specifications

Microprocessor	STM32F205VGT7 32-bit, 1MByte flash memory
Isolation	300 Vrms 4-way Digital Isolation (Power, Inputs, Outputs and CAN are isolated from each other.)
Typical Quiescent Current	125 mA@ 12Vdc; 65 mA @ 24Vdc typical
Response Time	30 mSec
LED Indicators	2 bicolour LED's (Red and Green) Power, heartbeat, input fault indication and output fault indication
Simulink® Block Library	Model AX130540 was developed using Simulink®. Simulink® is a model-based design tool from Mathworks®.
CAN Communications	1 Isolated CAN port (SAE J1939) (CANopen® on request) Models: AX130540 – Auto Baud Rate (250 kbps, 500 kbps, 1 Mbps)
NFC Communications	Near Field Communication Full-duplex Data rate: 106 <u>kbit/s</u> Complies with ISO1443 (RF protocol), ISO13239, and ISO7816 Protected and secure configuration
User Interface	E-WRITE NFC Application is available from the Google Play Store for simple configurations.
Software Reflashing	Electronic Assistant P/N: AX070502
User Interface	The AX130540 setpoints can be viewed and programmed using the standard J1939 memory access protocol through the CAN port and the PC-based Axiomatic Electronic Assistant. The EA can store all setpoints in one setpoint file and then flash them into the unit in one operation. The setpoint file is created and stored on disk using a command <i>Save Setpoint File</i> from the EA menu or toolbar. The user then can open the setpoint file, view or print it and flash the setpoint file into the AX130540. The Electronic Assistant, P/N: AX070502 , for <i>Windows</i> operating systems comes with a royalty-free license for use on multiple computers. It includes an Axiomatic USB-CAN converter to link the device's CAN port to a <i>Windows</i> -based PC.
Operating Conditions	-40 to 85 °C (-40 to 185 °F)
Storage Temperature	-55 to 125 °C (-67 to 257°F)
Protection	IP20
Weight	0.30 lb. (0.136 kg)
Enclosure and Dimensions	Phoenix Contact: ME MAX 22,5 G 2-2 KMGY – 2713638 Polyamide, UL94V0, cULus recognized, China RoHS DIN rail TH 35-7.5 99 x 114.5 x 22.5 x 99 mm (L x H x W x D) Refer to Figure 2.0.
Electrical Connections	4 Phoenix Contact PSPT 2,5/ 4-ST KMGY spring clamp connectors Accepts 24-14 AWG wire. Refer to Table 3.0 and Figure 2.0. for pin out.
Installation	DIN rail mount TH 35-7.5
Network Termination	It is necessary to terminate the network with external termination resistors. The resistors are 120 Ohm, 0.25W minimum, metal film or similar type. They should be placed between CAN_H and CAN_L terminals at both ends of the network.

Dimensional Drawing

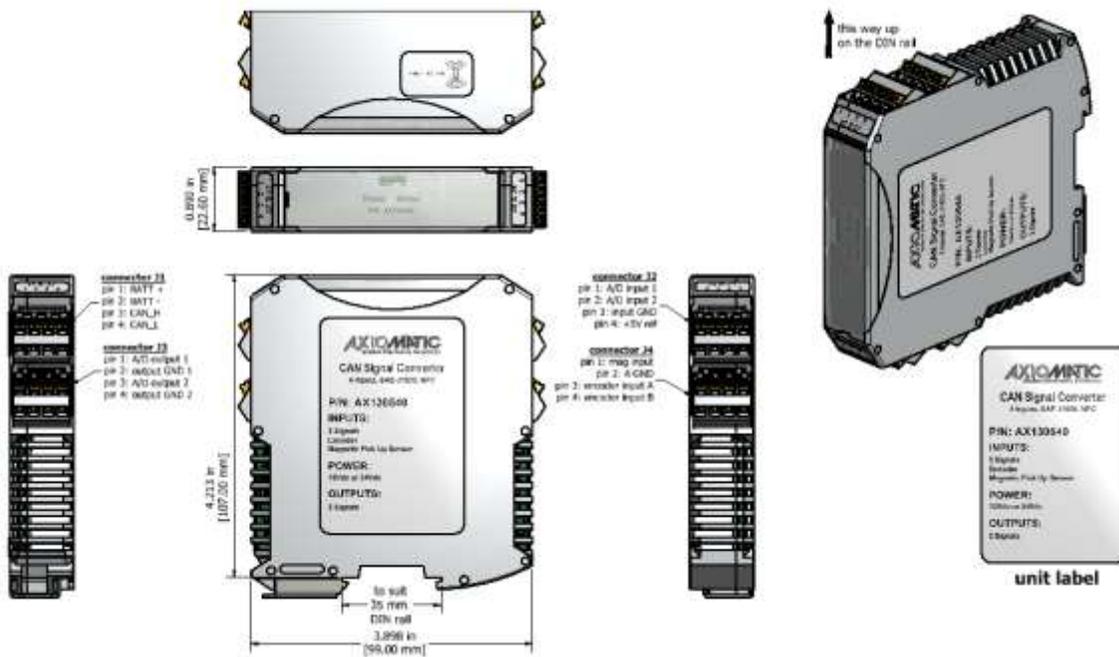


Table 43 – Pin Out

Power and CAN (J1)		Outputs (J3)		Inputs (J2)		Reference and GNDs (J4)	
PIN #	Function	PIN #	Function	PIN #	Function	PIN #	
1	BATT +	1	Output 1+	1	Universal Signal Input 1	1	Magnetic Pick Up Input
2	BATT –	2	Output 1-	2	Universal Signal Input 2	2	Common Analog GND
3	CAN_H	3	Output 2+	3	Input GND	3	Encoder Input A
4	CAN_L	4	Output 2-	4	+5V Reference	4	Encoder Input B

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 Simulink® is a registered trademark of The Mathworks, Inc.



OUR PRODUCTS

Actuator Controls
Automotive Ethernet Converters
Battery Chargers
CAN bus Controls
CAN/Wifi, CAN/Bluetooth
Current/Voltage Converters
DC/DC Power Converters
Engine Temperature Scanners
Ethernet/CAN Converters, Switches
Fan Drive Controllers
Gateways, CAN/Modbus Protocols
Gyroscope Inclinometers
Hydraulic Valve Controllers
Inclinometers, Triaxial
I/O Controls
LVDT Simulators
Machine Controls
Modbus Controls
Motor Controls
Power Supplies
PWM Signal Converters/Isolators
Resolver Signal Conditioners
Service Tools
Signal Conditioners, Converters
Strain Gauge CAN Controls
Surge Suppressors

OUR COMPANY

Axiomatic provides electronic machine controls, components, and systems to the off-highway, commercial vehicle, electric vehicle, power generator set, material handling, renewable energy and industrial OEM markets.

We innovate with engineered and off-the-shelf machine controls that add value for our customers. We emphasize service and partnership with our customers, suppliers, and employees to build long term relationships and mutual trust.

QUALITY DESIGN AND MANUFACTURING

Axiomatic in Canada operates an ISO 9001:2015 registered design and manufacturing facility.

SERVICE

All products to be returned to Axiomatic require a Return Materials Authorization Number (RMA#). Please request an RMA# from sales@axiomatic.com.

Please provide the following information when requesting an RMA number:

- Serial number, part number
- Axiomatic invoice number and date
- Hours of operation, description of problem
- Wiring set up diagram, application
- Other comments as needed

All products should be serviced by Axiomatic. Do not open the product and perform the service yourself.

DISPOSAL

Axiomatic products are electronic waste. Please follow your local environmental waste and recycling laws, regulations and policies for safe disposal or recycling of electronic waste.

WARRANTY, APPLICATION APPROVALS/LIMITATIONS

Axiomatic Technologies Corporation reserves the right to make corrections, modifications, enhancements, improvements, and other changes to its products and services at any time and to discontinue any product or service without notice. Customers should obtain the latest relevant information before placing orders and should verify that such information is current and complete. Users should satisfy themselves that the product is suitable for use in the intended application. All our products carry a limited warranty against defects in material and workmanship. Please refer to our Warranty, Application Approvals/Limitations and Return Materials Process as described on www.axiomatic.com/service.html.

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