

???????BMS?

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CAN ???

CAN [] [] Orion_BMS2 : 0x301 0x300 0x2FF 0x200 0x210 [] PM100DX: 0x0A5 0x0A2

[] CAN RX [] UART [] CAN[] [] []

void decode DATA[] RX [] [] DATA[]

[] 6v 0.3A STM 5v 0.2A

CAN ACK [] [] TTRECO9

CAN-R02A ??????????

title: CAN-R02A ?????????? tags:
Manual, CAN-R02A, ???

CAN-R02A ??????????



[TOC]

1. ?????

:::info [] CAN-R02A [] 2 [] CAN []

- [] [] USB [] OBD-II []
- [] []
- [] [] USB [] :::

2. ????????

[]	[]
[] (USB [])	[] 4.7-5.5V [] 135mA/5V [] 70uA/5V
[] (OBD-II [])	[] 6-32V [] 40mA/24V [] 85uA/5V
[]	-40°C ~ +80°C
[]	5%~95% RH []
[]	TF [] 512G

項目	仕様
CAN 規格	ISO 11898
CAN 速度	10Kbit/s ~ 1Mbit/s
CAN 標準	ISO 11898 CAN2.0A/B
CAN 抵抗	120Ω
CAN 送信遅延	8000 ns
CAN 受信遅延	5us
外形寸法	88 x 47.6 x 25.6 (mm)

3. OBD-II ?????

端子番号	電圧	機能
16	6-32V	電源
4	接地	接地
6	CAN1_H	
14	CAN1_L	
3	CAN2_H	
11	CAN2_L	
15	接地	
その他		1, 2, 5, 7, 8, 9, 10, 12, 13

4. ?????????

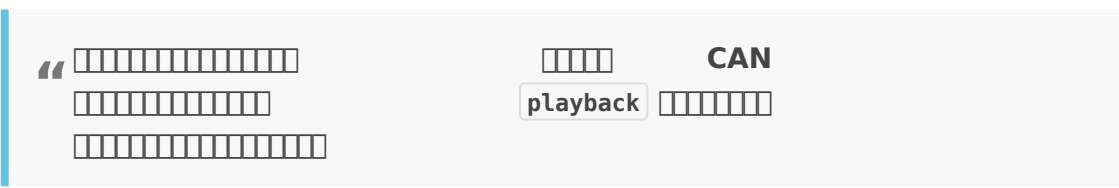
項目	仕様
電源	2 線 (電源) 0.5 線 (接地)
TF 端子	2 線 (電源) 0.5 線 (接地)
CAN 規格 (ISO 11898)	2 線 CAN 規格 2 線 CAN 規格
CAN 速度 (10Kbit/s ~ 1Mbit/s)	2 線 CAN 規格 2 線 CAN 規格
抵抗	2 線 CAN 規格 2 線 CAN 規格

- FAT FAT32 exFAT
- 16K-128K

10. ?????

?????????

- [] []
- [] [] + [] + [] + []
- [] []



?????????

- [] TF [] playback []
- [] []
- [] [] playback [] (TRC, ASC, CAN, CSV)
- [] [] 1 [] 1 [] 2 [] 1

PCAN-Explore 6 - ??symbol

image

??

????

Enums	signals	symbols
image	image	DBC image

image






Eenums

image

Symbols

image

PCAN-Explore 6 tutorial

1. 
2. 
3.  symbol
4. 
5. GUI 
- 6.

image

SavvyCAN ??????.asc ??? PCAN ?????

[TOC]

1. ??

SavvyCAN [Progress Bar]

CAN Bus [Progress Bar]

1. [Progress Bar] [Progress Bar] Vector [Progress Bar] .asc [Progress Bar]
2. [Progress Bar] **(Live Stream)** [Progress Bar] PCAN [Progress Bar] CAN Bus [Progress Bar]

- [Progress Bar] [SavvyCAN.com](#)
- [Progress Bar] : [csselectronics.com](#)
- [Progress Bar] : [SavvyCAN V189 documentation](#)
- [Progress Bar] [Progress Bar] PCAN, Kvaser, SocketCAN, ESP32 [Progress Bar]

2. ?? .asc ?? (Import Data)

[Progress Bar]

Vector CANalyzer/CANoe [Progress Bar]

1. [Progress Bar] SavvyCAN [Progress Bar]
2. [Progress Bar] **File** [Progress Bar]
3. [Progress Bar] **Load File...** ([Progress Bar] Import "Vector ASC" File) [Progress Bar]
4. [Progress Bar] [Progress Bar] .asc [Progress Bar]

:::info [Progress Bar] [Progress Bar] [Progress Bar] >500MB

[Progress Bar]

:::

3. ????????

[Progress Bar]	[Progress Bar]	[Progress Bar]
[Progress Bar]	Frame List	[Progress Bar] CAN [Progress Bar] (ID, Data) [Progress Bar]

□□	□□	□□□□
□□□□	Graphing Window	□□□□□□□□
□□□□	Connections/DBC	□□□□□□□□ DBC □□□□

4. ?? DBC ??????? (Decode)

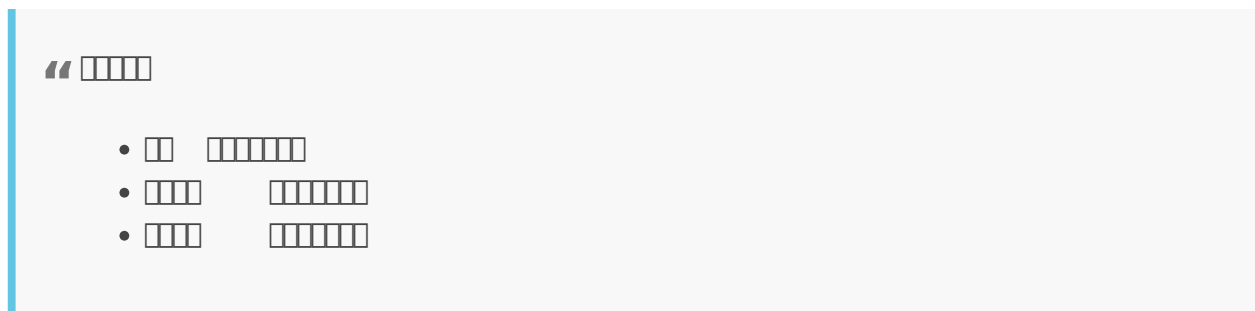
□□□□ DBC□□□□□□□□ HEX □□□□

1. □□□□ **File -> Load DBC File...**□
2. □□□□ □□□□
3. □□□□□□ **Frame List** □□□□□□□□
4. □□□□□□□□□□ **"Signals"** □□□□□□□□□□ (□ Speed, RPM)□

5. ?????? (Graphing)

□□□□□□□□ SavvyCAN □□□□

1. □□ DBC □□□□
2. □□□□□□□□□□□□□□ **CAN ID**□
3. □□□□□□ (Signal List) □□ □□ □□□□□□□□
4. □□□□ **Graph Window** □□□□□□□□



6. ????? ID (Filtering)

1. □□□□□□□□ **Filter** □□□□
2. □□ ID (□□ Hex □□□□ □)□
3. □□□□□□□□□□ ID□

4. ???????? (The Math)

VESC [REDACTED]

A. ??? (Pole Pairs) ? ERPM

VESC [REDACTED] **ERPM (Electrical RPM)** [REDACTED]

1. Pole Pairs (???) ??

$$\text{Pole Pairs} = \frac{\text{[REDACTED]} \text{ (Magnets)}}{2}$$

- [REDACTED] 16 [REDACTED] \rightarrow **8 Pole Pairs**
- [REDACTED] [REDACTED] Motor Settings > General > Additional Info [REDACTED]

2. ERPM ????

$$\text{ERPM} = \text{[REDACTED]} \text{ (RPM)} \times \text{Pole Pairs}$$

- [REDACTED] 300 RPM [REDACTED] 8
- $\text{ERPM} = 300 \times 8 = 2400$

3. ?????????? (???? 25 km/h)?

[REDACTED] 26 [REDACTED] ([REDACTED] 2.07m) [REDACTED] 8 [REDACTED]

- [REDACTED] **RPM** $25 \text{ km/h} \approx 417 \text{ m/min}$ $\text{RPM} = 417 / 2.07 \approx 201 \text{ RPM}$
- [REDACTED] **ERPM** $\text{Limit ERPM} = 201 \times 8 = 1608 \text{ ERPM}$
- [REDACTED] [REDACTED] General > RPM > Max ERPM [REDACTED] 1608 ([REDACTED])
1:5 [REDACTED] ERPM [REDACTED] 5)

B. ?? vs ??? (Current vs Duty Cycle)

[REDACTED]

???? (Mermaid Chart)

```
graph LR
  A[REDACTED] --> B[REDACTED]
  B -- Current Control --> C[REDACTED/REDACTED]
  B -- Duty Cycle --> D[REDACTED/REDACTED]
  C --> E[REDACTED: REDACTED]
```

D --> F[[]: [][]]