
MEX PDI Builder

Release 6.12.46

Embention

2025-02-11

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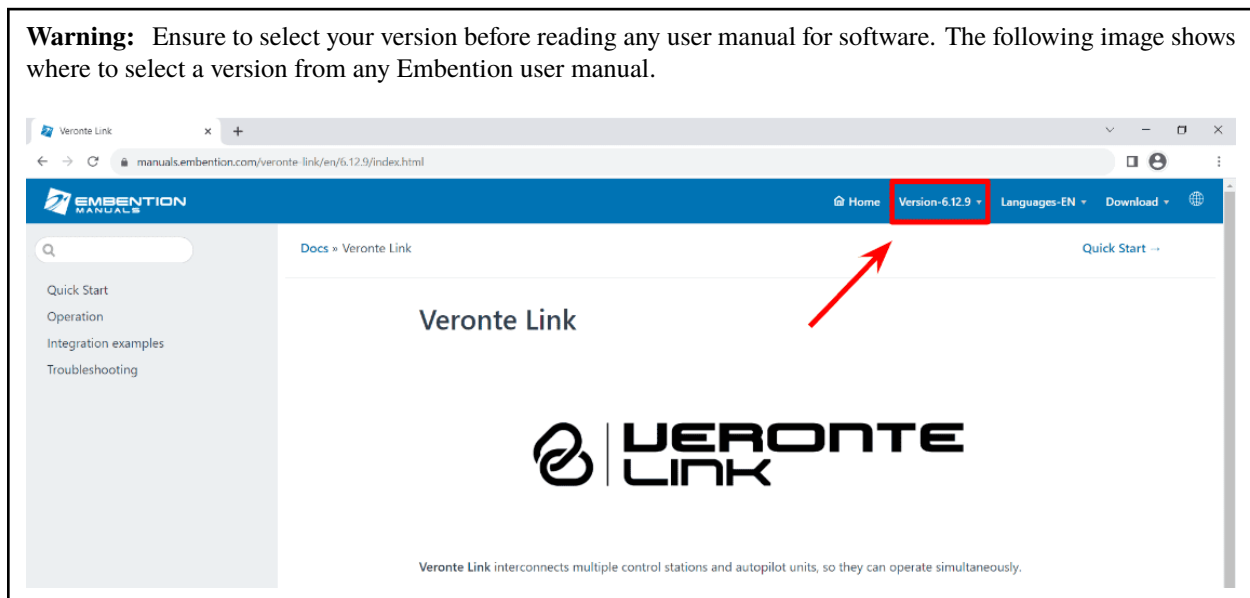
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MEX | PDI BUILDER

MEX PDI Builder is used to set all the configurable parameters of **MEX** (Magnetometer CAN Expander). **MEX** can be adjusted according to different inputs, outputs, CAN communications, sticks, arbitrations and telemetries.

Warning: Ensure to select your version before reading any user manual for software. The following image shows where to select a version from any Embention user manual.



QUICK START

MEX PDI Builder is the main configuration tool to adapt a **MEX** to a specific vehicle, including user-defined communication protocols. It includes:

- Telemetry: real-time onboard UAV metrics, such as sensors, actuators and control states.
- Communications: through General Purpose Inputs and Outputs, PWMs and CAN channels.
- Stick control signal management: compatible with **Stick Expander**, Futaba, Jeti, FrSky and TBS. It includes custom configuration for other sticks.
- Arbitration: **MEX** is able to send PWM signals using arbitration in the same way **Veronte Autopilot 4x** does.

1.1 System Requirements

Before executing this software, users should check the following sections with the minimum and recommended PC hardware requirements.

Minimum requirements

- CPU: Intel Core i5-8365UE
- RAM: 8 GB DDR4
- STO: 256 GB SSD

Recommended requirements

- CPU: 12th Gen Intel(R) Core(TM) i7-12700H 14 cores up to 4,70 GHz
- RAM: 32 GB
- STO: 1 TB SSD M.2 NVMe PCIe

1.2 Download

Once the **MEX** has been purchased, a GitHub release should be created for the customer with the application.

To access to the release and download the software, read the [Releases](#) section of the **Joint Collaboration Framework** manual.

1.3 Installation

To install **MEX PDI Builder** on Windows just execute the “MEXPDIBuilder.exe” file and follow the indications of the *Setup Wizard*. Administrator rights are needed.

Warning: If users have any problems with the installation, please disable the antivirus and the Windows firewall. Disabling the antivirus depends on the antivirus software.

To disable the firewall, go to “Control Panel” → “System and Security” → “Windows Defender Firewall” and then, click on “Turn windows Defender Firewall on or off”.

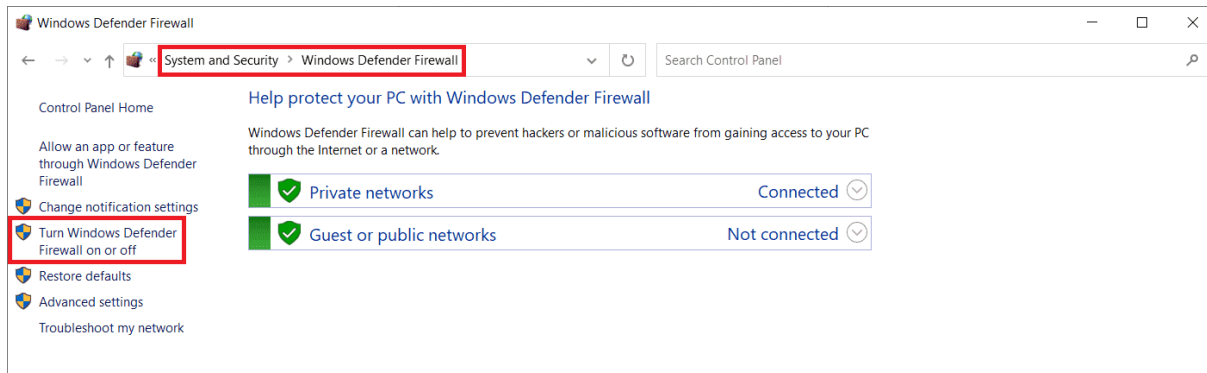


Fig. 1: Windows Defender Firewall

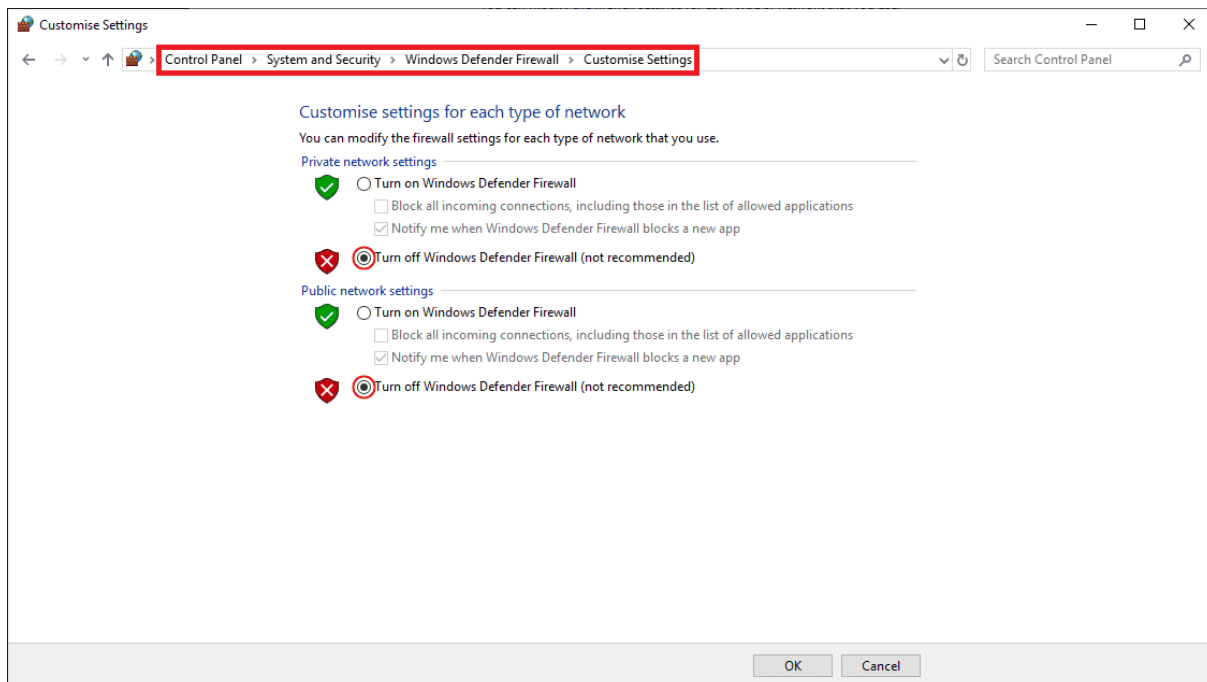


Fig. 2: Windows Defender Firewall: Settings

CONFIGURATION

This section explains each option and parameter available in **MEX PDI Builder**.

Once the installation is finished, open **MEX PDI Builder** and select the unit.

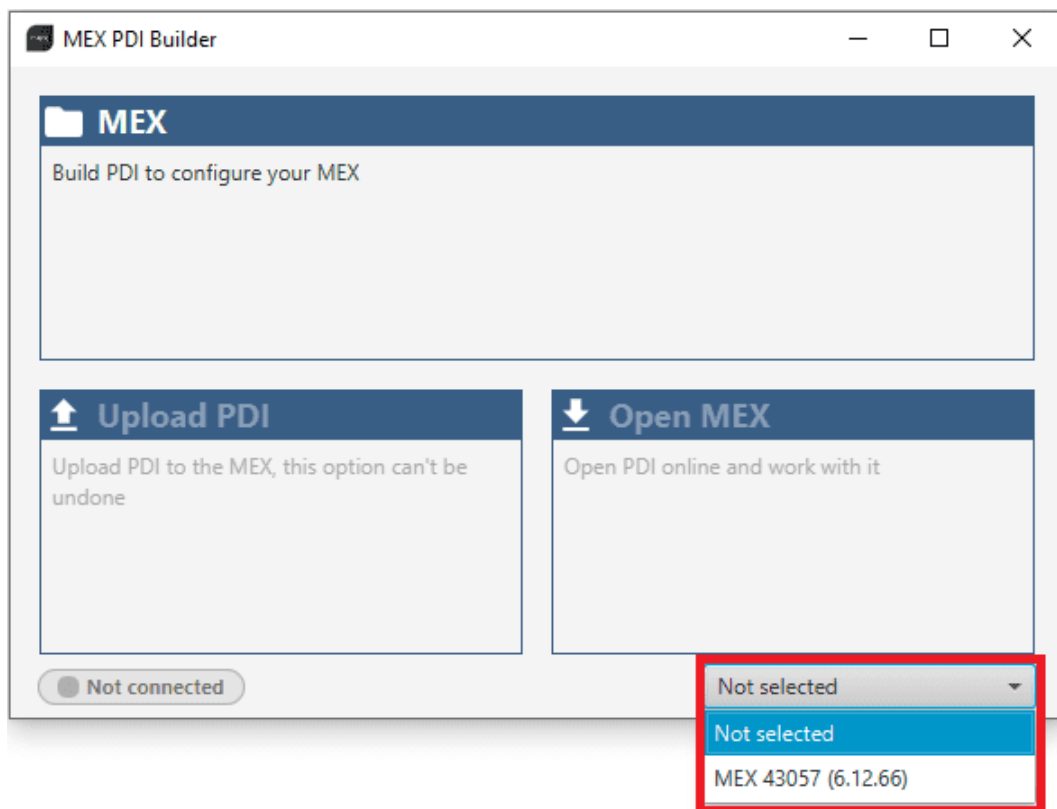



Fig. 1: MEX ID

If correctly connected, **MEX PDI Builder** will display the **mode** in which the connected unit is. In addition, a **PDI error button**  will appear:

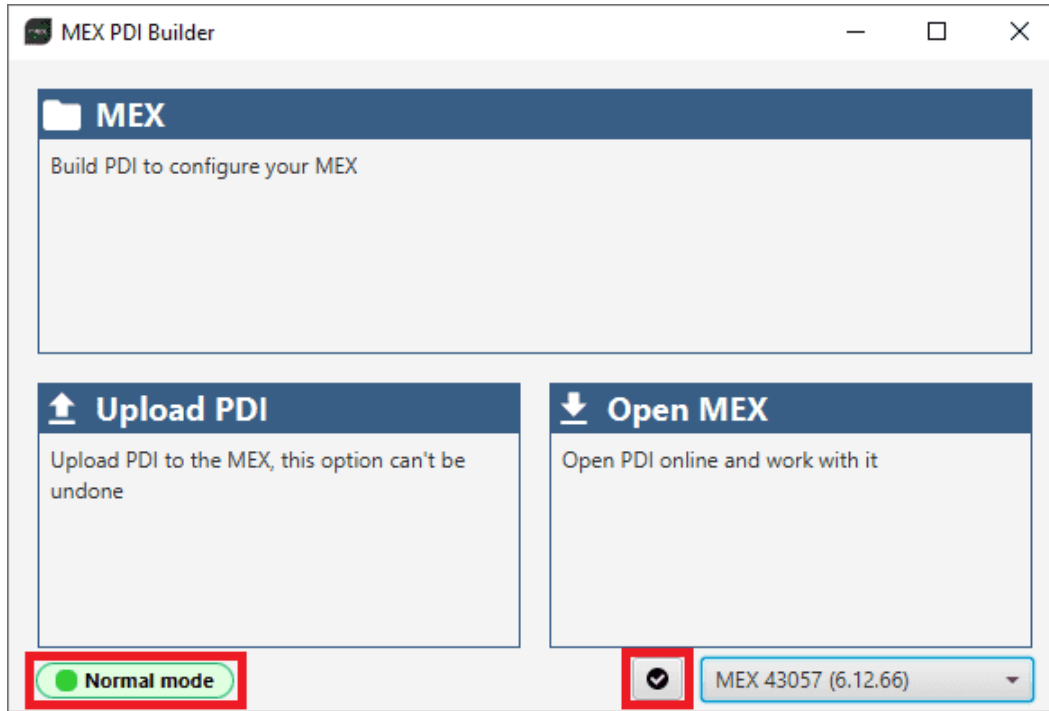


Fig. 2: MEX PDI Builder

- **MEX mode:** The MEX unit should appear in **Normal mode**, as shown in the figure above, or **Maintenance mode**.

It can also appear as **Maintenance mode (loaded with errors)** or **Normal mode - Disconnected**.

Note: **Maintenance mode (loaded with errors)** appears when something went wrong in the configuration. For more information, see *Maintenance mode (loaded with errors) - Troubleshooting* section of this manual.


-  **PDI Errors** button: The user can check if the connected unit has PDI Errors by simply clicking on it. If there are no errors, the following message appears:



Fig. 3: MEX PDI Builder - PDI Errors message

The user can access now to 3 configuration options:

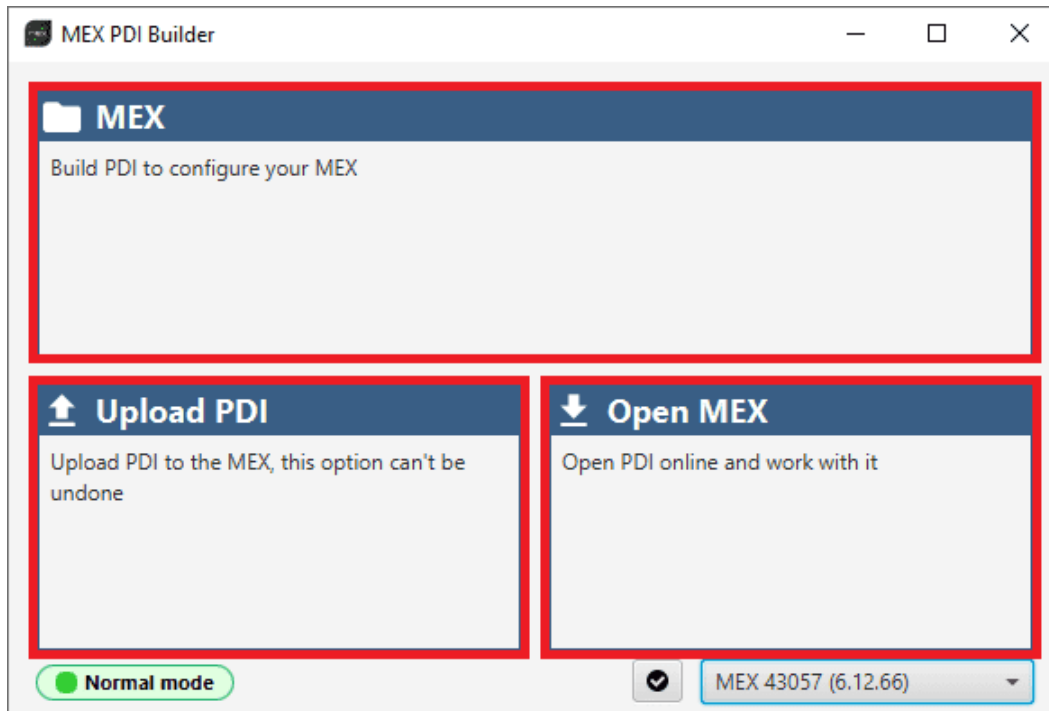


Fig. 4: MEX PDI Builder options

- **MEX:** It allows the user to work with **offline** configurations. A previously exported MEX PDI configuration can be opened and modified or it is also possible to build a new one from the default configuration.
- **Upload PDI:** A previously exported **MEX PDI configuration** can be imported to the linked **MEX**.

Warning: When a configuration is loaded into MEX with a version older than the software version being used, an **automatic migration** from the configuration version to the software version being used will be performed.

For more information on this, see [Migrate configuration - Troubleshooting](#) section of this manual.

- **Open MEX:** By clicking on this option, **MEX PDI Builder** configuration menu opens with the configuration (the PDI files) loaded in the MEX. Then, the user can modify it **online**.

Note: PDI files are the files that contain the configuration of the **MEX**. These files are located in a single folder, *setup*, which contains several .xml files, where all parameters and the control system are stored.



Fig. 5: PDIs files

Finally, click on ‘MEX’ to edit a configuration offline or ‘Open MEX’ to open the configuration and start editing it online.

Note: MEX unit must enter in **Maintenance mode** for the user to start editing, so it is necessary to accept the confirmation panel below.

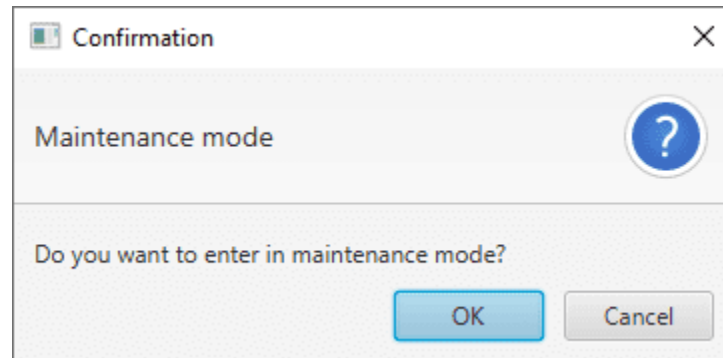


Fig. 6: Enter maintenance mode - Confirmation panel

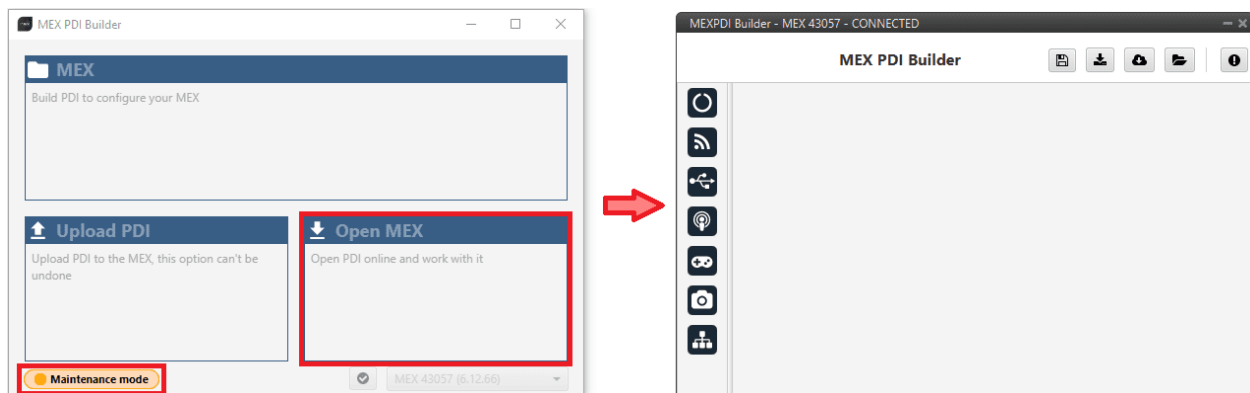


Fig. 7: Open MEX

Once in Maintenance mode, the user can access the *Initial menu*. The different ‘buttons’ that can be seen in this menu of the **MEX PDI Builder** are explained below.

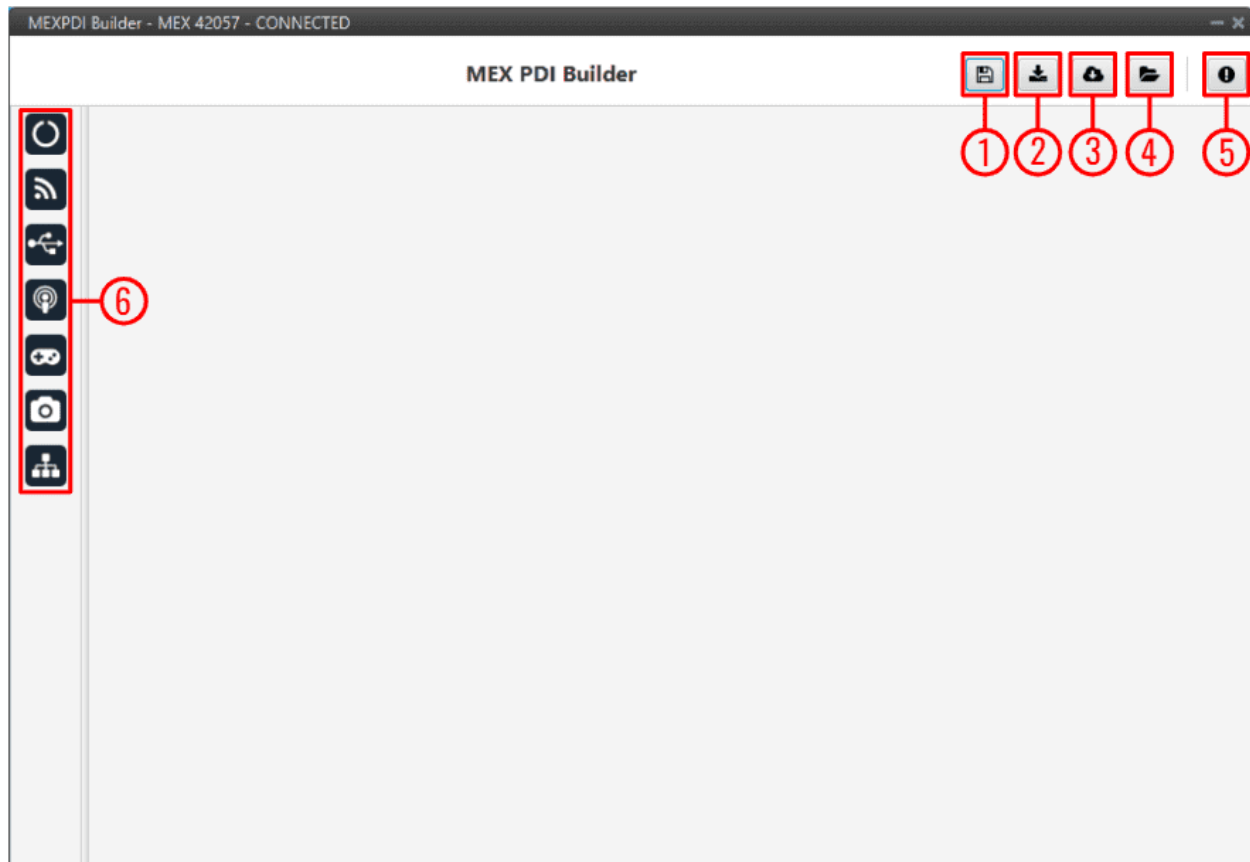


Fig. 8: Initial menu

1. **Save and close:** After changes are done, press on the save button to apply the changes. While saving, a percentage of saving process is displayed.

In order to save the configuration in the **MEX** unit it is necessary to **RESET**, therefore the **MEX PDI Builder** software will close. For this reason, the user must accept the following panels:

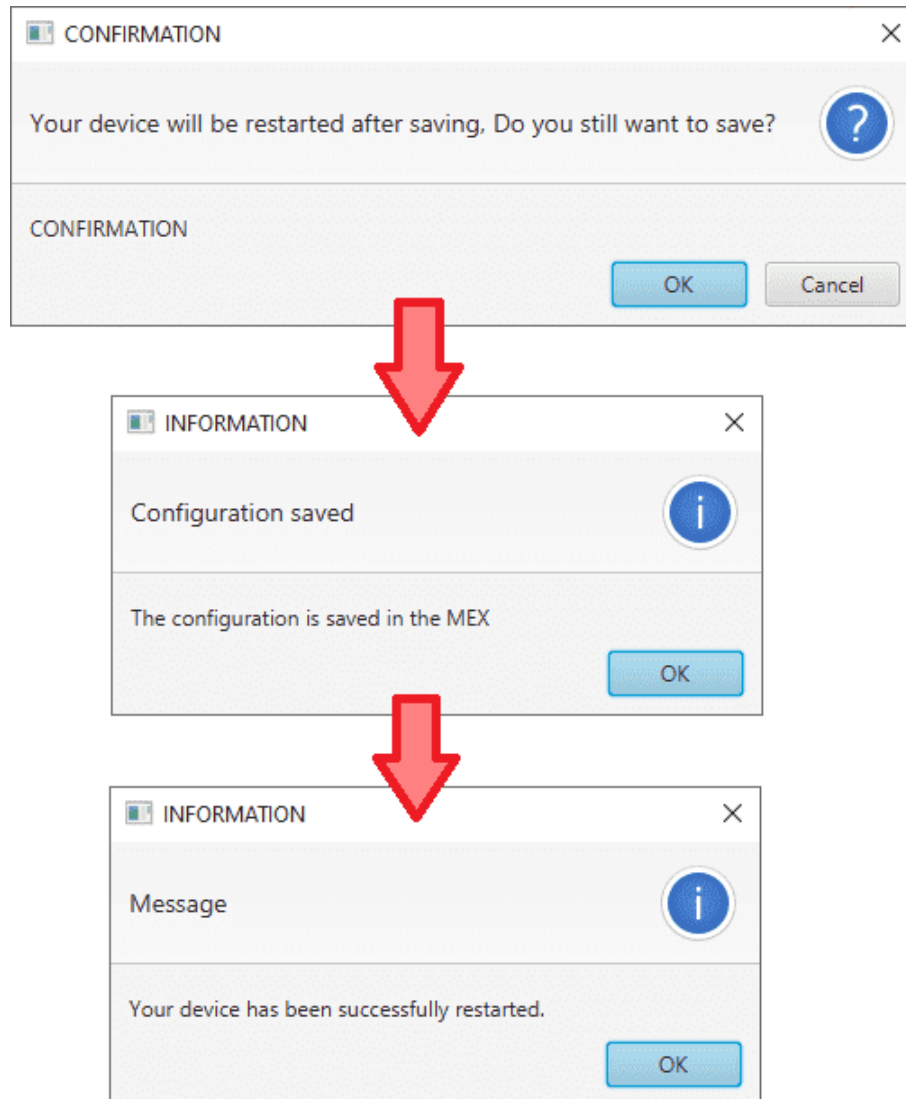


Fig. 9: Save and close - Confirmation panels

Danger: As MEX is **reset**, it is **not advisable to save changes during flight tests**.

Note: This button will only appear if a **MEX** is connected, i.e. when working offline this button will not be available.

2. **Export PDI:** After modifying a configuration, press the export button to store the configuration in the local storage.

Users can store this configuration in an empty folder or in the folder where the previously imported configuration is stored. With the latter option, the “original” configuration will be overwritten by the one with the new changes.

3. **Import PDI from repo:** The user can import a configuration file from the GitHub repository and modify it. After

that, if the **Save and close** button (1) is pressed, this configuration will be uploaded to the connected **MEX**.

4. **Import PDI from local storage:** The user can import a configuration file from the local storage and modify it. After that, if the **Save and close** button (1) is pressed, this configuration will be loaded into the connected **MEX**.
5. **Feedback:** Users can report a problem they have encountered by **creating an issue in their own ‘Joint Collaboration Framework’**. The **‘Download’** button downloads a zipped folder with the current **MEX** configuration and more information needed for Embention to resolve the issue. It is advisable to attach this folder when creating the issue.

Note: The user’s **‘Joint Collaboration Framework’** is simply a **Github repository for each customer**.

In case of having any questions about this Joint Collaboration Framework, please see [Joint Collaboration Framework](#) user manual or contact sales@embention.com.

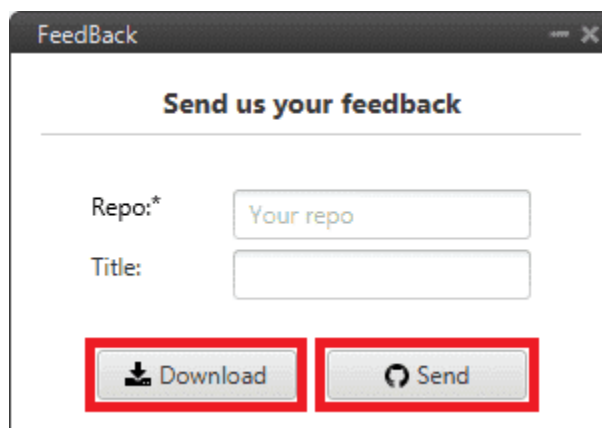









Fig. 10: Feedback window

6. These are the different functions of MEX. They are explained in the following sections.

-  *MEX*
-  *Sensors*
-  *Input/Output*
-  *Communications*
-  *Stick*
-  *Devices*
-  *Arbitration*

2.1 MEX

2.1.1 Mex Base

MEX is able to send information about its version and Jeti telemetry from devices connected to **MEX**, this is the “status message”. It is possible to define the CAN Id used for those messages.

Enable the **Extended** checkbox to use the extended CAN protocol (with a 29-bit identifier), disable it to use the standard protocol (11-bit identifier).

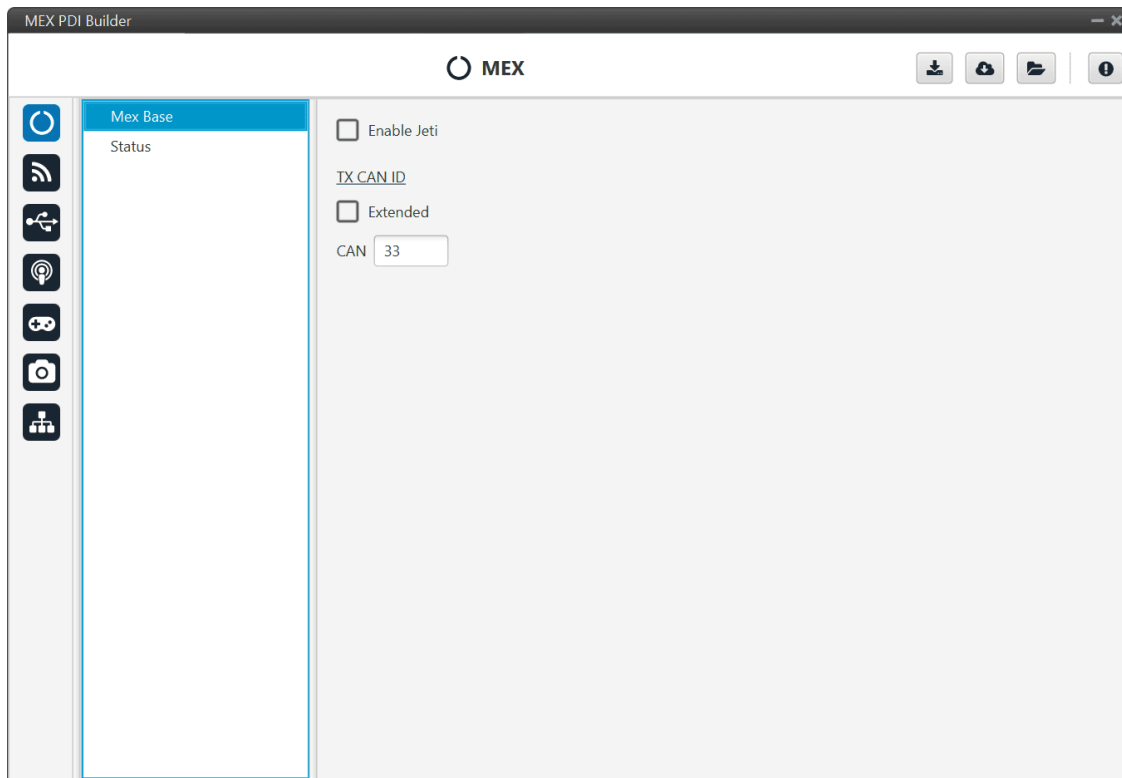


Fig. 11: Mex base panel

2.1.2 Status

This option enables the periodic sending of the status message that **Veronte Link** uses to recognize the **MEX**.

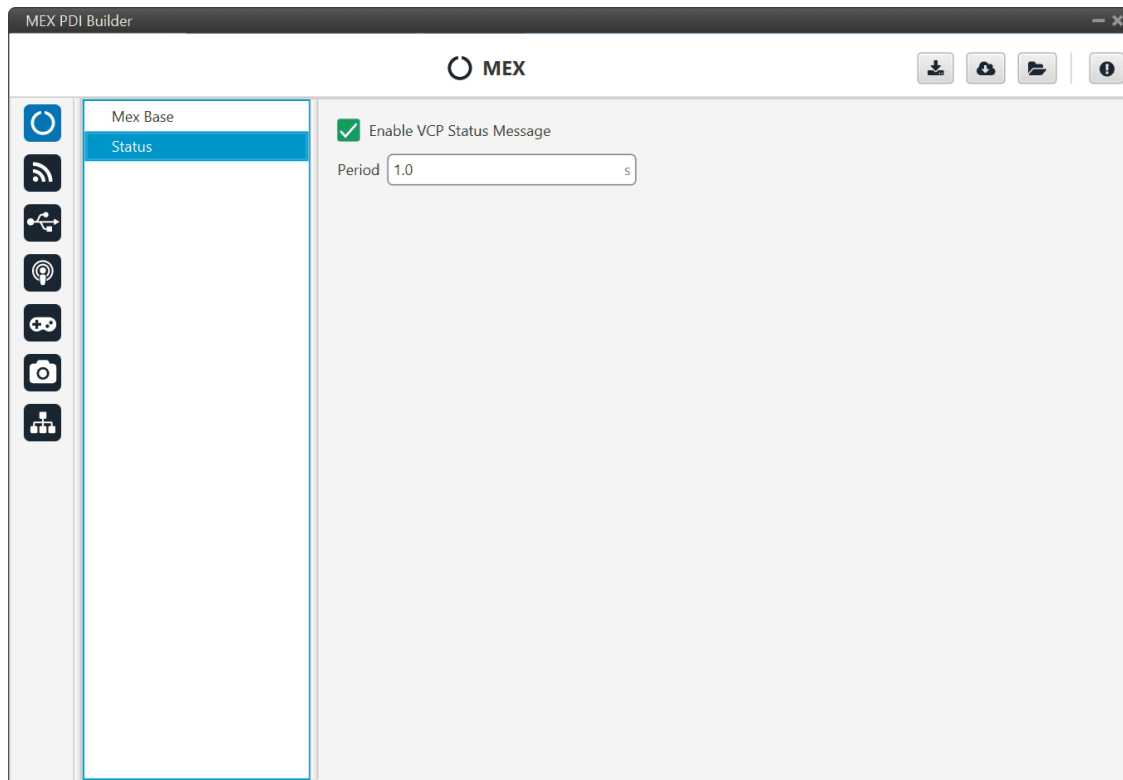


Fig. 12: Status panel

- **Period:** Enter a desired period to send repeatedly the status message.

Note: VCP is the Veronte Communication Protocol. To know more, read the [VCP](#) user manual.

2.2 Sensors

2.2.1 RPM

MEX can measure RPMs by reading from up to four input sources:

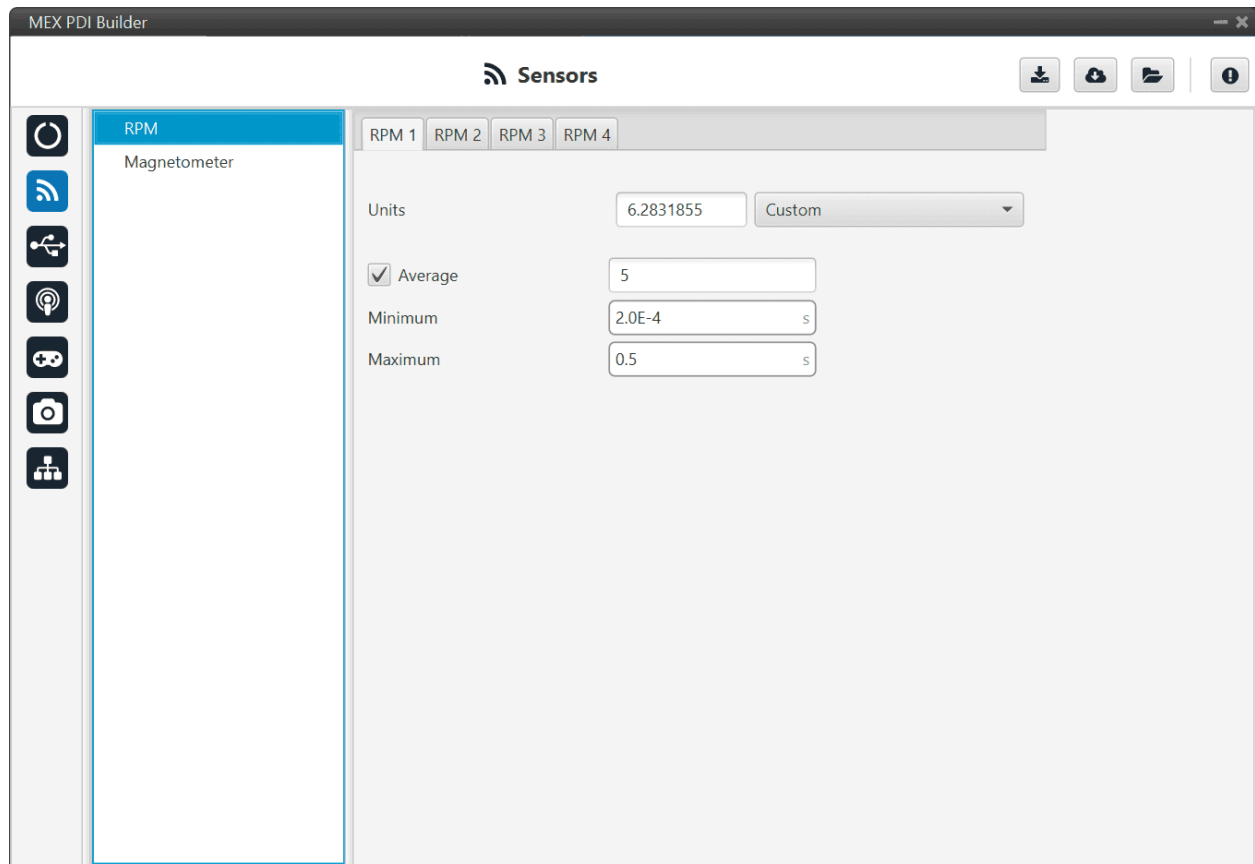


Fig. 13: RPM panel

- **Units:** Sensor conversion factor. It can be *Custom*, *Radians per pulse* or *Pulse per cycle*.
- **Average:** Filter to prevent voltage spikes. The readout of the pulse can be filtered as an average output. The amount of measurements to do the average needs to be specified.
- **Minimum:** Here the minimum expected pulse period needs to be specified. This will discard spurious pulses (e.g. induced by EMI) which are smaller than this minimum pulse.
- **Maximum:** The maximum period of time allowed without capturing. If no incoming pulse is received for more than this time, the output RPMs will be 0.

An example about sending RPMs can be found in [Reading/Sending RPMs - Integration examples](#) section of the present manual.

2.2.2 Magnetometer

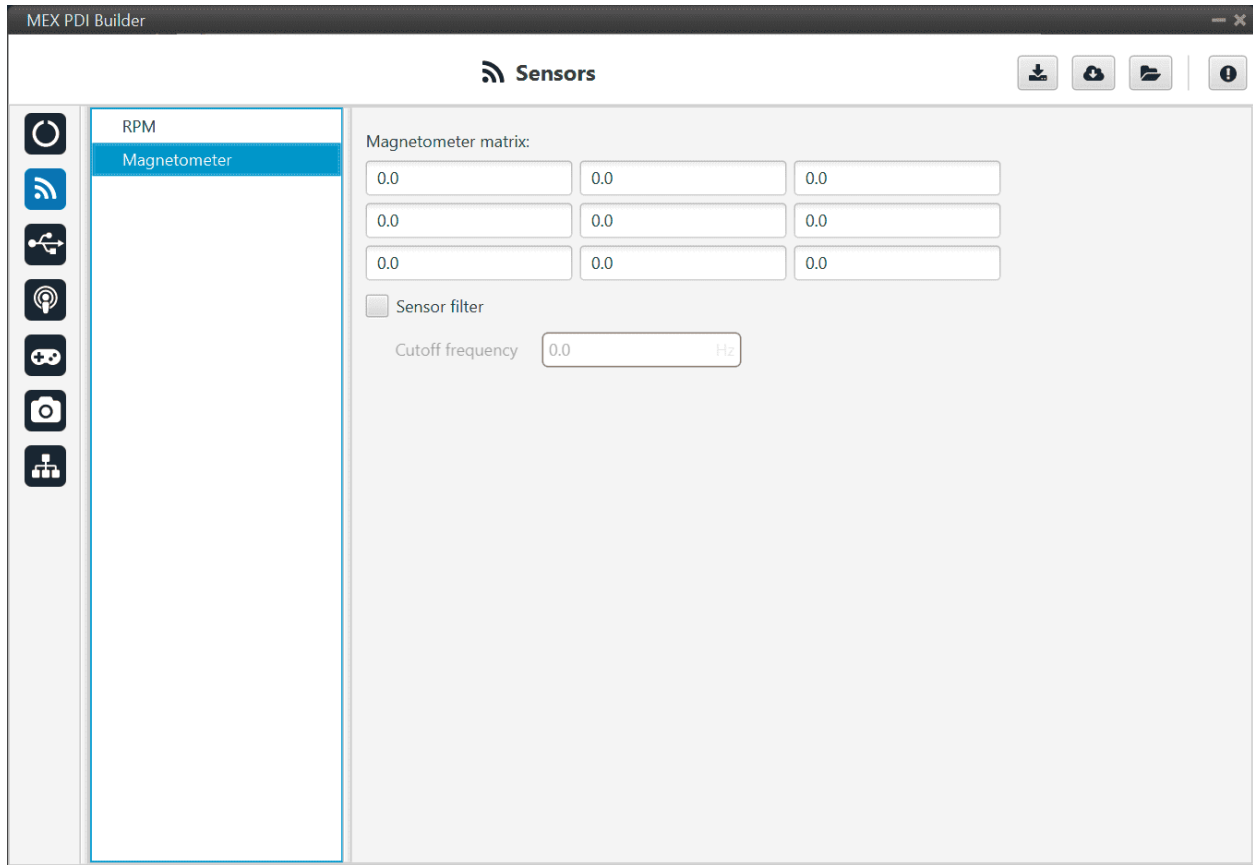


Fig. 14: Magnetometer panel

Magnetometer matrix: This rotation matrix represents the rotation of **MEX** coordinates with respect to the aircraft body. The behavior of the matrix varies depending on how **MEX** is used.

- **If MEX is used independently (without Veronte Autopilot 1x):** The rotation matrix should convert **MEX** coordinates to the **Aircraft Body** coordinates. That is, the conversion is directly from **MEX** to the aircraft coordinates.
- **If MEX is used together with Veronte Autopilot 1x:** The rotation matrix should convert **MEX** coordinates to **Veronte Autopilot 1x** coordinates, and then **Veronte Autopilot 1x** will convert the data to the **Aircraft Body** coordinates; for more information on the rotation matrix of **Autopilot 1x**, please refer to the [Magnetometer - Sensors](#) section of the **1x PDI Builder** user manual. Therefore, the coordinate transformation sequence is: **MEX** → **1xVeronte** → **Aircraft Body**.

Error: The rotation matrix **cannot** be a **zero matrix** and must respect **the orthogonality of the axes**. Not complying with this requirement means an invalid rotation and, consequently, the calibration of this magnetometer will not be possible.

The axis of **MEX** are physically drawn on the device. The **coordinates axis of the aircraft** are like other Veronte products, which are **defined by the Standard Aeronautical Convention**.

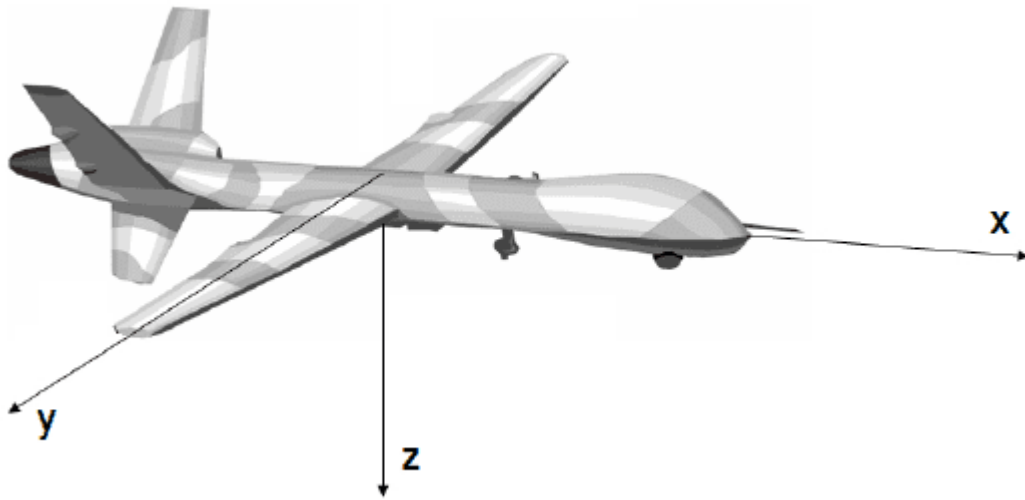


Fig. 15: Aircraft coordinates (Standard Aeronautical Convention)

- **Sensor filter:** The magnetometer measurements may vary with high frequencies and be difficult to read. To solve this problem, **MEX** has this second order low-pass filter to mitigate high frequency variations. It is a **software filter**. This filter can be enabled clicking on this checkbox.
- **Cutoff frequency:** Sensor filter cutoff frequency is manually configured, allowing the user to enter any desired value in Hz. Frequency variations higher than this value will be filtered out (if the filter is enabled).

2.3 Input/Output

2.3.1 GPIO

In this window, each individual GPIO (General Purpose Input/Output) behavior can be configured:

- **Signal:** Pin ID as described in the [Pinout - Hardware installation](#) section of the **MEX Hardware Manual**.
- **GPIOId:** GPIO ID of the microcontroller.
- **IO:** Define GPIO as an input or output.
- **Pull-up:** Enable or disable the pull-up resistance.
- **Function:** Mux 0/GPIO: GPIO, Mux 1: PWM, Mux 2 or Mux 3. These are the different functionalities that the GPIO can have, depending on the multiplexer.

Warning: Check that the corresponding **Enable** checkbox in the *PWM menu* is changed.

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- **6 Samples:** Same as **3 samples**, but checking 6 times instead of 3.
- **ASync:** No checks are performed. It is used when it is not used as GPIO.

2.3.2 PWM

In this panel, each PWM can be configured:

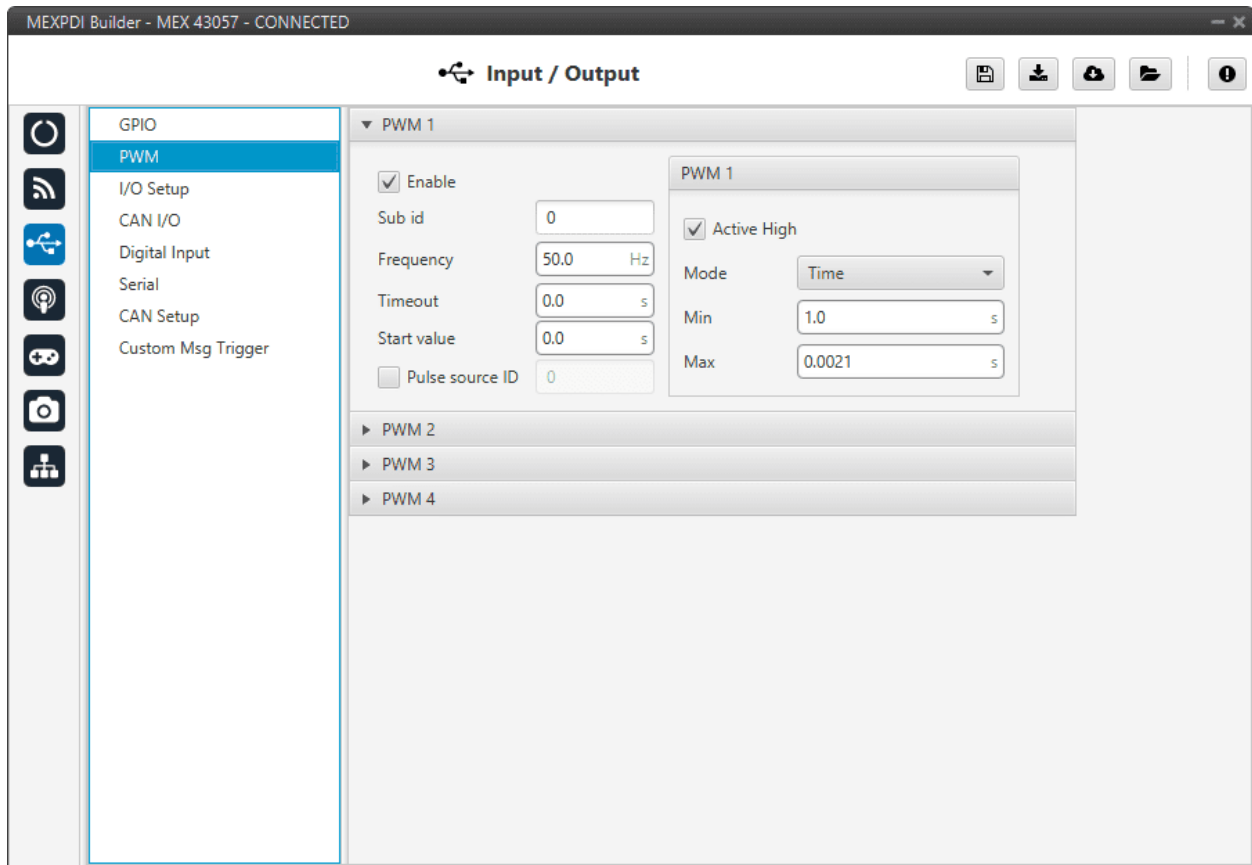


Fig. 17: PWM panel

Note: PWMs in MEX work in normalized mode, when the input value is 0 the output value will be the minimum configured, and when the input value is 4095 (12 bits all with ones), the output will be the maximum configured. This approach allows usage of the maximum resolution for the commanded value.

- **Enable:** Defines if the PWM is enabled or not.

Note: This checkbox disables the pin as GPIO and enables it as PWM. Hence, in the *GPIO menu* the “Function” parameter shall change to “**Mux 1**”.

- **Sub id:** Identifies the sub-id of the PWM and, according to this value, determines the command to be used using one type of CAN message or another.
- **Frequency:** PWM output frequency. This determines the period of the pulses sent by the MEX

- **Timeout:** If a PWM message is not received in less than this time, the PWM will send as output the start value.
- **Start value:** Value used before any PWM message arrives and on timeout.
- **Pulse source ID:** PWM input ID [0,3], defined in the *Digital Input panel*.
- **Active High:** Polarity high or low (high if enabled).
- **Mode:** The available options are **Time** and **Duty cycle**.
 - **Time:** The values indicated in **Min** and **Max** parameters are expressed in time units.

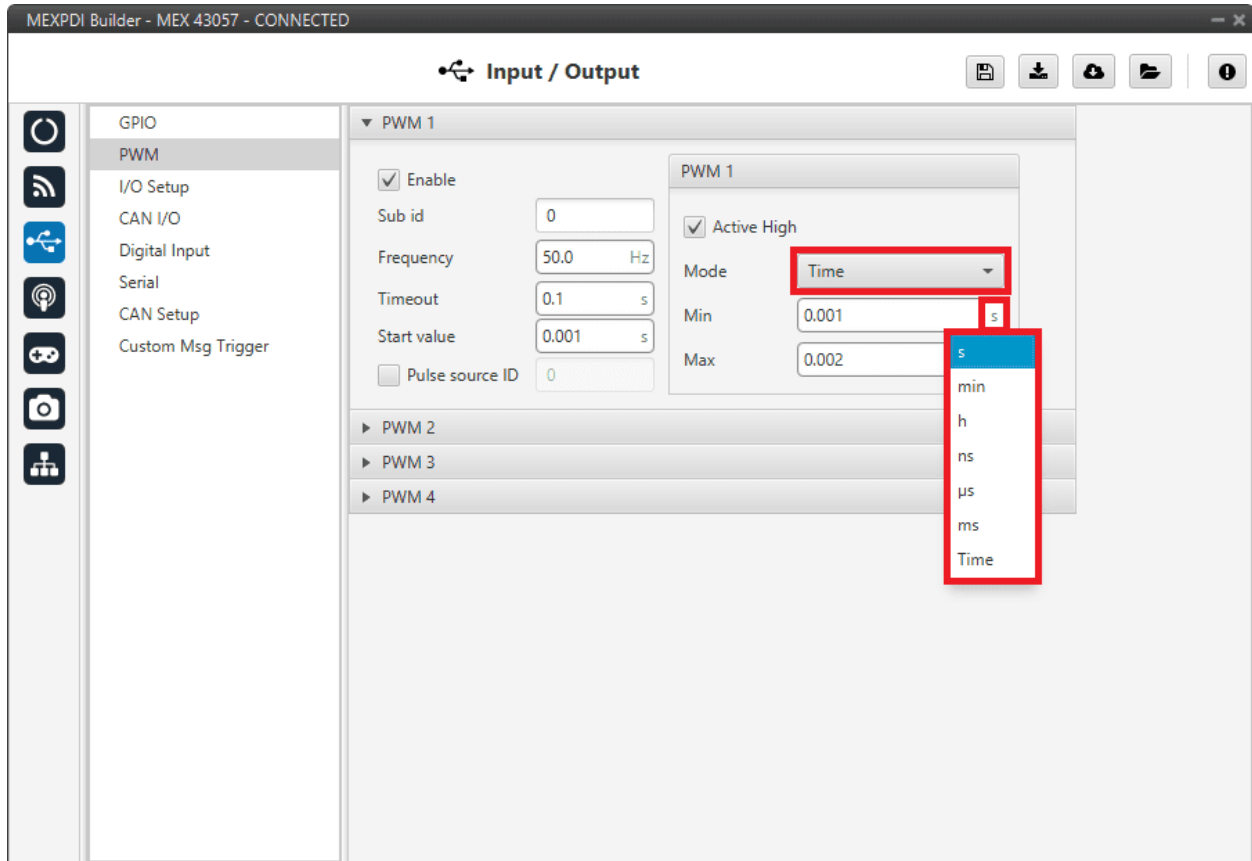


Fig. 18: PWM panel - Time units

- **Duty cycle:** This option is a different way of indicating the pulse width. Now the value indicated in **Min** and **Max** parameters is a percentage which corresponds to the relation between the pulse width over the total period of the sent signal.

So a 100% duty cycle will correspond to a signal with a constant value of 1, while a 0% duty cycle implies a constant signal with value 0. Between this two extremes, the pulse width can vary as in the examples shown in the following figure.

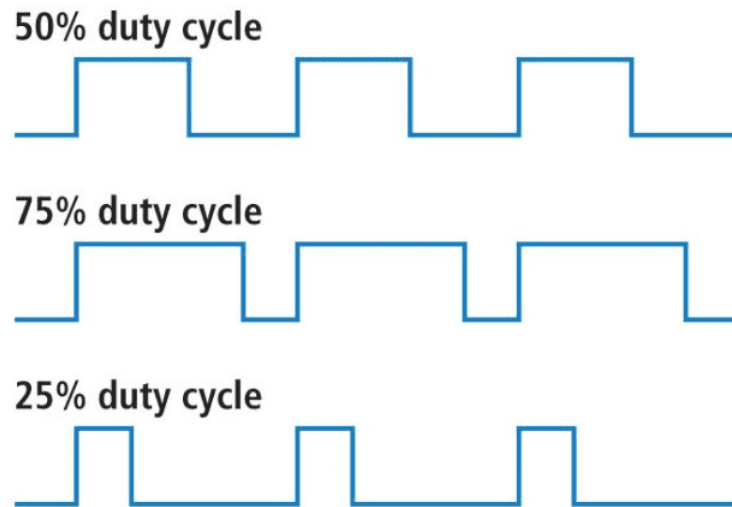


Fig. 19: Duty cycle

Note: Duty cycle percentages can be expressed in percent and per unit.

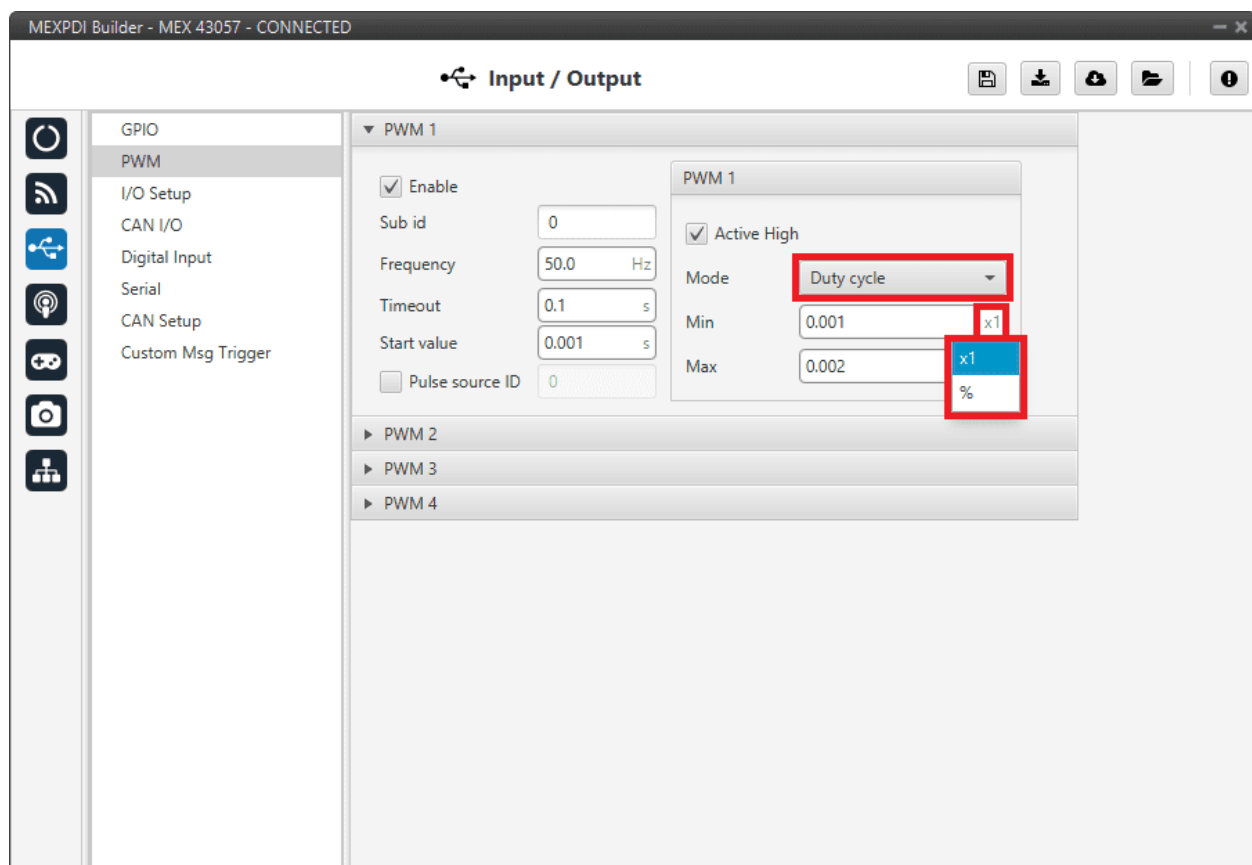


Fig. 20: PWM panel - Duty cycle units

- **Min:** This parameter is the pulse width value that will make the servo/actuator go to its **lowest position**. It will be the output when the PWM message specifies **0**.
- **Max:** This parameter is the pulse width value that will make the servo/actuator go to its **highest position**. It will be the output when the PWM message specifies **4095**.

An example about reading PWM signals can be found in *Commanding/Reading PWMs - Integration examples* section of the present manual.

2.3.3 I/O Setup

In this panel the user can establish the relationship between a determined signal with a I/O port. This allows users to configure external sensors, custom messages, etc.

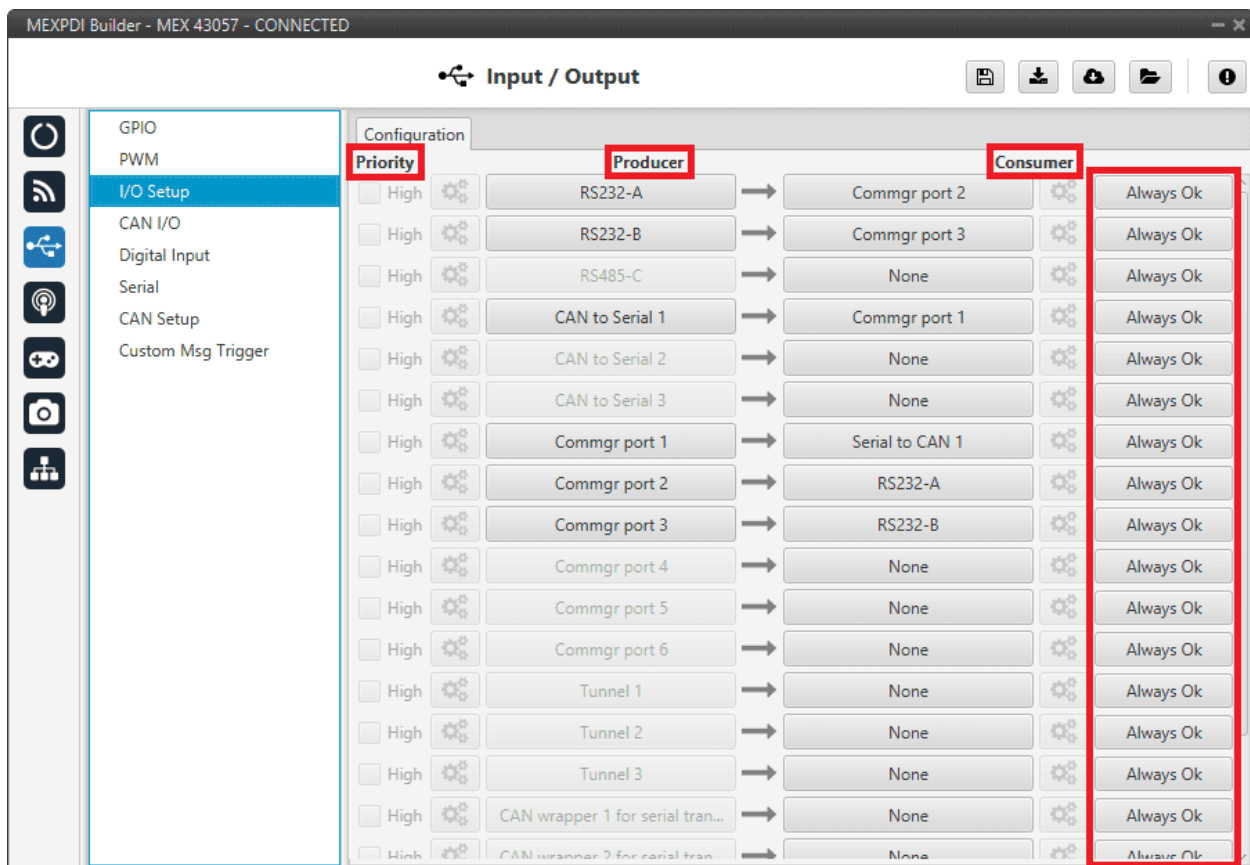


Fig. 21: I/O Setup panel

- **Priority:** Connections between I/O ports can be marked with **high priority** with this checkbox. If **enabled**, they will **run at high frequency: 1000 Hz**.
- **Producer:** Functions for creating and sending messages.
- **Consumer:** Functions for receiving and parsing messages.
- **Bit:** This assigns each connection to a bit. Thus, the connection is activated/deactivated depending on the status of the selected bit. By default, the *Always Ok* bit is set to all connections so that they are always active.

The following are the steps to setting up reception or transmission between ports:

1. Choose the **Producer** to use.
2. To configure the desired **Consumer** that will be bind to the chosen **Producer**, it is first required to establish the **relationship** between them:
 - **Bind** →: Unidirectional relationship.
 - **Bind Bidirectional** ↔: Bidirectional relationship. This enables a port to receive or send information.

Note: Once the **Consumer** has been selected, it is possible to undo the selection by pressing the **Clear** button.

3. Select the desired **Consumer** element.
4. (optional) Configure the **Bit** parameter. By pressing on the bit button, the user can select the bit to assign the connection to.

The following I/O ports are available:

Field	Description
RS232-A	Serial Port 232 A
RS232-B	Serial Port 232 B
RS485-C	Serial Port 485
Commgr port	COM Manager ports send and receive VCP messages. This is the protocol used by Veronte products to communicate. For more information, read the VCP user manual
Tunnel	Creates a bidirectional bridge between two devices, see Tunnel
Custom message producer/consumer	This allows user to send/receive a serial custom message, see Serial Custom Messages
CAN to Serial / Serial to CAN	Serial to CAN sends serial streams over a CAN Bus / CAN to Serial undoes the transformation 'Serial to CAN'
CAN wrapper for serial transmission / Serial CAN unwrapper	CAN wrapper for serial transmission sends CAN streams over a serial Bus / Serial CAN unwrapper undoes this transformation. For more information on these ports, please refer to CAN wrapper/CAN unwrapper - Input/Output section of the 1x PDI Builder user manual
Tribunus ESC	Reads telemetry data from the Tribunus ESCs by connecting it to one of the serial ports
Lift - MCU	Created for communication with a Lift MCU
JETI box	Simulates a Jetibox to read telemetry from legacy Jeti devices, see JETI box
JETI telemetry	Reads telemetry from Jeti devices

More information about some elements can be found in the following sections.

2.3.3.1 Tunnel

A tunnel is a bidirectional bridge between units that communicate each other, sharing information about an external device connected to the serial or digital port. The following image shows an example of tunnel configuration:

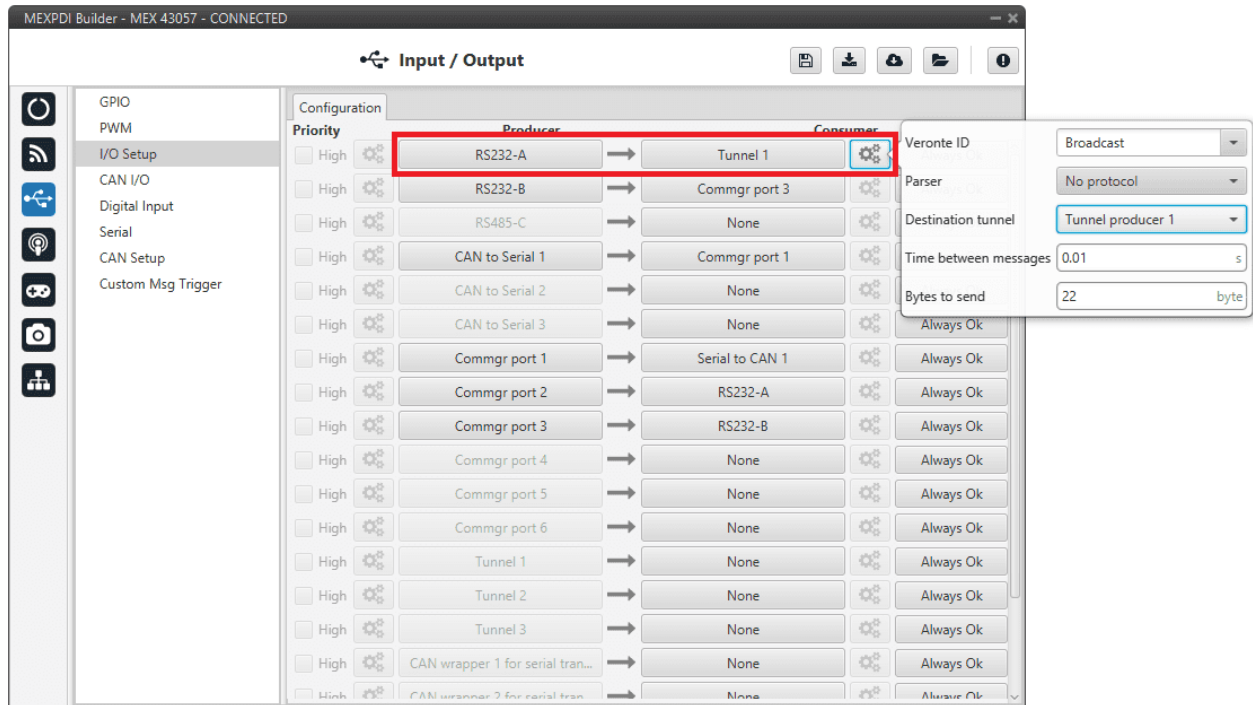


Fig. 22: Tunnel configuration

In the previous image there is a device connected to the **RS232-A (Producer)** and there is a **Tunnel (Consumer)** which sends that information to all units on network (Broadcast). On the other hand, another Veronte device has to be configured to receive the signal sent by another device. In this case, the **Producer** will be **Tunnel**, while **Consumer** will be the **port or destination tunnel where the device is connected**.

The options available when configuring Tunnel as **Consumer** are:

- **Veronte ID:** Enter the address that will receive the information. The following options are the most common:
 - **App 2:** Veronte applications address.
 - **Broadcast:** All units on the network. Select this option for a generic configuration.
 - Address of a specific Veronte unit, it can be a 1x, a 4x, a CEX, a MEX, etc.

For more information on the available addresses, see [List of addresses](#) section of the **MEX Software Manual**.

- **Parser:** The user can choose the protocol to parse message data. The options available are:
 - No protocol
 - RTCM3
 - CAN serial
- **Destination tunnel:** Number of port is used to avoid mistakes and identify each Tunnel when using more than one. *Tunnel 1, 2 and 3* are available.
- **Time between messages.**
- **Bytes to send:** Sets the message size to send.

When configuring Tunnel as **Producer** (i.e. on the unit that receives the information), no configuration is required. It is only necessary to connect it to a **Consumer**, usually to a serial port.

2.3.3.2 Serial Custom Messages

Warning: MEX has the following limitations for serial messages:

- **10** maximum **vectors**.
- **32** maximum **fields** (adding all serial messages).

It is possible to configure messages sent and received through the serial port and its conversion to system variables. To do that, select the option **Custom message producer/consumer** and configure the I/O port.

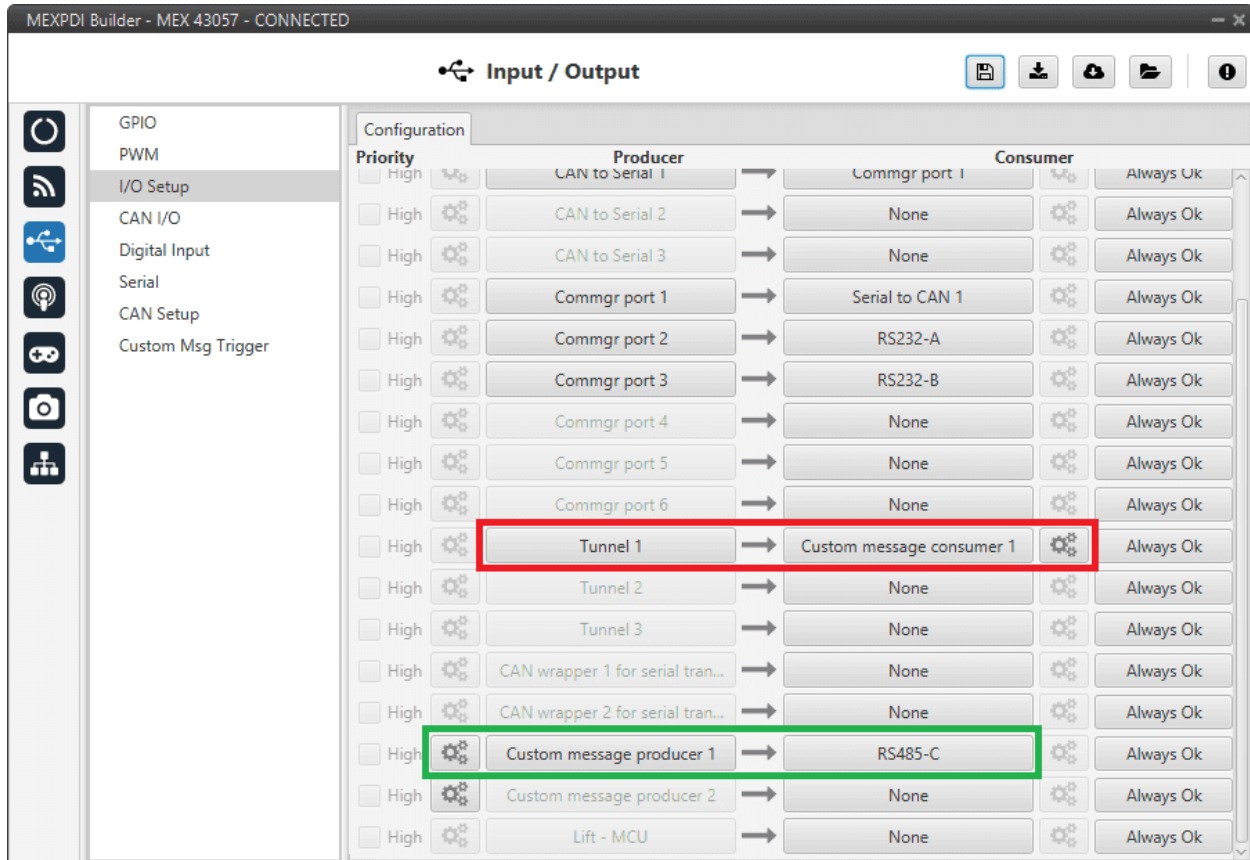


Fig. 23: Serial Custom Messages

The previous image illustrates two possible configurations using a Custom Message.

The red one is configured to receive a given message from Tunnel 1 and the green is used to send a Custom Message through the RS485-C serial port. It is also possible to use the same Custom Message for both tasks if the bidirectional relationship is selected (the arrow indicates this, ↔).

To configure a Custom message, the user must follow the next steps:

1. Press the **configuration button** (⚙️ icon) and another window will be displayed.

In this window press the **+** icon to add a custom message.

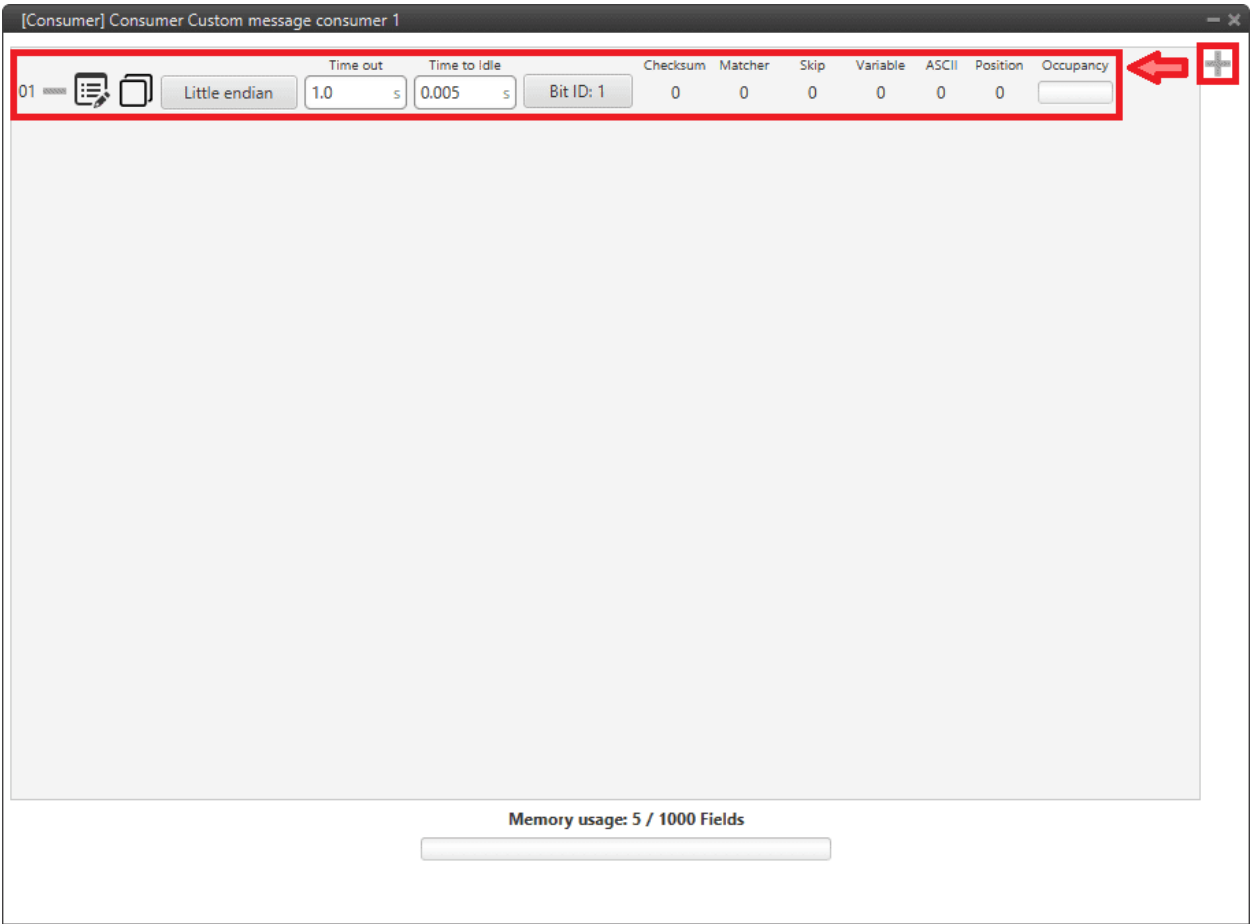


Fig. 24: Serial Custom Message configuration

2. When it is already added, the following options are available to configure a custom message:

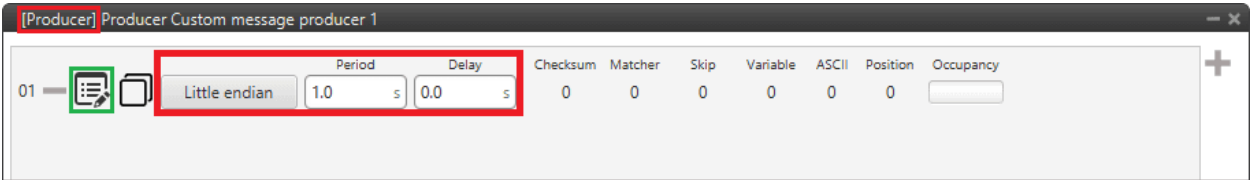


Fig. 25: Custom Message producer configuration

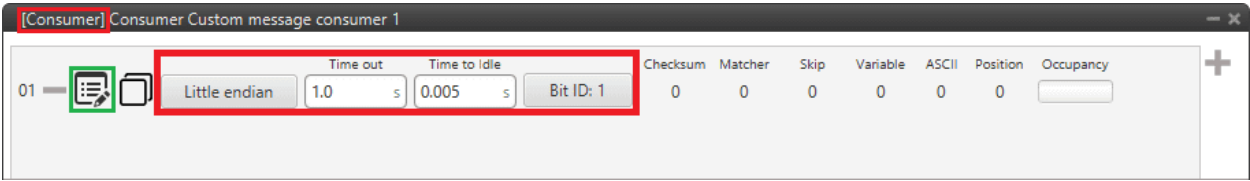




Fig. 26: Custom Message consumer configuration

- **Endianness:** Depending on the order the message is made, it is possible to select:

- **Big endian:** Set value from left to right.
- **Little endian:** Set value from right to left.
- **Mixed endian:** Some devices use this format. If users need to configure it, please contact the support team (create a ticket in the customer's **Joint Collaboration Framework**; for more information, see [Tickets](#) section of the **JCF** manual).
- **Period/Time out:** This option has a dual role depending on whether it is used to transmit or receive data.
 - **Period - Producer:** Time between produced messages. It is the inverse of the send frequency
 - **Time out - Consumer:** Time threshold between receptions to consider that messages are not received correctly.
- **Delay/Time to Idle:** This option has a dual role depending on whether it is used to transmit or receive data.
 - **Delay - Producer:** Delay applied before sending the message. This serves to send messages with the same period without overloading the Serial bus.
 - **Time to Idle - Consumer:** Time that MEX waits before discarding partially parsed bytes.
- **Bit ID:** This option is only available when a message is configured as **Consumer**. The user bit selected in Bit ID box will be true if the message is being received correctly.

Warning: Pay attention that the user bit selected in **Bit ID** is not in use for another task.

3. To create the structure of the message, click on the  icon and then press the  icon to add fields to it. The following type of messages are available to configure a structure: **Variable, Checksum, Matcher, Skip** and **Parse ASCII**.

The configuration of each structure is covered in the [Custom Messages types - Input/Output](#) section of the **1x PDI Builder** user manual.

Warning: Before configuring any message, user has to know the structure according to the device that is connected to the port. Each device may have a different message structure when it sends or receives information.

2.3.3.3 JETI box

JETIBOX is a universal communication terminal which can be used with any JETI products.

JETIBOX operates as a two-way terminal, showing all data stored in the JETIBOX Compatible product. Employing its **four buttons**, users browse its menu and set the selected values.



Fig. 27: JETI box device

To simulate it, it is necessary to link the specific **JETI box consumer** to a serial port:

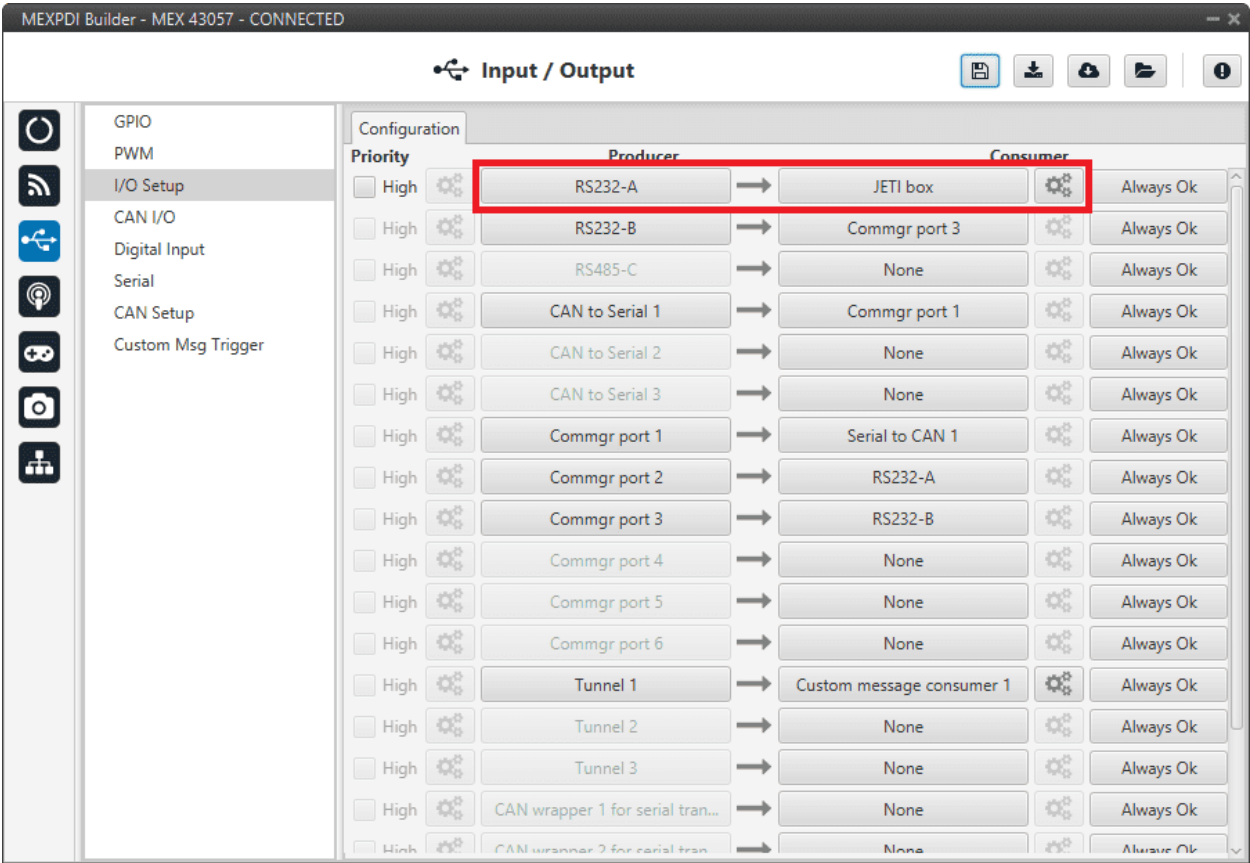




Fig. 28: JETI box Consumer

Then, the sequence to retrieve data shall be configured by clicking on :

To add a Custom Message, just click on the  icon:

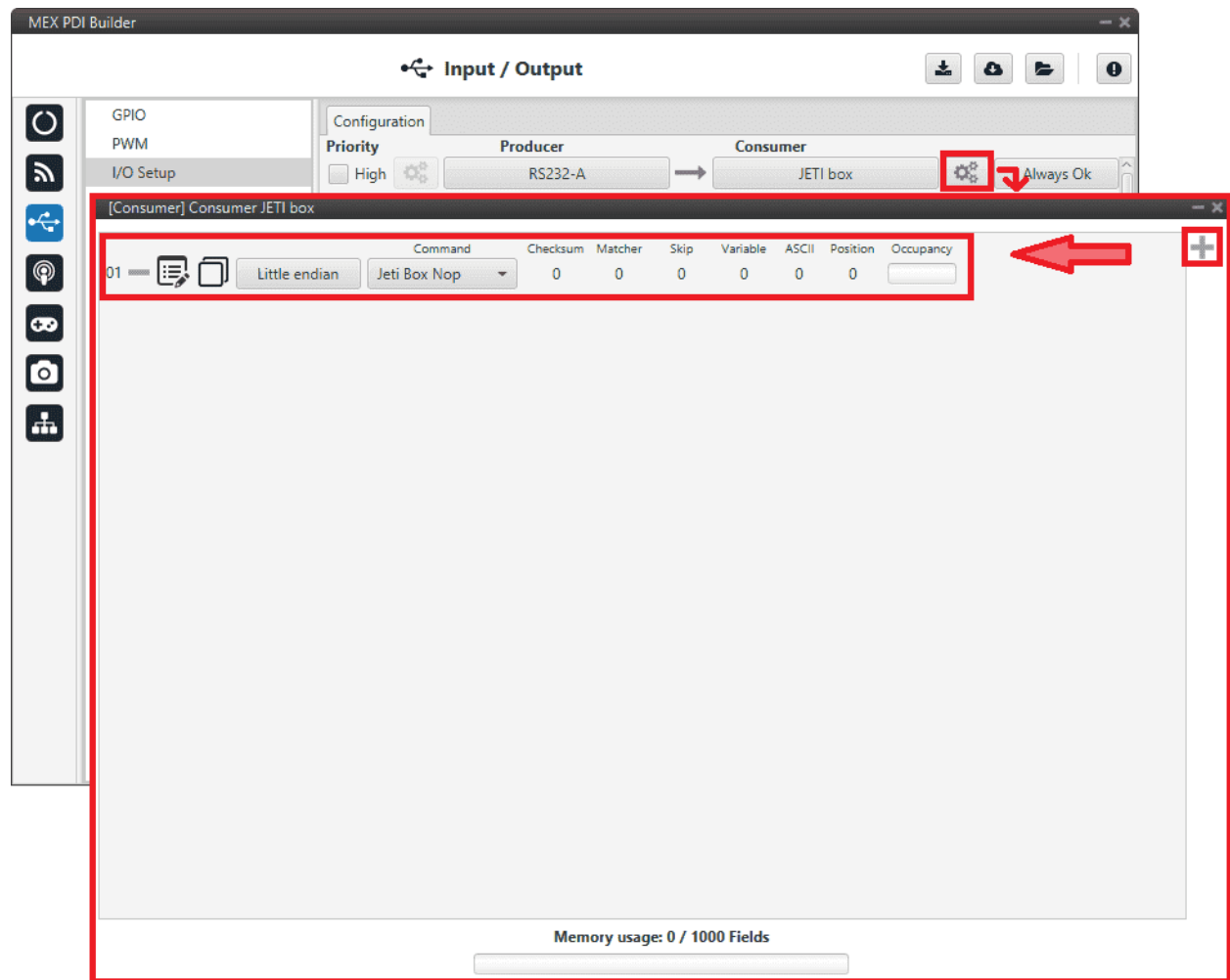


Fig. 29: JETI box Configuration

The following parameters can be configured in the previous pop-up window:

- **Endianness:** Depending on the order in which the device issues the message, it is possible to select:
 - **Big endian:** Sets values from left to right.
 - **Little endian:** Sets values from right to left.
 - **Mixed endian:** Some devices use this format. If users need to configure it, please contact the support team (create a ticket in the customer's **Joint Collaboration Framework**; for more information, see [Tickets](#) section of the **JCF** manual).
- **Command:** Here the user can select between **Jeti box Left**, **Jeti box Down**, **Jeti box Up**, **Jeti box Right** or **Jeti box Nop**. These correspond to the **four buttons** on the physical JETIBOX (see image above), except the **Jeti box Nop** that is only for simulating a “wait”.

For example, to read the **Actual Voltage** of a **Jeti MasterSpin 220** the Consumer must be configured with a series of custom messages (use **Big endian** for all messages).

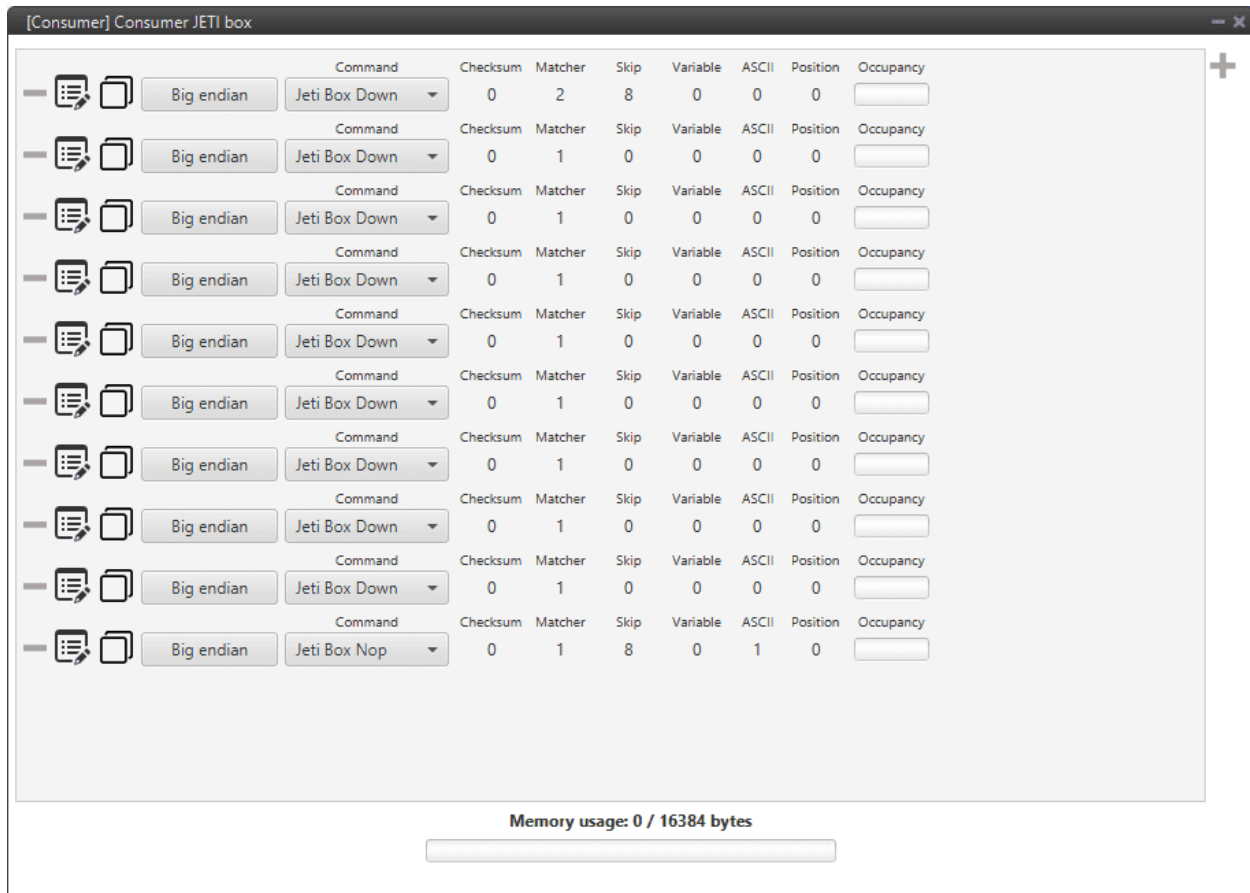


Fig. 30: JETI box example

The following example shows the configuration of one of these messages, the full example can be found in *Jetibox - Integration examples* section of this manual.

- Expected text: “CONTROLLER TYPE MasterSpin 220~”
- Command: **Jeti box Down**
 - Matcher(32) “CONT” 0x434F4E54 (1129270868)
 - Skip(24*8) 192
 - Matcher(32) “220~” 0x3232307E (842150014)

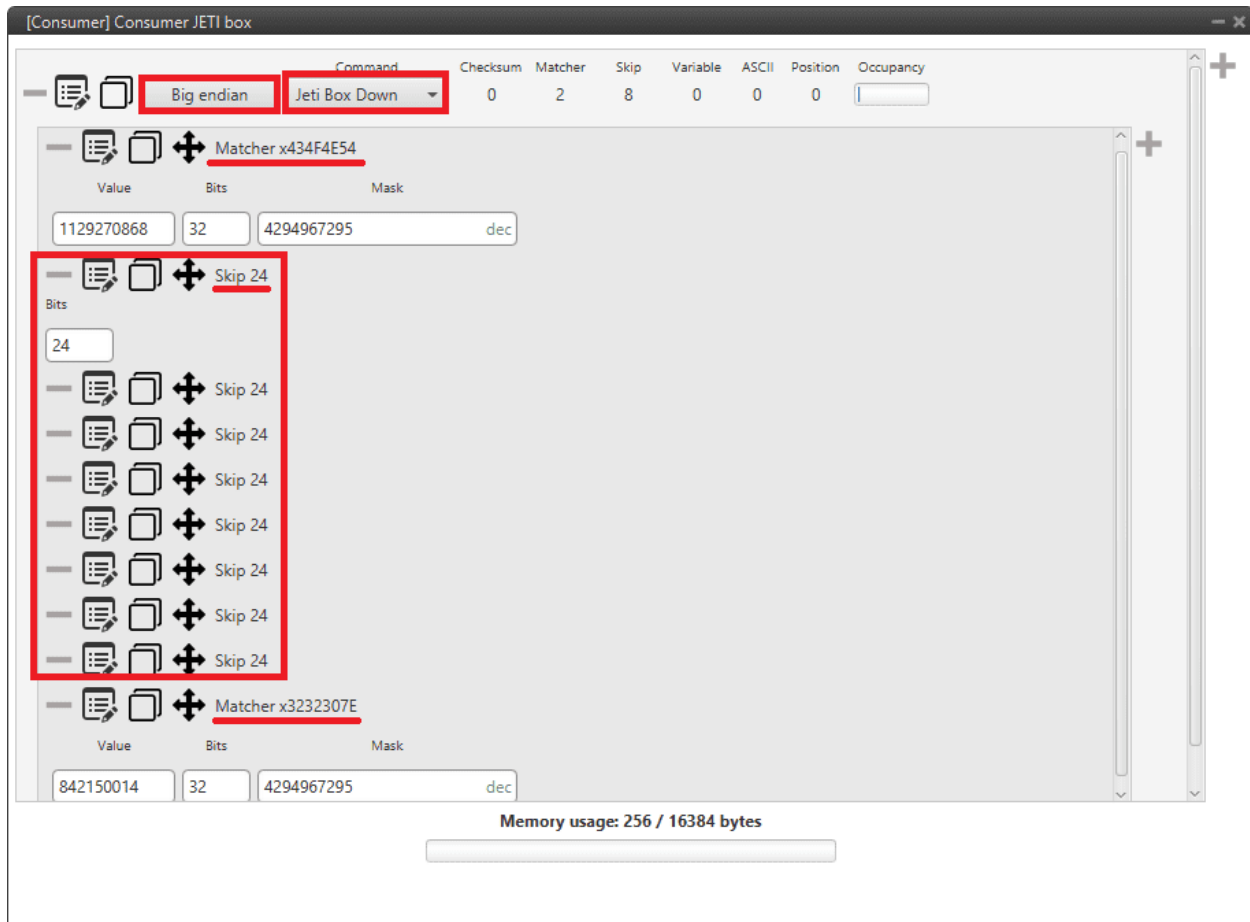


Fig. 31: JETI box custom message example

2.3.4 CAN I/O

A CAN (Controller Area Network) Bus is a robust standard communication protocol for vehicles widely used in the aviation sector. **MEX** has two CAN buses that can be configured independently.

The structure of a CAN message can be seen in the following image:

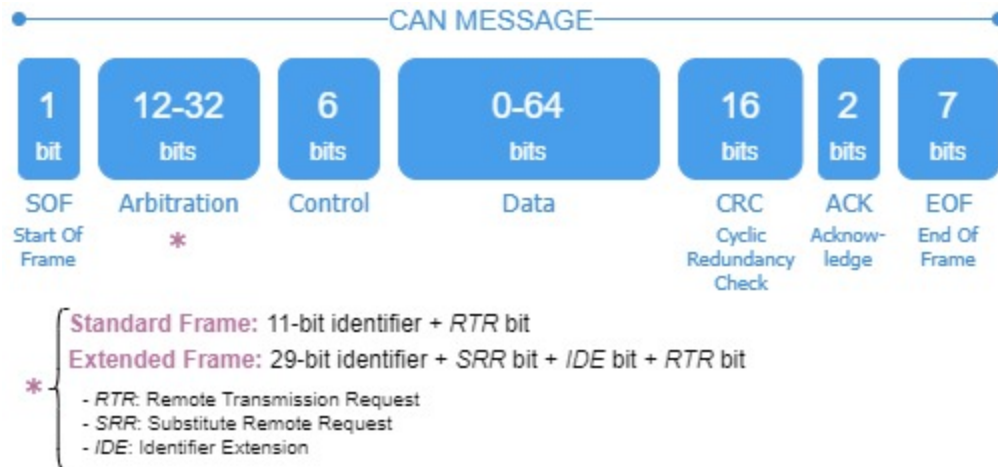


Fig. 32: CAN message structure

Only the ID is introduced in the system, the rest of the message layout is already coded. The data field is built by the user to send, and parsed when received.

For more information on the CAN Bus protocol, see [CAN Bus protocol](#) section of the **MEX Software Manual**.

The baudrate of both CAN buses can be configured in the [CAN Setup panel](#).

2.3.4.1 Configuration

This menu allows the configuration of CAN communications between different devices.

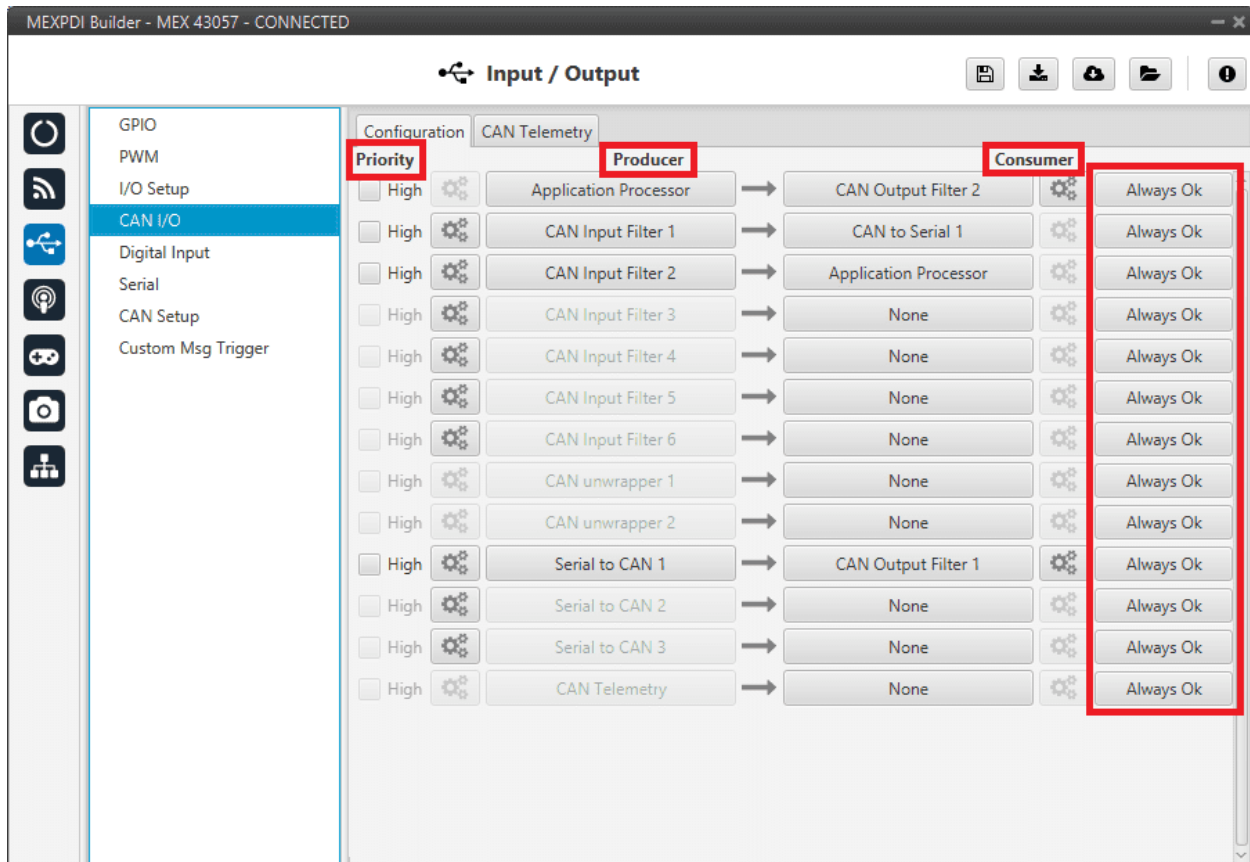


Fig. 33: CAN I/O - Configuration panel


In this menu, the user can find the same ‘columns’ (**Priority**, **Producer**, **Consumer** and **Bit**) as in the *I/O Setup panel*. In addition, the process for configuring producers and consumers is also the same as described in the *I/O Setup - Input/Output* section.

Warning: In CAN, while the specified period is not guaranteed in the Low state, in the High state it is.

However, only those **messages that are critical for external devices** should be set as **high priority**, as this may disrupt the proper functioning of MEX.

On the one hand, **MEX** has the following list of **producers**:

- **Application Processor:** Sends a specific set of information, the “**status message**”.
This message is composed as: version (major . minor . revision), address (serial number), system bit error, system power up bit error, PDI bit error, memory allocation bit, fily system bit error, CAN A bit error, CAN B bit error, arbiter enabled and arbiter status.
- **CAN Input Filter:** Those CAN messages received in one filter can no longer be received in subsequent filters.

The following parameters need to be configured by clicking on :

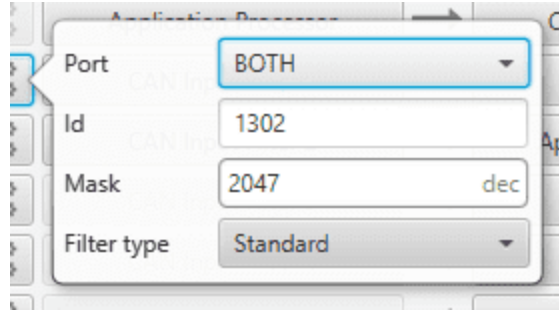



Fig. 34: CAN Input Filter configuration

- **Port:** It is required to configure the CAN bus from which it listens, the user can choose between *CAN A*, *CAN B* or *BOTH*.
- **Id:** CAN Id must be set and it is used to identify messages. The value set has to be **decimal format**.
- **Mask:** A CAN Id mask can be set to filter messages. **The mask marks which bits of the message id (in binary) are matched.**

For example, to admit standard Ids (11 bits) from 8 to 11 (100 to 111 in binary) the user should set the mask to binary 1111111100, that is 2044 in decimal.

Warning: Make sure that mask is set properly to be able to receive the desired CAN messages. The mask should be **11 bits for Standard** frame format and **29 bits for Extended** frame format. More information about this can be found in [How to calculate a mask - FAQ](#) section of this manual.

- **Filter type:** The available options are *Standard* (frame format with a 11-bit identifier), *Extended* (frame format with a 29-bit identifier) and *Both*.
- **CAN unwrapper:** This undoes the ‘CAN serial wrapper’ action, it has to be connected to *I/O Setup consumer* (*Serial CAN unwrapper*).
- **Serial to CAN:** Serial messages through CAN output, it has to be connected to *I/O Setup consumer*. It can be configured in , a pop-up window will appear:

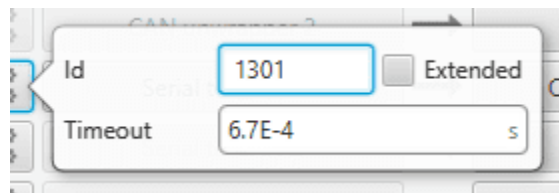



Fig. 35: Serial to CAN configuration

- **Id:** CAN Id must be set and it is used to identify messages. The value set has to be **decimal format**.
- **Extended:** If it is enabled, the frame format will be ‘Extended’, i.e. with a **29-bit identifier**. Otherwise, the frame format ‘Standard’ (11-bit identifier) is set by default.
- **Time out:** This is the threshold time between receptions to consider that it is not being received correctly.
- **CAN Telemetry:** Telemetry messages sent via CAN (such as CAN custom messages on **Veronte Autopilot 1x**). They are configured in the next section: [CAN Telemetry](#).

On the other hand, the **consumers** are the following:

- **Application Processor:** Receives a specific set of information sent by **Veronte Autopilot 1x** or **Arbiter**.
- **CAN Output Filter:** CAN output filters. The user can choose between *CAN A*, *CAN B* or *BOTH* in .

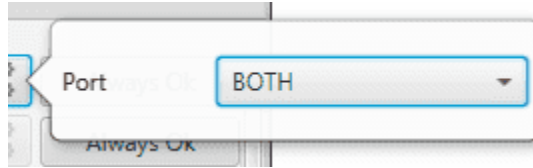


Fig. 36: **CAN Output Filter configuration**

- **CAN serial wrapper:** CAN messages through serial output, it has to be connected to *I/O Setup producer* (*CAN wrapper for serial transmission*).
- **CAN GPIO consumer:** CAN messages from **Autopilot 1x** or **4x** for GPIO inputs.
An example of how to implement it can be found in *GPIO Command - Integration examples* section of the present manual.
- **CAN to Serial:** This undoes the ‘Serial to CAN’ action, it has to be connected to *I/O Setup producer*.

2.3.4.2 CAN Telemetry

In the CAN Telemetry tab, the user chooses the telemetry to be sent/received over the CAN buses. The following elements can be configured:

- **TX Ini:** Used to configure transmitted messages that are only sent once at the beginning of the operation (sent when the MEX boots up). They can be used to initialize some devices.
- **TX:** It is employed to configure transmitted messages.

Warning:

- The **maximum capacity** of a **CAN message is 64 bits** (8 bytes), so to send more information it must be divided into several messages.
- MEX has the following **CAN limitations**:
 - Maximum number of **vectors** (fieldsets): **8** → **1 for TX Ini** and **7 for TX**.
 - Maximum number of **fields**: **32** (adding all CAN messages).

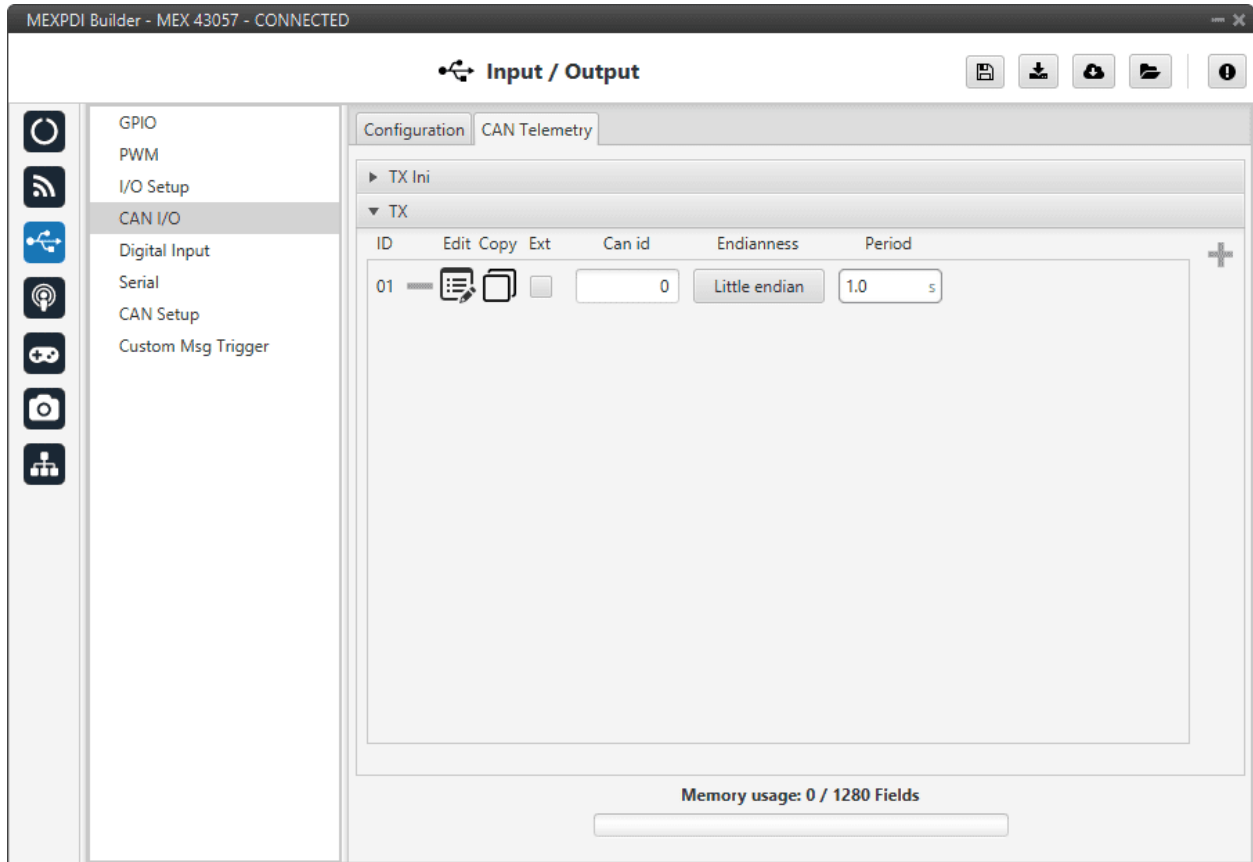


Fig. 37: CAN I/O - CAN Telemetry panel

Since this panel works in a similar way as in the **1x PDI Builder** software, the explanation to configure the telemetry messages via CAN can be found in the [Custom Messages - Input/Output](#) section of the **1x PDI Builder** user manual.

An example of the sending of **CAN telemetry messages** can be found in the [CAN communication - Integration examples](#) section of this manual.

2.3.5 Digital Input

Digital inputs can be used to measure pulse count, pulse widths and PPM signals from a RC radio. Each source shall be connected to the desired consumer to allow measurements.

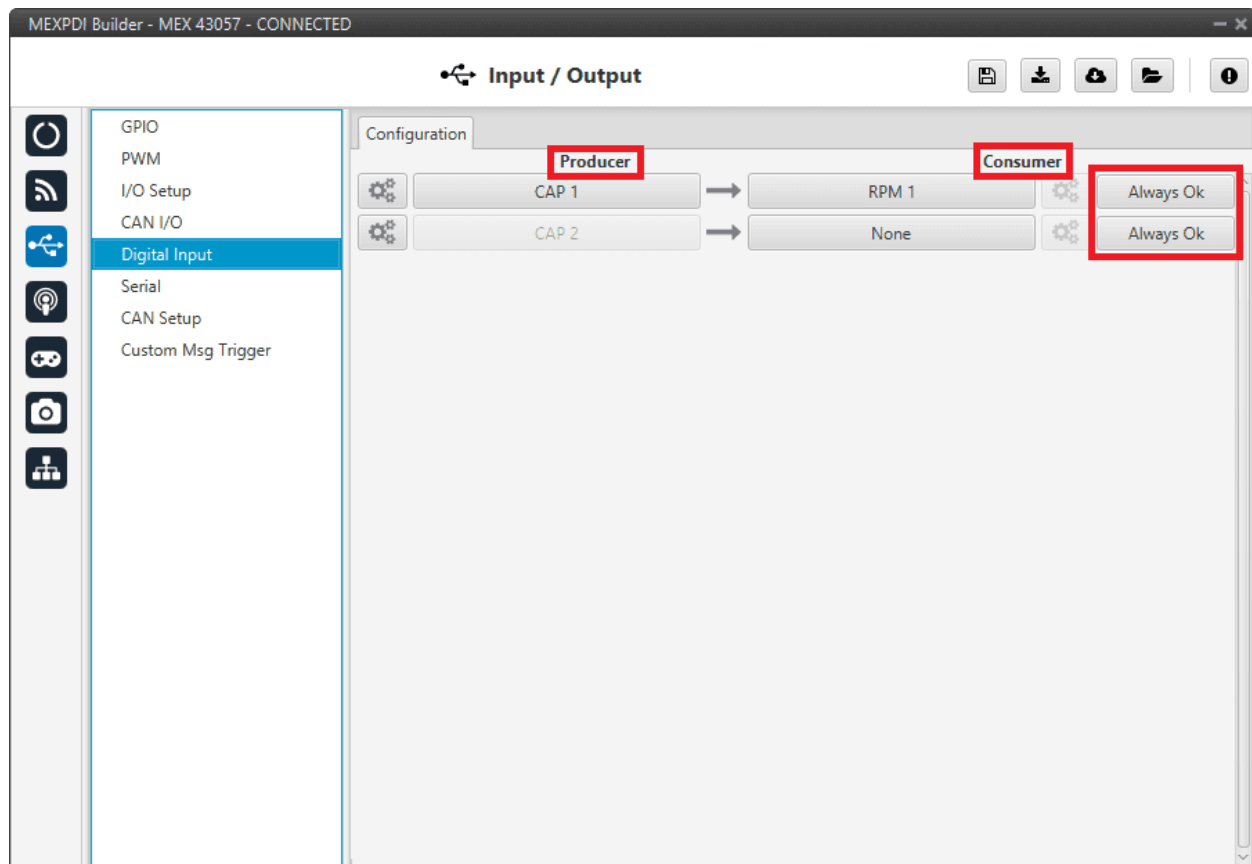


Fig. 38: Digital Input panel

In this menu, the user can find the same ‘columns’ (**Producer**, **Consumer** and **Bit**) as in the *I/O Setup menu*. In addition, the process for configuring producers and consumers is also the same as described in the *I/O Setup - Input/Output* section.

The process to configure a device can be done as follows:

1. Select and configure a **Producer** to read the external signal. There are 2 possible producers: CAP 1 and 2.

Press on the configuration button  and a pop-up window will show.

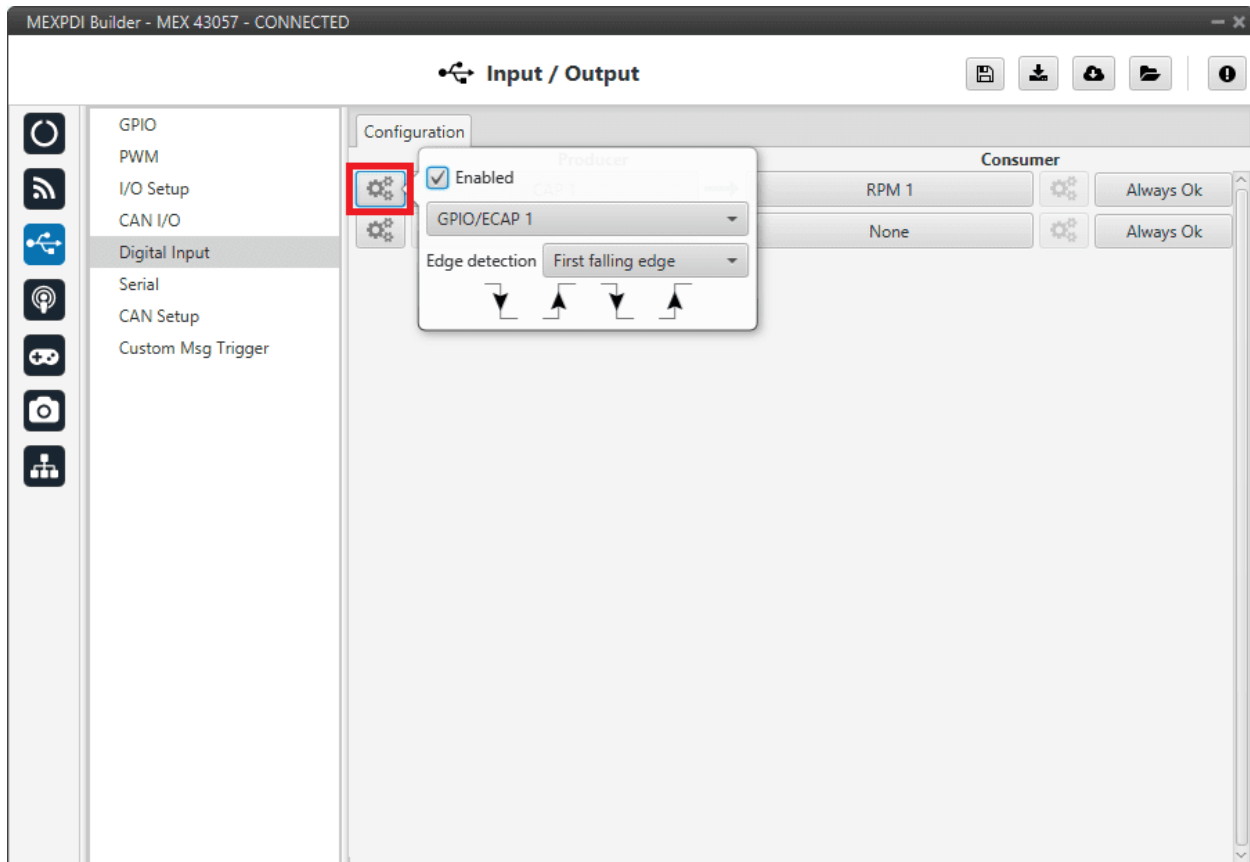


Fig. 39: Digital Input panel - Producer

The pop-up window contains the following configurable elements:

- **Enable:** By ticking this checkbox, the corresponding producer is enabled.

Note: When enabling it, in the *GPIO menu* the “Function” parameter corresponding to this pin shall automatically change to “Mux 1”.

Warning: Please check that this change has been made.

- **CAP pin entry:** Selects which **pin** this CAP is associated to and, therefore, to which device is connected. They are associated in this way: **CAP 1** with **GPIO/ECAP 1** and **CAP 2** with **GPIO/ECAP 2**.
- **Edge detection:** How the pulses are read and transformed into a digital signal (how they are processed). By clicking on the drop-down menu, the following options can be selected:

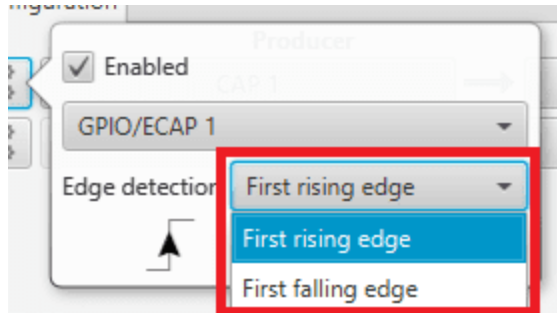


Fig. 40: Digital Input panel - Edge detection option

- **First rising edge:** With this option, when the rise of the pulse is detected, the data will start to be stored. Recommended when consumer is **PPM** or **Pulse**.
- **First falling edge:** With this option, when the **fall** of the pulse is detected, the data will start to be stored.

Note: By clicking on the marked arrows, it can also be configured as desired.

For example, if the user has selected the 'First rising edge' option, but clicking on the arrows gets the arrow scheme of another defined edge detection option, the name of the edge detection will not be 'First rising edge', but will become that edge detection option's name.

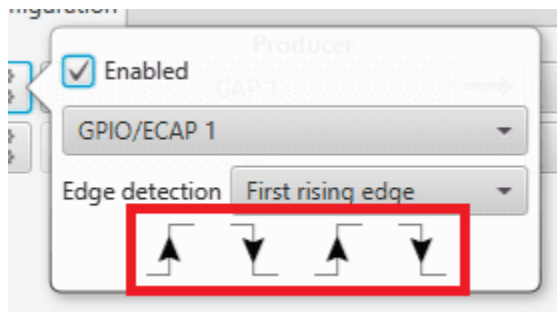


Fig. 41: Digital Input panel - Edge detection arrows

2. Click on the **Bind** button to select the type of **Consumer**, it is possible to choose PPM0 (Stick PPM), RPM 1-4 (RPM Sensor) or Pulse 1-4 (Pulse Sensor).

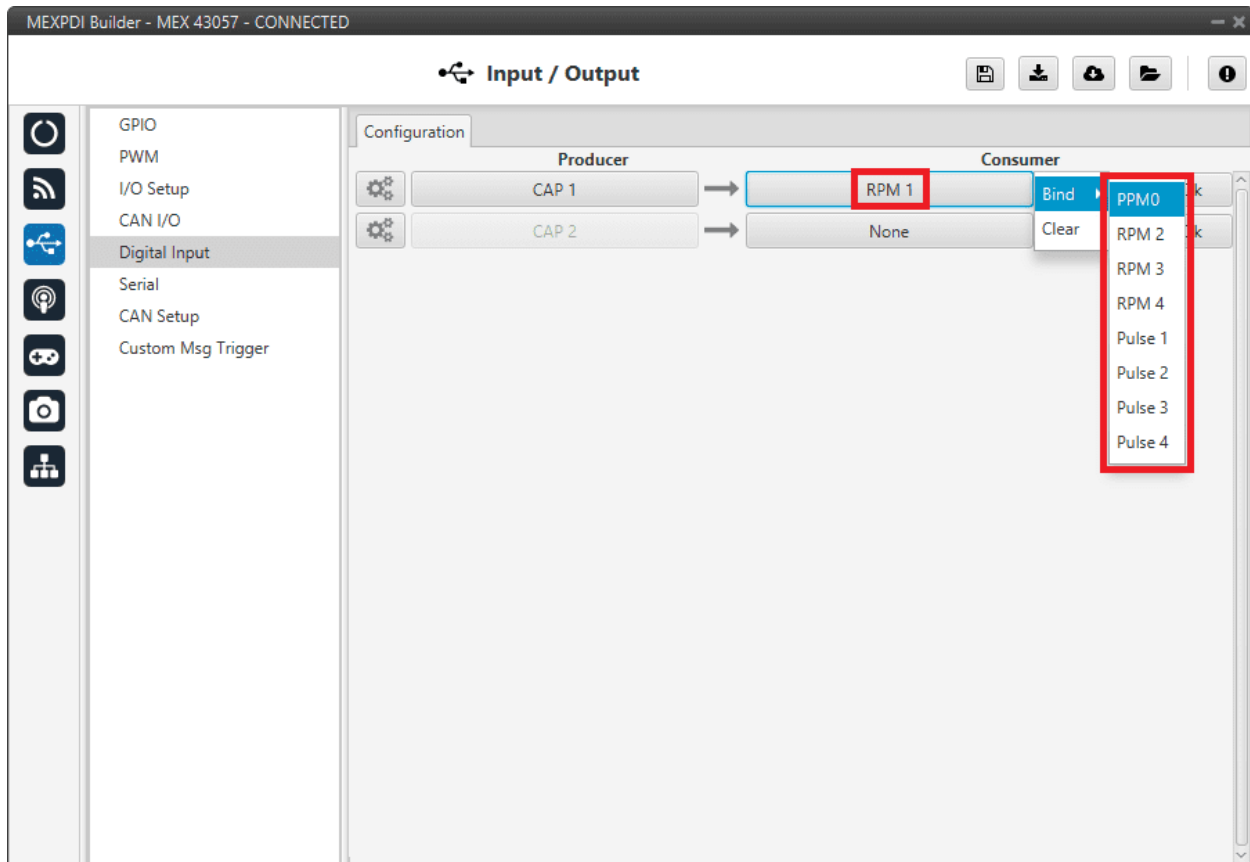



Fig. 42: Digital Input panel - Consumer

- **PPM 0:** The variable where the information is stored is 'PPM channel 1 output'. Stick PPM is configured in the *Stick panel*.
- **RPM 1-4:** The variables where the information read here is stored are 'RPM 1-4'. For more information about RPM configuration, read the [RPM](#) section.
- **Pulse 1-4:** The variables where the information is stored are 'Captured pulse 1-4'. It is possible to configure it clicking on .

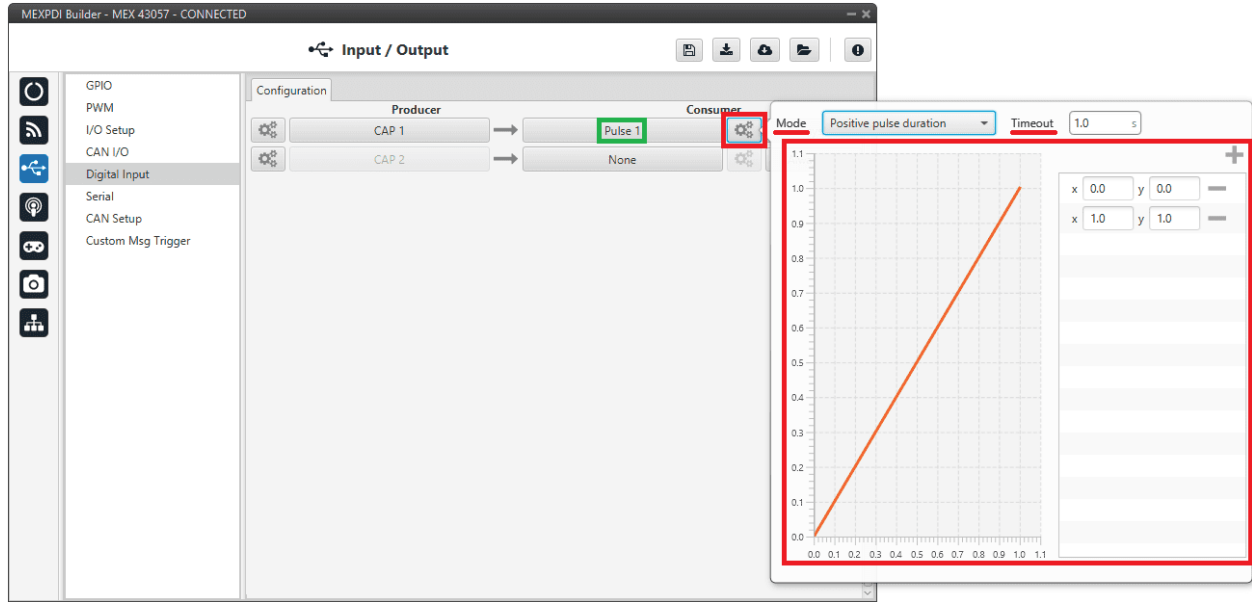


Fig. 43: Digital Input panel - Pulse

In the pop-up window, users will find the following options for configuration:

- **Mode:**
 - **Positive pulse duration:** The period of the pulse is obtained. It takes the time in 'High' state.
 - **Negative pulse duration:** The period of the pulse is obtained. It takes the time in 'Low' state.

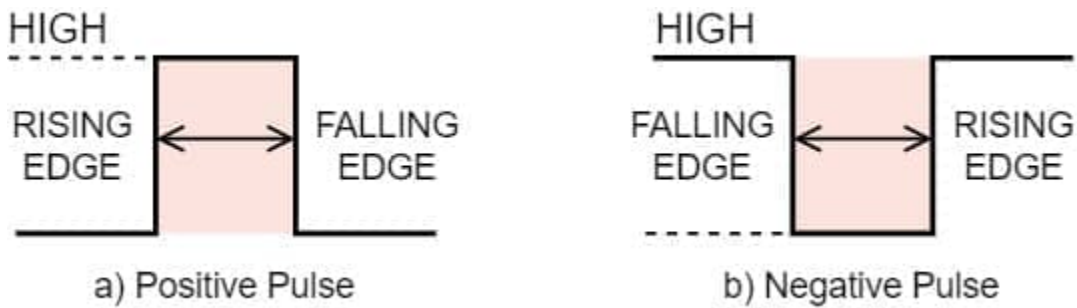


Fig. 44: Positive/Negative pulse duration

- **Positive duty cycle:** The duty cycle of the pulse is obtained. It takes the time in 'High' state.
- **Negative duty cycle:** The duty cycle of the pulse is obtained. It takes the time in 'Low' state.

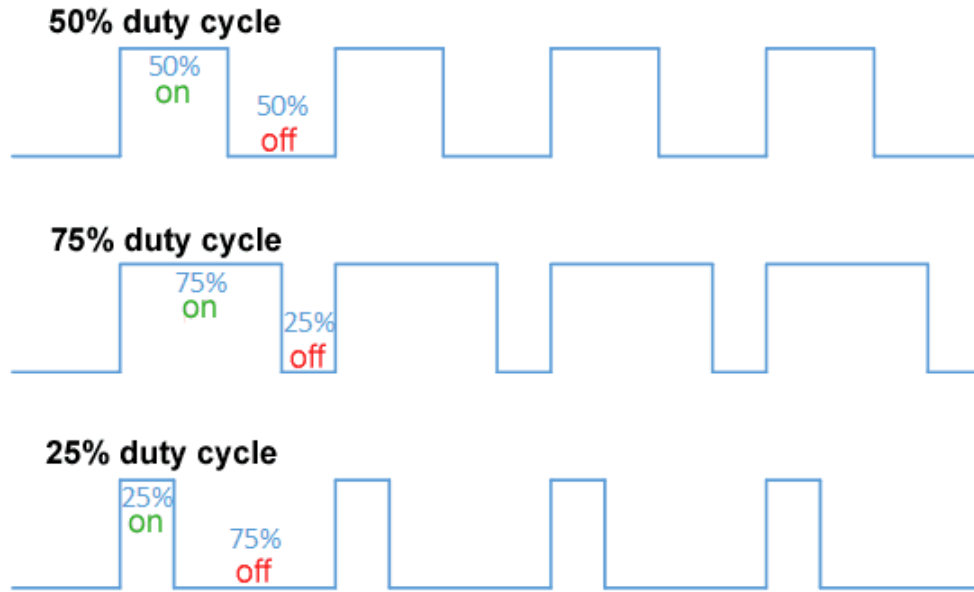


Fig. 45: Positive/Negative duty cycle

- **Time out:** This defines the time to consider that no signal is received.
- **Function:** Here the user can customize a function to handle values. Normally, a function is set with the points [0,0] and [1,1], so no transformation is applied (output = input). However, the user can configure it as desired.

Example

Let's imagine that **First rising edge** has been selected as the edge detection option in Producer and the pulse that MEX has to read is a square signal with a period of 2 seconds and a duty cycle of 25% (see the image below).

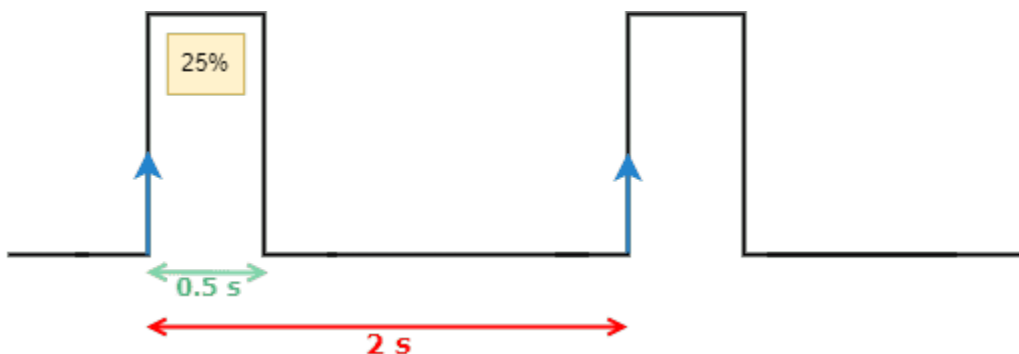


Fig. 46: Signal generated

Therefore, if **Positive pulse duration** is selected as Consumer and it is configured as in the previous image (*Digital Input - Pulse*), it will get **0.50 s** as value in the variable **Captured pulse** (*Captured pulse 1* in the following example), since it corresponds to the period of the “positive pulse” of that pulse.

Nonetheless, if **Positive duty cycle** is selected as Consumer, the value obtained in the variable **Captured pulse** (*Captured pulse 2* in the following example) will be **0.25**, since it corresponds to the positive cycle of that pulse.

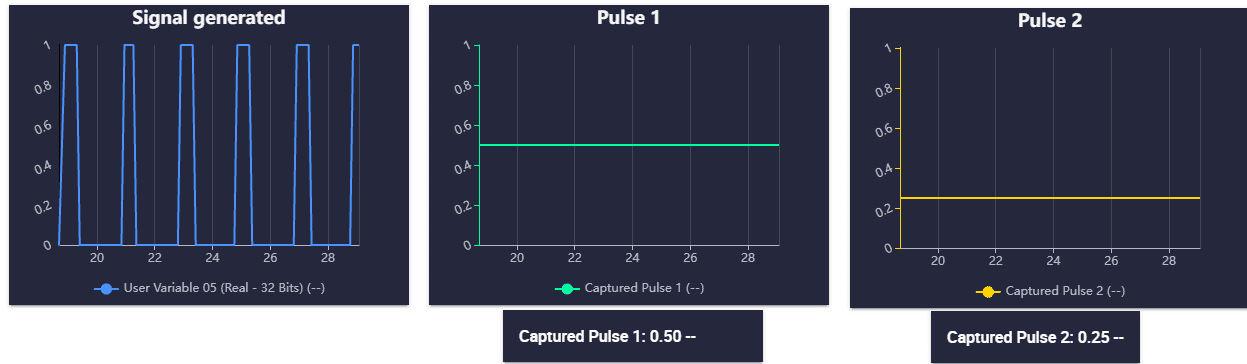


Fig. 47: Digital Input example

2.3.6 Serial

MEX can use up to three serial peripherals (SCI A, SCI B and SCI C). Serial ports A, B and C parameters can be edited in this menu to fit the serial protocol requirements.

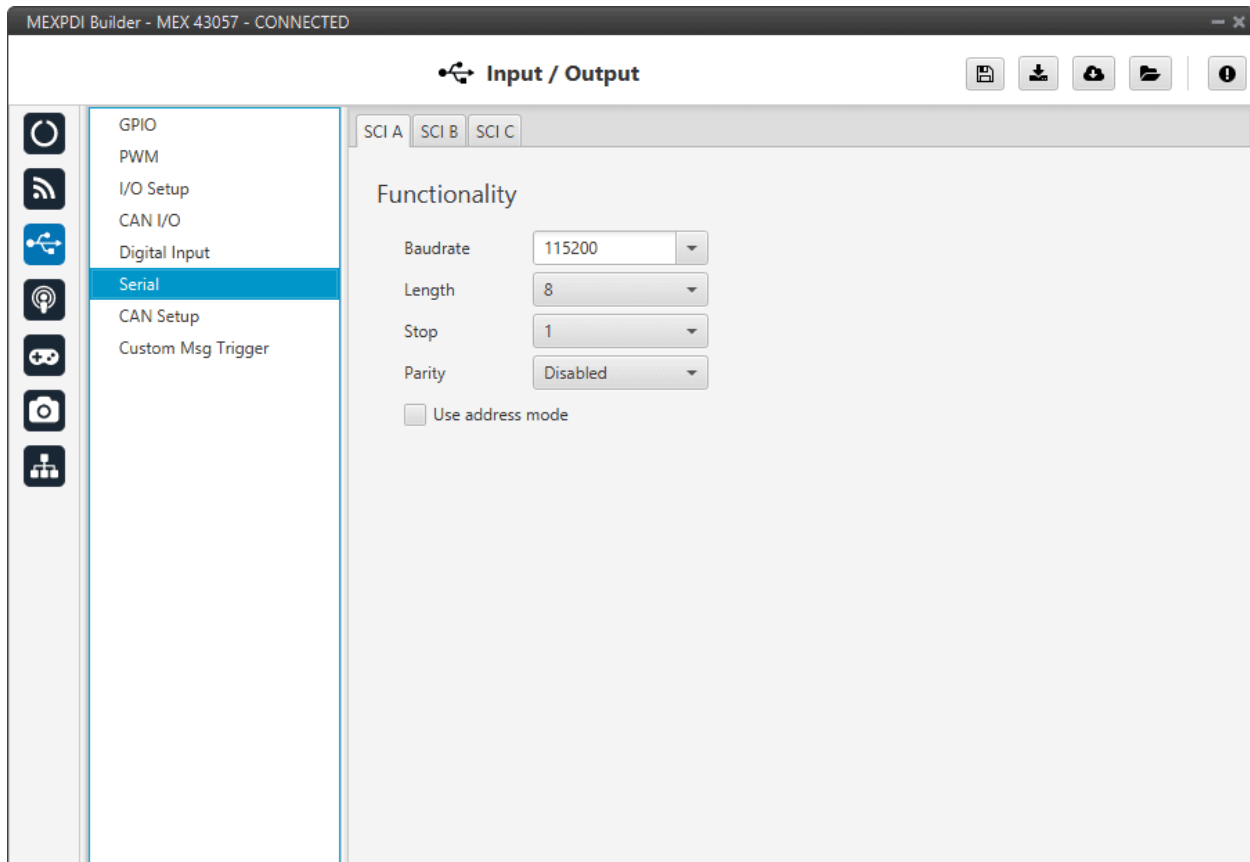


Fig. 48: SCI panel

- **Baudrate:** This specifies how fast data is sent over a serial line.
- **Length:** Number of data bits for each character: 4 to 8 bits.

- **Stop:** Number of stop bits sent at the end of each character: 1, 1.5 or 2.
- **Parity:** Method to detect errors during transmission. When parity is used with a serial port, an extra data bit is sent with each data character, arranged so that the number of 1 bits in each character, including the parity bit. **Disabled, odd or even.**
- **Use address mode:** 9-bit data framing uses the bit typically associated with parity error detection to identify address messages. Sent serial data that does not have the address bit set will be ignored (unless the device had previously identified an address message associated with it). This option can be disabled or enabled.

Note: SCI A corresponds to port RS232-A, SCI B to port RS232-B and SCI C to port RS485-C.

2.3.7 CAN Setup

In this screen users can configure the **baudrate** and the **reception mailboxes** of each **CAN Bus** (CAN A or CAN B), as well as enable an **internal CAN resistor**.

Since **MEX** is going to receive data on the CAN Bus, it is mandatory to configure a certain number of mailboxes to store that data until **MEX** reads it.

A mailbox can be configured for multiple CAN message IDs as long as the mask is configured correctly and these messages are **sent spaced out** with enough time between them to allow the high priority core to read each one individually. More information on masks can be found in [How to calculate a mask - FAQ](#) section of this manual.

Warning: Since **MEX PDI Builder** allows up to 32 mailboxes, users should make sure to **leave at least one mailbox free for transmission (TX)**.

If any mailbox is **full** and another message arrives, the **new** message is **discarded**.

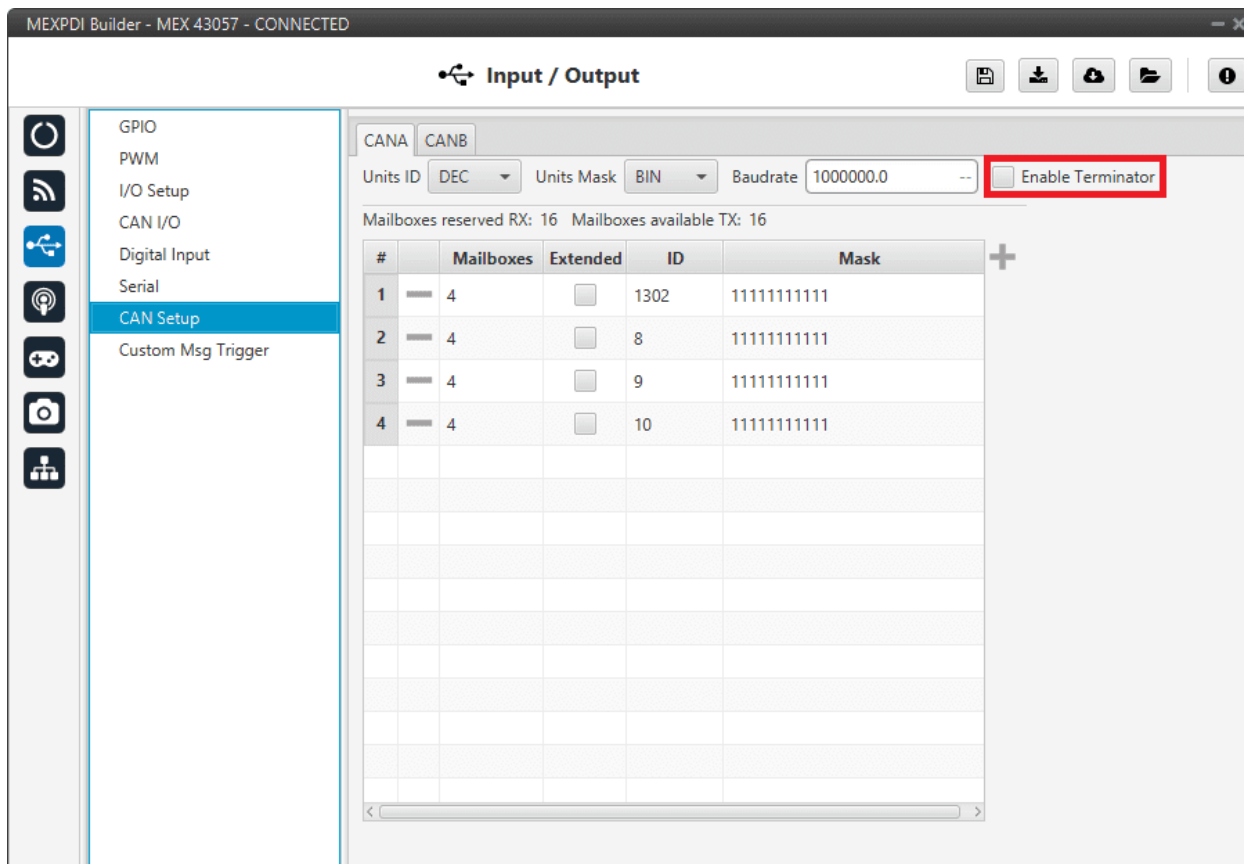


Fig. 49: CAN Setup panel

By activating ‘**Enable Terminator**’, the internal MEX resistor of $120\ \Omega$ is activated. For more information on this resistor, refer to the [Electrical diagram of CAN bus - Hardware Installation](#) section of the **MEX Hardware Manual**.

More information about Mailboxes can be found in the [Mailboxes - Input/Output](#) section of the **1x PDI Builder** user manual.

2.3.8 Custom Msg Trigger

This menu allows the user to **send custom messages** (which have been previously configured) every time there is a **new magnetometer reading/measurement**.

It works similar to the [Custom Serial TX](#) and [Custom CAN TX](#) automations of **1x PDI Builder** software.

In this case, the “automation” will work like this:

- Events: Each new magnetometer reading/measurement.
- Action: Sending of the custom message already configured.

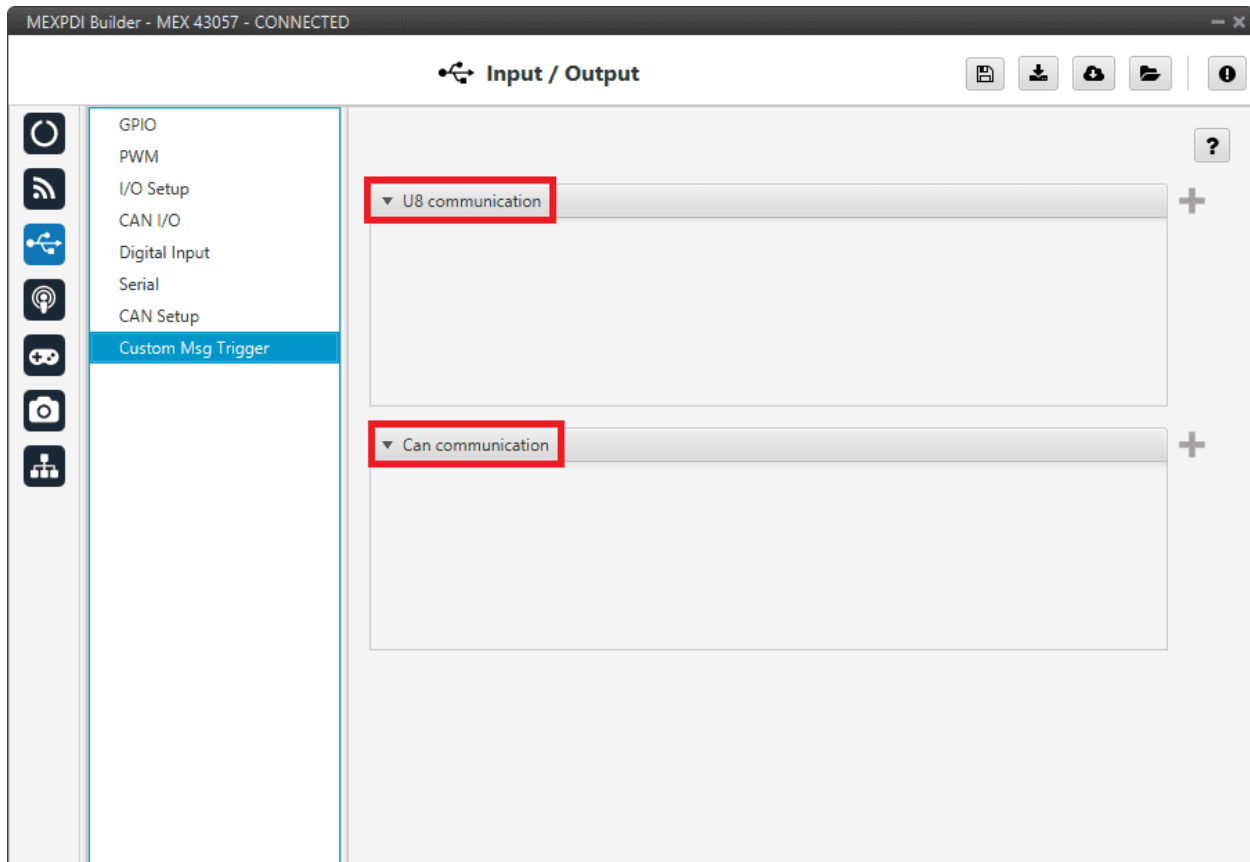


Fig. 50: Custom Msg Trigger panel

Users can configure custom messages to be sent via **serial** or **CAN**:

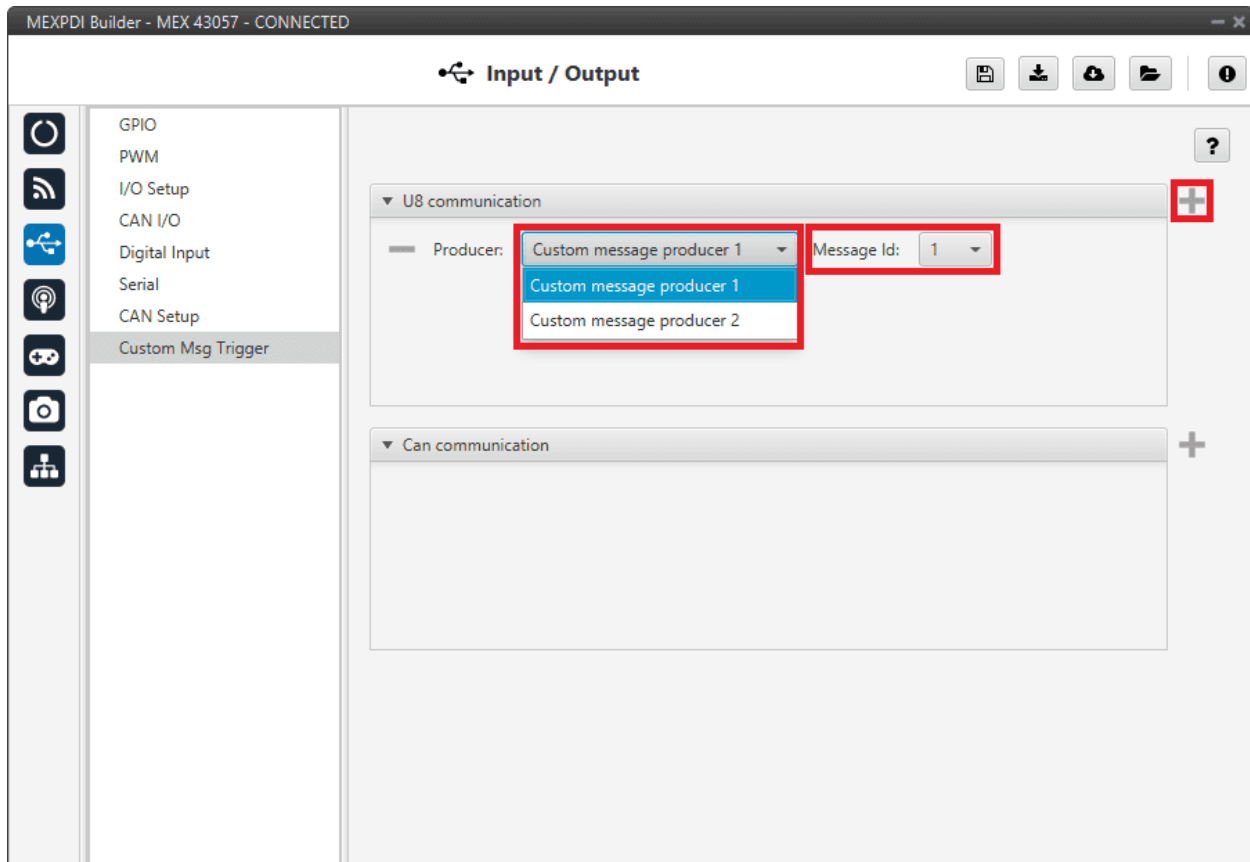


Fig. 51: Custom Msg Trigger panel - U8 communication

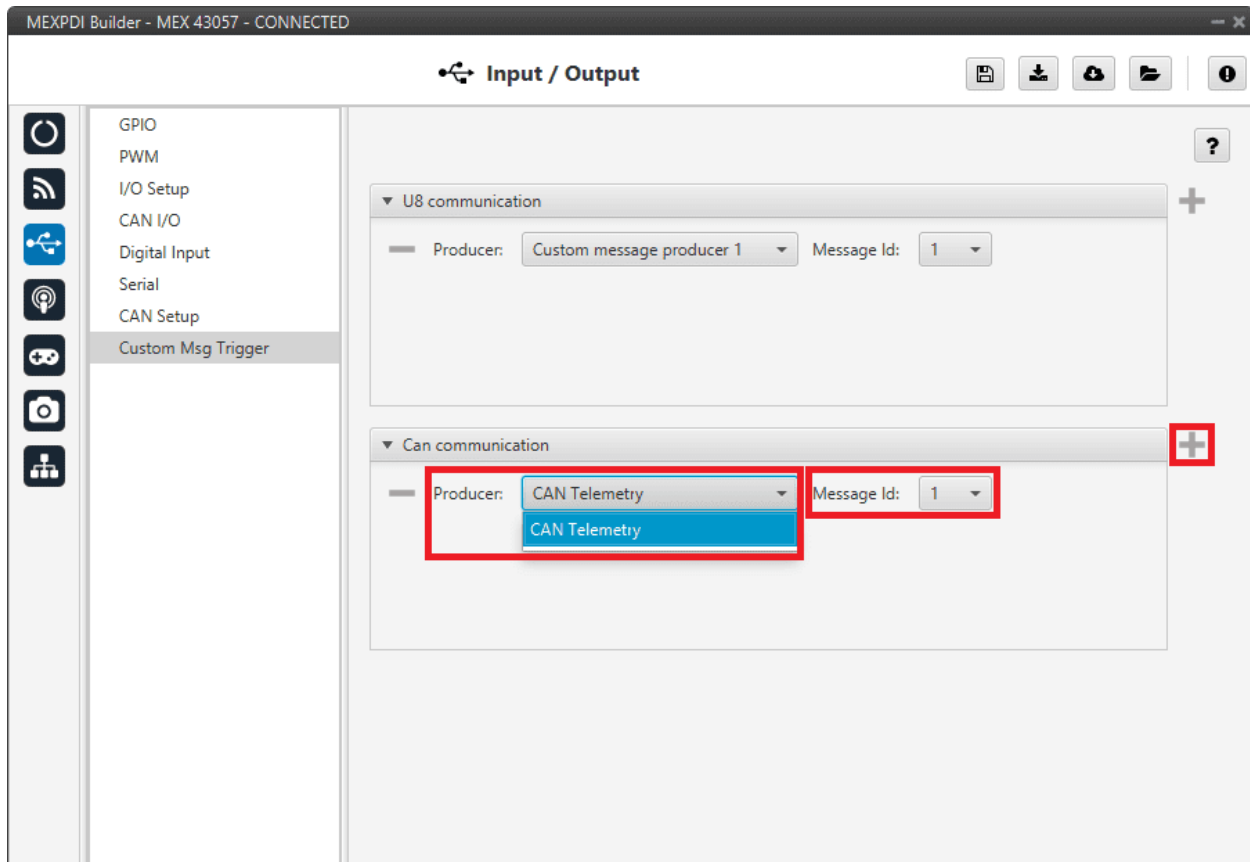


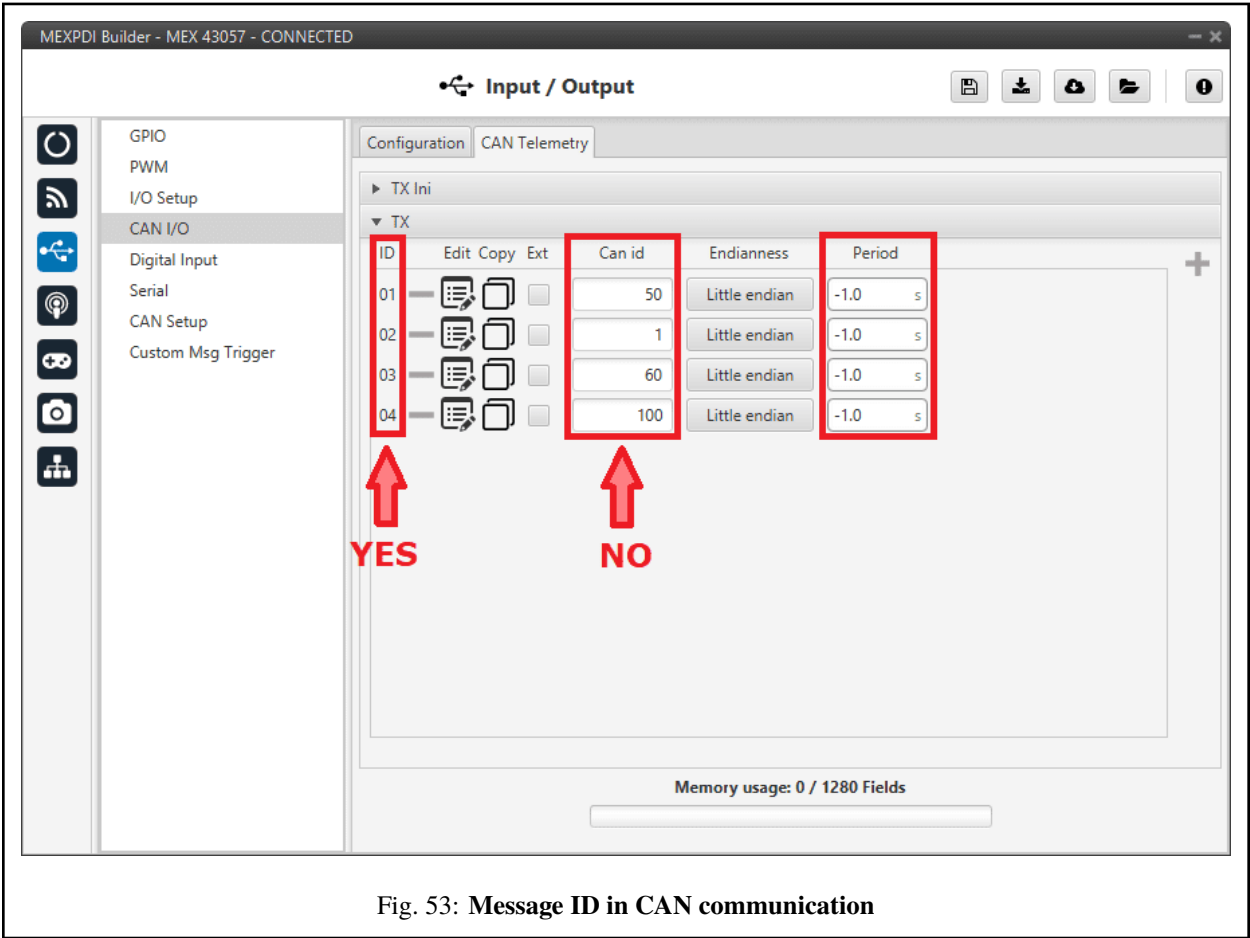
Fig. 52: Custom Msg Trigger panel - CAN communication

The two parameters to configure in this menu are:

- **Producer:** The user has to specify where the custom message is located (mailbox):
 - For **serial**: Custom message producer 1 or 2.
 - For **CAN**: CAN Telemetry
- **Message ID:** The ID of the custom message (not the CAN ID) that will be sent.

Warning:

- As it is used to send a single message on demand, in its configuration in **Custom Messages**, the user must set its **period to -1**. This way, this **message will only be sent when there is a new magnetometer reading/measurement**.
- For CAN communications, do not confuse it with the **CAN ID** of the custom message:



2.4 Communications

Ports configuration allows to configure which communication ports (Commgr Ports in *I/O Setup*) will be used for communication. When using the **Route** feature, **MEX** can be configured to **route VCP messages** for an external Veronte device with a known address (ID) through a given port.

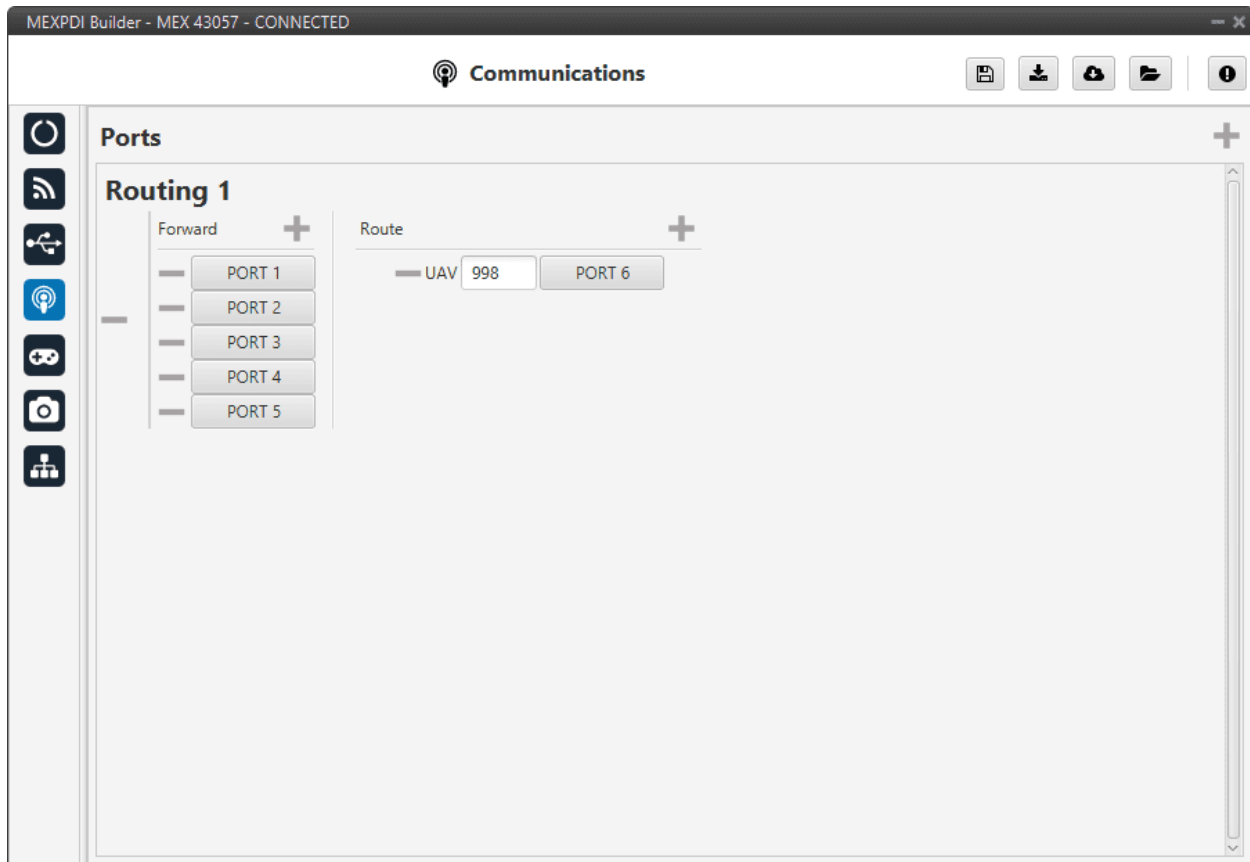


Fig. 54: Communications menu

Each port can be configured as either of the following options:

- **Forward:** Any messages generated by this unit (i.e. Telemetry or response messages to certain commands) will be sent through these ports.
- **Route:** Any messages received at any Commgr Port with the defined address will be re-sent through the defined port. It is possible to route several addresses through the same port, but is **not possible** to route the same address through several ports. Only the first configured port will be used. Routing also applies to messages generated by the unit for the defined address.

Note: The same **port** cannot be used as **Forward** and **Route** at the same time.

It is possible to define up to 4 routing setups, which can be switched using the [Ports action](#) in the **Automations** menu of the **1x PDI Builder** software.

Routing 1 will always be selected by default when booting **MEX**.

2.5 Stick

The wired transmitter is configured through the following tabs, which cover the following content:

- Setting of the transmitter's parameters.
- Definition of exponential response-curves for the desired channels.
- Trimming of the channels' neutral position.
- Setting of the data receiving port on the autopilot.

2.5.1 PPM

This tab provides the options to configure a Pulse Position Modulation (PPM) radio controller to control the platform fitted with the autopilot.

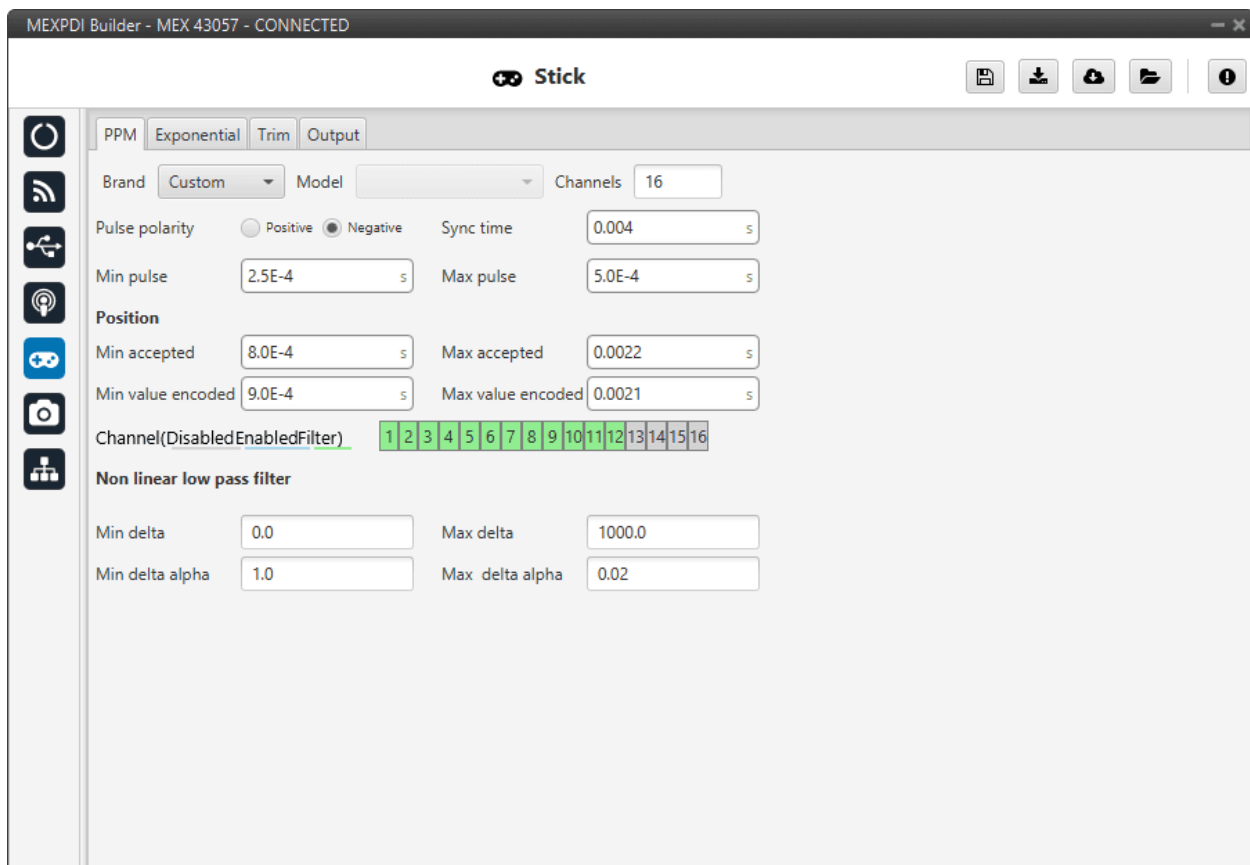


Fig. 55: PPM panel

- **Brand, Model and Channels:** MEX PDI Builder has been configured to provide the user with the expected parameters to configure different transmitters models.

Brand	Models	Channels
Futaba	8J/10J/12K/14SG	8 (for 8J and 10J)
		12 (for 12K and 14SG)
	T18SZ	8
Jeti	DC 16/DC 24	16
FrSky	Taranis X9D	8
	Horus X12S	8
TBS	Crossfire	8
Embention	Stick Expander	16
Custom	-	-

- Custom: If the user's transmitter is not among those mentioned above, choose this option and replace the parameter values with the appropriate ones.
- **Pulse polarity:** Indicates the pulse polarity:
 - **Positive:** Default signal is low and goes up to high.
 - **Negative:** Default signal is high and goes down to low.
- **Sync time:** Minimum time on the PPM output till the next frame. It tells the receiver to reset its channel counter.
- **Minimum/Maximum pulse:** Pulse length, it depends on the system and it is a constant value (usually 0.2-0.5 ms).
- **Position**
 - **Minimum/Maximum accepted:** Pulse length accepted for each channel. Standard for R/C servos uses a pulse of 1 ms for the maximum position at one end, 1.5 ms for the midpoint and 2 ms for the maximum position at the opposite end.
 - **Minimum/Maximum encoded:** If there is noise and the signal is varying around the minimum/maximum values accepted, **MEX** will encode those values to the ones set here. For instance, a pulse length between 0.8-0.9 ms will be considered as one of 0.9 ms.
 - **Channels:** Sets the number of channels accepted. Besides, it is possible to Disable/Enable/Filter each channel individually.
- **Non linear low pass filter**
 - **Minimum/Maximum delta:** Default parameters are recommended.
 - **Minimum/Maximum delta alpha:** Default parameters are recommended.

The figure below shows the PPM signal that arrives to **MEX**:

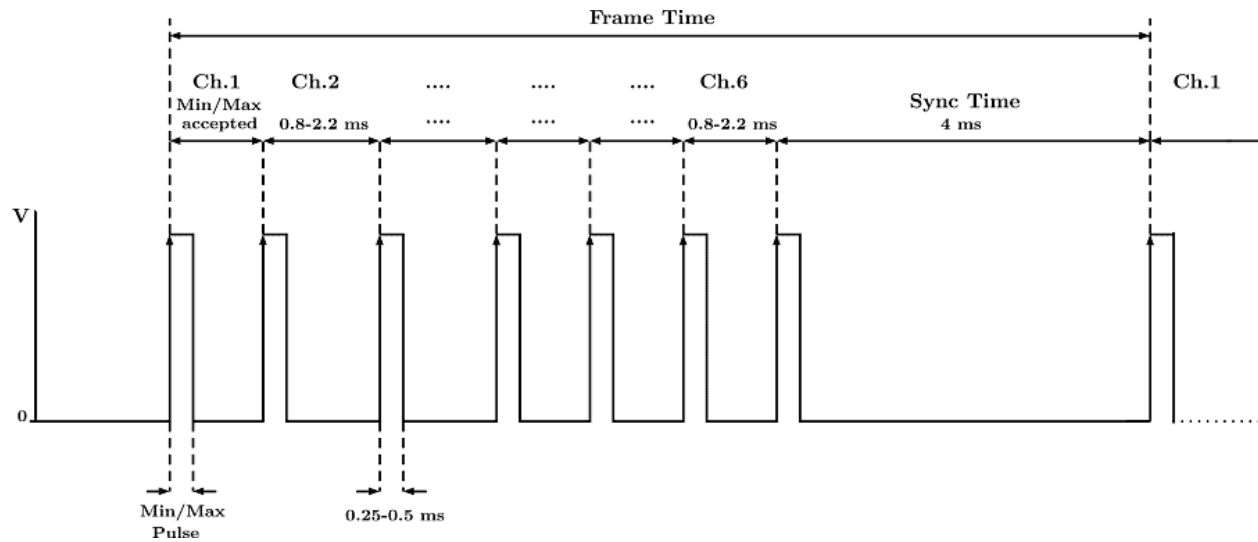


Fig. 56: PPM signal

2.5.2 Exponential

The second tab allows the user to define an exponential stick response for every channel.

The allowed inputs range from 0 to 1 and there is a graph showing the generated response curve, as can be seen in the figure below.

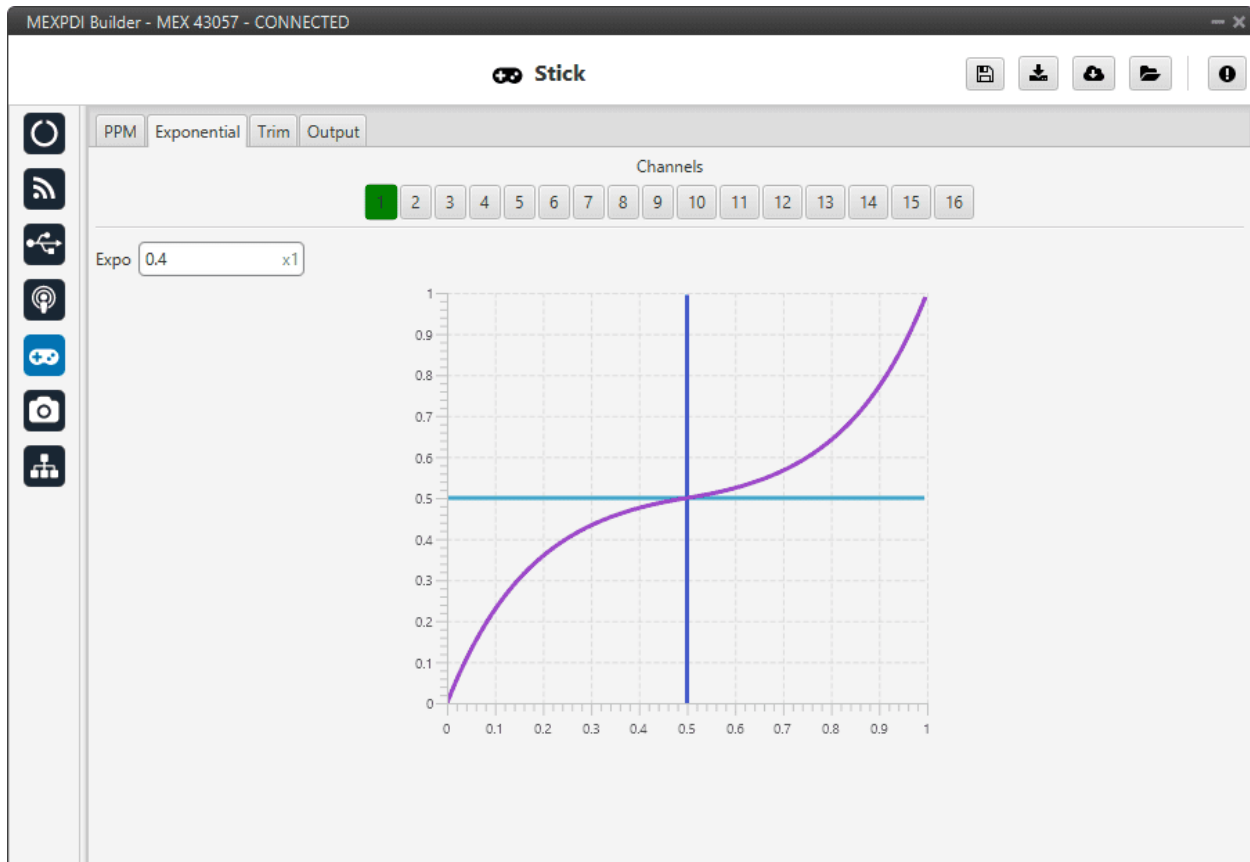


Fig. 57: Exponential panel

The **X axis** of the graph corresponds to the stick input and the **Y axis** is the result of applying the exponential function to that stick input.

2.5.3 Trim

The third tab available is the Trim option.

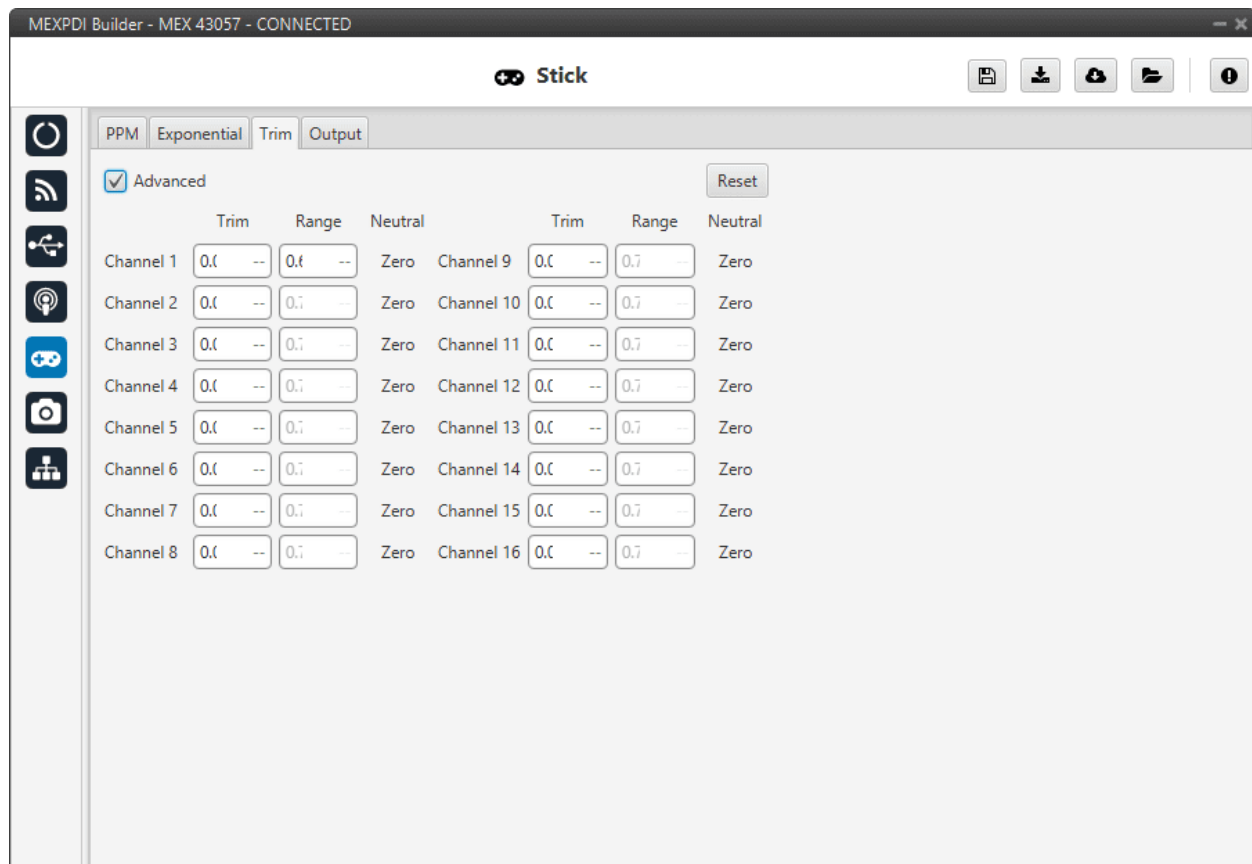


Fig. 58: Trim panel

By enabling the **Advanced** option, the user can set the expected trim values manually. The user should have a deep knowledge on its transmitter if this option is selected.

Finally, on the right hand side, the **Reset** button puts every parameter back to 0.

2.5.4 Output

In this menu the user sets the receiving port and process the incoming commands.

Once the stick has been configured, the commands that arrive at the ground autopilot have to be sent to the air unit.

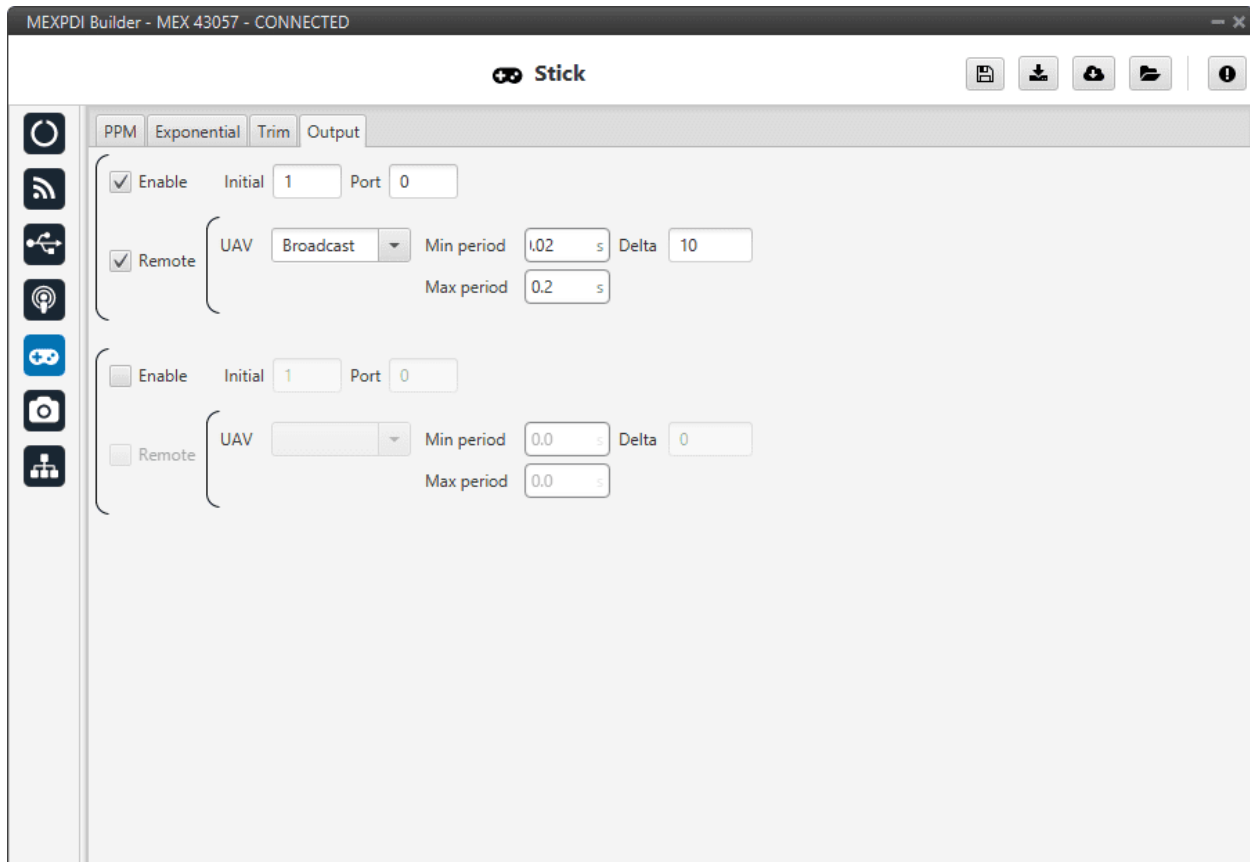


Fig. 59: Output panel

In this menu, the following parameters can be configured:

- **Enable.**
- **Initial Channel at destination:** The user indicates to which channel of the air autopilot will be sent the first channel received in the ground unit. The channels arrive at the platform in order and without spaces between them.

For example, if at the GND channels 6, 7, 8, 9 and 10 are enabled, the AIR will receive channels 1, 2, 3, 4 and 5. Therefore channel 6 of the stick will be channel 1 in the AIR configuration.
- **Port:** If more than one transmitter is configured, each transmitter must be configured on a different port. This has to match the port set on the air unit.
- **Remote:** It has to be enabled if the user wants to allow the delivery of the commands to the platform.
 - **UAV:** The address of the UAV that receive the commands has to be indicated. The following options are the most common:
 - * App 2: Veronte applications address.
 - * Broadcast: The commands are sent to all units on the network. **This option is recommended.**
 - * 1x v4.X XXXX: The address of a specific air unit.

For more information on the available addresses, see [List of addresses](#) section of the **MEX Software Manual**.

- **Min period:** As the period is the inverse of the frequency, this defines the **maximum frequency**. Therefore, to give the pilot more control, this defines the frequency that is set when the **stick is commanding**. A *Min period* of **0.02s** is recommended.
- **Max period:** As the period is the inverse of the frequency, this determines the **minimum frequency**. Thus, to free up bandwidth, this defines the frequency that is set when the **stick is idle**. A *Max period* of **0.2s** is recommended.
- **Delta:** This parameter determines whether the frequency is set to the minimum or maximum period set above.

If **MEX** detects a **change above** the **delta value**, the frequency goes to the **maximum frequency** (minimum period). While if the **changes are less than this value**, it switches to the **minimum frequency** (maximum period). **10 Hz** are recommended.

Note: An example of how to configure a stick can be found in the [Stick - Integration examples](#) section of the **1x PDI Builder** user manual.

2.6 Devices

2.6.1 Jetibox

MEX can simulate a Jetibox to read telemetry from Legacy Jeti devices.

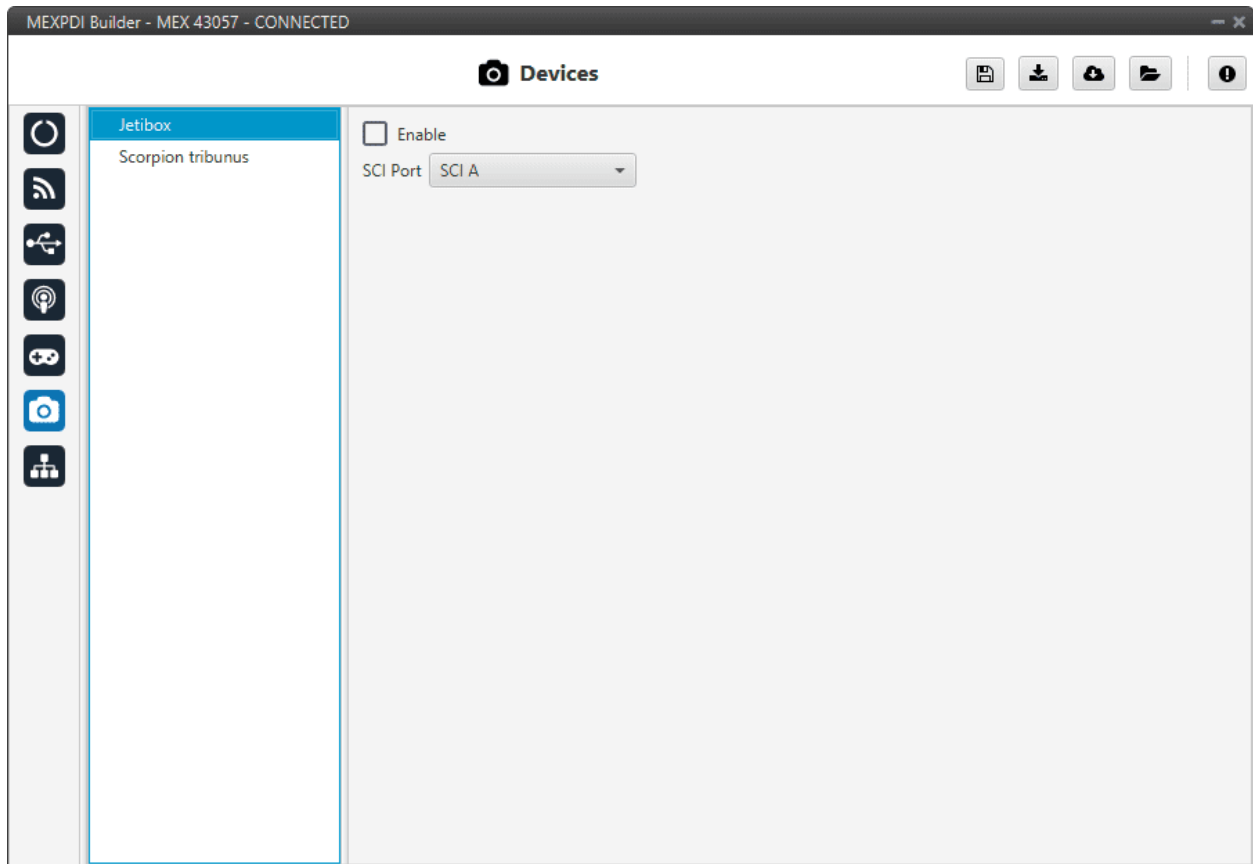


Fig. 60: Jetibox panel

- **Enable:** It can be enabled or disabled by the user.
- **SCI Port:** A SCI port must be selected. The available options are: **SCI A**, **SCI B** or **SCI C**.

Besides, a configuration is needed in the *Serial* and *I/O Setup* panels.

An example of this can be seen in the *Jetibox - Integration examples* section of the present manual.

Note: The serial port will be totally reserved for this, so it will not be usable to other things and the I/O Setup affecting it will be ignored.

2.6.2 Scorpion tribunus

MEX can read telemetry from Tribunus ESC connecting it to a serial port.

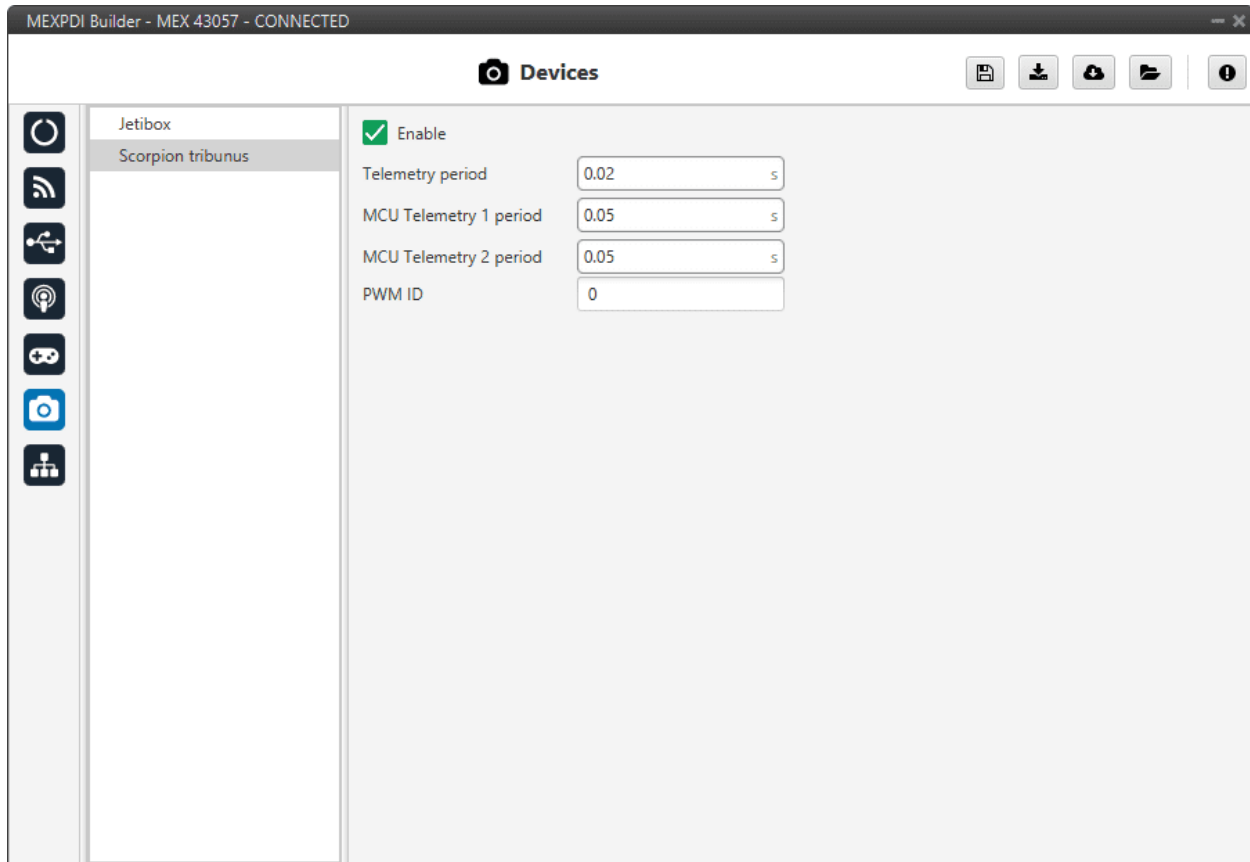


Fig. 61: Scorpion tribunus panel

The following parameters are configurable:

- **Enable:** It can be enabled or disabled by the user.
- **Telemetry period.**
- **MCU telemetry 1/2 period:** Telemetry period for MCU devices.
- **PWM ID:** PWM ID associated to the Scorpion Tribunus.

The serial port has to be configured in the *I/O Setup panel*.

An example is explained in the *Scorpion tribunus - Integration examples* section of this manual.

Note: The serial port will be totally reserved for this, so it will not be usable by other things and the I/O setup affecting it will be ignored.

2.7 Arbitration

The arbitration algorithm is explained in detail in the [Arbitration](#) section of the **4x PDI Builder** user manual.

2.7.1 Arbitration

MEX is able to send PWMs using arbitration in the same way **Veronte Autopilot 4x** does. This functionality requires to be enabled in the **Enable** checkbox.

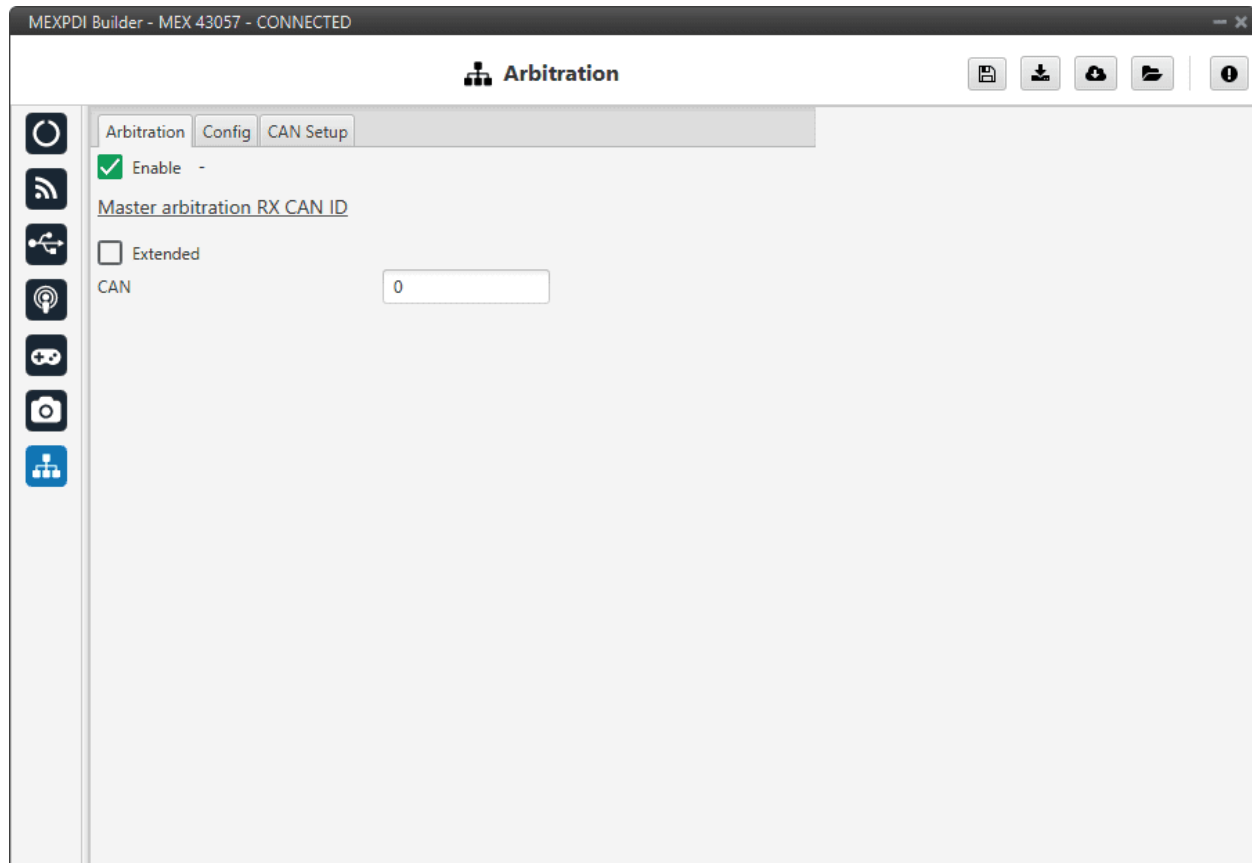


Fig. 62: Arbitration panel

Master arbitration RX CAN Id is exclusive for **MEX** when it is used alongside a **Veronte Autopilot 4x**. If **enabled**, when an arbitration message is received from the Arbiter of the **Autopilot 4x** (with the **CAN Id** configured here), the selected autopilot will be updated according to the data received.

2.7.2 Config

In this tab the parameters of the arbiter algorithm are set.

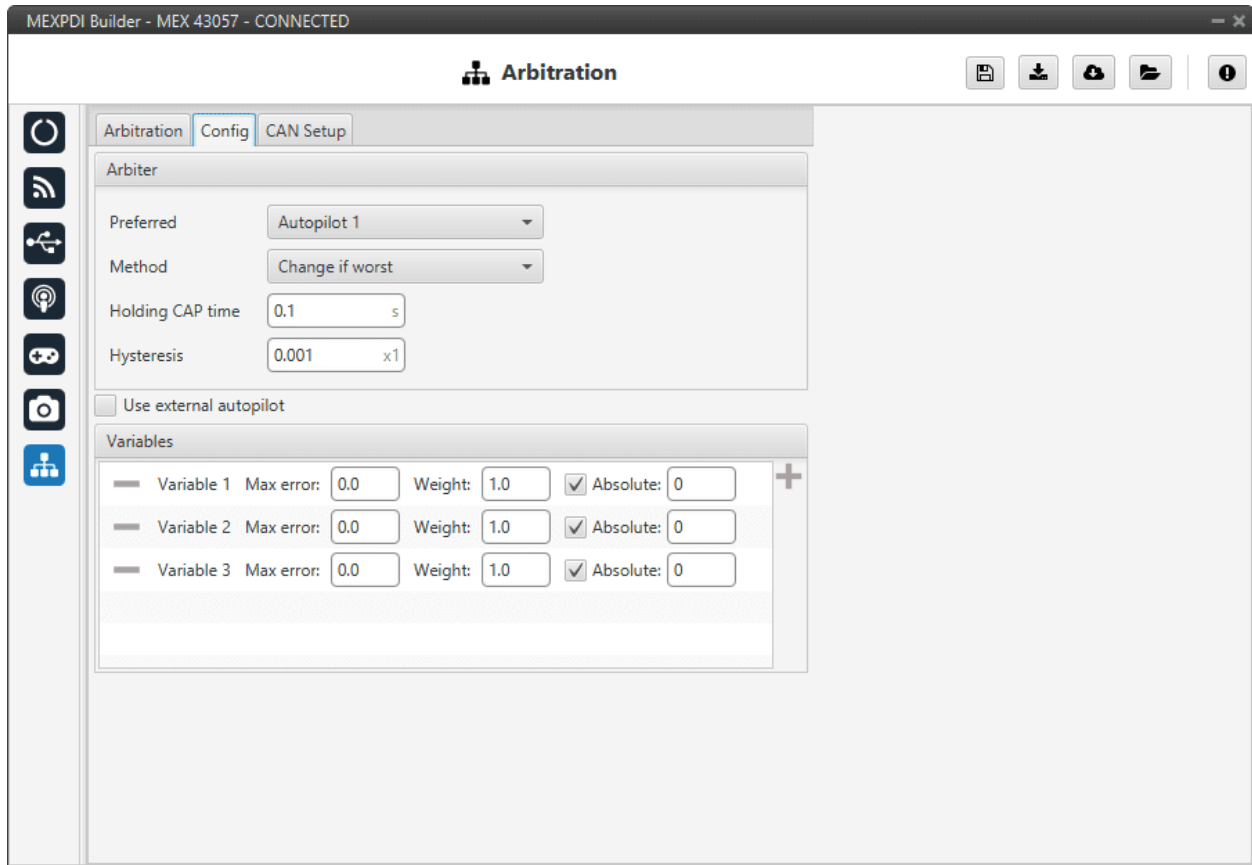




Fig. 63: Configuration panel

- **Preferred:** The preferred autopilot will be chosen in case of a score draw. **Fixed while ok** mode will always select this autopilot first.
- **Method:** The method of arbitration can be chosen by the user. The available options are:
 - **Always best:** It chooses always the best autopilot.
 - **Change if worst:** The arbiter will only switch if the currently selected autopilot has the worst score. In that case, it will switch to the one with the best score.
 - **Round robin control:** Using the **Holding CAP** time parameter, the **arbiter** will periodically switch between autopilots. This mode is meant for testing purposes only.
 - **Fixed:** Arbitration is disabled and one autopilot is selected. In this mode **Autopilot 4x** will behave as an **Autopilot 1x**.
 - * **Fixed 1:** Autopilot 1 is selected.
 - * **Fixed 2:** Autopilot 2 is selected.
 - * **Fixed 3:** Autopilot 3 is selected.
 - **Fixed while ok:** This mode does not take into account scores. In this mode, the **Preferred** autopilot will be selected by default. A switch will only happen if the current autopilot is considered **Dead**.

- **Holding CAP time:** Amount of time needed from last switch in order to allow a new switch.
- **Hysteresis:** When comparing scores, the difference between them needs to be bigger than this proportional value, in order to assess scores. The difference is proportional to the score of the selected autopilot.
i.e: If current selected autopilot is the number 1, arbitration mode is **Always best**, hysteresis is **0.5** and score for AP 1 is **0.3**, AP 2 will need a score lower than **0.15** in order to be selected.
- Enable arbitration of **external autopilot**.
- **Variable - Max error:** Arbitration maximum error for each variable.
- **Variable - Weight:** Arbitration weight for each variable.
- **Variable - Absolute:** If it is enabled, it will indicate that it is an absolute variable. The value set here will be used to compare the variables in order to choose the best autopilot.

Click on  to add variables and  to delete them. Currently, the **maximum** amount of **arbitration variables** supported is **32**.

2.7.3 CAN Setup

This menu allows to configure the receiving CAN Ids for each of the 3 possible **Veronte Autopilots 1x** that are sending data to **MEX**. Therefore, to send data from any of them to **MEX**, these Ids must be specified.

Note: If arbitration is not enabled, only the configuration for Autopilot 1 will be used.

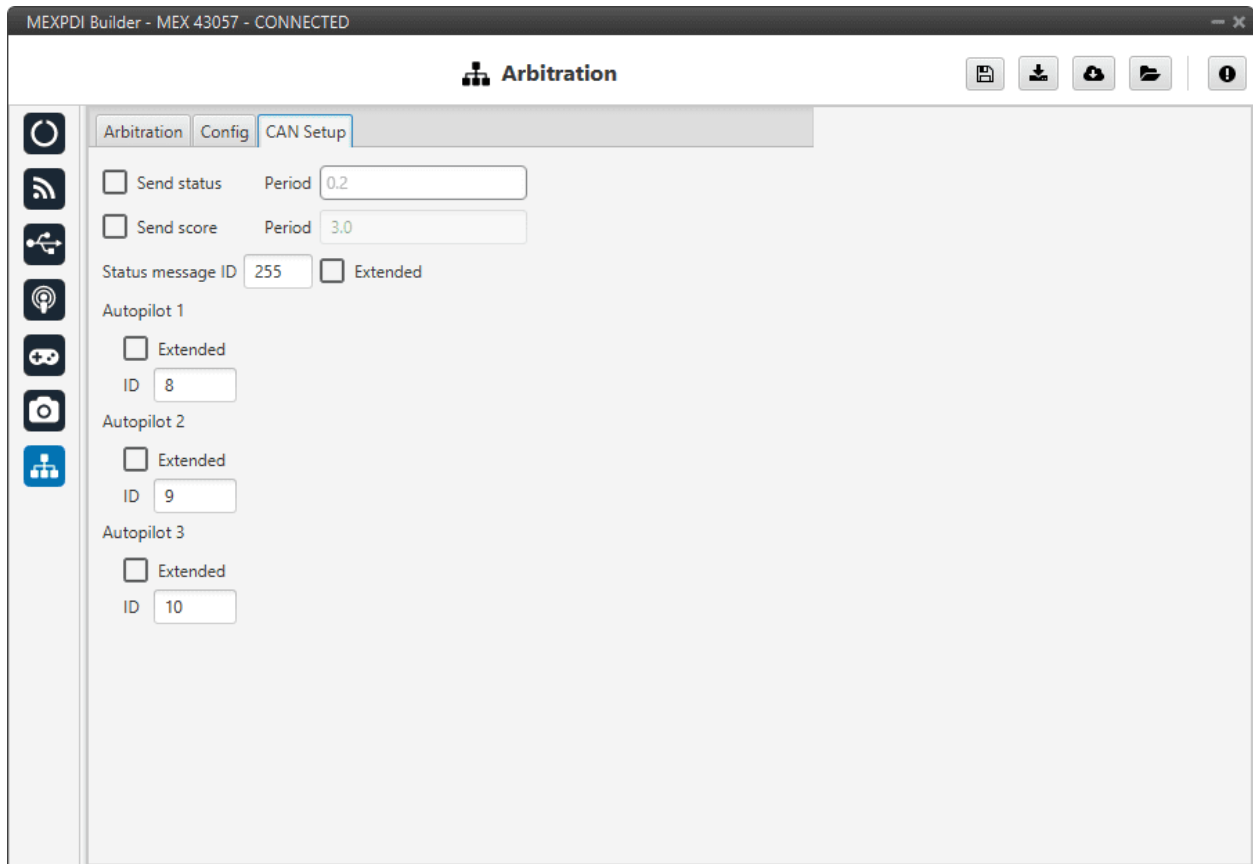


Fig. 64: CAN Setup panel

- **Send status and Period:** The user can enable status message sending and set its period.

Note: The *Send status Period* must be set to **0.2 s**, otherwise the arbitration algorithm will force the selection of autopilot 1.

- **Send score and Period:** Users can enable the score message and define its period.
- **Status message ID:** CAN ID to which Status and Score messages are sent when there is **no External Arbitration** and therefore MEX works as **arbiter**.
 - **Extended:** If enabled, the frame format will be '**Extended**' (with a **29-bit identifier**). Otherwise, the frame format '**Standard**' (with a **11-bit identifier**) is set by default.
- **Autopilot 1-3:** CAN IDs used for the reception of autopilot 4x arbitration messages for each autopilot.
 - **Extended:** If enabled, the frame format will be '**Extended**' (with a **29-bit identifier**). Otherwise, the frame format '**Standard**' (with a **11-bit identifier**) is set by default.

INTEGRATION EXAMPLES

3.1 CAN communication

MEX can send and receive messages via CAN.

3.1.1 CAN messages transmission

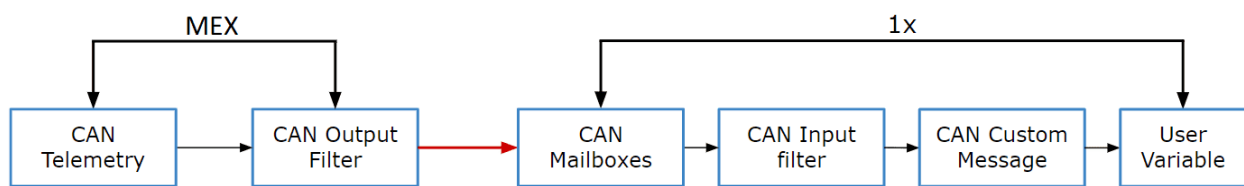


Fig. 1: CAN messages transmission - Communication diagram MEX → 1x

Users must follow the steps below to send telemetry via CAN and configure an **Autopilot 1x** to read this telemetry.

1. Go to Input/Output menu → CAN I/O panel → **Configuration tab**.

Connect **CAN Telemetry** to a **CAN Output Filter** as follows:

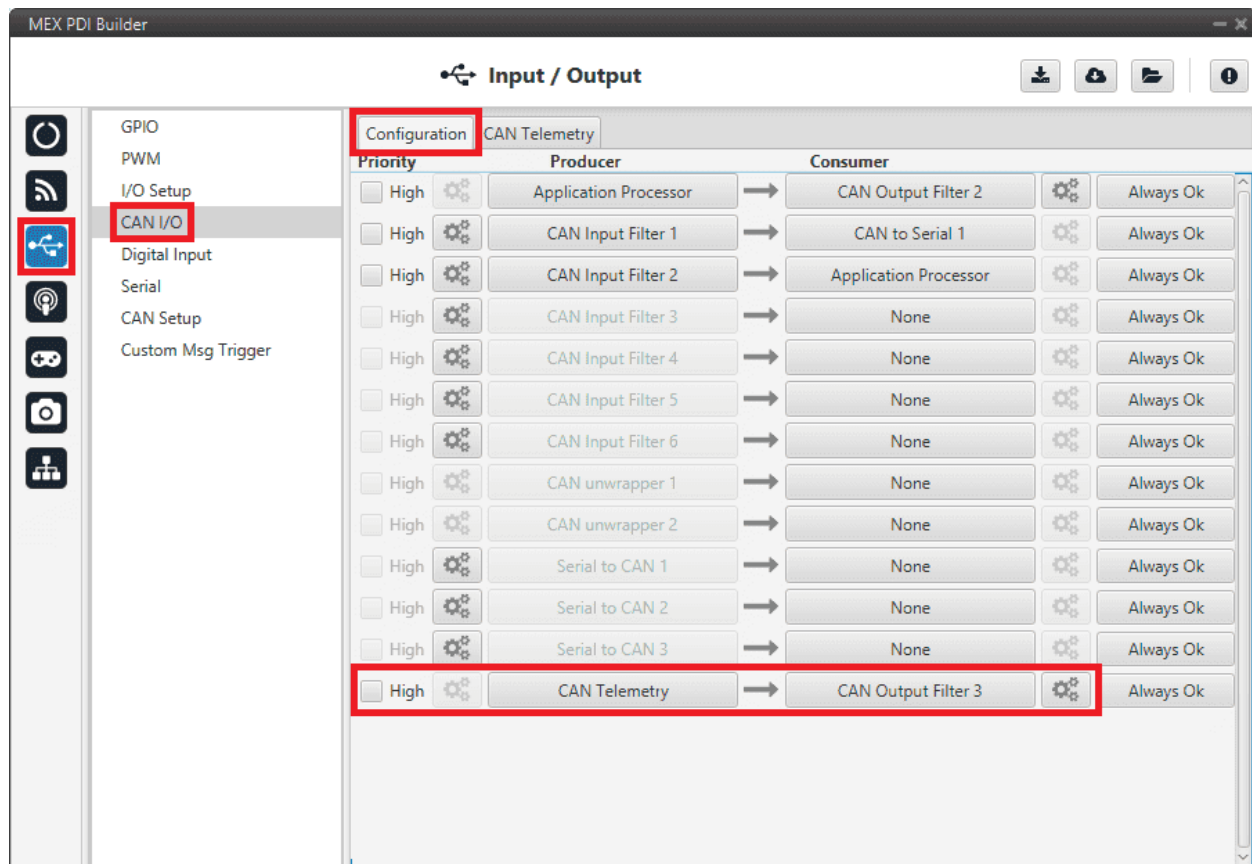


Fig. 2: CAN messages transmission - CAN I/O configuration

- Go to Input/Output menu → CAN I/O panel → **CAN Telemetry** tab.

Select the fields to send in the **TX**. More information about the configuration of telemetry messages can be found in the *CAN Telemetry - Input/Output* section of this manual.

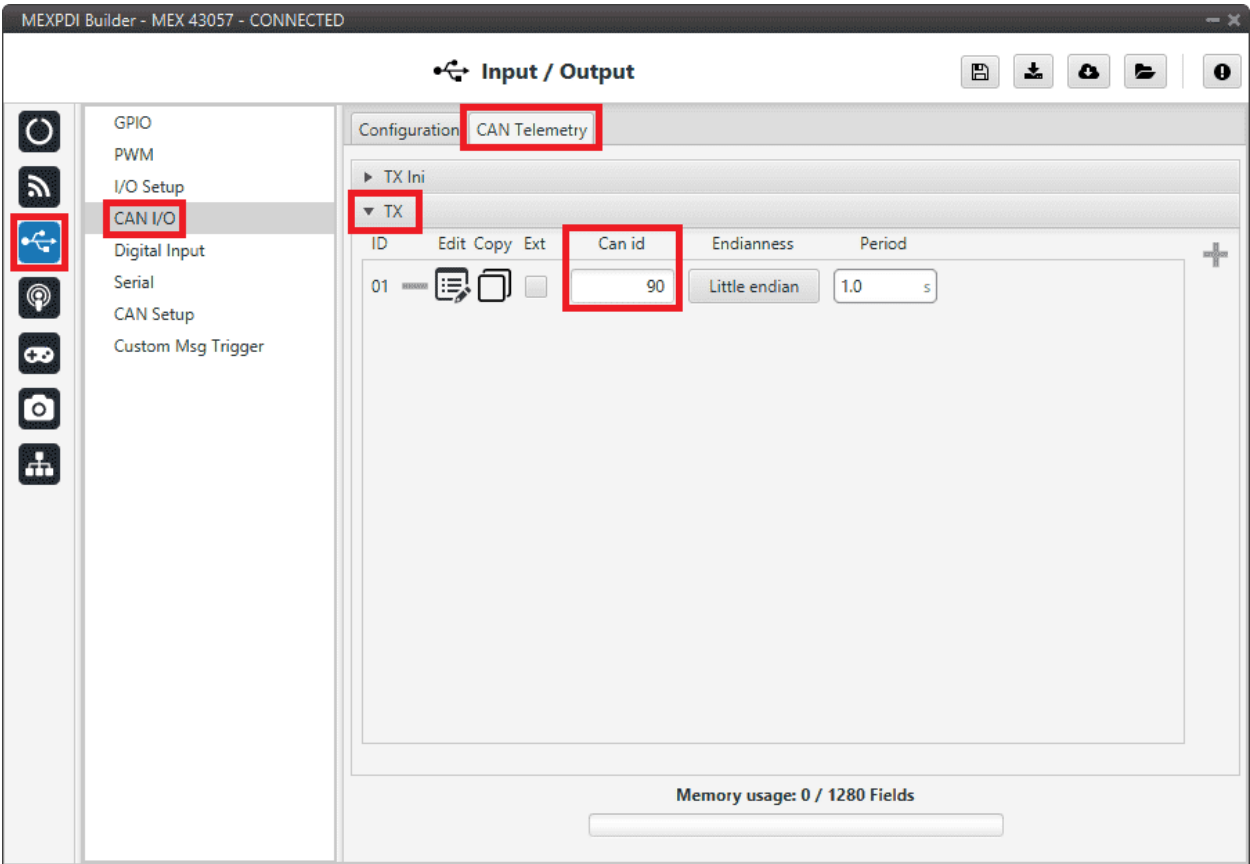


Fig. 3: CAN messages transmission - CAN Telemetry

For example, a telemetry message with a variable set to ID 90:

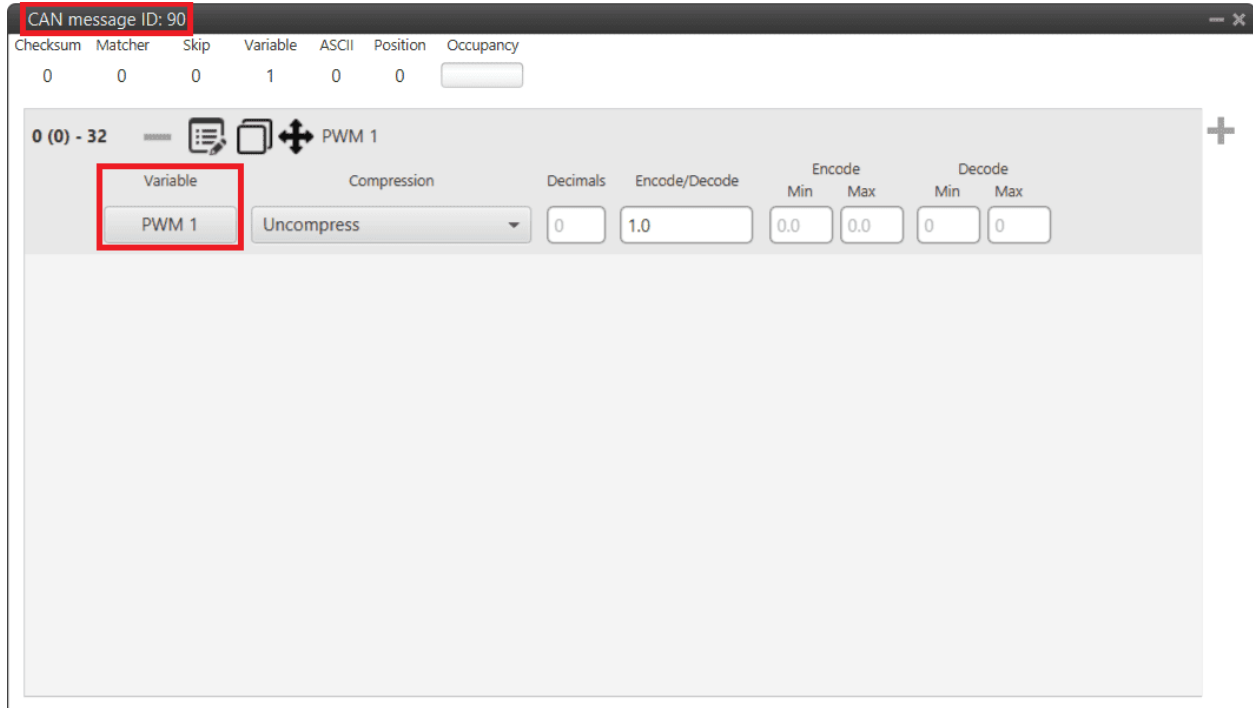


Fig. 4: CAN messages transmission - CAN Telemetry example

3. Configure the **Autopilot 1x** to read telemetry from **MEX**, following the [CAN messages reception - Integration examples](#) section of the **1x PDI Builder** user manual.

Note: The configured CAN ID must match the one in **MEX**.

3.1.2 CAN messages reception

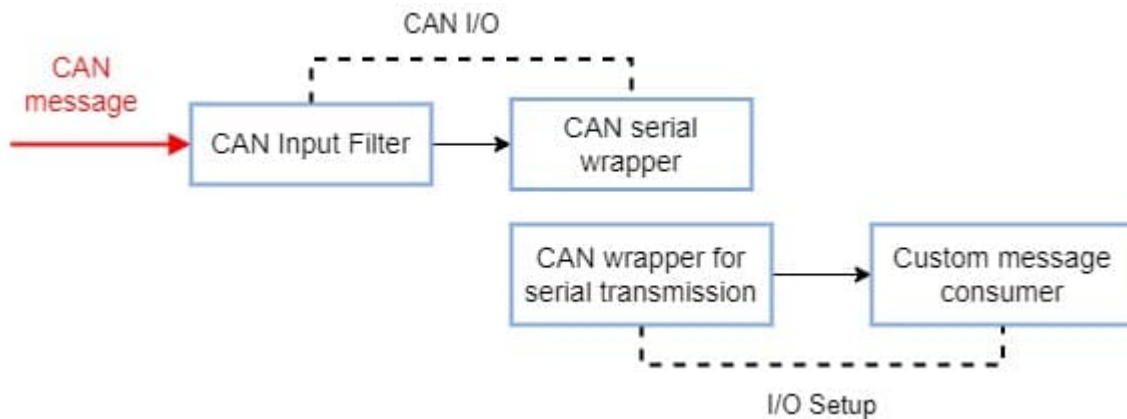


Fig. 5: CAN messages reception - Communication diagram

Users must follow the steps below to read CAN messages.

1. Go to Input/Output menu → CAN I/O panel → **Configuration tab**.

Connect a **CAN Input Filter** to a **CAN serial wrapper** as follows:

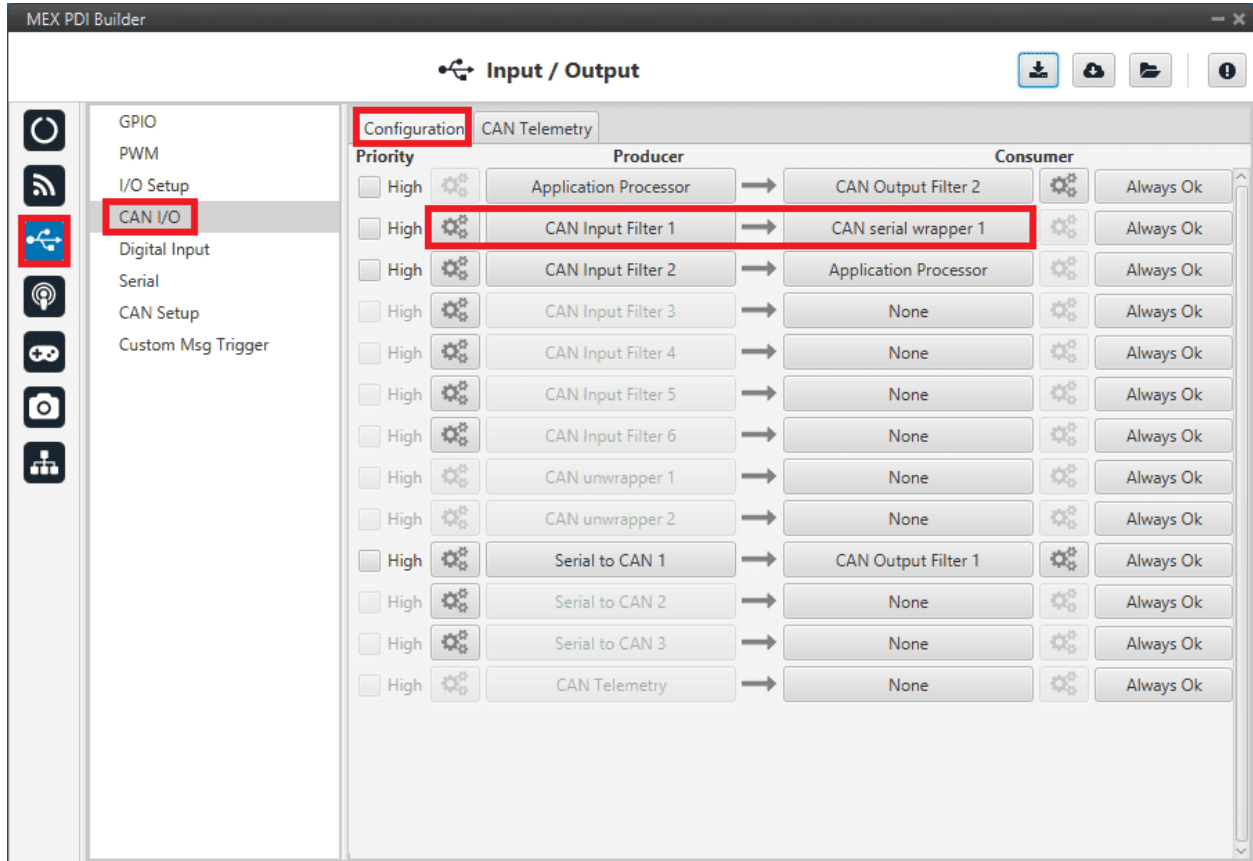



Fig. 6: CAN messages reception - CAN I/O configuration

2. Click on the  button of the **CAN Input Filter** and configure the *Port* and *CAN Id*, according to the messages to receive.
3. Go to Input/Output menu → I/O Setup panel → **Configuration tab**.
Connect the corresponding **CAN wrapper for serial transmission** to a **Custom message consumer**.

Note: The **CAN wrapper for serial transmission** index must match the index of the **CAN serial wrapper** configured in the previous step (in this example, CAN wrapper for serial transmission with **index 1** is used).

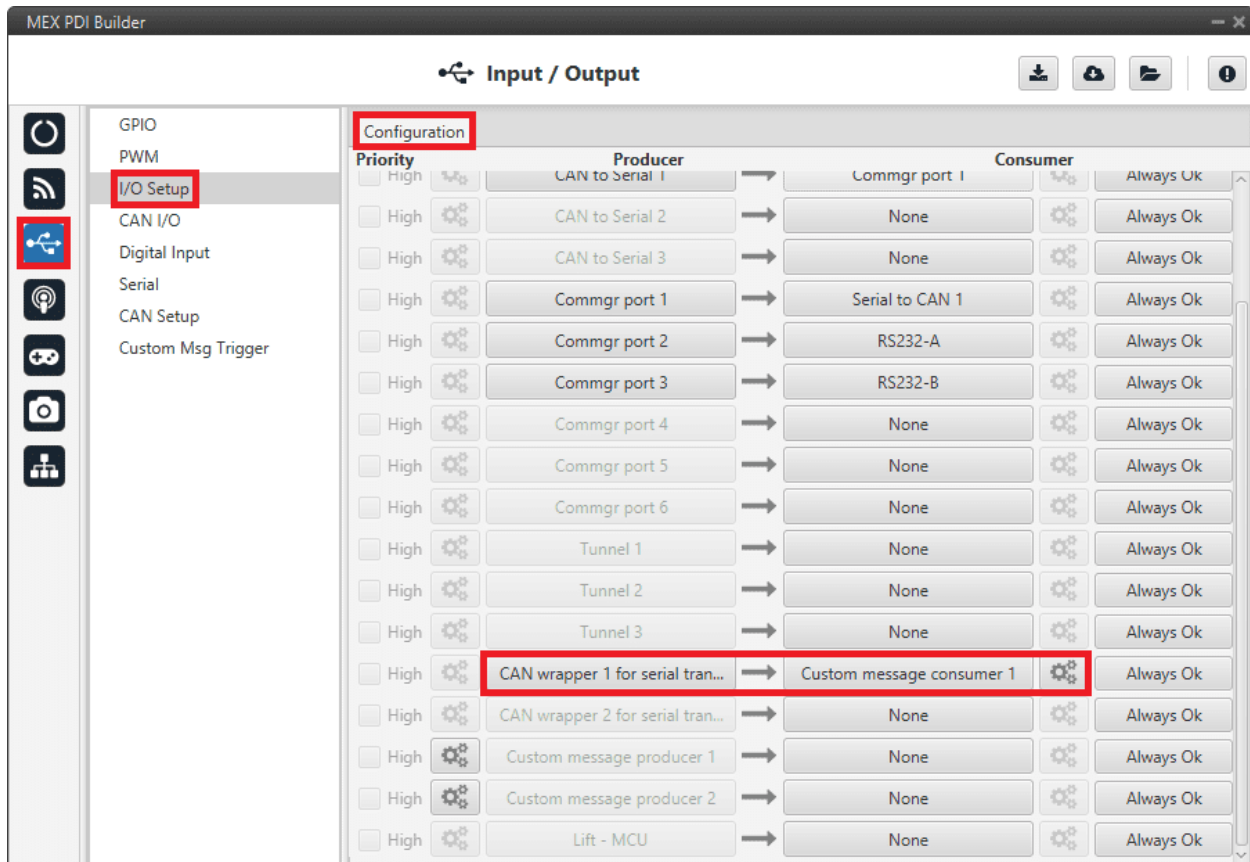



Fig. 7: CAN messages reception - I/O Setup configuration

4. Click on the  button of the **Custom message consumer** to access its configuration. To correctly read the CAN message, it must be setup as follows:
 - **Endianness:** Little endian
 - **Matcher:**
 - Value: 202
 - Bits: 8
 - **Skip 40**
 - **User variables to receive.**
 - **CRC:**
 - Type: Polynomial
 - Endianness: Little endian
 - Crc-Preset: crc16veronte
 - BackFrom: Number of bytes from which the CRC is computed, in this case, bytes comprehended between the Matcher and this CRC.
 - BackTo: 0
 - Binary mode

If users wish more detailed information on this configuration, please refer to [Custom message types - Input/Output](#) section of the **1x PDI Builder** user manual.

The configuration of the **Custom message consumer** below is an example of **the reception of three Real variables**.

Note: The **CRC BackFrom** entry is 17 since there are 5 bytes in the **Skip 40** and 12 bytes for the User variables.

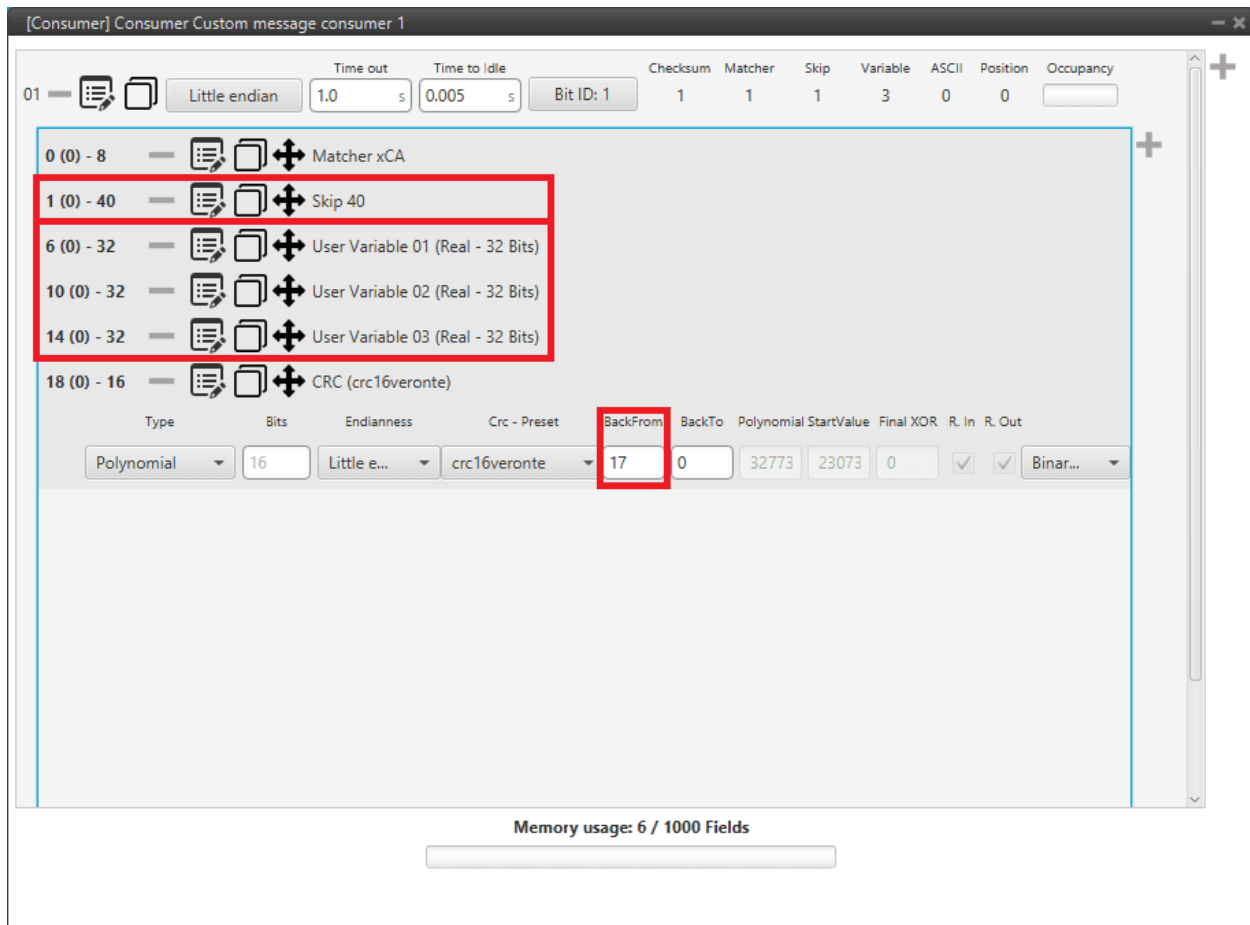


Fig. 8: CAN messages reception - Custom message configuration example

3.2 CAN Isolator

MEX can operate as a CAN bus isolator, since it manages both CAN buses as desired. The system has a built-in microcontroller; which manages CAN buses in real-time. Both buses are not electrically connected, in consequence, electrical signals that do not follow the CAN protocol will be isolated.

The functionalities of a CAN isolator are the following:

- *CAN Input Filter*
- *Filtered CAN subnet*
- *CAN tunnel*

The following diagram summarizes the behavior of MEX as a CAN bus isolator:

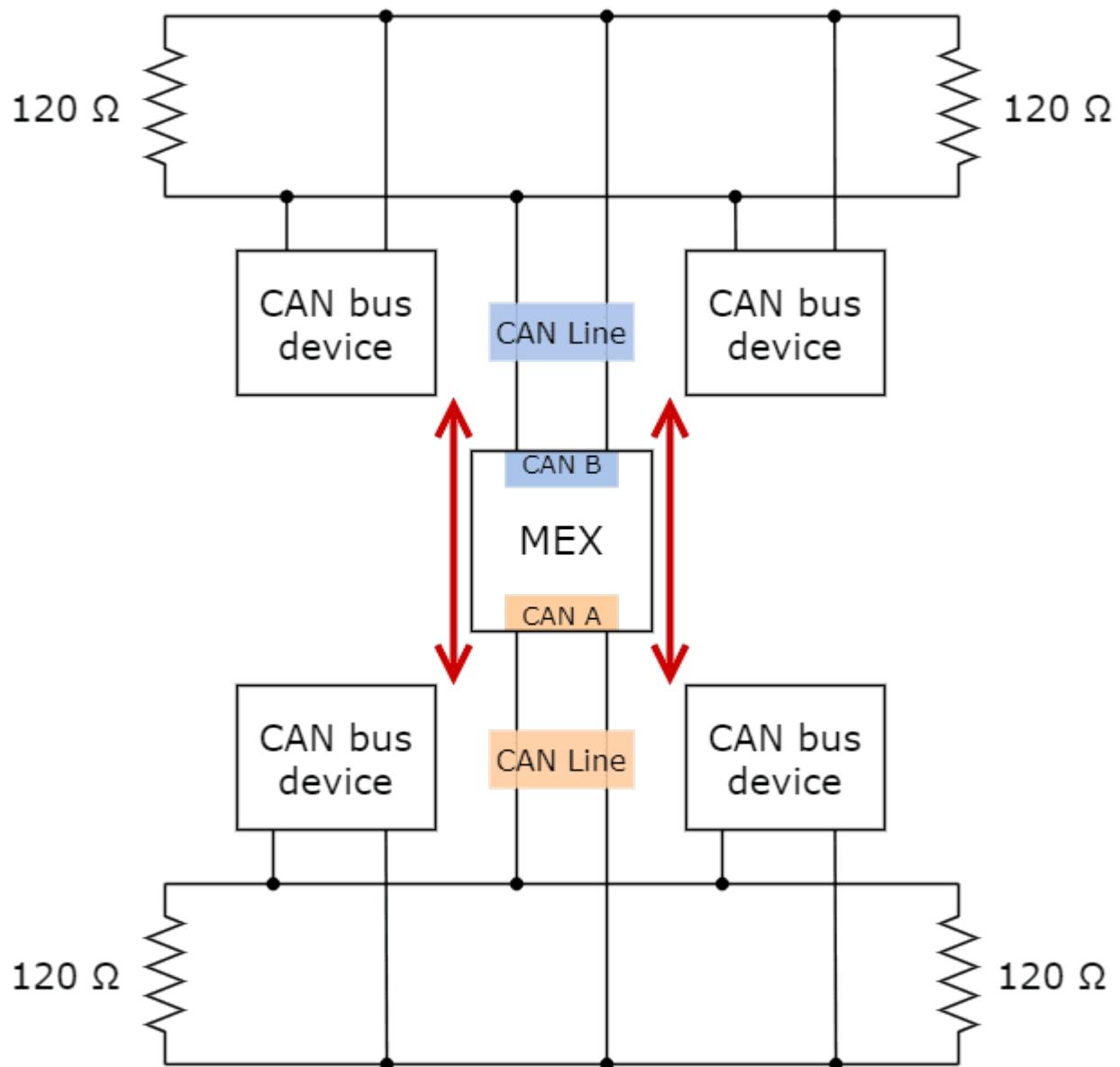


Fig. 9: Subnets CAN diagram

3.2.1 Filtered CAN subnet

With **MEX** it is possible to isolate CAN nets, by filtering certain messages from one CAN line and only transmitting specific information through **MEX** to the other one.

In this example, only a certain range of CAN IDs will be allowed to cross from one CAN line to the other using the two CAN ports of **MEX**. Specifically, information will pass **from CAN B** of MEX to **CAN A** of MEX:

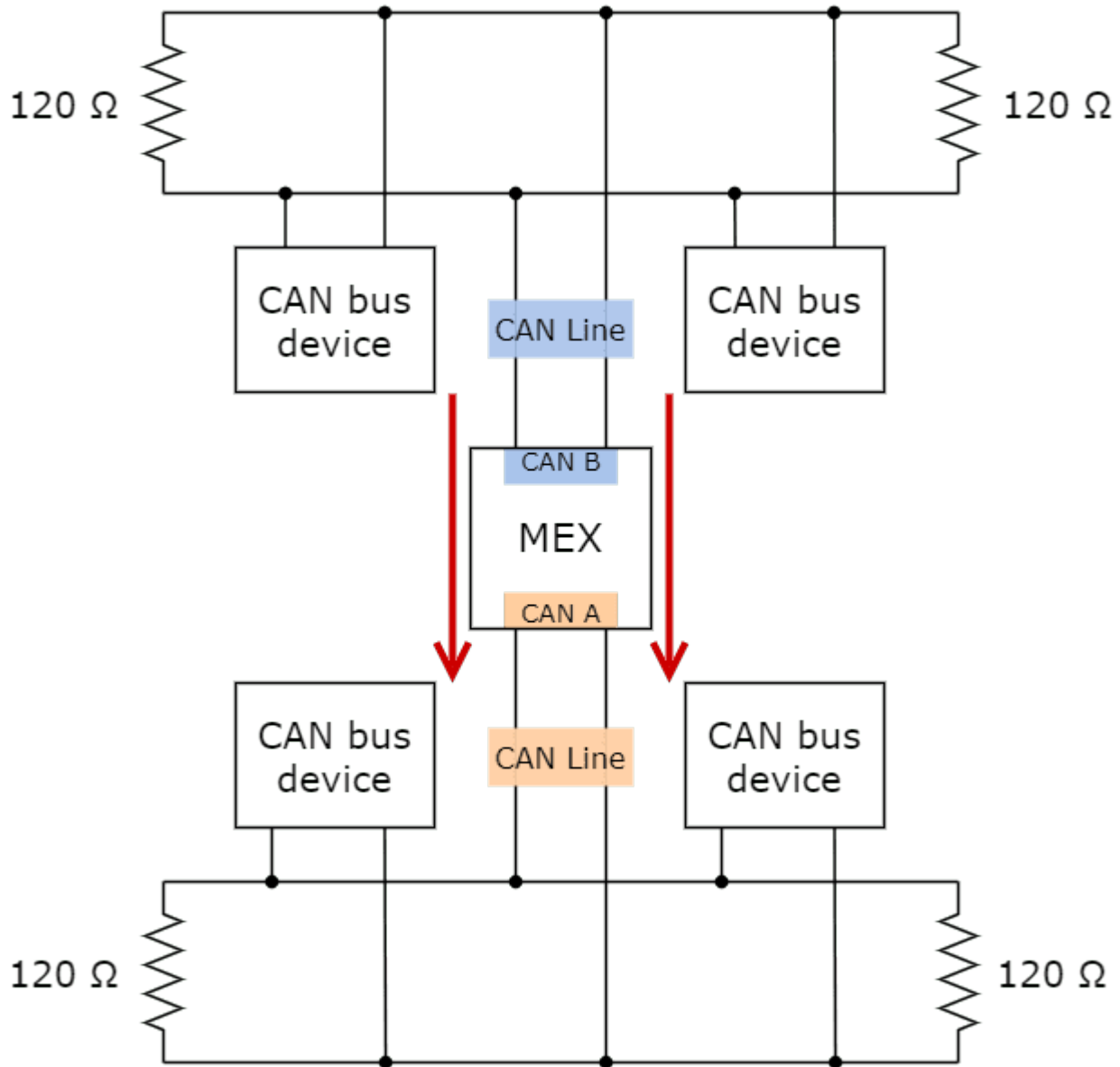


Fig. 10: Subnets CAN example - From CAN B to CAN A

The allowed range will be from **0x550** to **0x55F**.

1. Create a new mailbox entry for **CAN B**.

To do this, go to Input/Output menu → CAN Setup panel → **CAN B tab**.

Assign some of the mailboxes to it and set the ID to **0x550**. This example uses an ID expressed in **hexadecimal** notation.

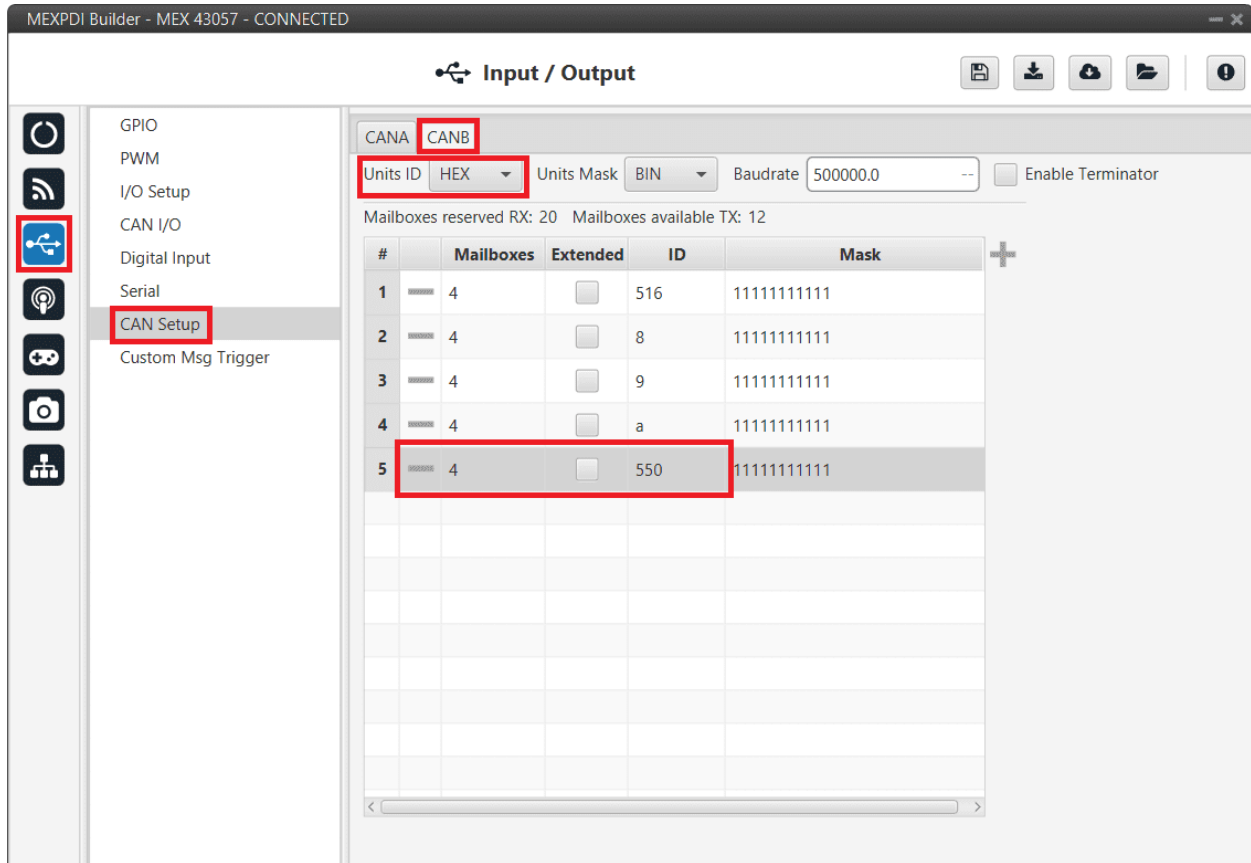


Fig. 11: Filtered CAN subnet - CAN Setup configuration

2. Set a Mask which will ignore the last 4 bits.

Note: Although the ID has been entered in hexadecimal notation, note that the Mask has been set in **binary** format.

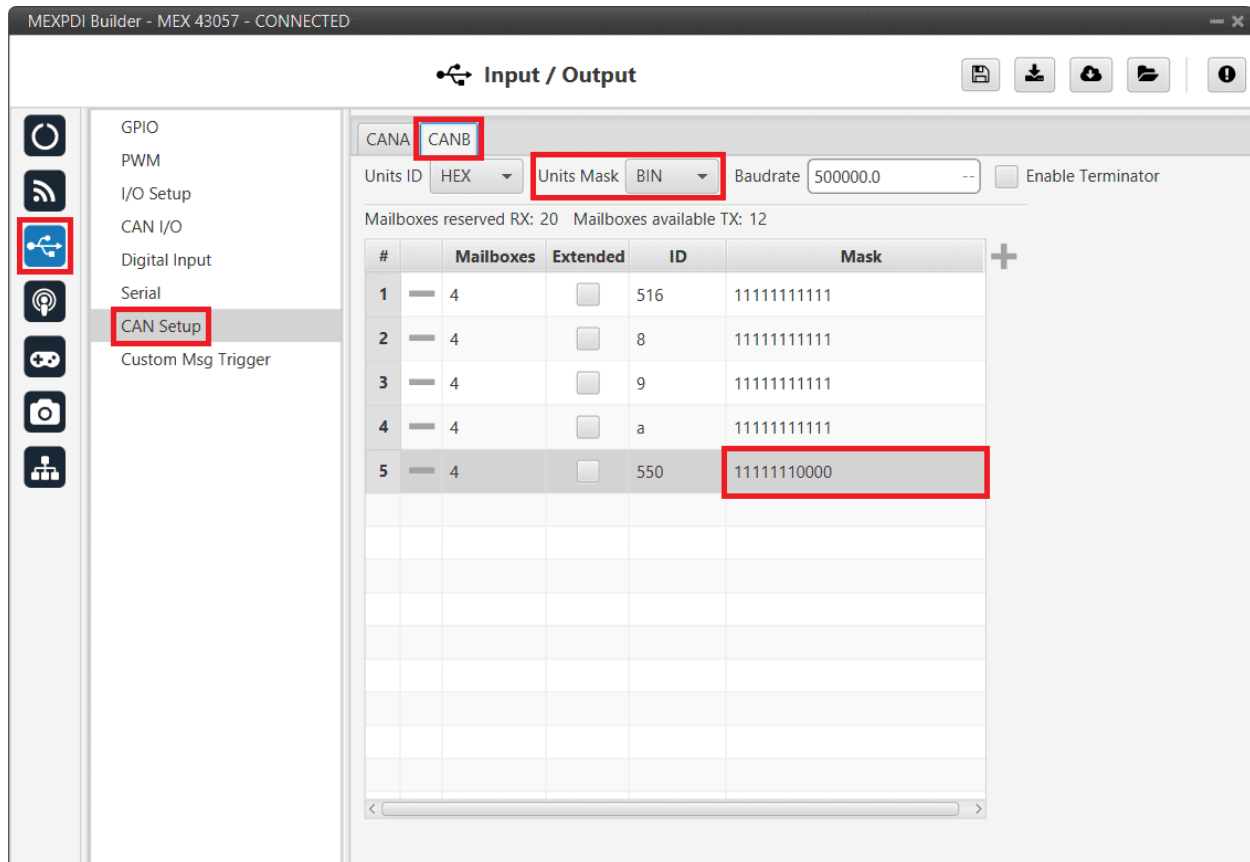


Fig. 12: Filtered CAN subnet - CAN Setup mask configuration

- Go to Input/Output menu → CAN I/O panel → **Configuration tab**.

Configure **CAN Input Filter 3** on **CAN B**, with the same settings as the **Mailbox**.

Important: This menu only allows setting the Id with **decimal numbers**. For this example the Id 0x550 is represented as **1360** in decimal format, and the Mask is also represented in decimal format as **2032**.

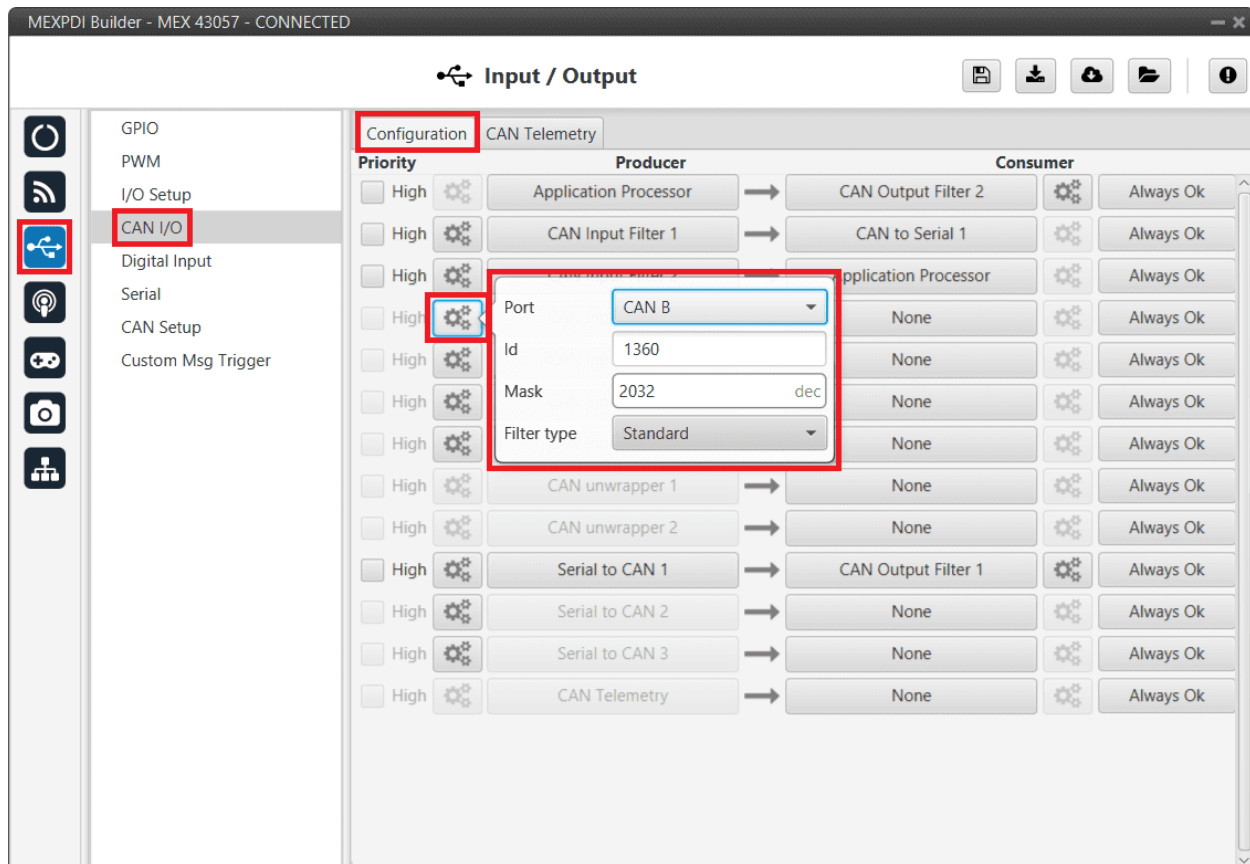


Fig. 13: Filtered CAN subnet - CAN Input Filter configuration

4. Bind CAN Output Filter 3 to CAN Input Filter 3 and, configure the CAN Output Filter to CAN A.

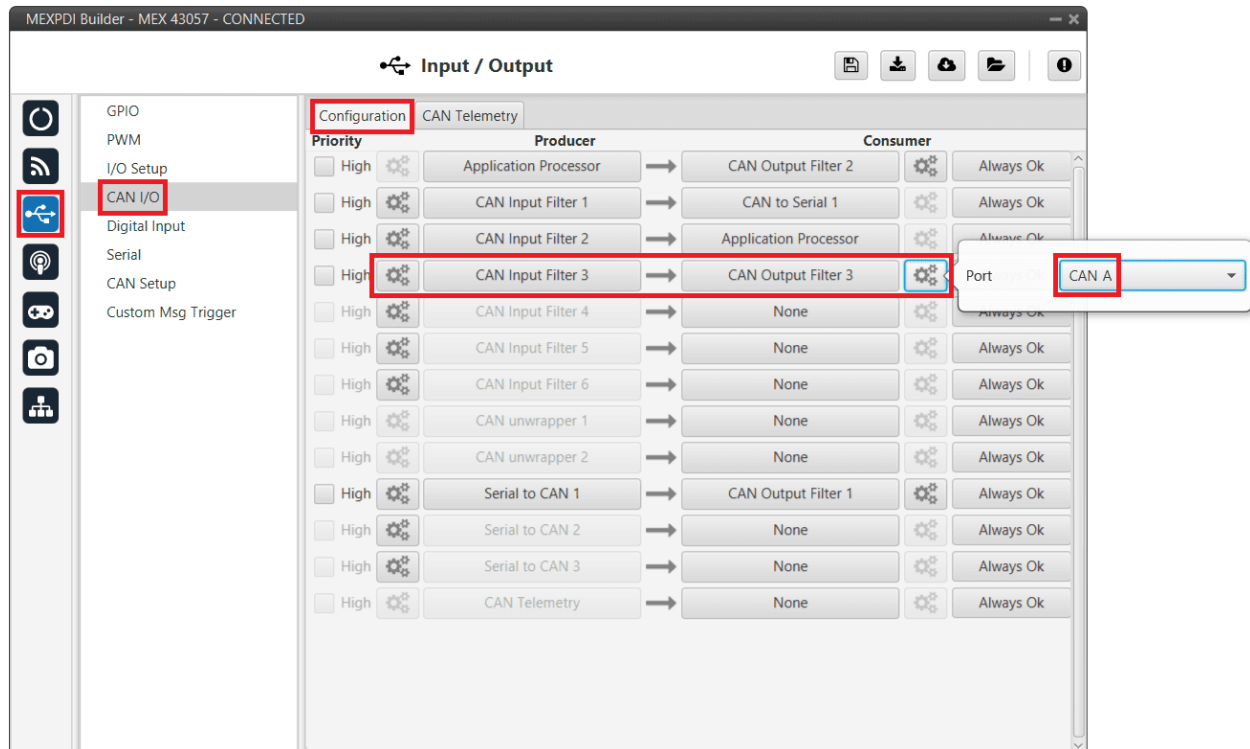


Fig. 14: Filtered CAN subnet - CAN Output Filter configuration

3.2.2 CAN tunnel

A CAN tunnel is a specific case of [a message tunnel](#); where messages are tunneled from one CAN port of **MEX** to the other.

In this example, a transparent tunnel will be created. So, any messages received on **Interface A** will be sent through **Interface B**:

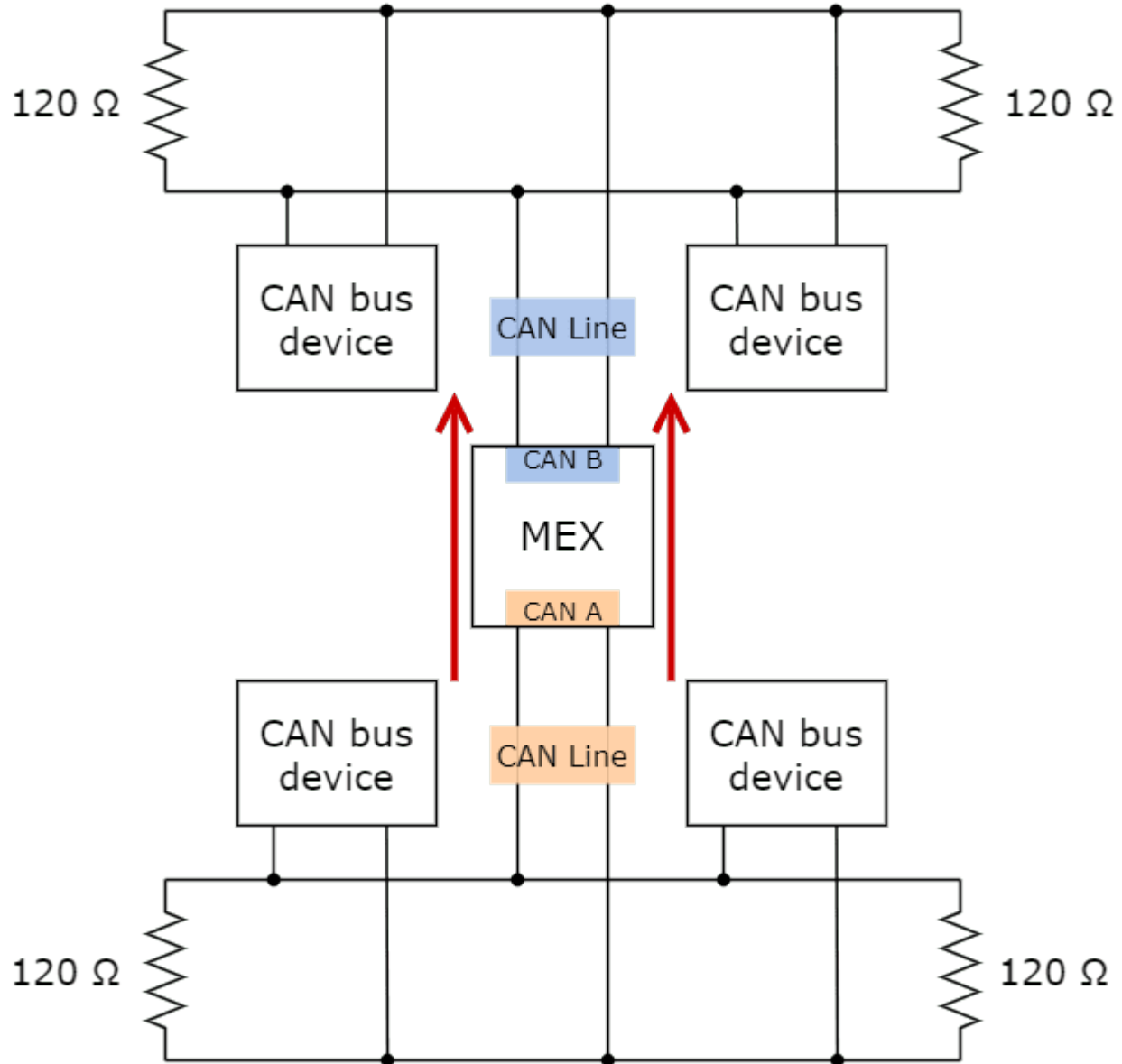


Fig. 15: Subnets CAN example - From CAN A to CAN B

Optionally, the mailboxes can be equally distributed to support both standard and extended CAN IDs.

1. Create a new mailbox entry for **Interface A**.

To do this, go to Input/Output menu → CAN Setup panel → **CAN A tab**.

Assign half of the mailboxes to it and set a **Mask** of 0.

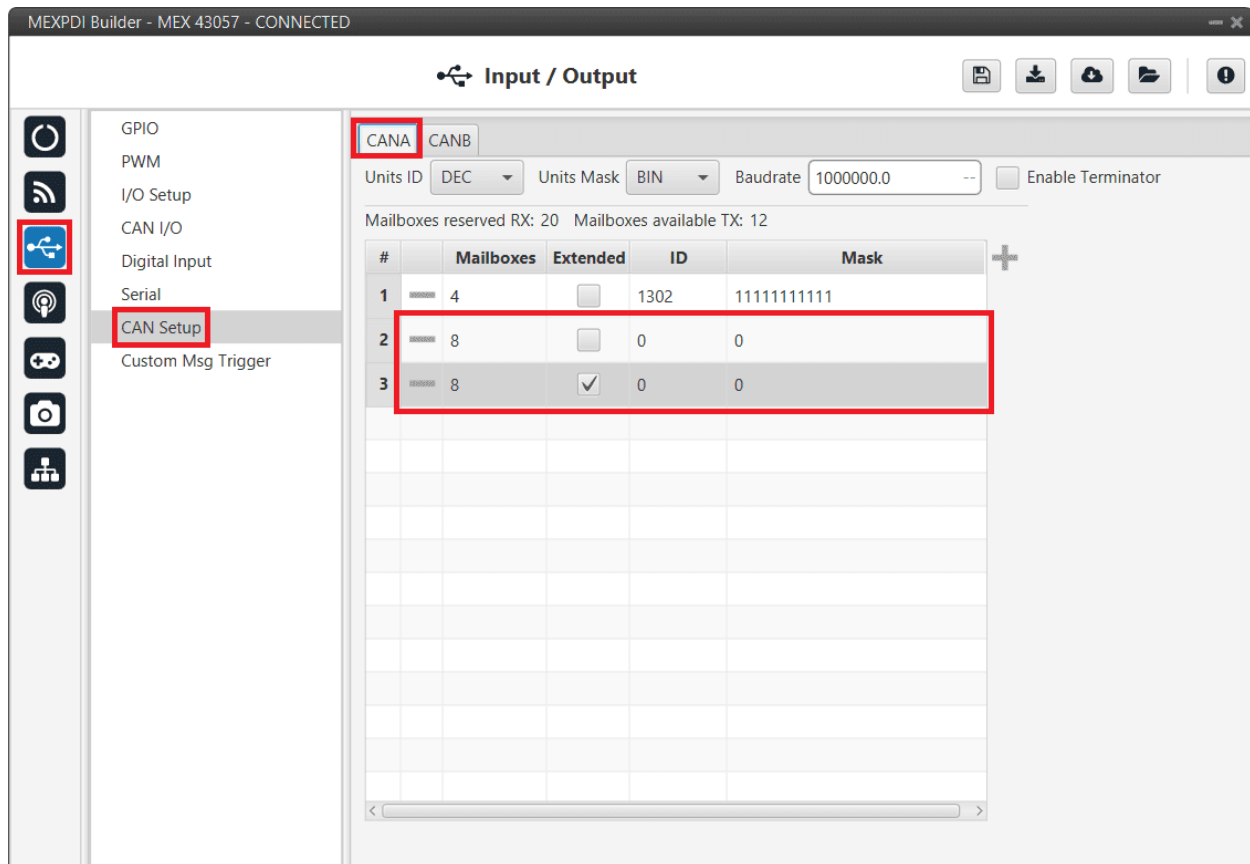


Fig. 16: CAN tunnel - CAN Setup configuration

- Go to Input/Output menu → CAN I/O panel → **Configuration tab**.

Configure **CAN Input Filter 3** on **CAN A**, with CAN id **0**, a **Mask** of 0 and **Both** as frame format type.

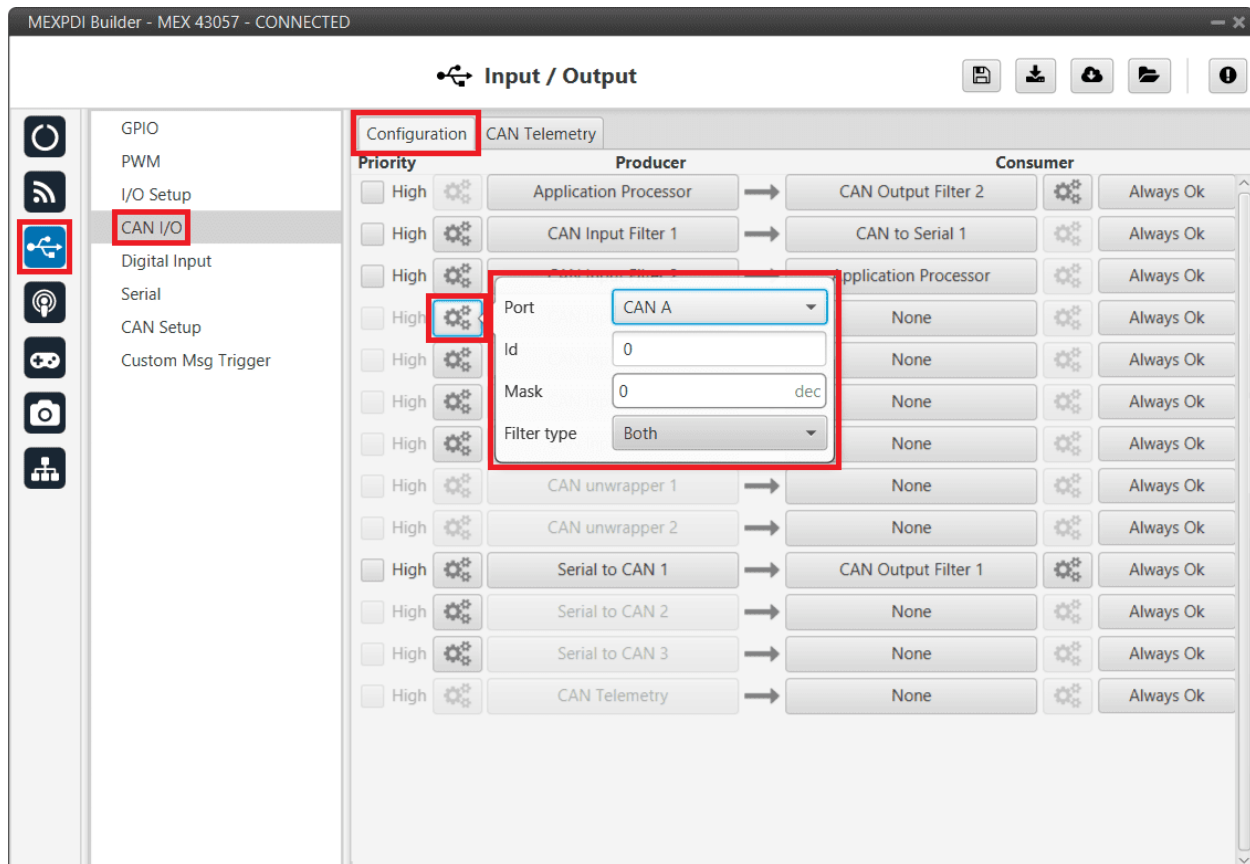


Fig. 17: CAN tunnel - CAN Input Filter configuration

3. Bind **CAN Output Filter 3** to **CAN Input Filter 3** and, configure the CAN Output Filter to **CAN B**.

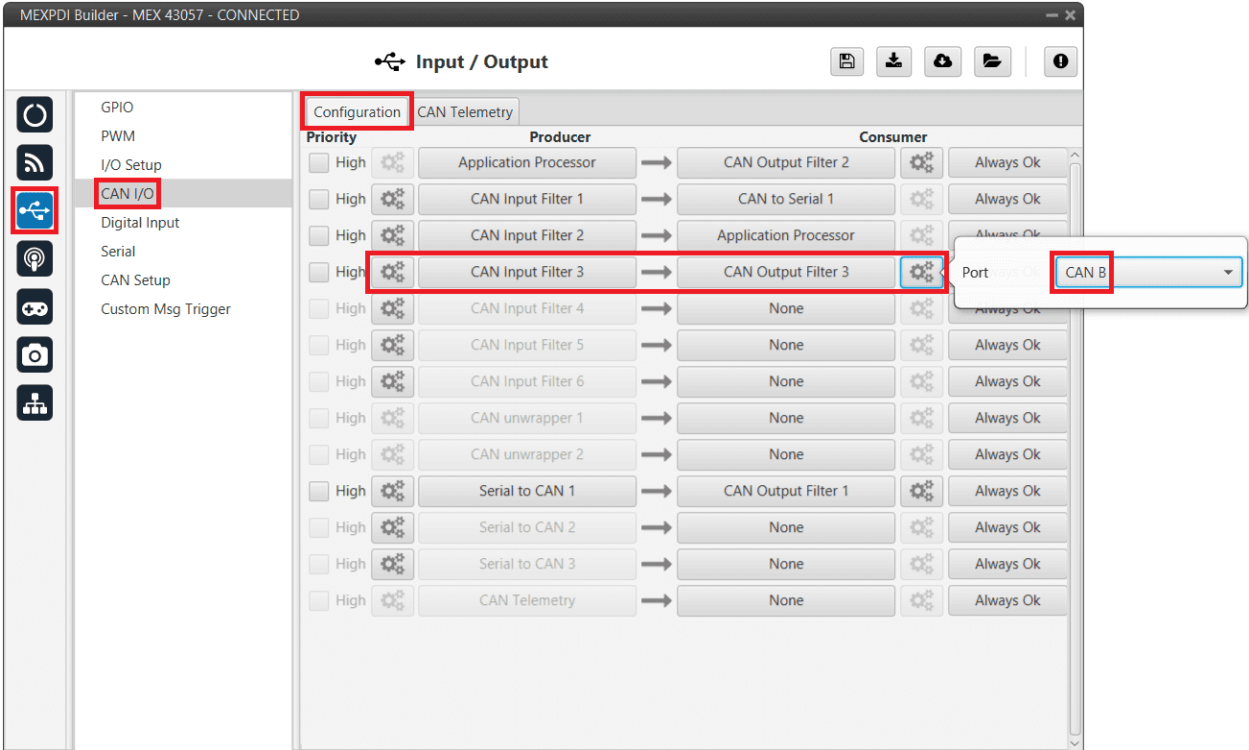


Fig. 18: CAN tunnel - CAN Output Filter configuration

3.3 Commanding/Reading PWMs

The appropriate PWM message format is described in [Command PWMs - CAN Bus protocol](#) section of the **MEX Software Manual**.

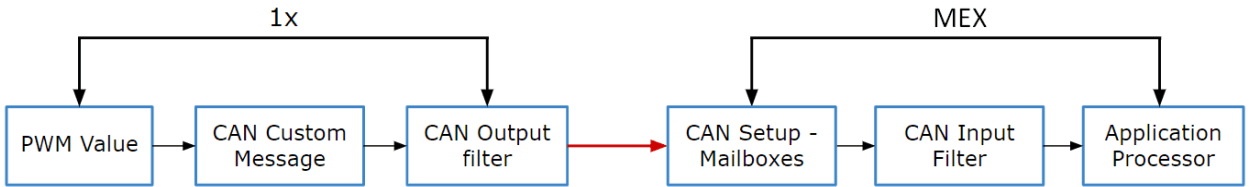


Fig. 19: PWM Command - Communication diagram 1x → MEX

The following steps command PWM from **Autopilot 1x** to **MEX**:

3.3.1 1x PDI Builder side

1. Go to Input/Output menu → CAN Setup panel → **Configuration tab**.

Connect a **CAN custom message** to an **Output filter** to send the message:

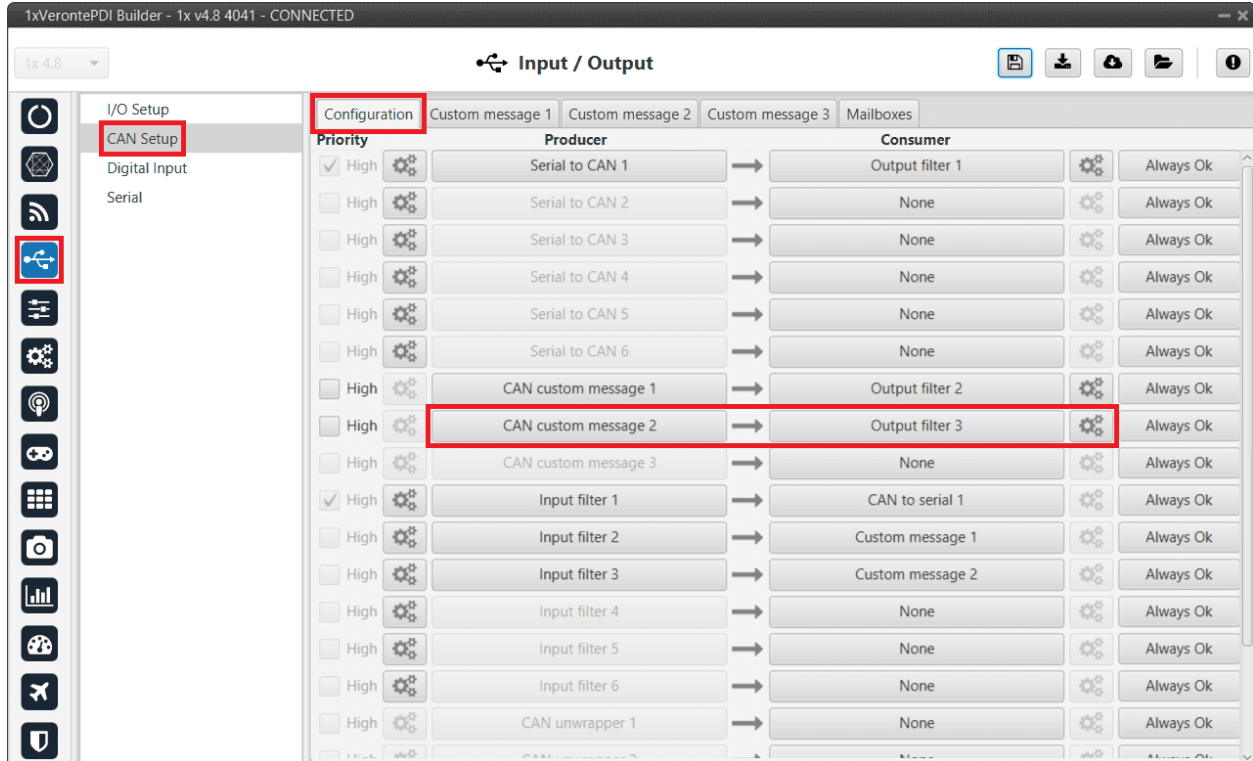


Fig. 20: 1x PDI Builder - CAN Setup configuration

2. Go to Input/Output menu → CAN Setup panel → **Custom Message 2 tab** (because Custom message 2 has been selected as producer).

Build a CAN Custom message using the PWM variable and the appropriate message format. Select the fields to send in the **TX** as it is a Producer. CAN ID is arbitrary, for this example ID 100 will be used:

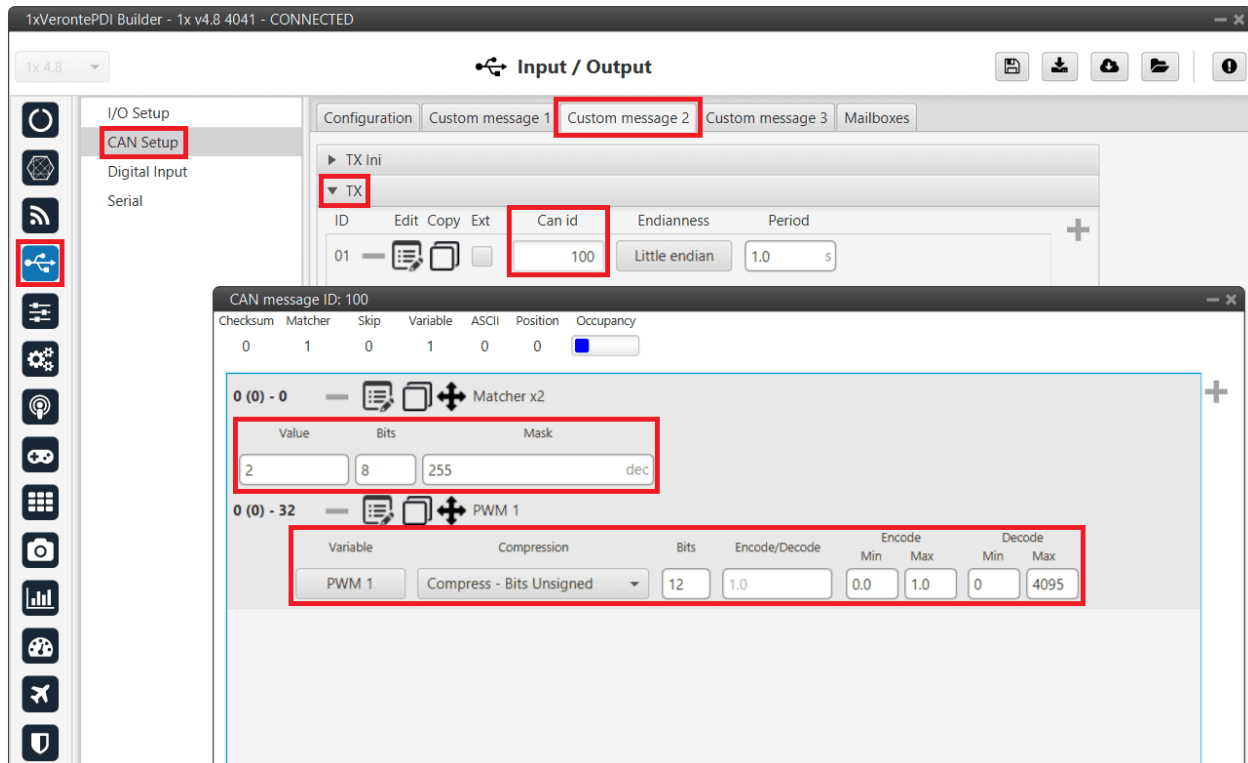


Fig. 21: 1x PDI Builder - CAN Custom message configuration

Message format:

- Matcher (2) [8 bits]
 - PWM 0 [12 bits]
 - PWM 1 [12 bits]
 - PWM 2 [12 bits]
 - PWM 3 [12 bits]
- Matcher (3) [8 bits]
 - PWM 4 [12 bits]
 - PWM 5 [12 bits]
 - PWM 6 [12 bits]
 - PWM 7 [12 bits]
- Each PWM variable has to be set using the following format:
 - Variable: PWM X
 - **Compression:** Compress - Bits Unsigned
 - **Bits:** 12
 - **Encode:** Min=0.0 / Max=1.0
 - **Decode:** Min=0 / Max=4095

3.3.2 MEX PDI Builder side

- Go to Input/Output menu → **CAN Setup panel**.

Create the mailbox to receive the new message (ID 100):

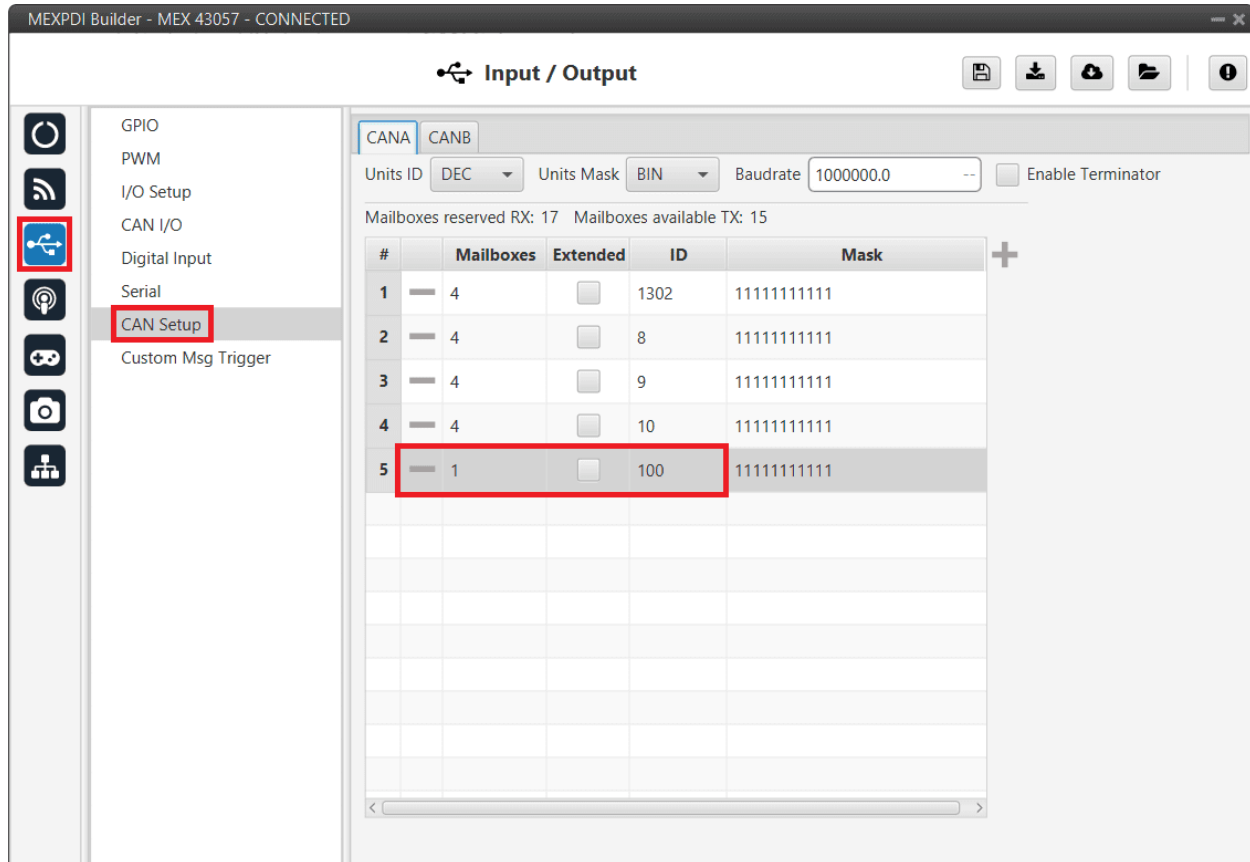


Fig. 22: MEX PDI Builder - CAN Setup configuration

- Go to Input/Output menu → CAN I/O panel → **Configuration tab**.

Connect a **CAN Input Filter** with the **right CAN ID** to the **Application Processor consumer**:

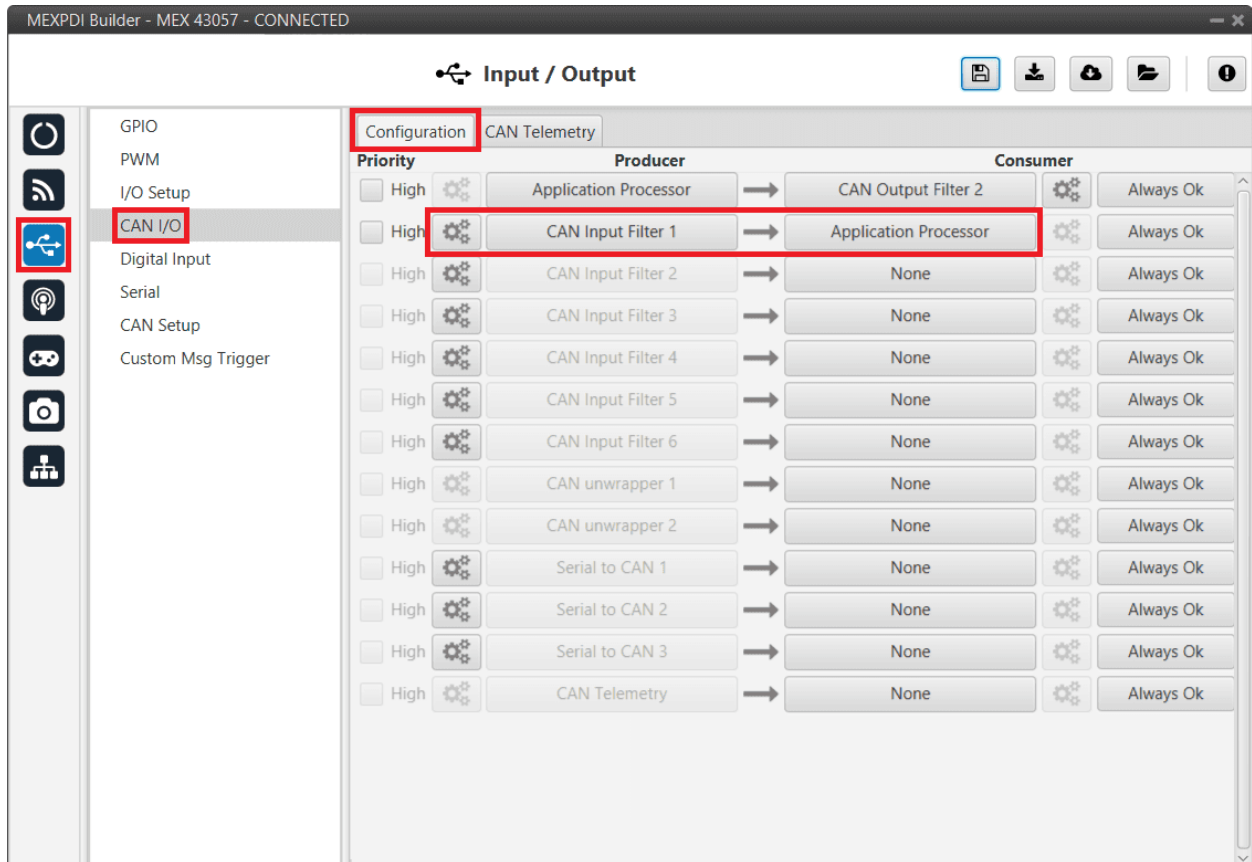


Fig. 23: MEX PDI Builder - CAN I/O configuration

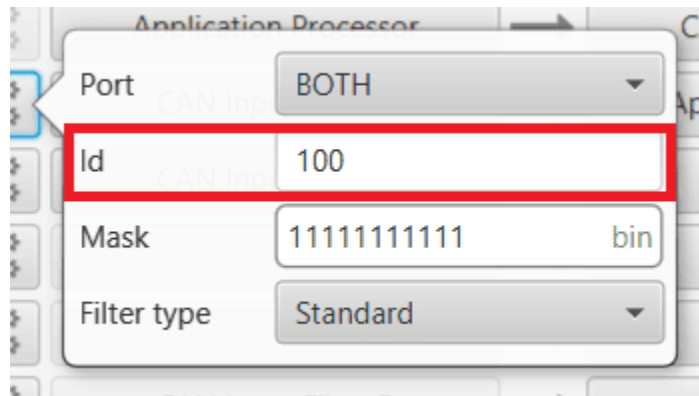


Fig. 24: MEX PDI Builder - CAN Input Filter configuration

- Go to Input/Output menu → PWM panel → **PWM 2 tab** (as PWM 1 has been selected in **1x PDI Builder**).

Note: Check the order of the PWM signal, the first PWM signal of Veronte Autopilot 1x must match the first PWM signal of MEX. **Numeration may differ** between Veronte applications depending on the used version.

Configure parameters for PWM 2:

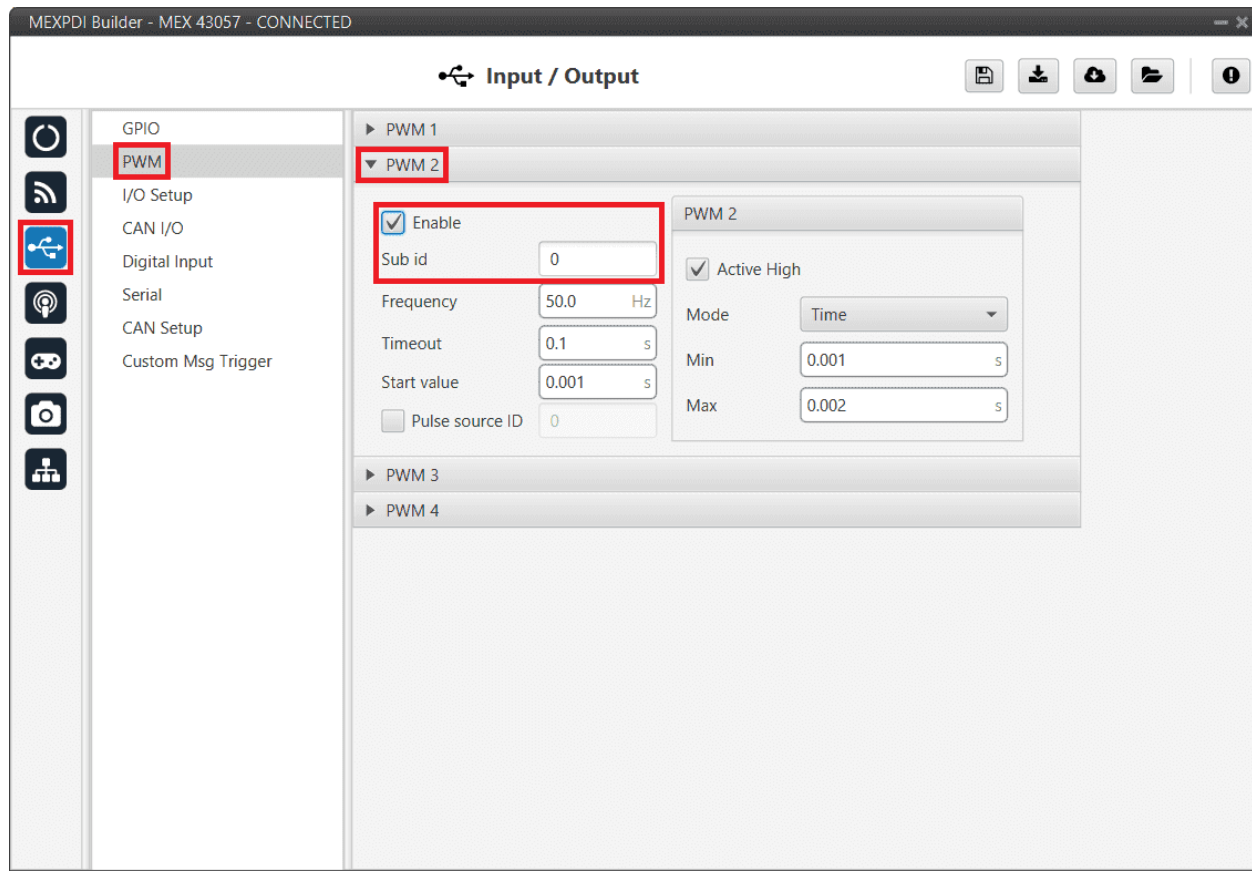


Fig. 25: MEX PDI Builder - PWM configuration

6. Go to Input/Output menu → **GPIO panel**.

Check that this PWM pin (**PWM 2** in this case) has correctly switched from GPIO to PWM.

It should look like this:

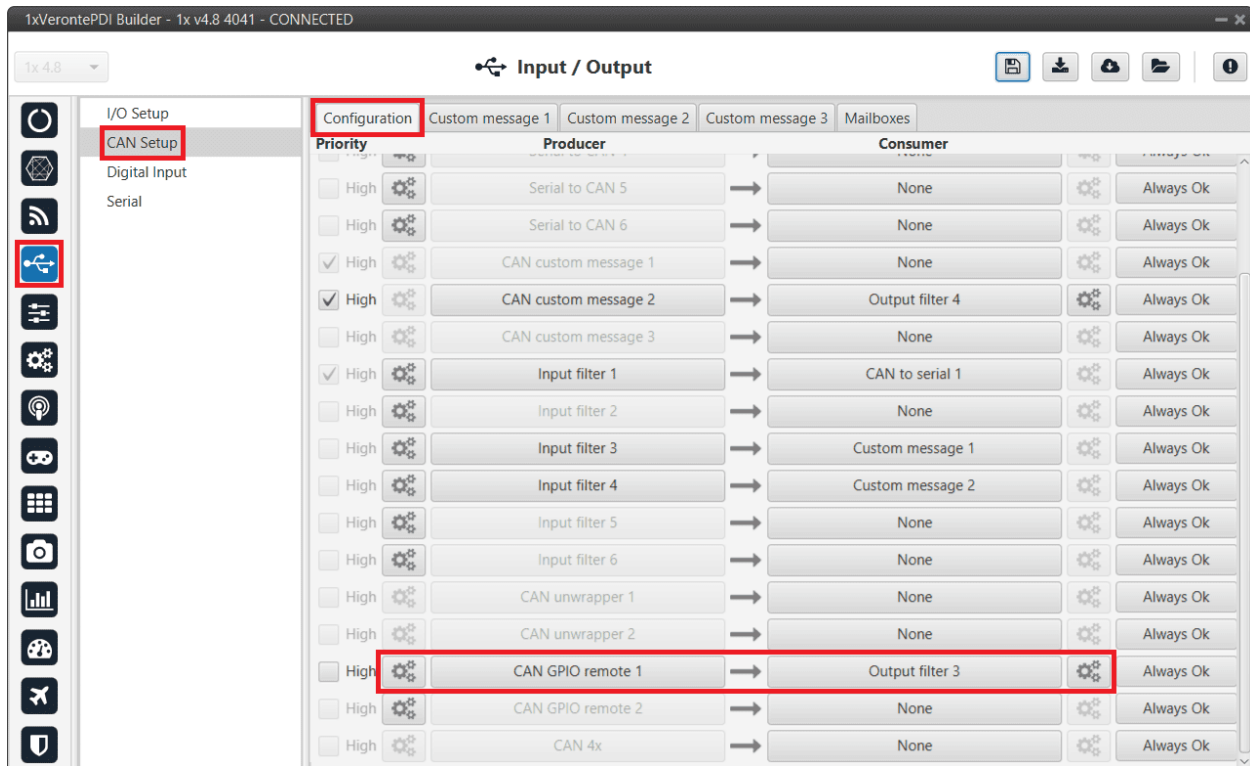


Fig. 27: 1x PDI Builder - CAN Setup configuration

CAN GPIO remote must be configured. For more information about its configuration, read [CAN Setup - Input/Output](#) section of **1x PDI Builder** user manual.

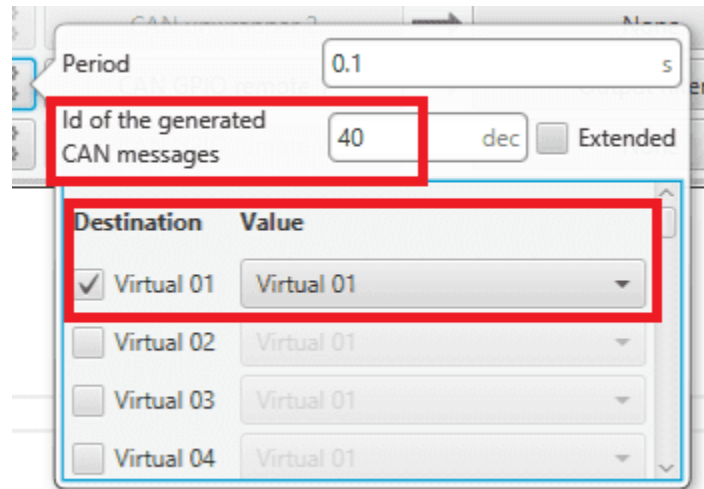


Fig. 28: 1x PDI Builder - CAN GPIO remote configuration

- Go to **Automations** menu.

GPIO must be activated using an 'Output' action:

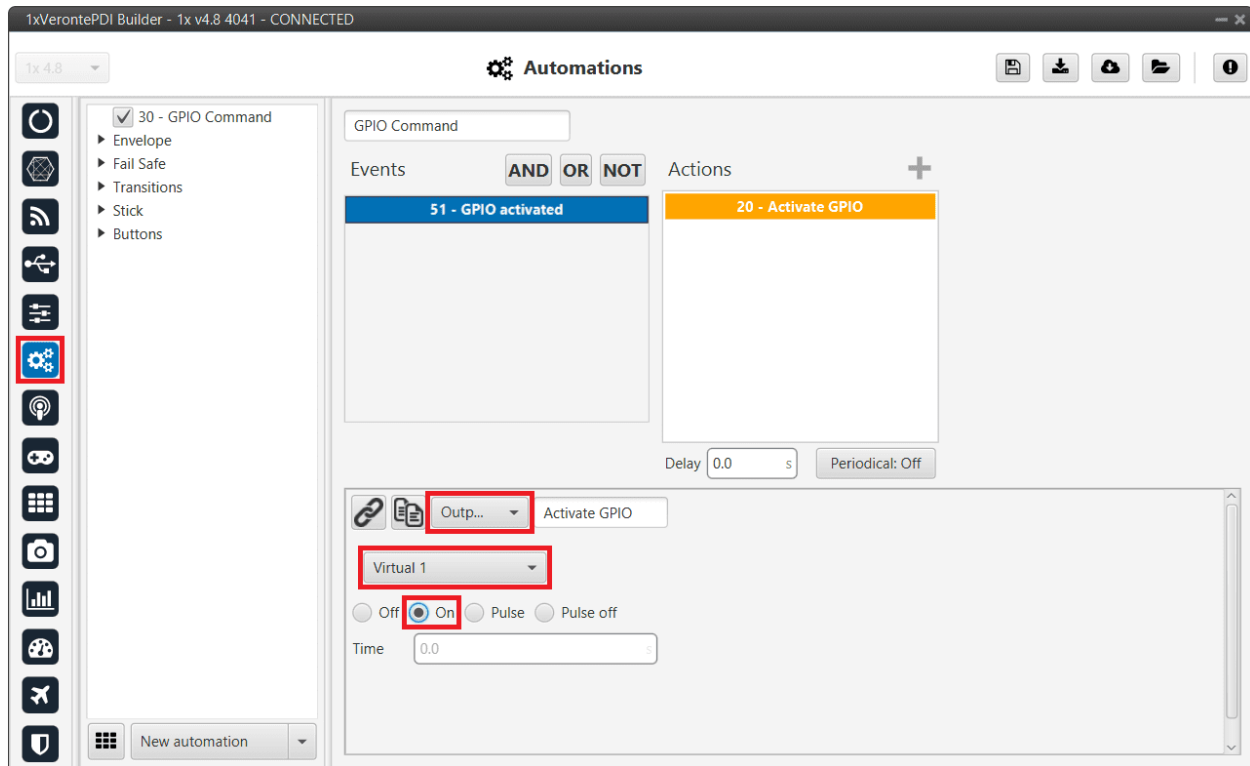


Fig. 29: 1x PDI Builder - Automation configuration

3.4.2 MEX PDI Builder side

- Go to Input/Output menu → CAN I/O panel → **Configuration tab**.

Finally, connect a **CAN Input Filter** to the **CAN GPIO consumer**:

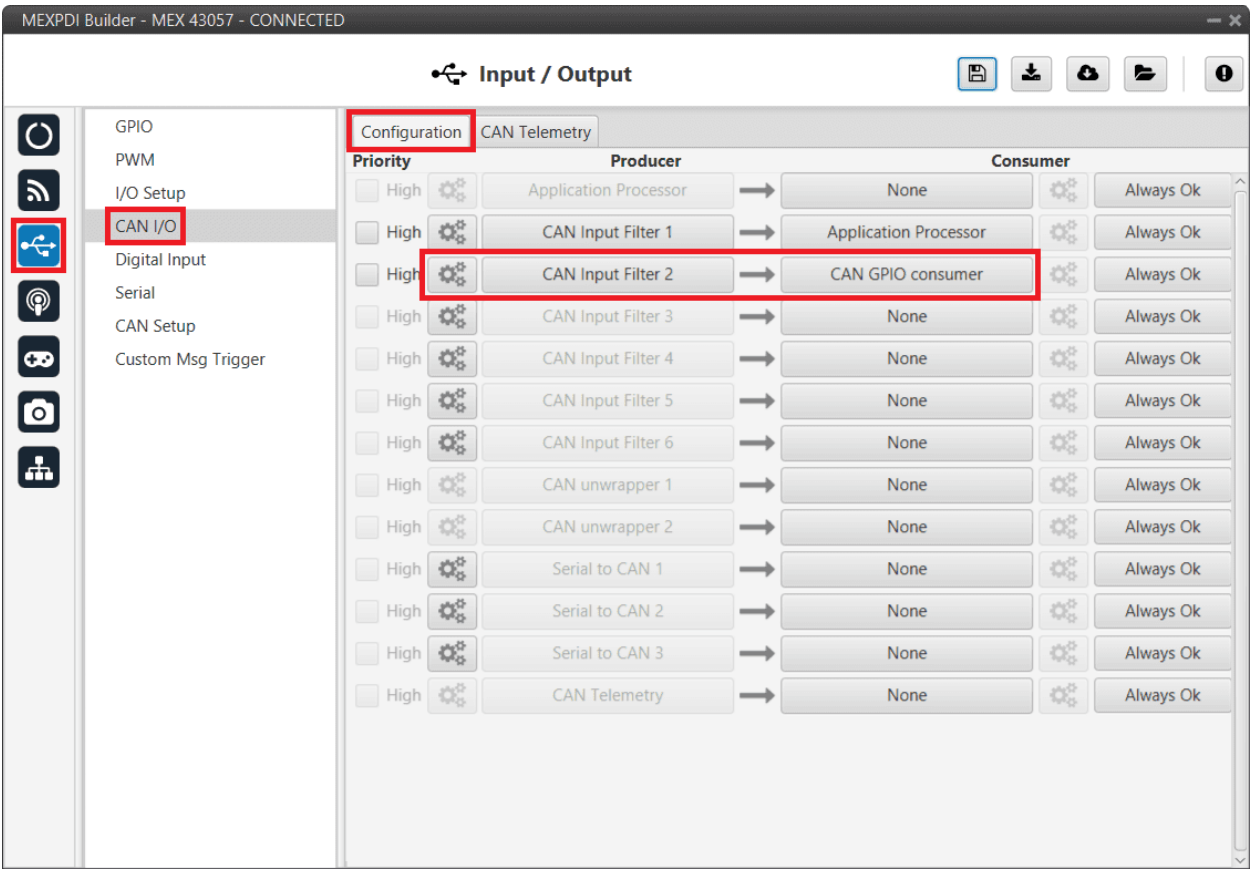


Fig. 30: MEX PDI Builder - CAN I/O configuration

The Id must match the one configured in 1x PDI Builder as Output filter:

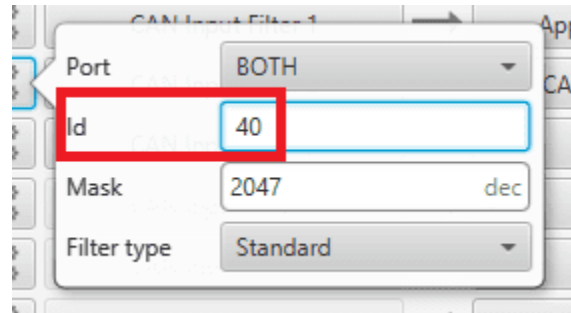


Fig. 31: MEX PDI Builder - CAN Input Filter configuration

3.5 MEX as external magnetometer Honeywell HMR2300 for Autopilot 1x

MEX has to be configured with **MEX PDI Builder** to send the magnetometer measurements by messages, in the same way as **magnetometer Honeywell HMR2300** does. **Autopilot 1x** also requires a configuration, which is made with **1x PDI Builder**.

This configuration can be done both via **Serial** or **CAN** interfaces.

3.5.1 Serial

3.5.1.1 MEX PDI Builder side

1. Go to Input/Output menu → **I/O Setup panel**.

Connect the **Custom message producer 1** or **2** to the **RS232-A**, **RS232-B** or **RS485-C** port.

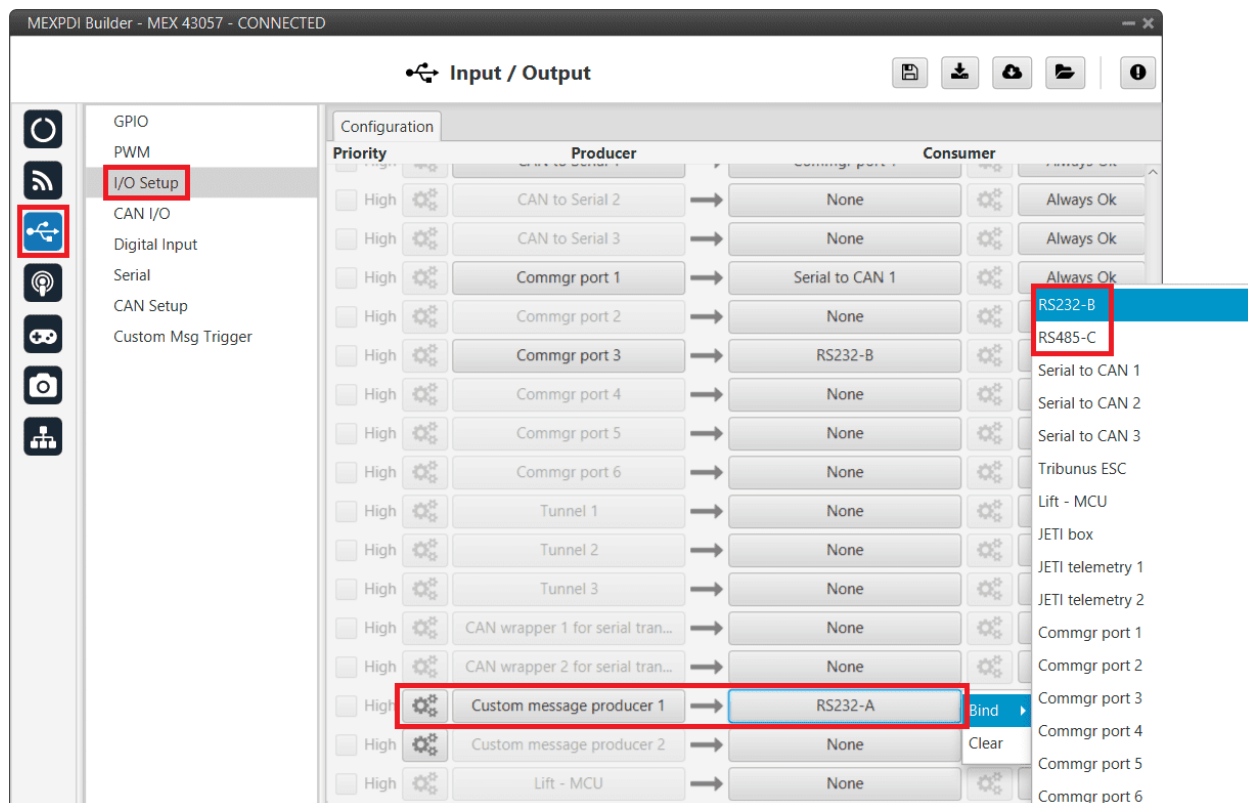




Fig. 32: MEX PDI Builder - I/O Setup configuration

2. Click on the  button of the chosen **Custom message producer** and add a new message (clicking on ) , then configure it as **Big endian** and set a **Period of 0.02 s**.

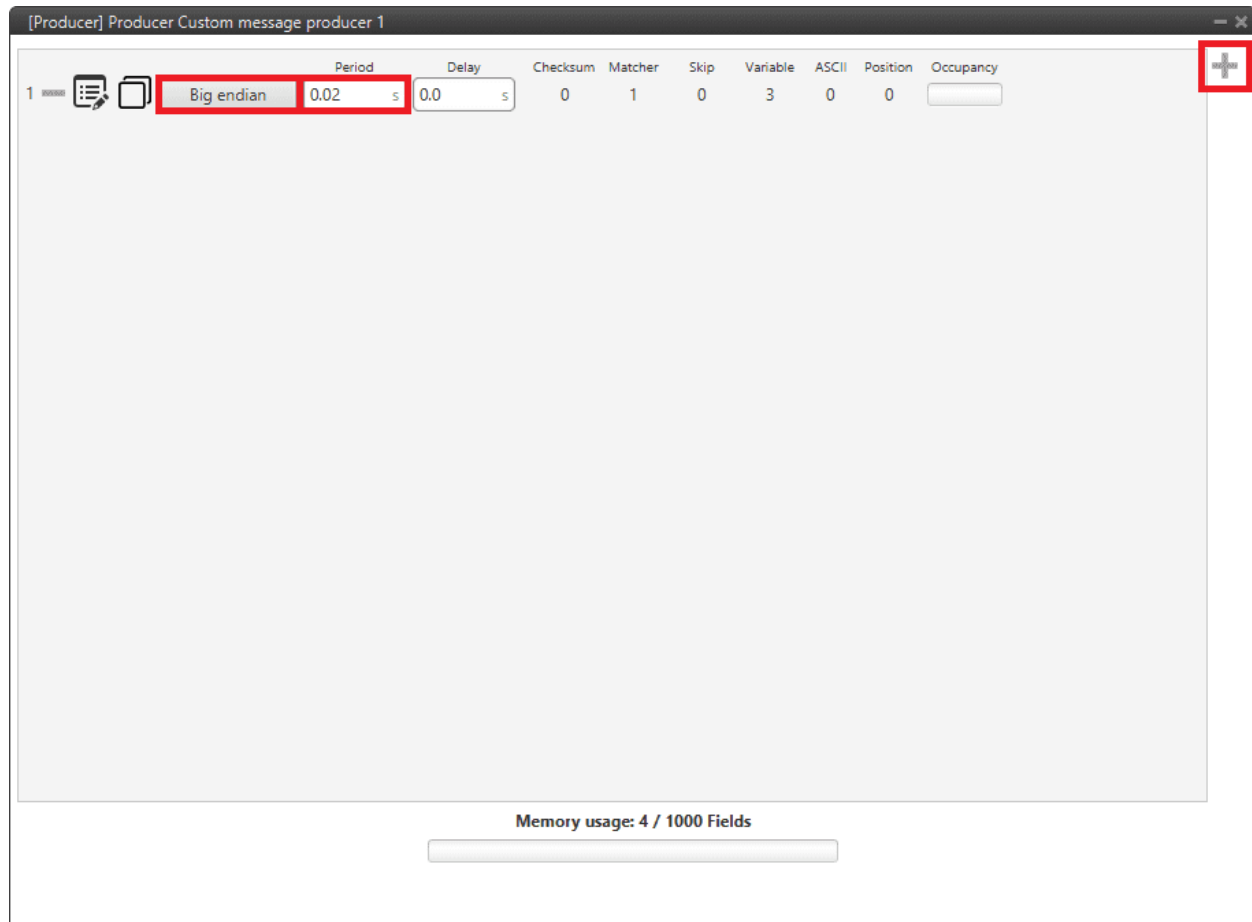



Fig. 33: MEX PDI Builder - Custom message configuration

3. Click on  to add the 3 following **Real variables**: **313**, **314** and **315**. Then configure them according to the following table:

Parameter	Configuration
Compression	Compress - Bits Signed
Bits	16
Encode	Min: -2.1845334E-4 / Max: 2.1844667E-4
Decode	Min: -32768 / Max: 32767

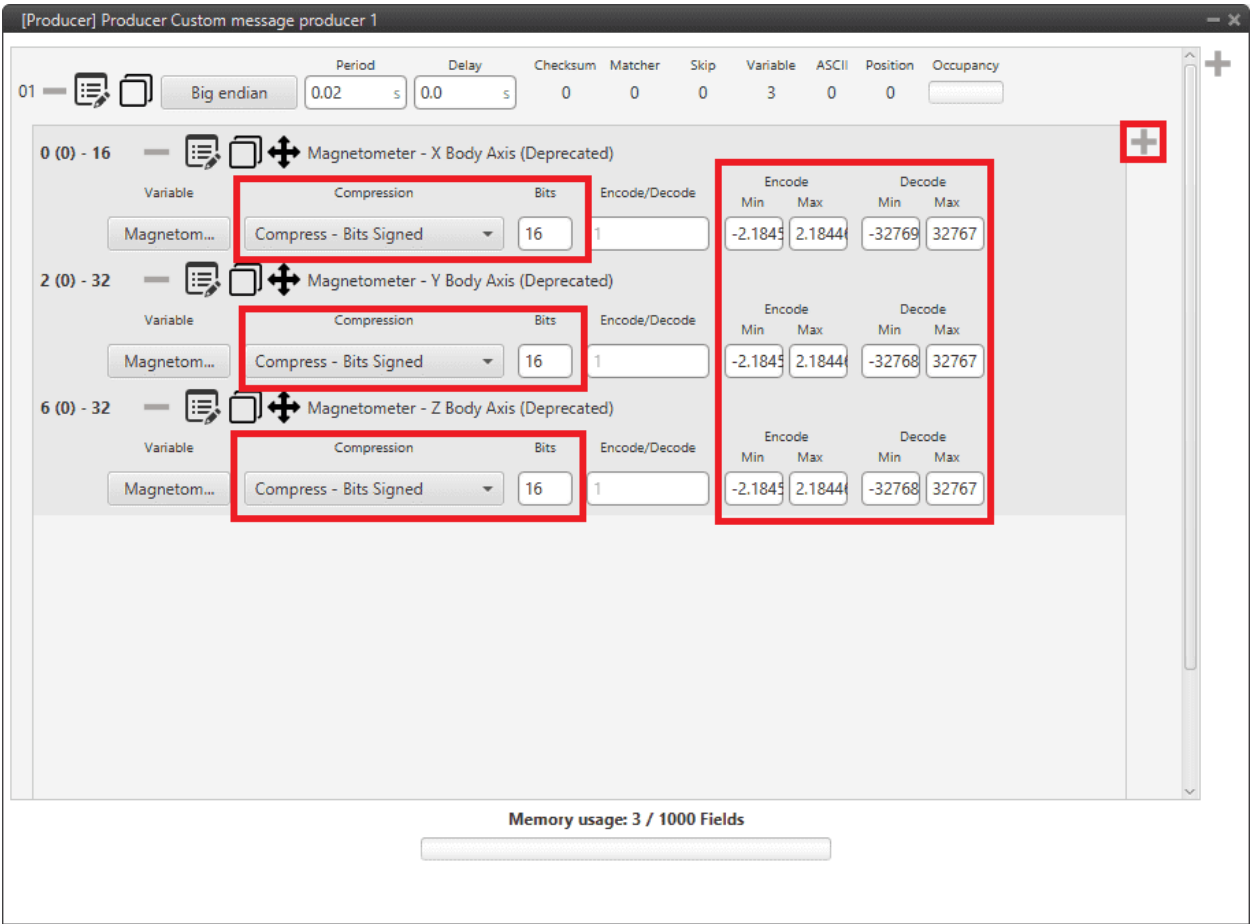


Fig. 34: MEX PDI Builder - Custom message Variables configuration

4. Click on **+** → **Matcher**, to add a matcher to the message and configure it as follows:

Parameter	Configuration
Value	13
Bits	8

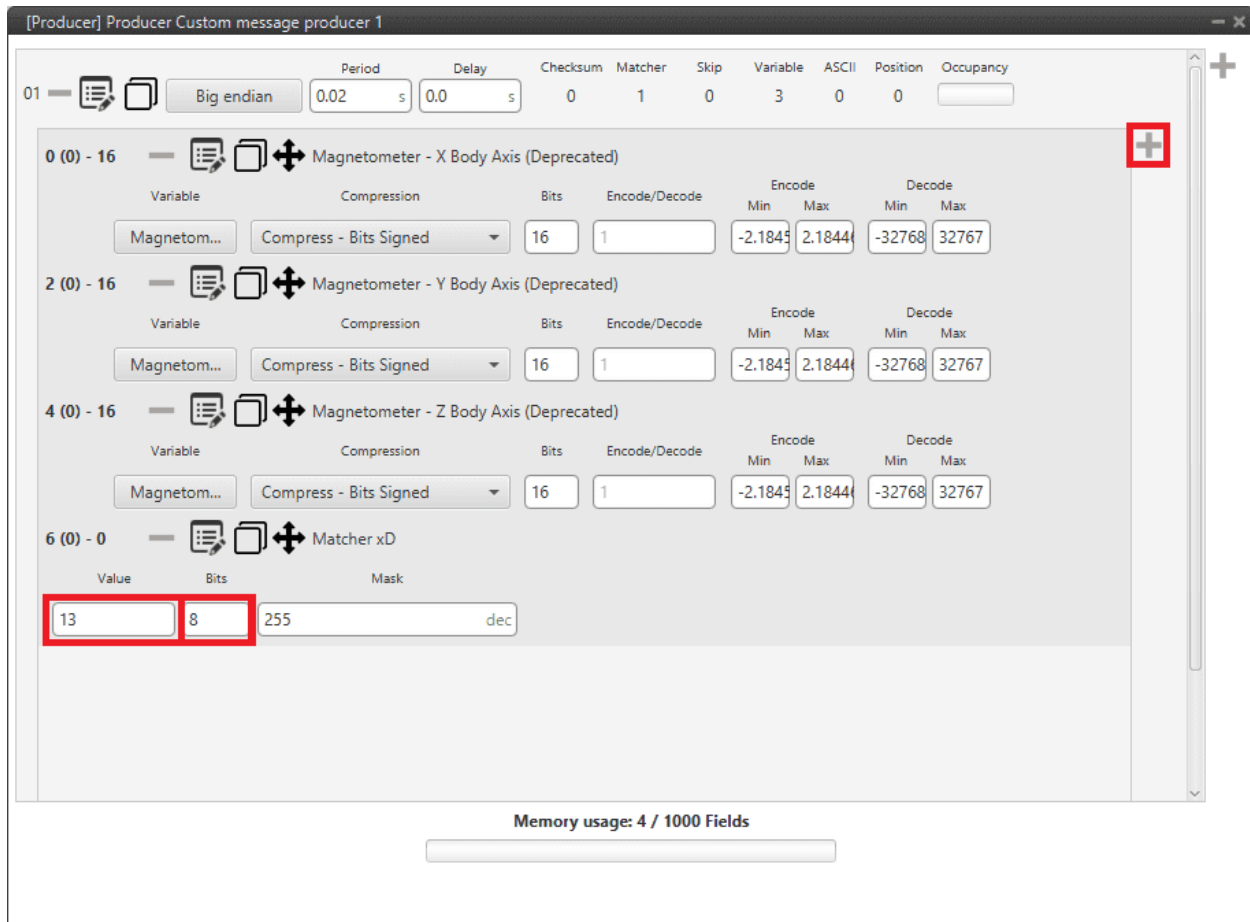



Fig. 35: MEX PDI Builder - Custom message Matcher configuration

Matcher explanation

The matcher is a binary code employed to discard messages with errors.

The length and the number represented can be edited clicking on  of the matcher. If the receiver does not receive the exact same matcher sequence, the entire message will be discarded, since it will be considered corrupted.

Warning: The order of variables and matcher must be the same.

For more information about custom messages and matchers, read [Custom Messages types - Input/Output](#) section of the **1x PDI Builder** user manual.

- Go to Input/Output menu → **Serial panel**.

Configure the **SCIA, B or C** tab accordingly to the consumer selected in step 1 (**RS232-A, RS232-B** or **RS485-C**). The configuration is the following:

Note: In this example, **RS232-A** was selected, so **SCI A** is configured.

Parameter	Configuration
Baudrate	115200
Length	8
Stop	1
Parity	Disabled
Use address mode	Disabled

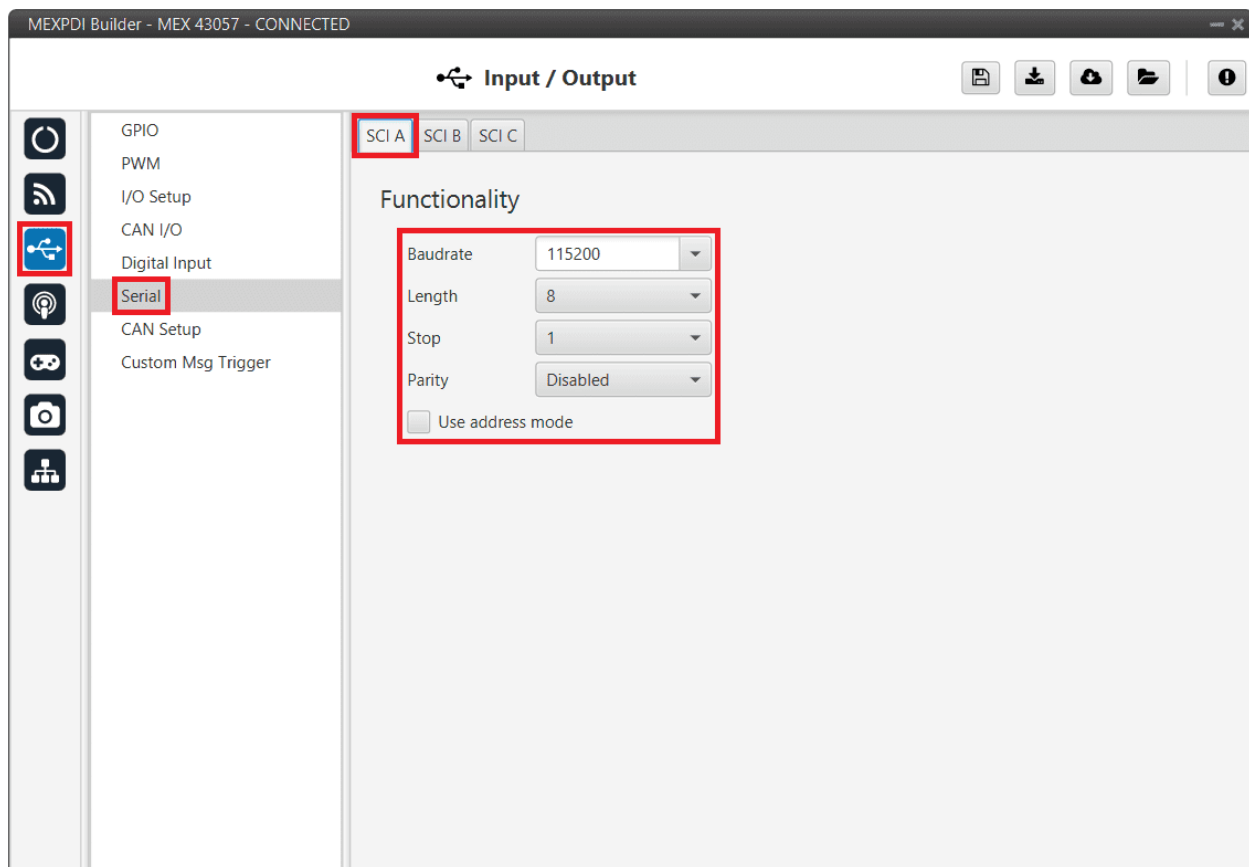


Fig. 36: MEX PDI Builder - Serial configuration

6. Once finished the configuration, click on  to write the configuration in **MEX**.

3.5.1.2 1x PDI Builder side

The configuration for the **Autopilot 1x** is explained in MEX as [Magnetometer Honeywell HMR2300 - Integration examples](#) section of the **1x PDI Builder** user manual.

3.5.2 CAN

3.5.2.1 MEX PDI Builder side

1. Go to Input/Output menu → **I/O Setup** panel.

Connect the **Custom message producer 1** or **2** to the **Serial to CAN 1**, **Serial to CAN 2** or **Serial to CAN 3** port.

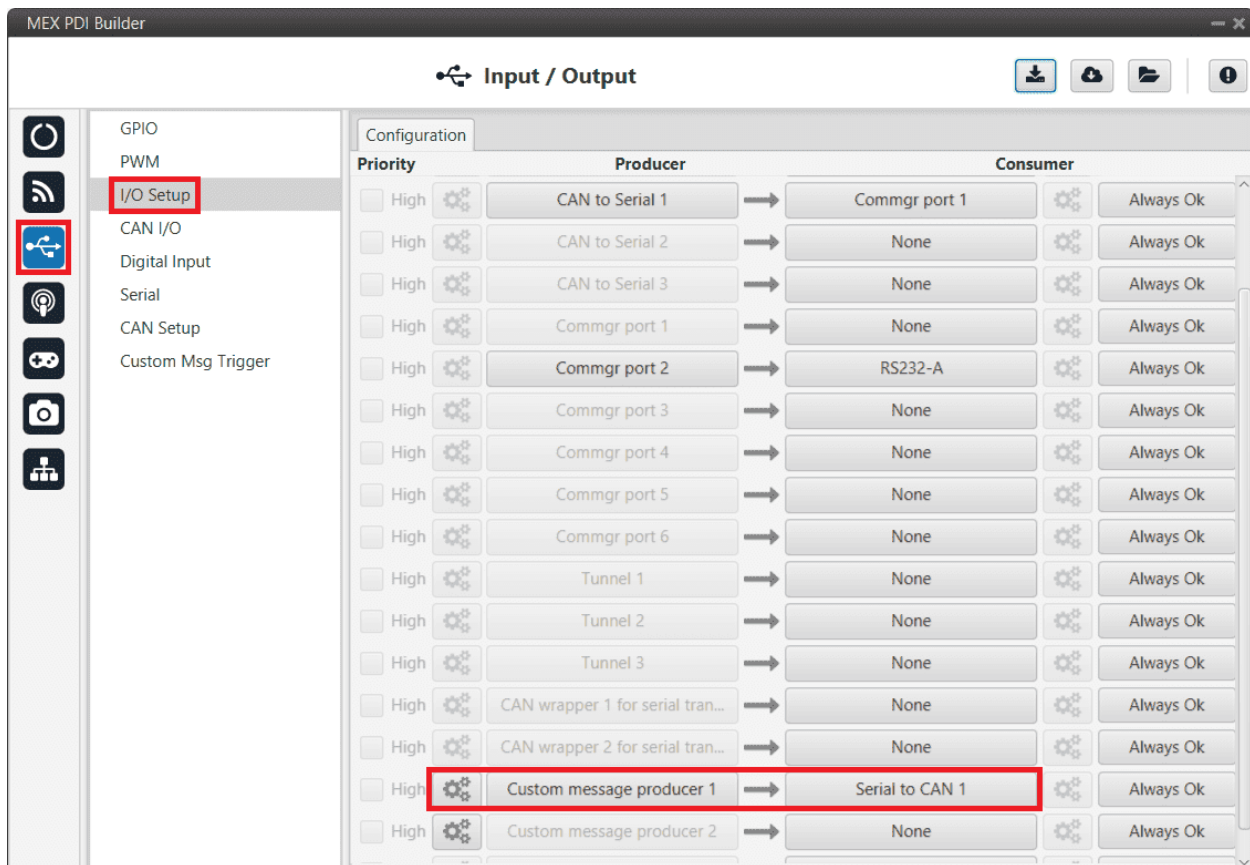




Fig. 37: MEX PDI Builder - I/O Setup configuration

2. Click on the  button of the chosen **Custom message producer** and add a new message (clicking on ) , then configure it as **Big endian** and set a **Period of 0.02 s**.

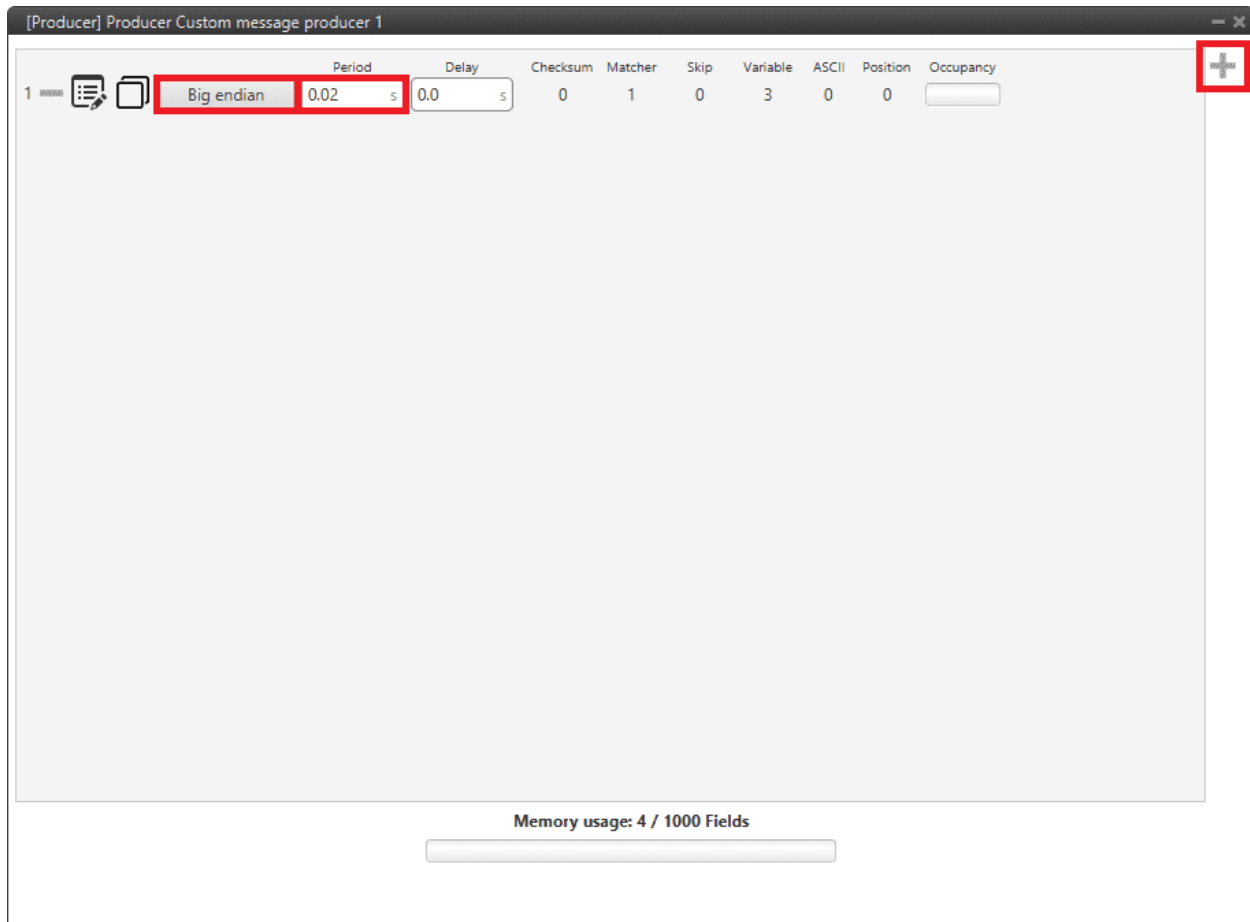



Fig. 38: MEX PDI Builder - Custom message configuration

3. Click on  to add the 3 following **Real variables**: **313**, **314** and **315**. Then configure them according to the following table:

Parameter	Configuration
Compression	Compress - Bits Signed
Bits	16
Encode	Min: -2.1845334E-4 / Max: 2.1844667E-4
Decode	Min: -32768 / Max: 32767

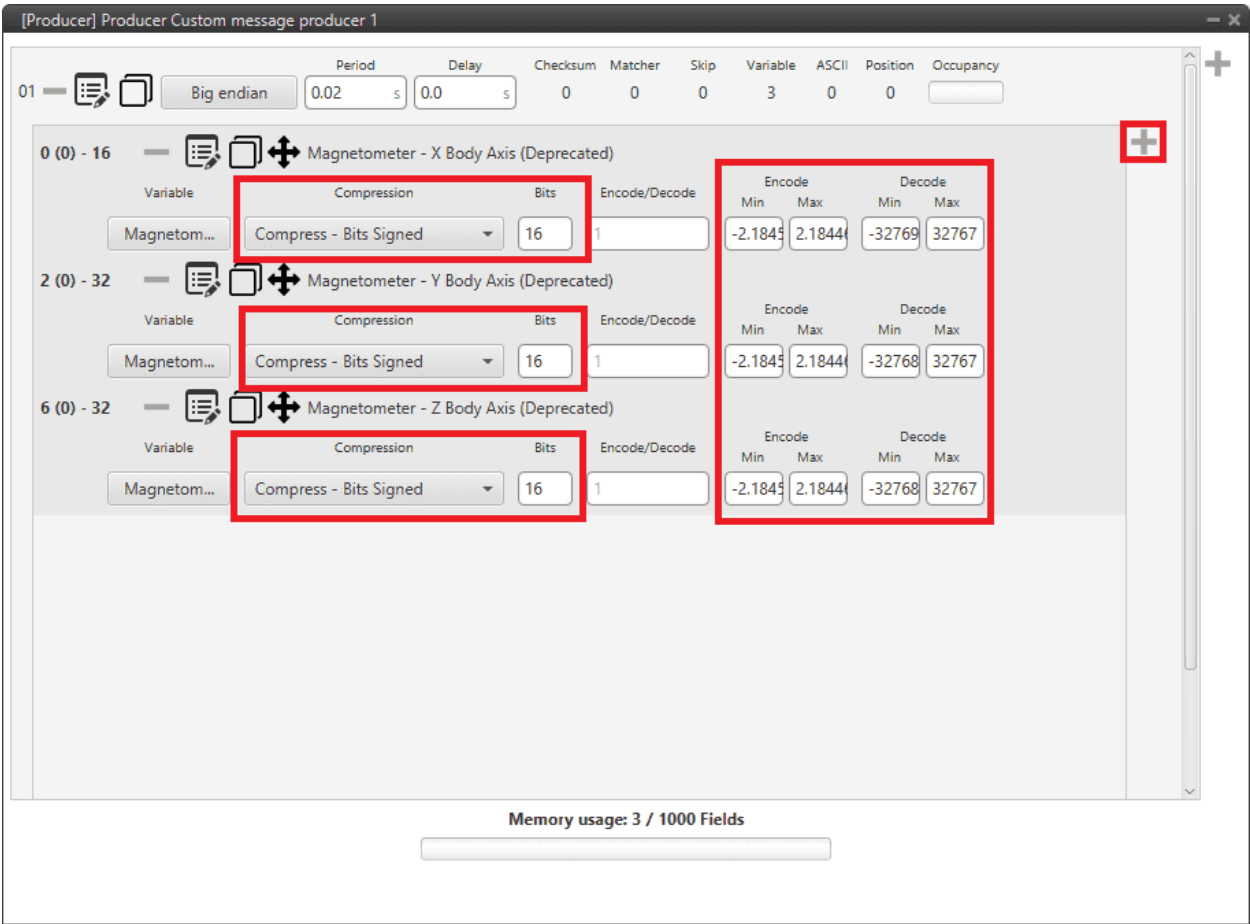


Fig. 39: MEX PDI Builder - Custom message Variables configuration

4. Click on **+** → **Matcher**, to add a matcher to the message and configure it as follows:

Parameter	Configuration
Value	13
Bits	8

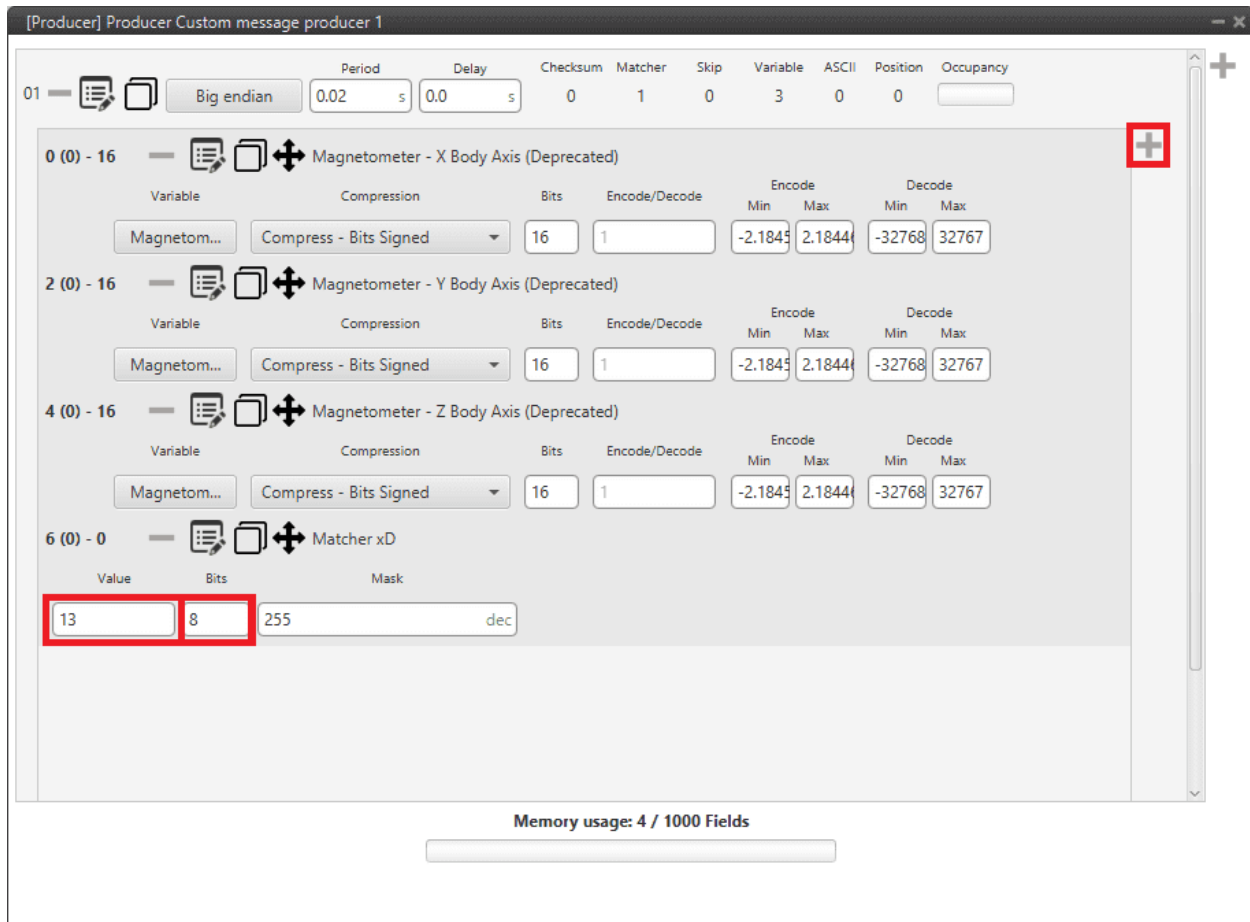


Fig. 40: MEX PDI Builder - Custom message Matcher configuration

Warning: The order of variables and matcher must be the same as shown above.

5. Go to Input/Output menu → CAN I/O panel → **Configuration tab**.

Connect the **Serial to CAN 1, 2 or 3** to a **CAN Output Filter**.

Note: The **Serial to CAN** index must match the one previously selected in the **I/O Setup panel** (step 1).

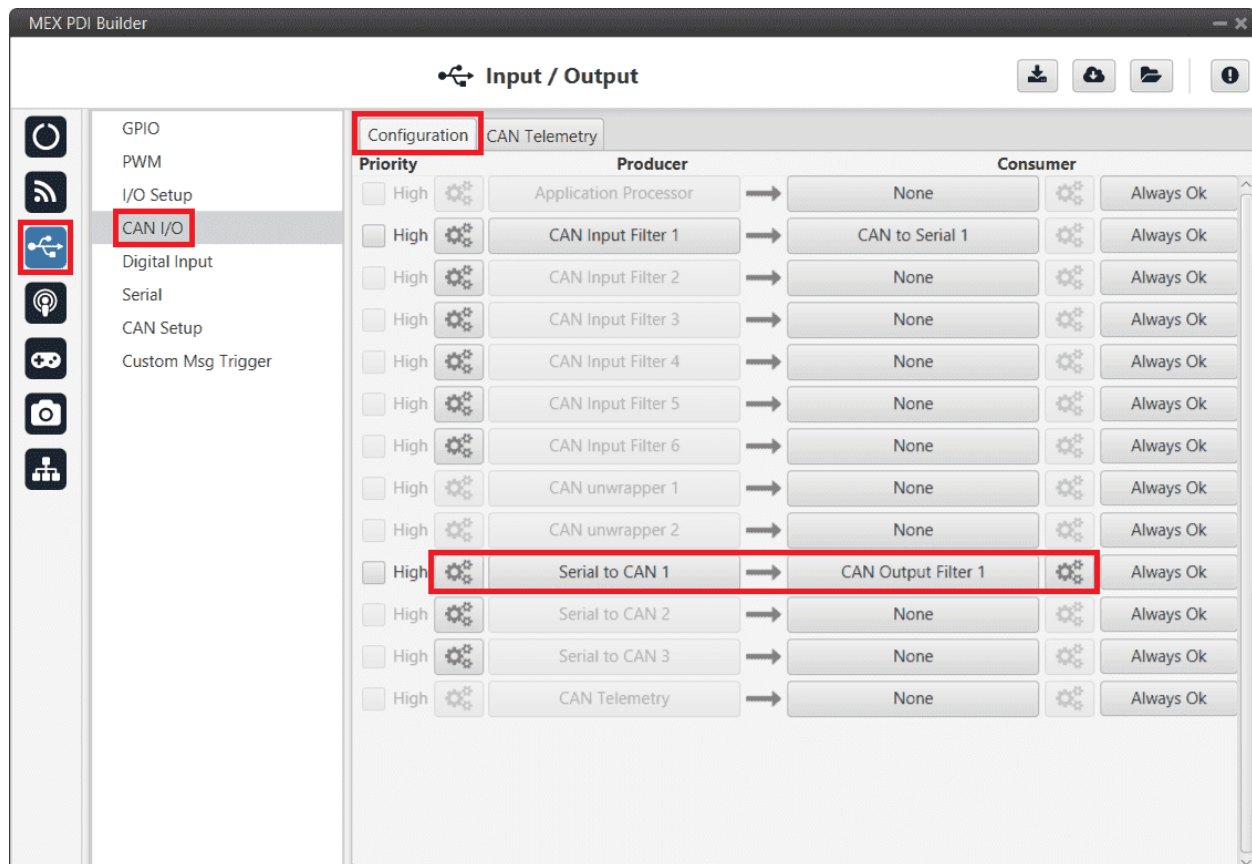


Fig. 41: MEX PDI Builder - CAN I/O configuration

6. Select the **CAN port** by clicking on the  button of the chosen **CAN Output Filter**.

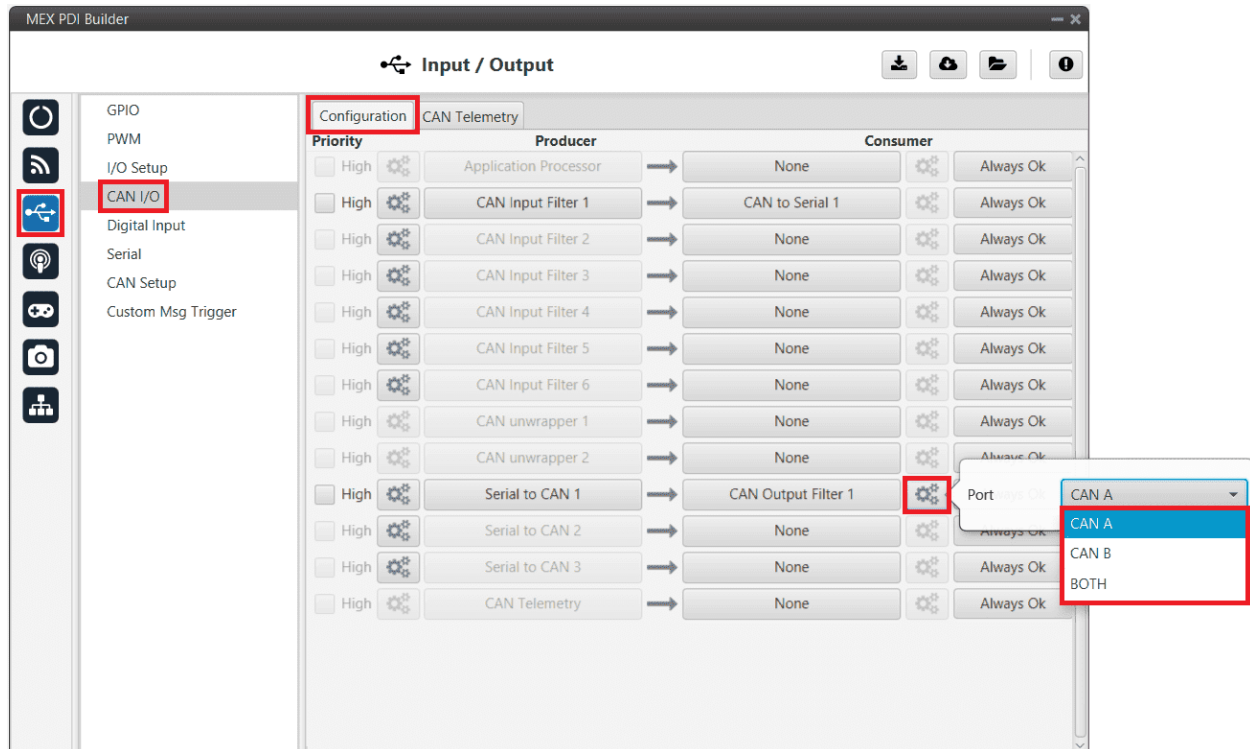


Fig. 42: MEX PDI Builder - CAN Output Filter configuration

- Assign a CAN ID to the **Serial to CAN 1**.

Note: This ID must match the one configured for reception in **Autopilot 1x** with the **1x PDI Builder** software.

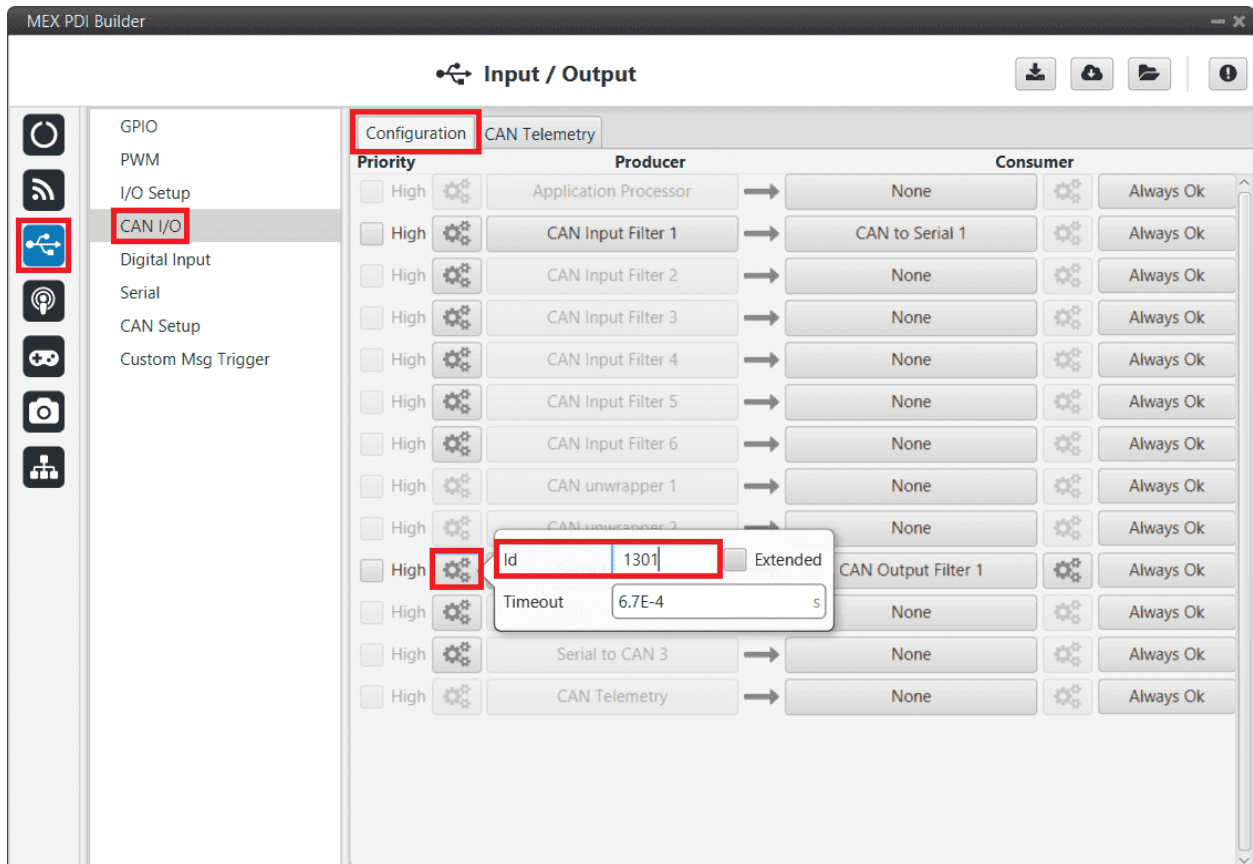


Fig. 43: MEX PDI Builder - Serial to CAN configuration

3.5.2.2 1x PDI Builder side

The configuration for the **Autopilot 1x** is explained in [MEX as Magnetometer Honeywell HMR2300 - Integration examples](#) section of the **1x PDI Builder** user manual.

3.6 Reading/Sending RPMs

This section explains the steps to read RPMs.

3.6.1 MEX PDI Builder side

1. Go to Input/Output menu → **GPIO panel**.

RPM can be read on the available digital inputs GPIO/ECAP 1 and 2. The chosen pin needs to be configured as “**GPIO as input**”. In the example shown here, GPIO/ECAP 1 is chosen.

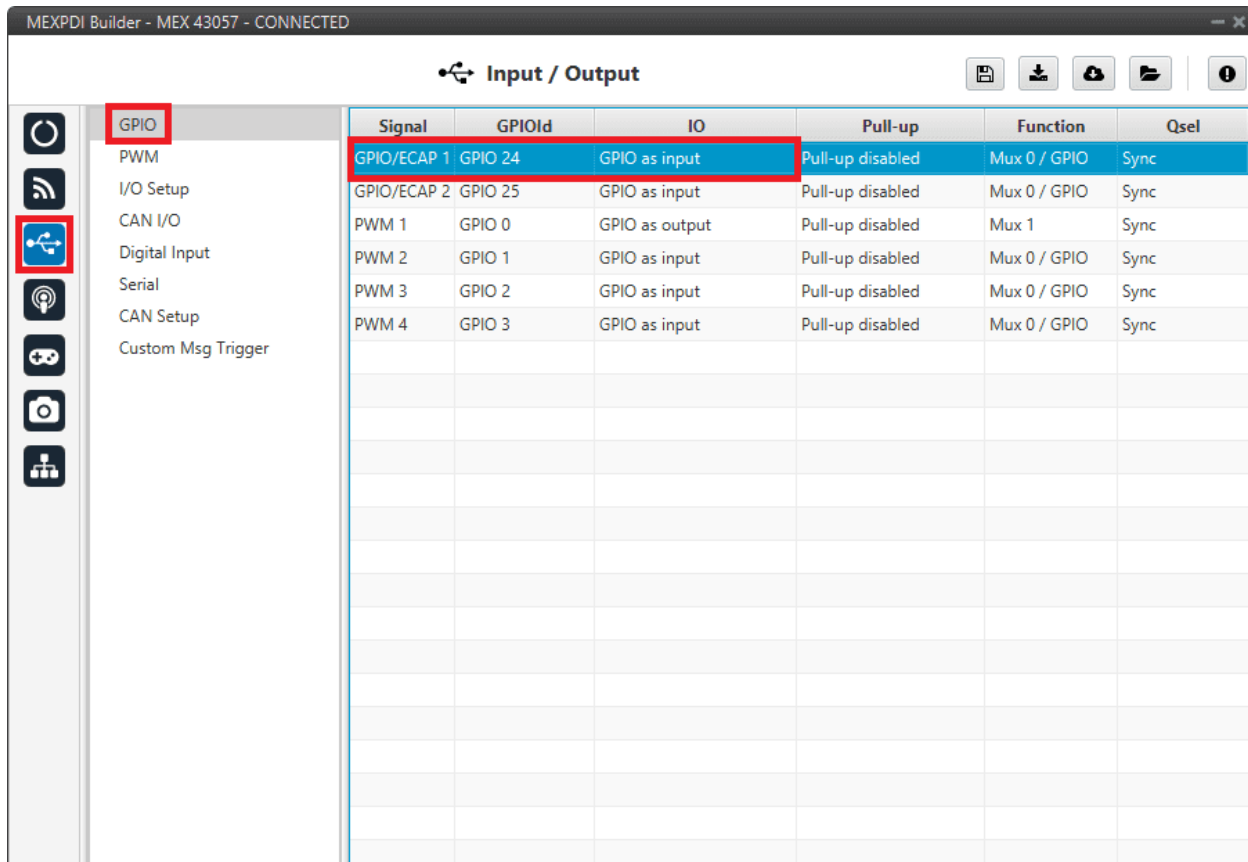


Fig. 44: MEX PDI Builder - GPIO configuration

- Go to Input/Output menu → **Digital Input** panel.

There are 2 possible producers: CAP 1 and 2. One needs to be chosen and linked to one of the RPMs consumers (RPM 1-4). For more information about Digital input configuration, read the [Digital Input - Input/Output](#) section of this manual.

Then, select an **edge detection** option: “First rising edge” or “First falling edge”.

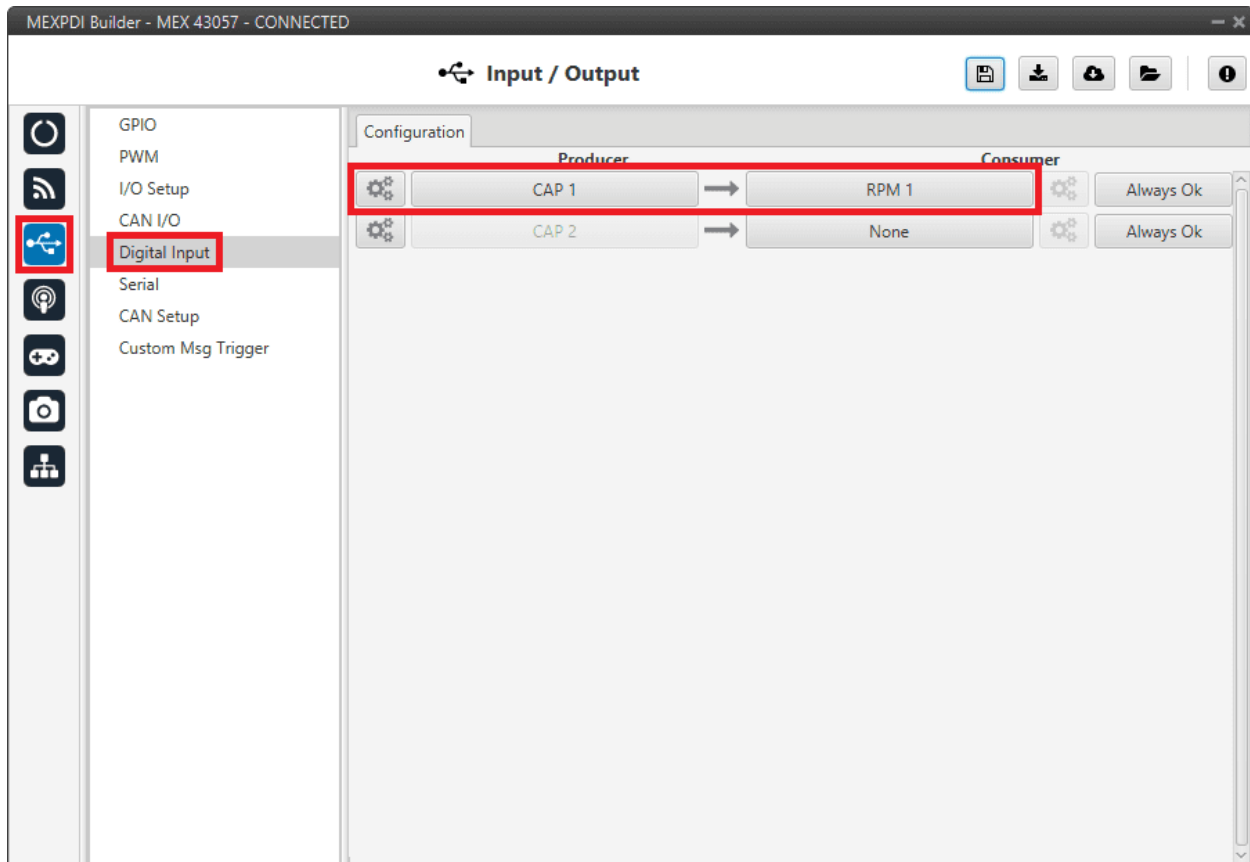


Fig. 45: MEX PDI Builder - Digital Input configuration

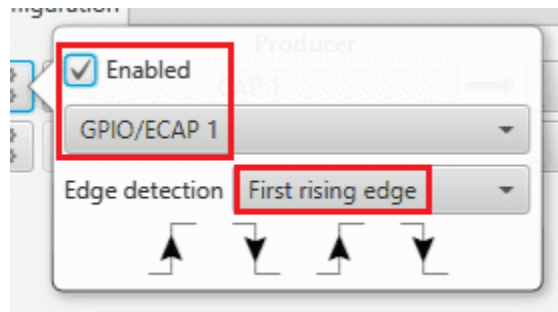


Fig. 46: MEX PDI Builder - Edge detection configuration

- Go to Sensors menu → RPM panel → **RPM 1 tab** (since RPM 1 has been selected in the Digital Input panel).
Here the expected pulse needs to be defined. For more information on RPM configuration, see *RPM - Sensors* section of this manual.

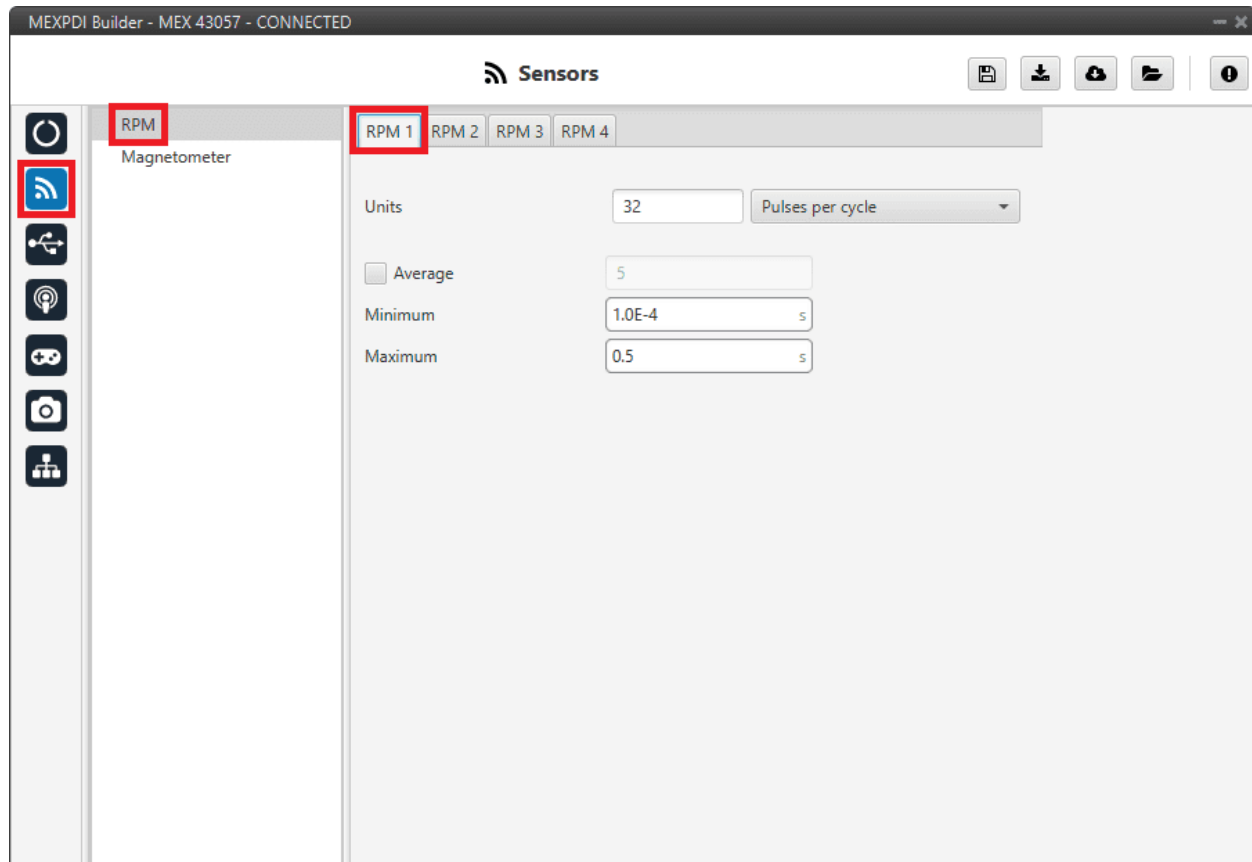


Fig. 47: MEX PDI Builder - RPM configuration

4. Go to Input/Output menu → CAN I/O panel → **Configuration tab**.

Connect **CAN Telemetry** to a **CAN Output Filter** as follows (in this example, the **RPM1** variable is sent over **CAN B** bus of the **MEX**):

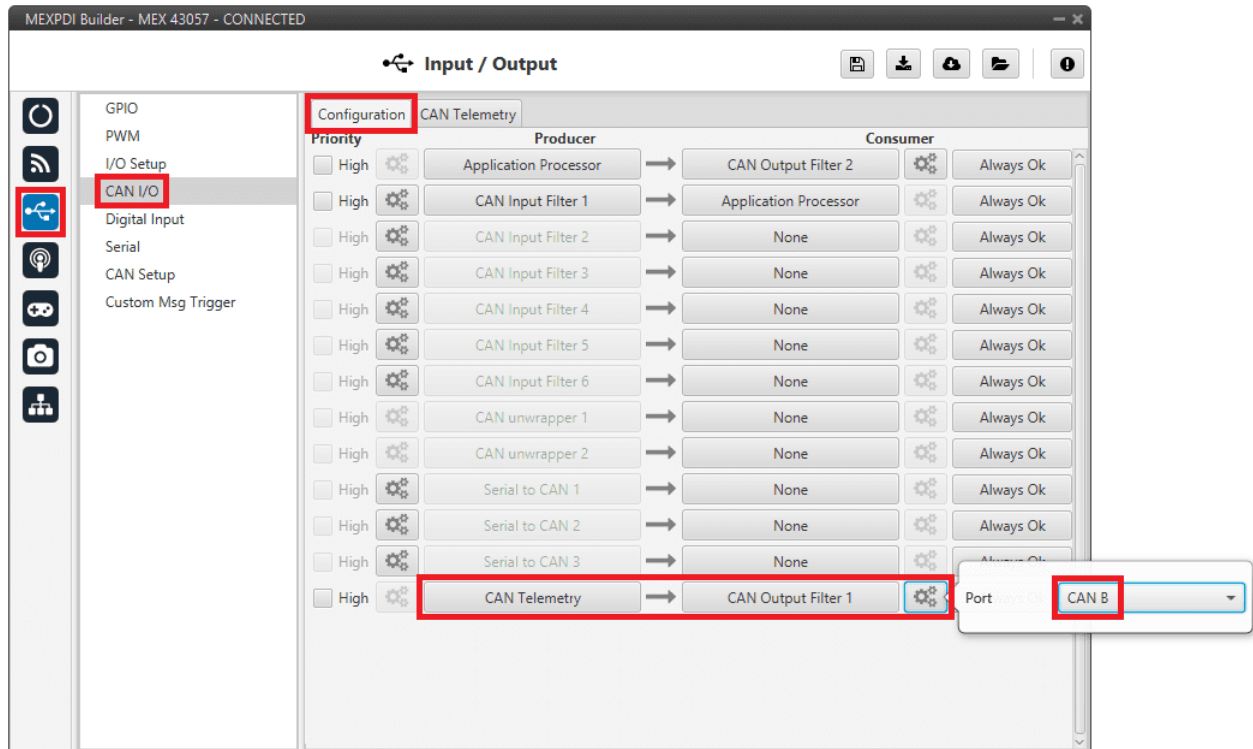


Fig. 48: MEX PDI Builder - CAN I/O configuration

5. Go to Input/Output menu → CAN I/O panel → **CAN Telemetry** tab.

A new telemetry message needs to be created with its correspondent ID, endianness and period.

- **Can ID:** 1200.
- **Endianness:** Little endian.
- **Period:** 0.01 s.

In the telemetry message one of MEX variables needs to be selected. As **RPM1** has been chosen as consumer in the **Digital Input**, the variable required to send is **RPM1**.

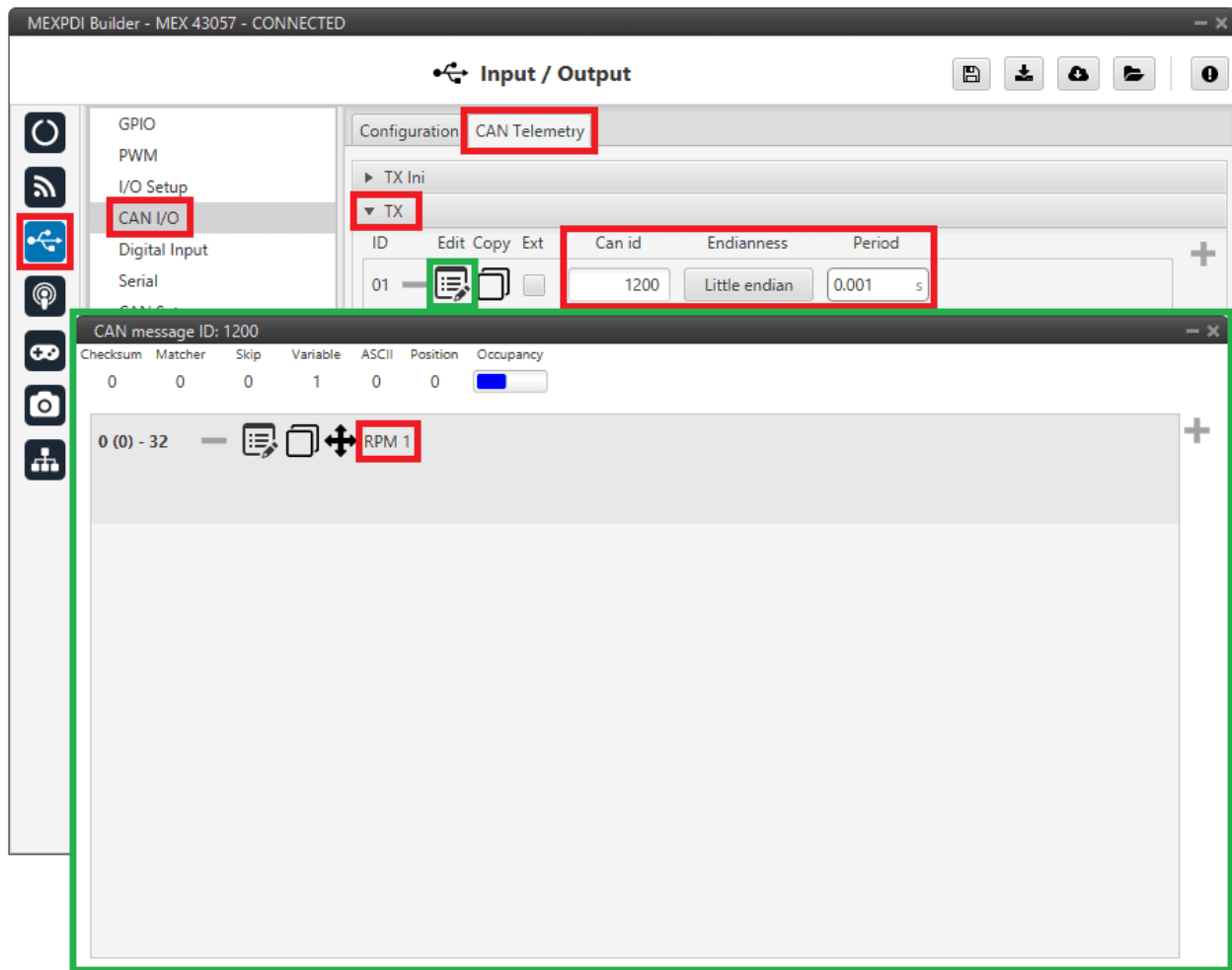


Fig. 49: MEX PDI Builder - CAN Telemetry configuration

More information on the configuration of Telemetry messages can be found in the *CAN Telemetry - Input/Output* section of this manual.

3.6.2 1x PDI Builder side

6. Go to UI menu → Variables panel → **Real Vars tab**.

Rename a Real User Variable (32 bits) that will be used to store the value received from **MEX**:

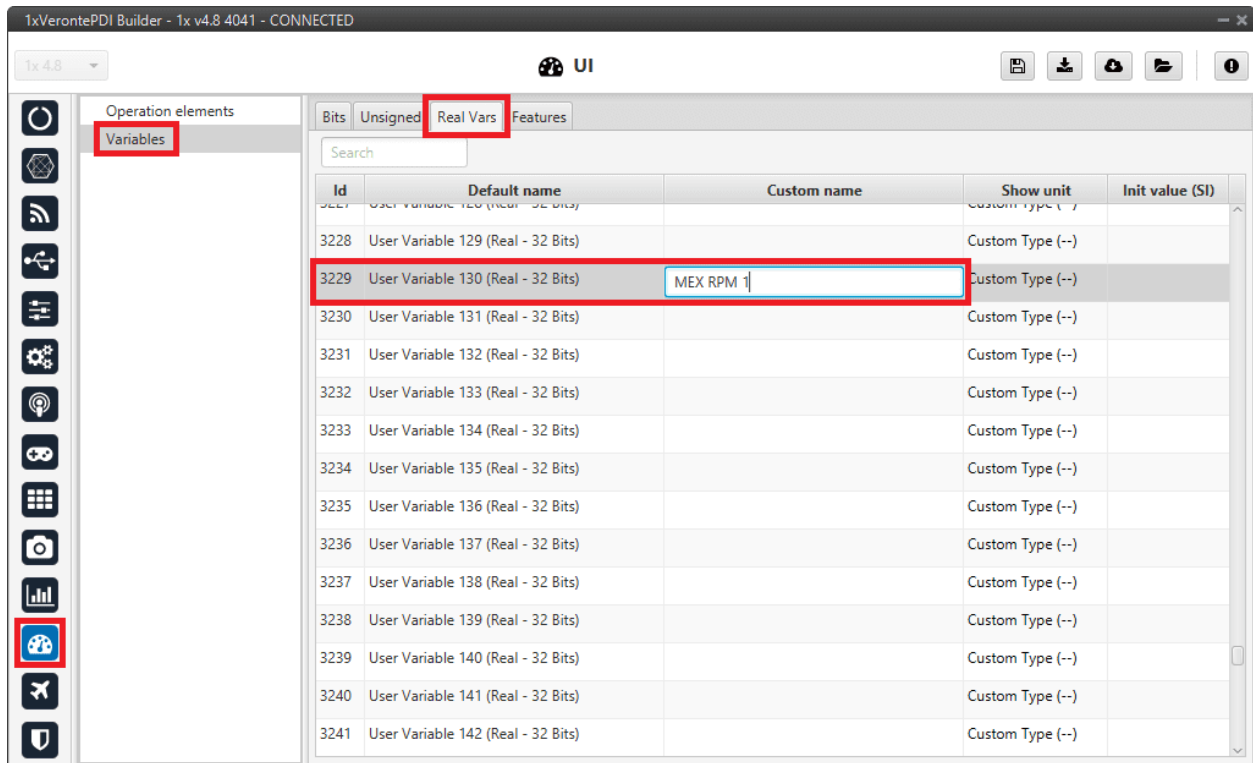


Fig. 50: 1x PDI Builder - User Variable renamed

7. Go to Input/Output menu → CAN Setup panel → **Mailboxes tab**.

Configure, in **CAN B**, some mailboxes to receive the message with **ID 1200**:

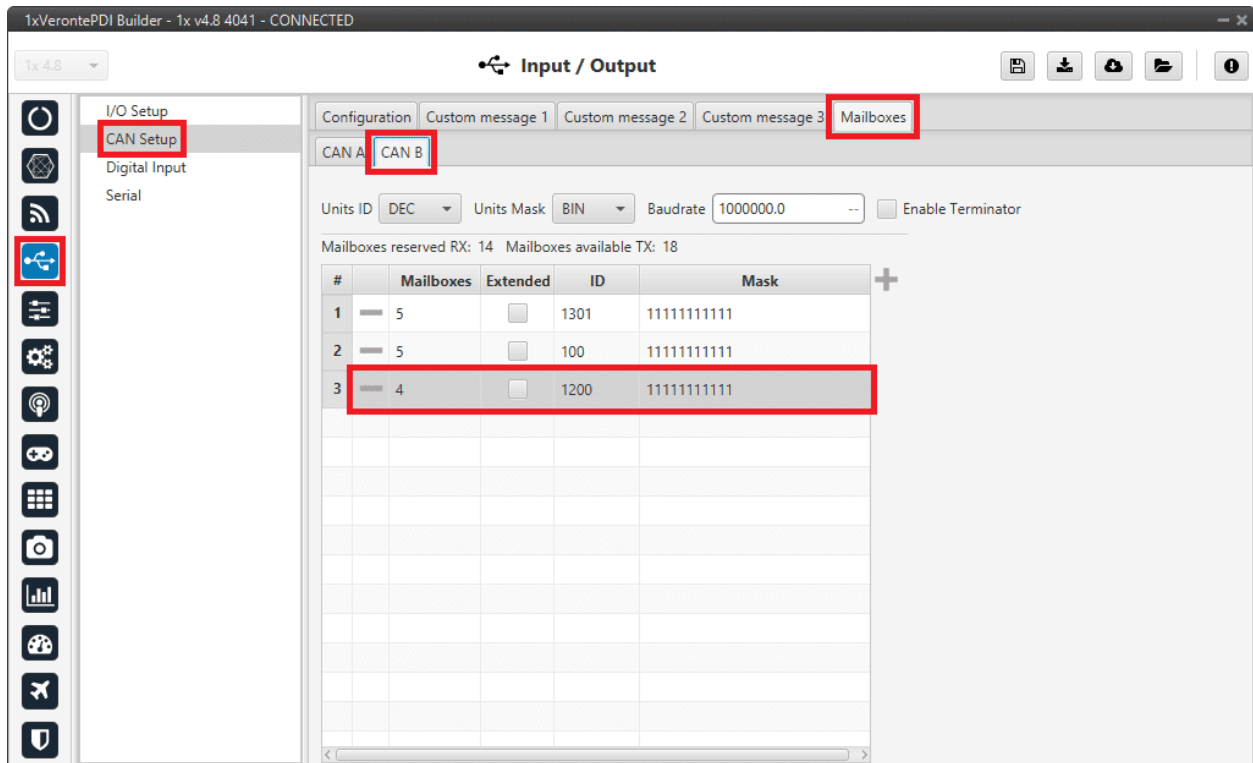


Fig. 51: 1x PDI Builder - Mailboxes configuration

- Go to Input/Output menu → CAN Setup panel → **Configuration tab**.

Connect an **Input filter** to a **Custom message consumer**. Both CAN buses of the Autopilot 1x can be used, as well as normal IDs and extended IDs:

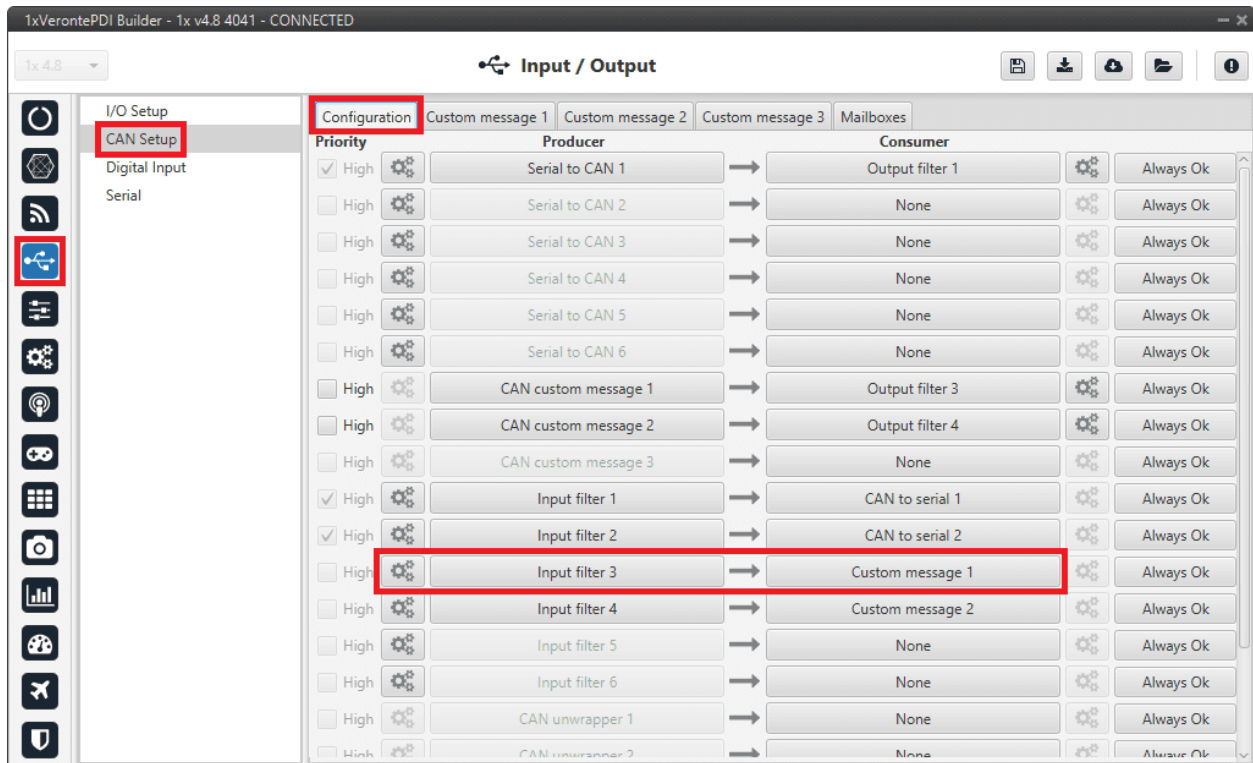


Fig. 52: 1x PDI Builder - CAN Setup configuration

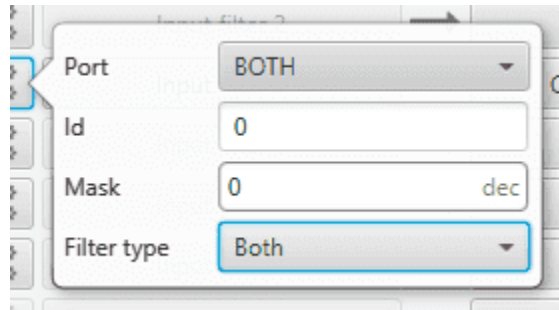


Fig. 53: 1x PDI Builder - Input filter configuration

- Go to Input/Output menu → CAN Setup panel → **Custom message 1 tab** (as Custom Message 1 has been selected as consumer).

Configure the message reading and store the received value in the user variable renamed above:

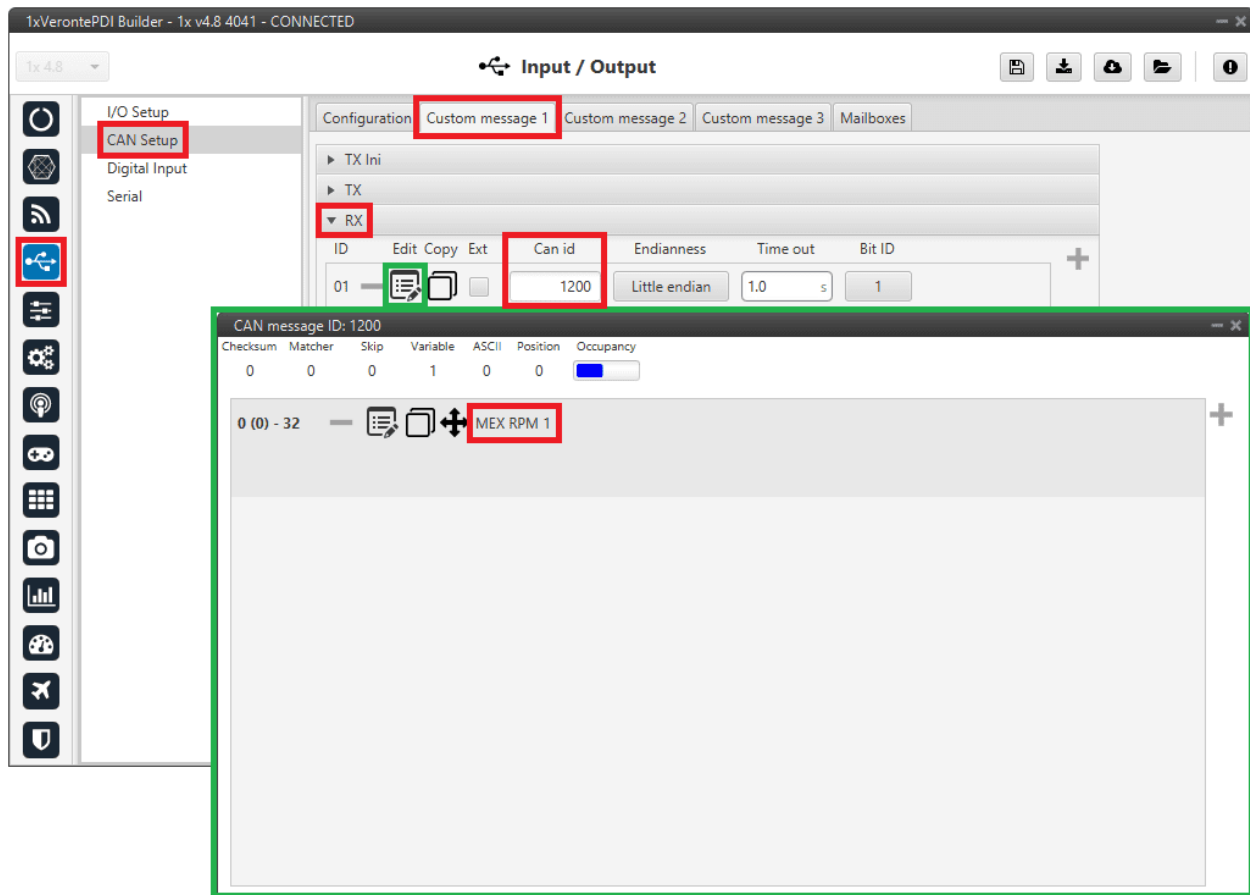


Fig. 54: 1x PDI Builder - Custom Message configuration

3.7 Serial communication

The user can send information through the serial ports of **MEX**. For this purpose, please read the following steps:

3.7.1 MEX PDI Builder side

1. I/O Setup configuration

- Reception of serial information on RS232-A (producer) is stored in Serial to CAN 2 (consumer).
- Transmission of serial information is sent using the CAN to Serial 2 (producer) through RS232-A (consumer).

(‘Serial to CAN’ and ‘CAN to Serial’ are explained in the [CAN I/O - Input/Output](#) section of this manual.)

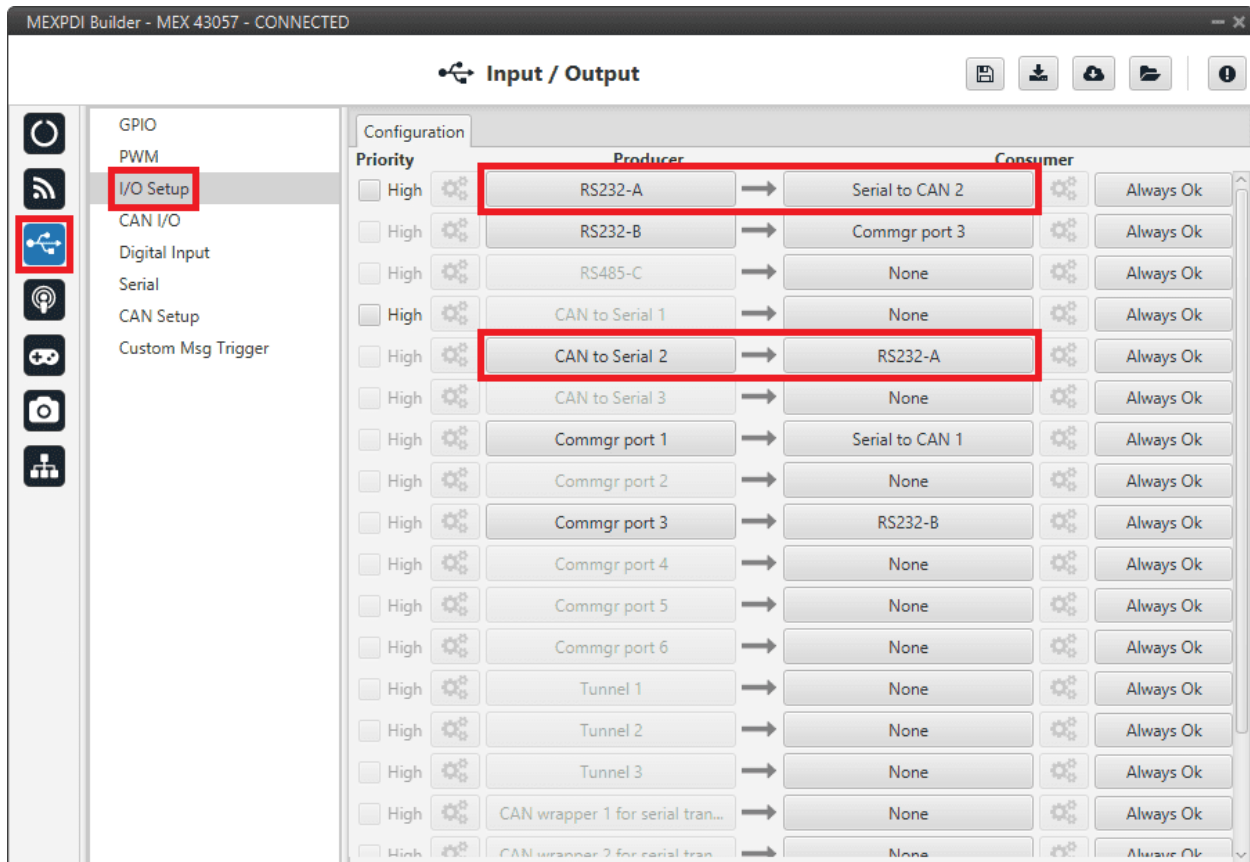


Fig. 55: MEX PDI Builder - I/O Setup configuration

2. CAN I/O configuration

- The information that will be **sent over serial port RS232-A** is going to be received on the **MEX** over its **CAN B** port. A **CAN Id of 51** is added to the **CAN Input Filter**. The incoming information (from **Veronte Autopilot 1x**) is processed in 'CAN to Serial 2'.
- The information **coming from port RS232-A** and processed as 'Serial to CAN 2' is going to be linked to a **CAN Output Filter**. The information of 'Serial to CAN 2' is going to be sent over **CAN B** with a **CAN ID of 50** (to be read by **Veronte Autopilot 1x**).

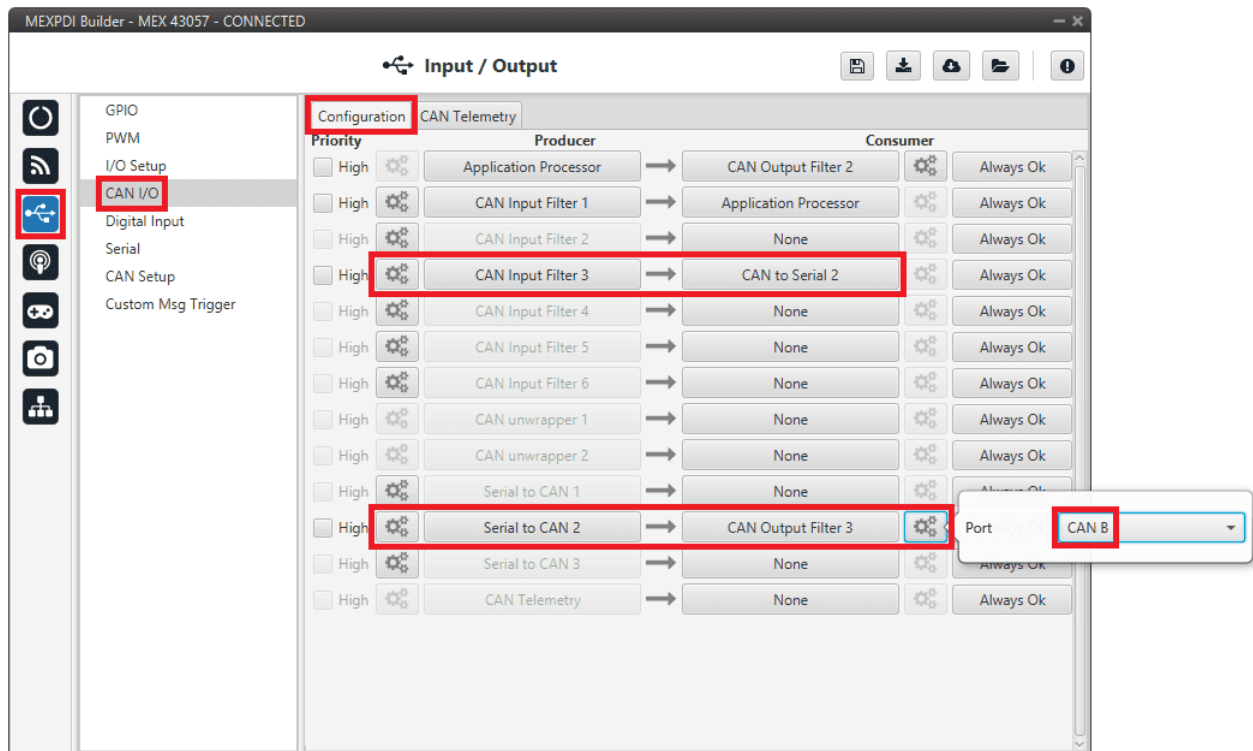


Fig. 56: MEX PDI Builder - CAN I/O configuration

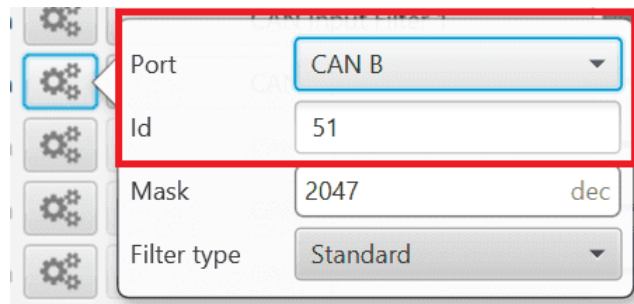


Fig. 57: MEX PDI Builder - CAN Input Filter configuration

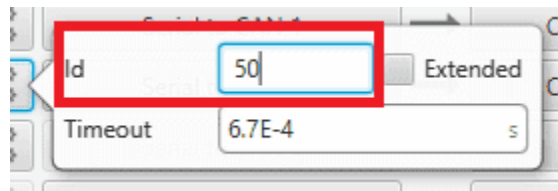


Fig. 58: MEX PDI Builder - Serial to CAN configuration

3. CAN Setup (mailboxes) configuration

Mailboxes need to be defined for the reception of CAN messages. In the example above, mailboxes for **ID 51** need to be added on **CAN B** port.

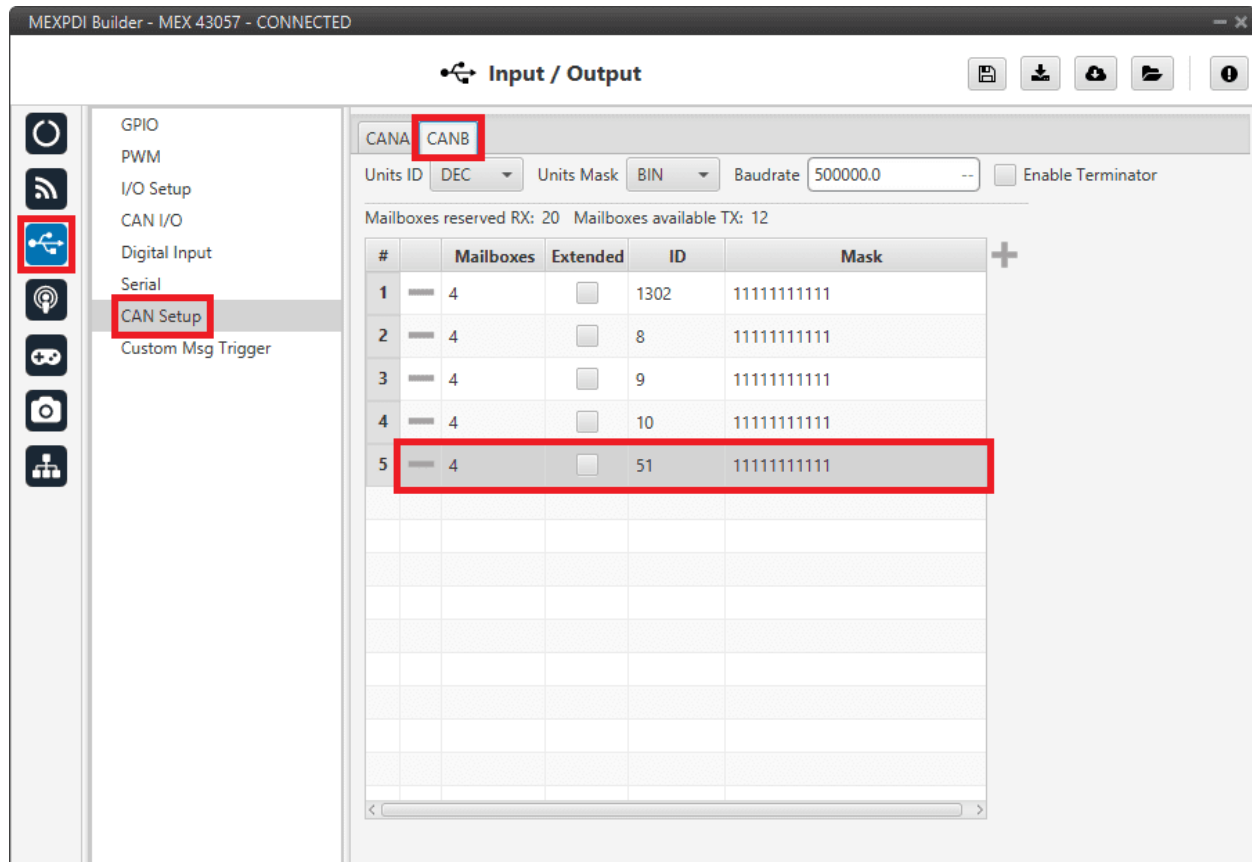


Fig. 59: MEX PDI Builder - CAN Setup configuration

3.7.2 1x PDI Builder side

4. I/O Setup configuration

First, on the **I/O Setup** panel link an **'RS custom message'** to a **'Serial to CAN'** with the serial data that **Autopilot 1x** is going to send to **MEX**.

Then, link a **'CAN to Serial'** to another **'RS custom message'** with the expected serial messages that **MEX** will receive in the selected serial port.

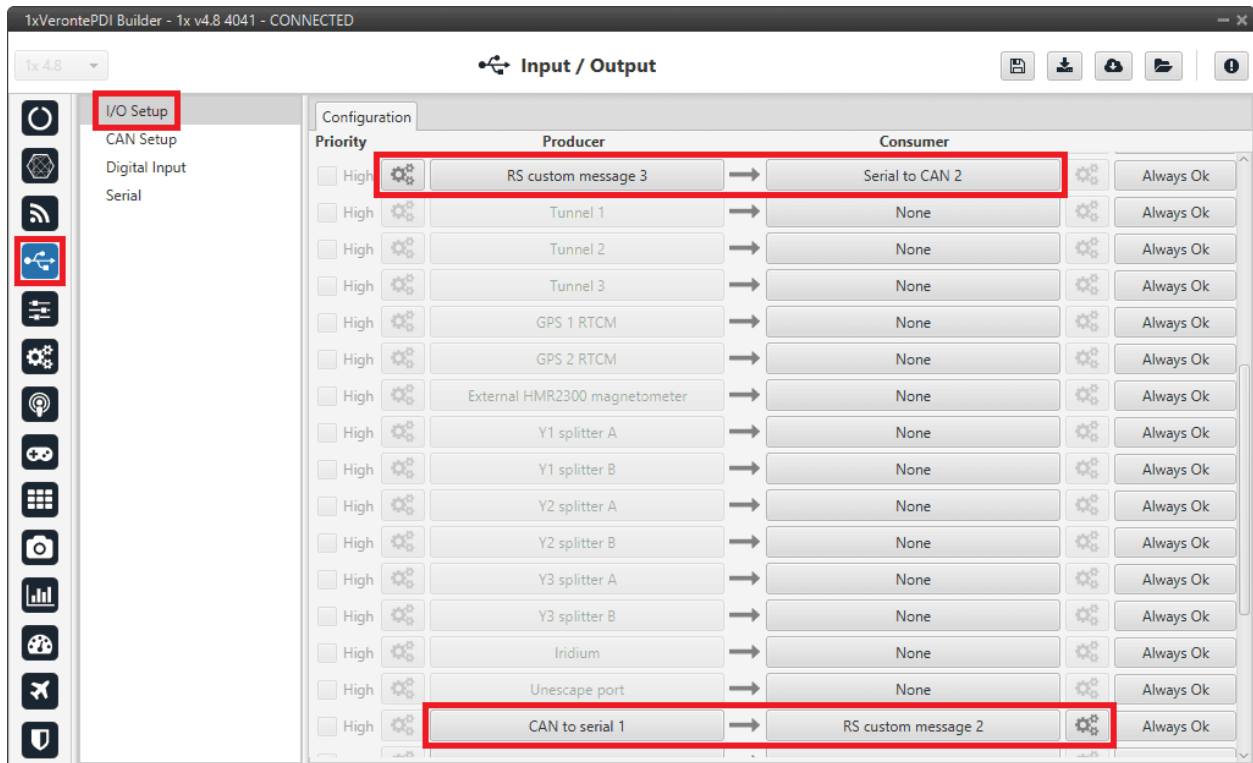


Fig. 60: 1x PDI Builder - I/O Setup configuration

5. CAN Setup configuration

Here, the same IDs employed in **MEX** for the CAN Input and CAN Output Filters are going to be employed on **Veronte Autopilot 1x** side, but they must be inverted.

Therefore, the **Input filter** linked to the chosen '**CAN to Serial**' needs to have **ID 50**. And the **Output filter** linked to the chosen '**Serial to CAN**' will have **ID 51**.

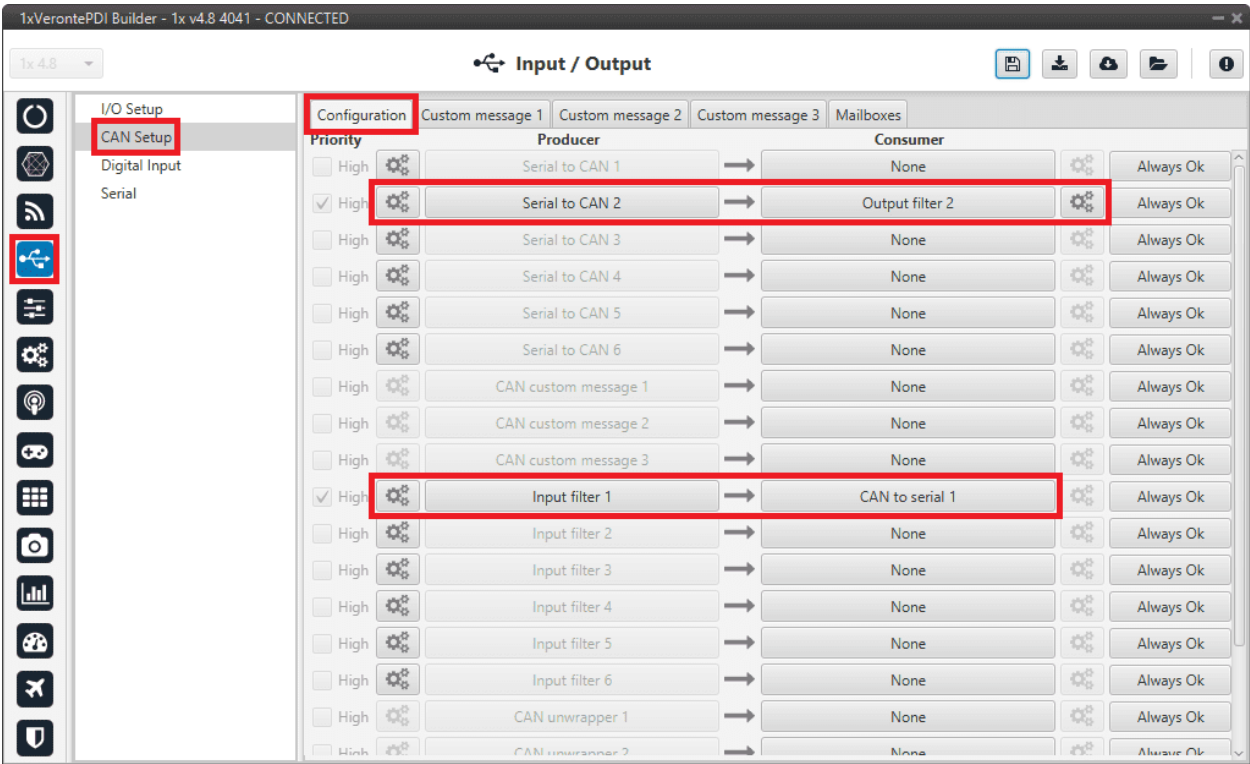


Fig. 61: 1x PDI Builder - CAN Setup configuration

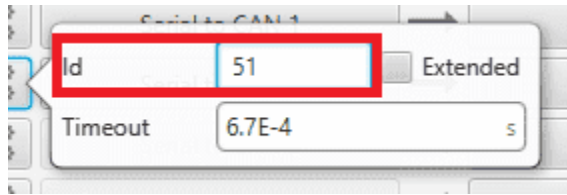


Fig. 62: 1x PDI Builder - Serial to CAN configuration

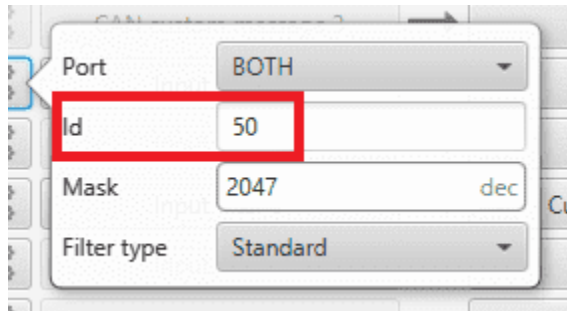


Fig. 63: 1x PDI Builder - Input filter configuration

6. Mailboxes configuration

Some mailboxes with ID 50 have to be created on whichever chosen reception CAN bus.

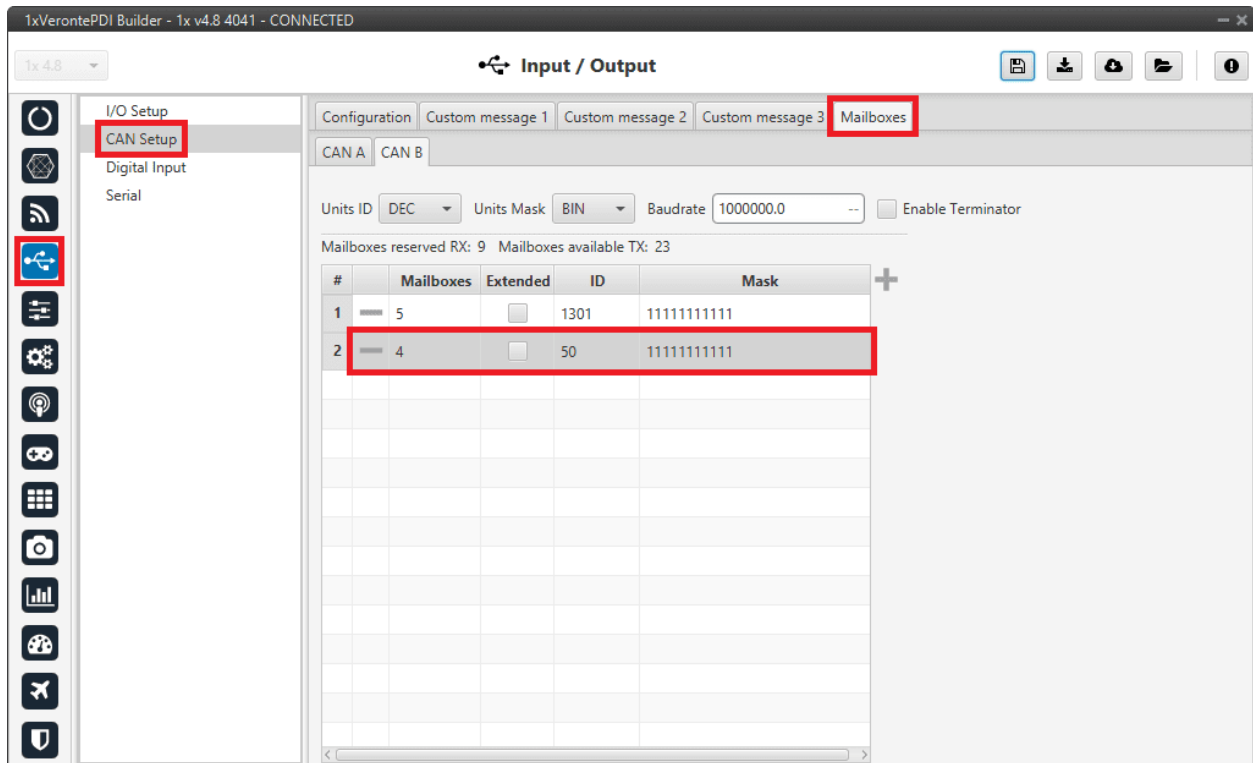


Fig. 64: 1x PDI Builder - Mailboxes configuration

3.8 External devices

The step-by-step instructions for the following external devices are explained in detail in the following sections:

- *Jetibox*
- *Scorpion tribunus*
- *Veronte products*

3.8.1 Jetibox

MEX is able to simulate a Jetibox to read telemetry from Legacy Jeti devices, the following steps need to be taken:

1. Go to Devices menu → **Jetibox panel**.

Enable it and select a **SCI Port**, in this example SCI A is selected:

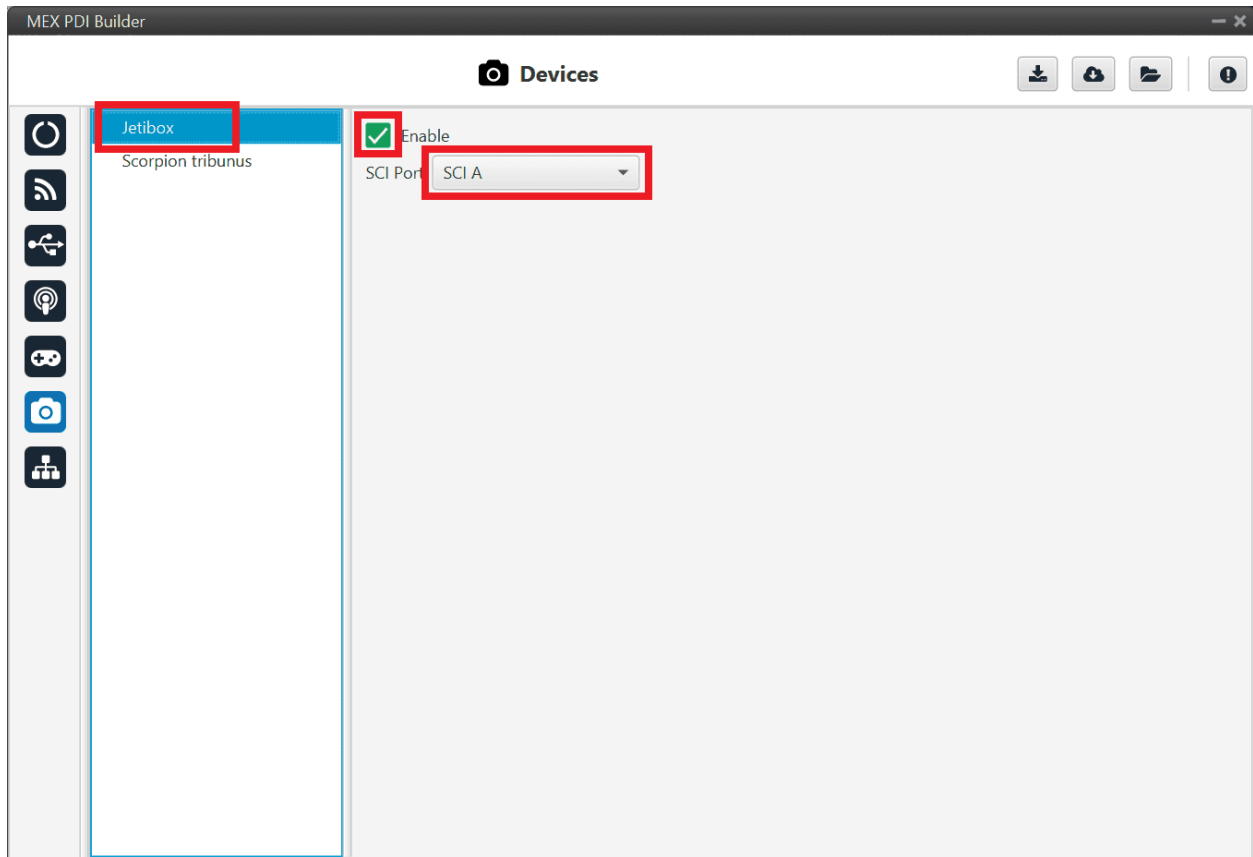


Fig. 65: **Jetibox - Devices configuration**

2. Go to Input/Output menu → **Serial panel**.

Configure the serial port (the one selected in step 1) as follows:

- **Baudrate:** 9800
- **Length:** 8
- **Stop:** 2 stop bits
- **Parity:** Odd
- **Use address mode:** Enabled

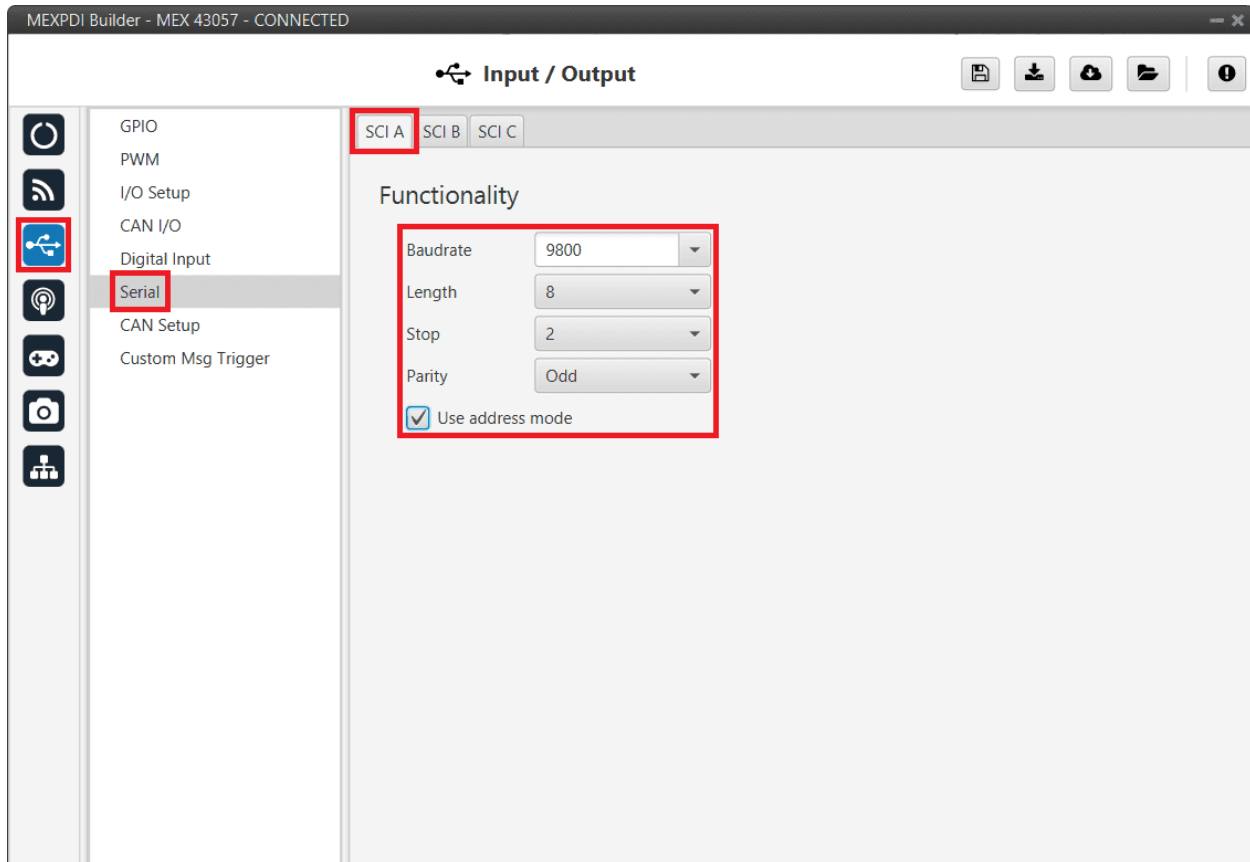


Fig. 66: **Jetibox - Serial configuration**

Note: The serial port will be completely reserved for this, so it cannot be used for any other purpose and the I/O Setup configuration affecting it will be ignored.

3. Go to Input/Output menu → **I/O Setup panel**.

Link the specific **JETI box** consumer to the **serial port** that has been configured in **step 2**:

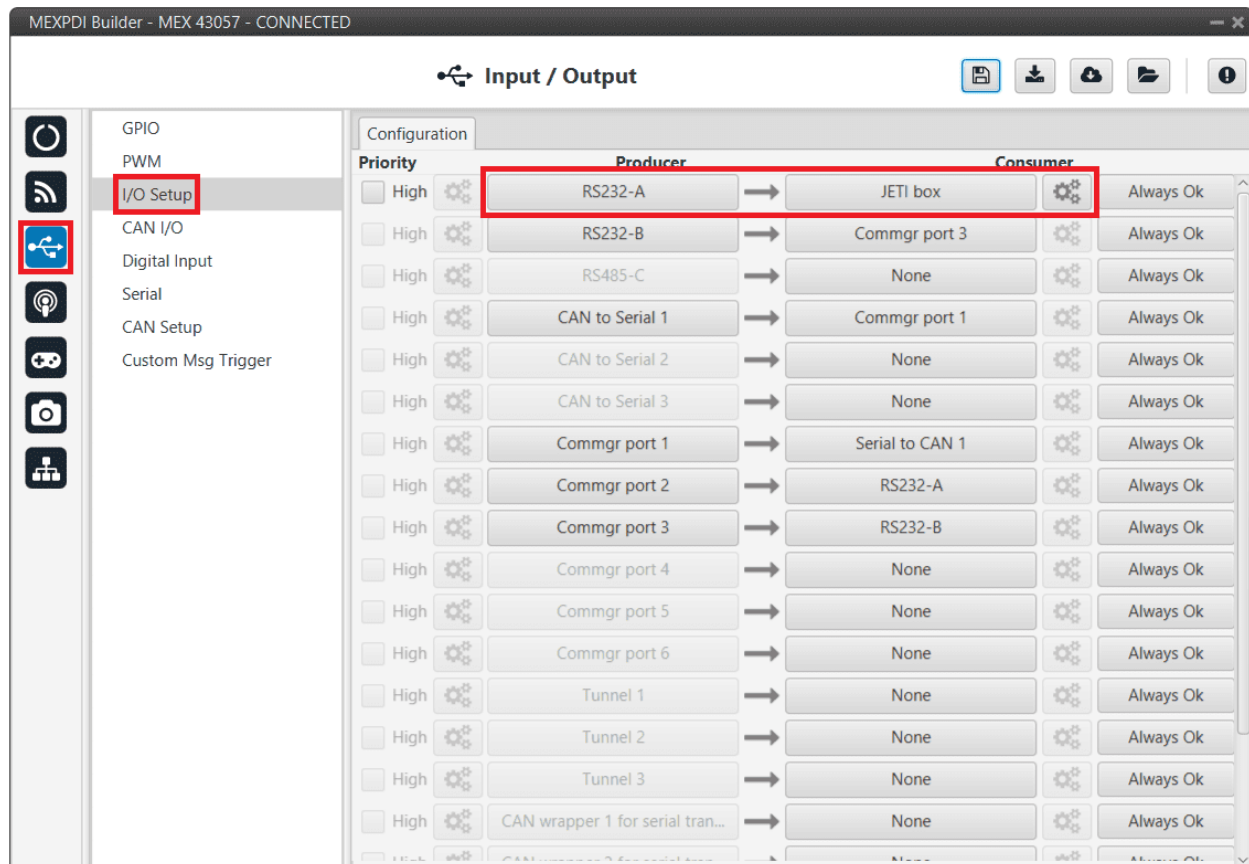



Fig. 67: Jetibox - I/O Setup configuration

4. Configure the Jetibox I/O consumer to retrieve the data. Click on the **configuration button** ( icon):

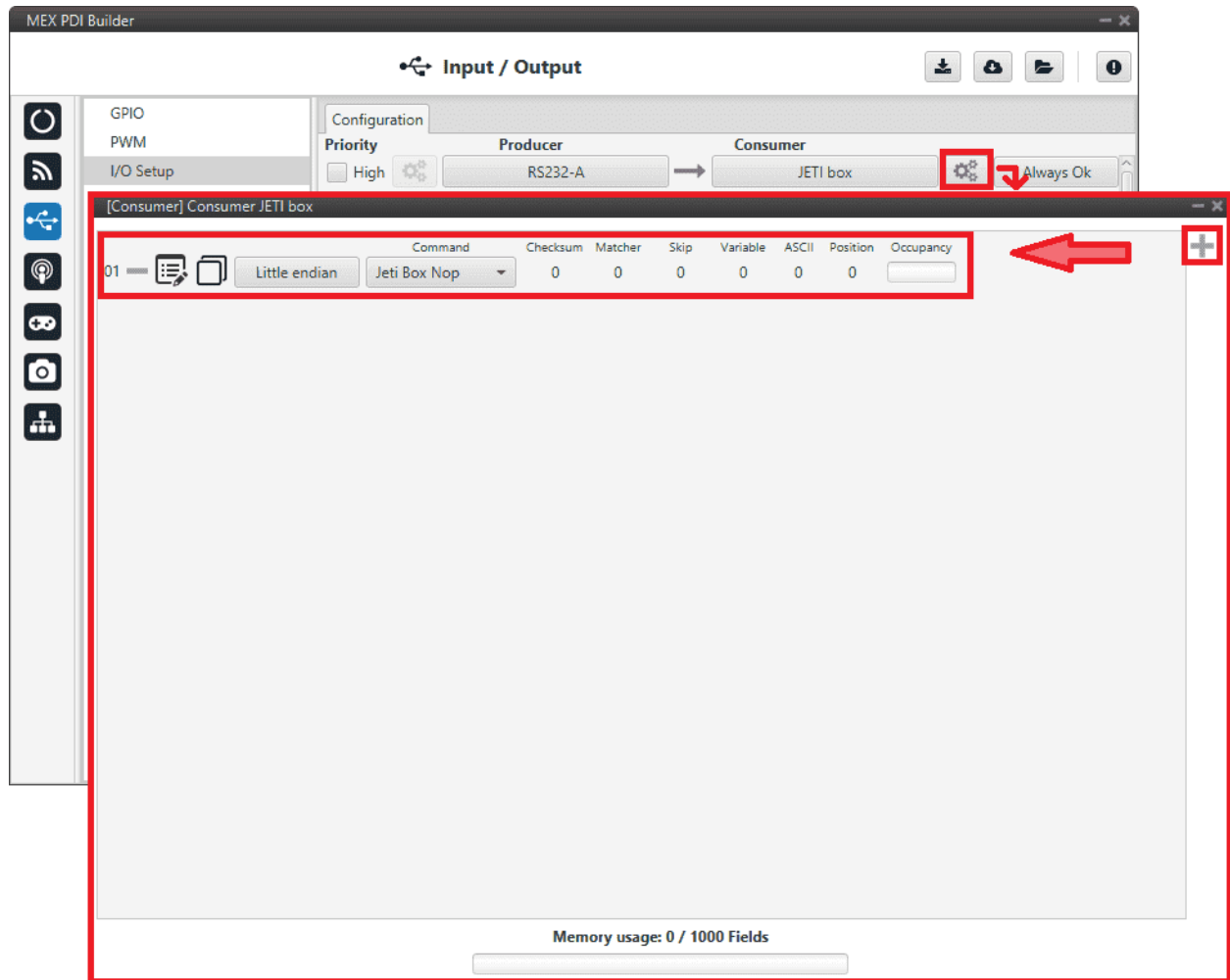


Fig. 68: Jetibox - JETI box Consumer configuration

Below is an example of the custom messages needed to read the Actual Voltage from a Jeti MasterSpin 220 (use **Big endian** in all messages):

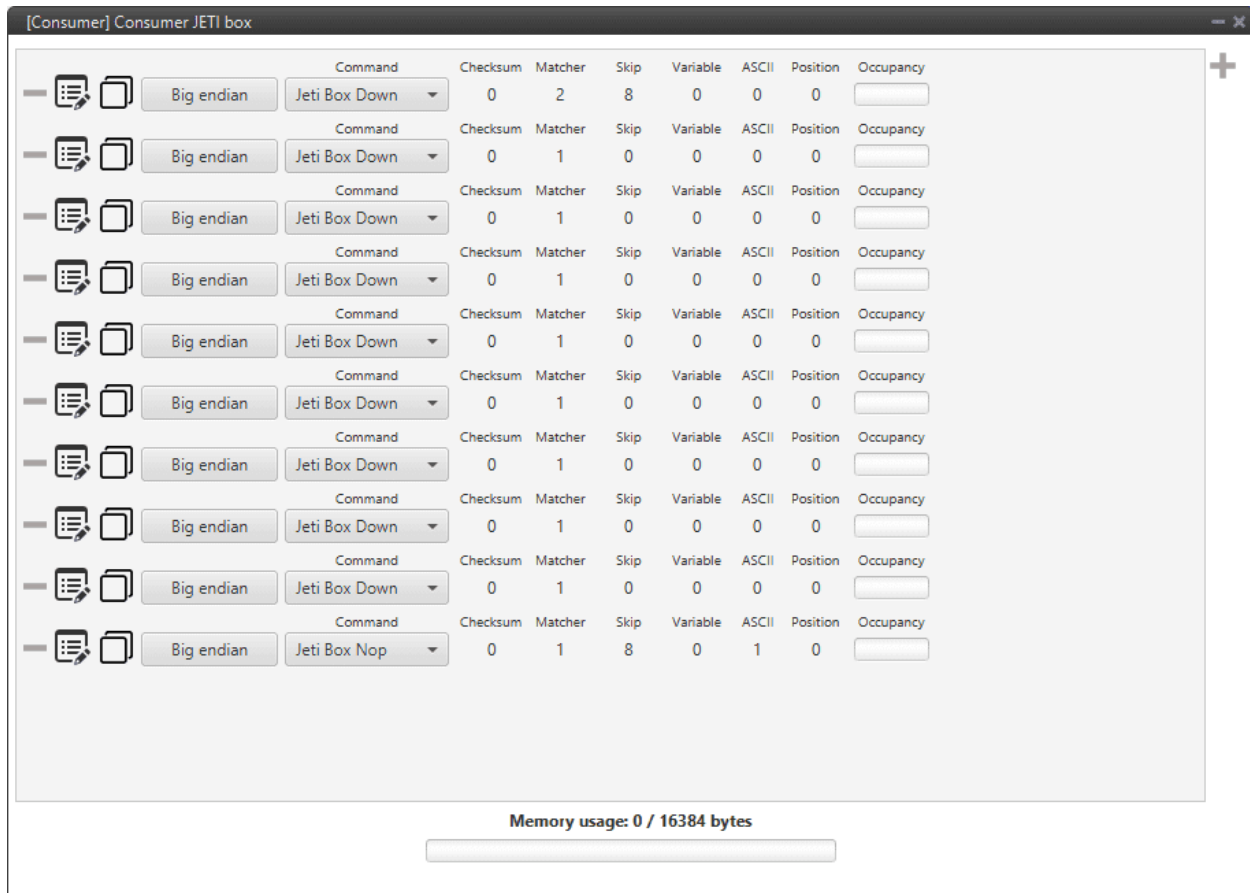


Fig. 69: JETI box custom message example

- Expected text: “CONTROLLER TYPE MasterSpin 220~”
 - Command: **Jeti Box Down**
 - Matcher(32) “CONT” 0x434F4E54 (1129270868)
 - Skip(24*8) 192
 - Matcher(32) “220~” 0x3232307E (842150014)

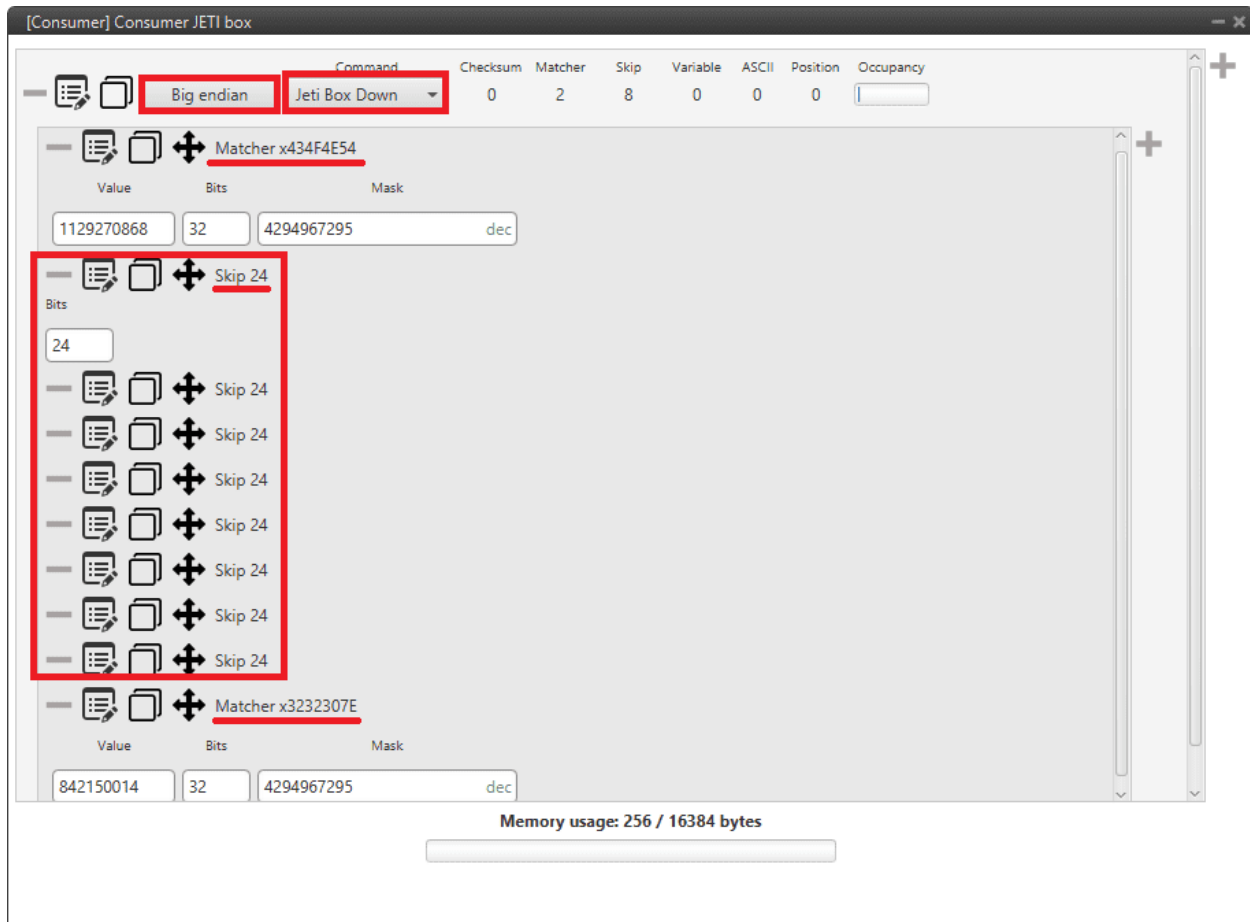


Fig. 70: JETI box first custom message example

2. Expected text: "MeasureOrSetting MEASURE ~"
 - Command: **Jeti Box Down**
 - Matcher(32) "Meas" 0x4D656173 (1298489715)
3. Expected text: "Max Temperature"...
 - Command: **Jeti Box Down**
 - Matcher(32) "Max " 0x4D617820 (1298233376)
4. Expected text: "Min Temperature"...
 - Command: **Jeti Box Down**
 - Matcher(32) "Min " 0x4D696E20 (1298755104)
5. Expected text: "Actual Temperature"...
 - Command: **Jeti Box Down**
 - Matcher(32) "Actu" 0x41637475 (1097036917)
6. Expected text: "MaxCurrent"...
 - Command: **Jeti Box Down**

- Matcher(32) “MaxC” 0x4D617843 (1298233411)
- 7. Expected text: “MinCurrent”...
 - Command: **Jeti Box Down**
 - Matcher(32) “MinC” 0x4D696E43 (1298755139)
- 8. Expected text: “Max Voltage”...
 - Command: **Jeti Box Down**
 - Matcher(32) “Max ” 0x4D617820 (1298233376)
- 9. Expected text: “Min Voltage”...
 - Command: **Jeti Box Down**
 - Matcher(32) “Min ” 0x4D696E20 (1298755104)
- 10. Expected text: “Actual Voltage 11,86 V “
 - Command: **Jeti Box Nop**
 - Matcher(32) “Actu” 0x41637475 (1097036917)
 - Skip(12*8) 96
 - Parse ascii: int(2), decimal(2), separator(‘,’)

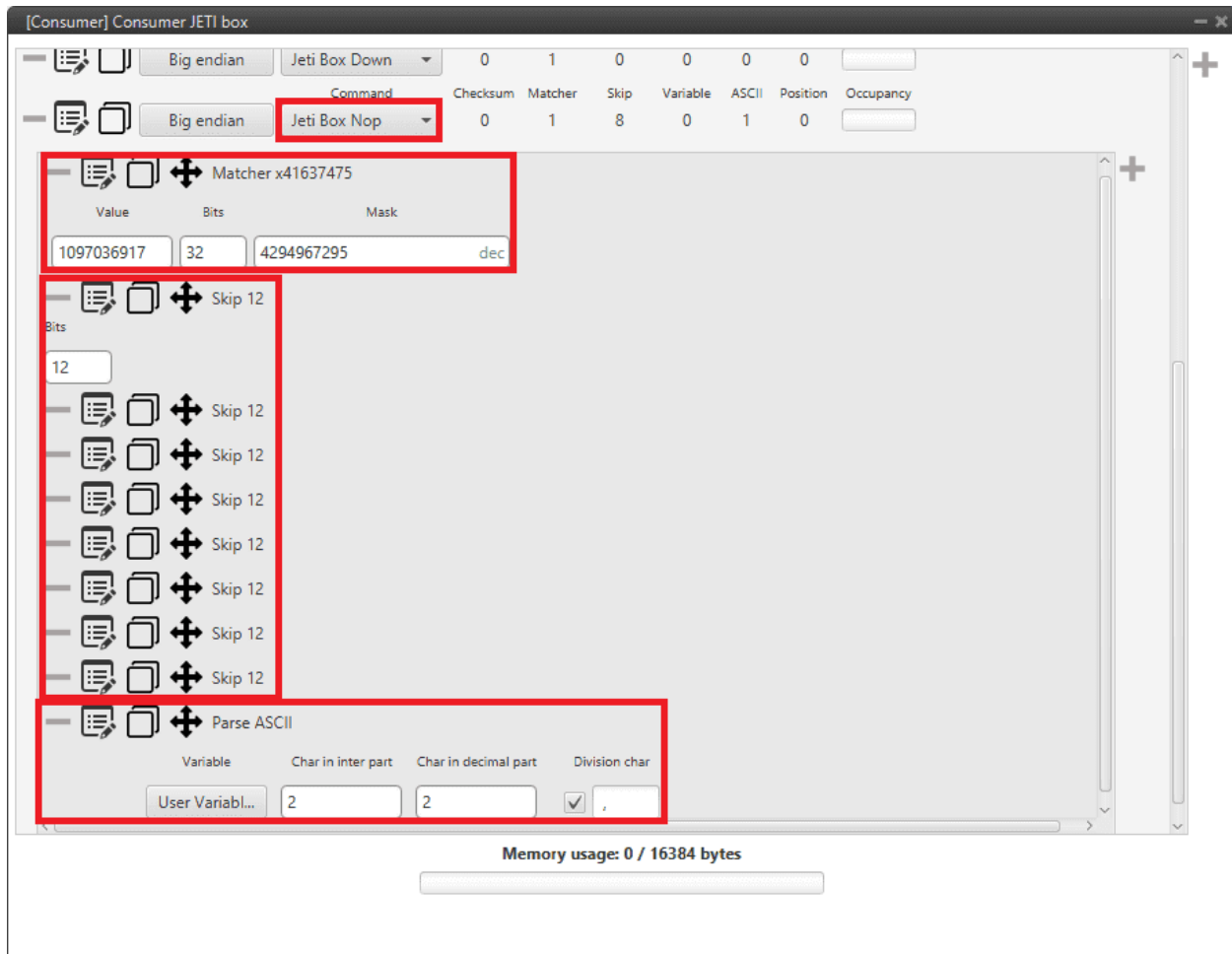


Fig. 71: JETI box last custom message example

3.8.2 Scorpion tribunus

MEX is able to read telemetry from Tribunus ESCs by connecting it to one of its serial ports. The following steps configure MEX to read this telemetry:

1. Go to Devices menu → **Scorpion tribunus** panel.

Enable it and configure it as shown:

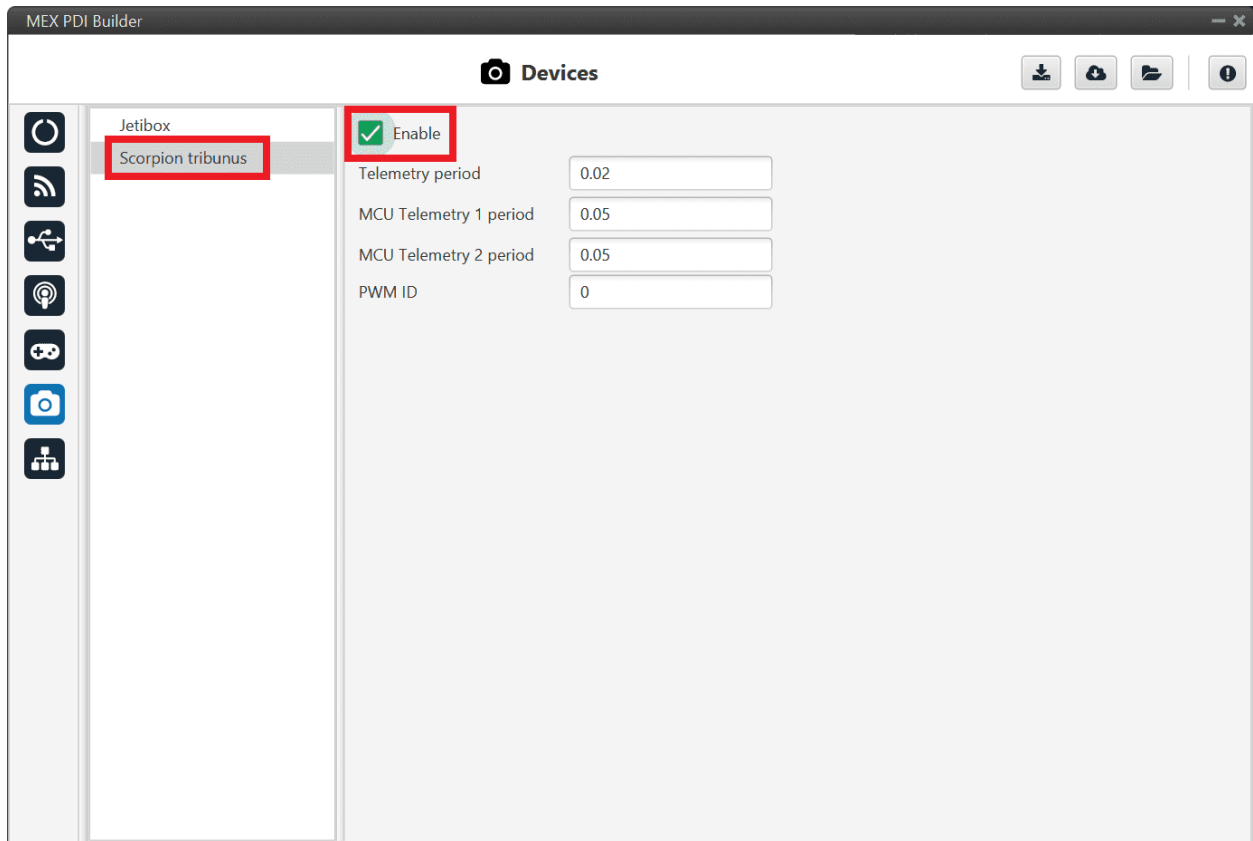


Fig. 72: Scorpion tribunus - Devices configuration

2. Go to Input/Output menu → **I/O Setup panel**.

Link the specific Tribunus ESC consumer to the desired port:

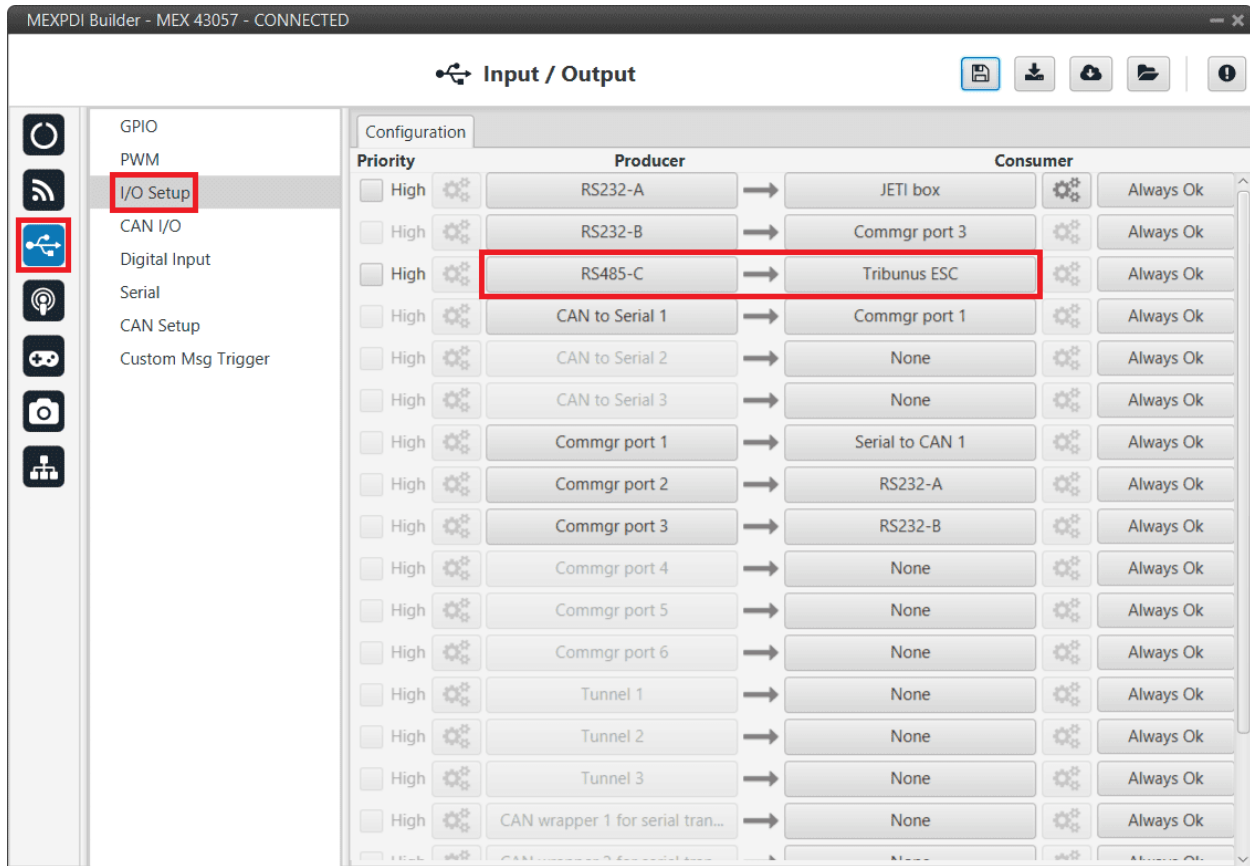


Fig. 73: Scorpion tribunus - I/O Setup configuration

3.8.3 Veronte products

3.8.3.1 Connection with Autopilot 1x via CAN

No configuration is necessary for **MEX**, the configuration for communication with **Autopilot 1x** is set by default.

The configuration required in **1x PDI Builder** to communicate with **MEX** via CAN is explained in the [CEX/MEX - Integration examples](#) section of the **1x PDI Builder** user manual.

3.8.3.2 Connection with Autopilot 4x via CAN

3.8.3.2.1 CAN Reception IDs

First of all, users can setup the receiving CAN IDs for each one of the three possible **Veronte Autopilots 1x** sending data to **MEX** in the **Arbitration** menu.

Go to Arbitration menu → **CAN Setup** panel:

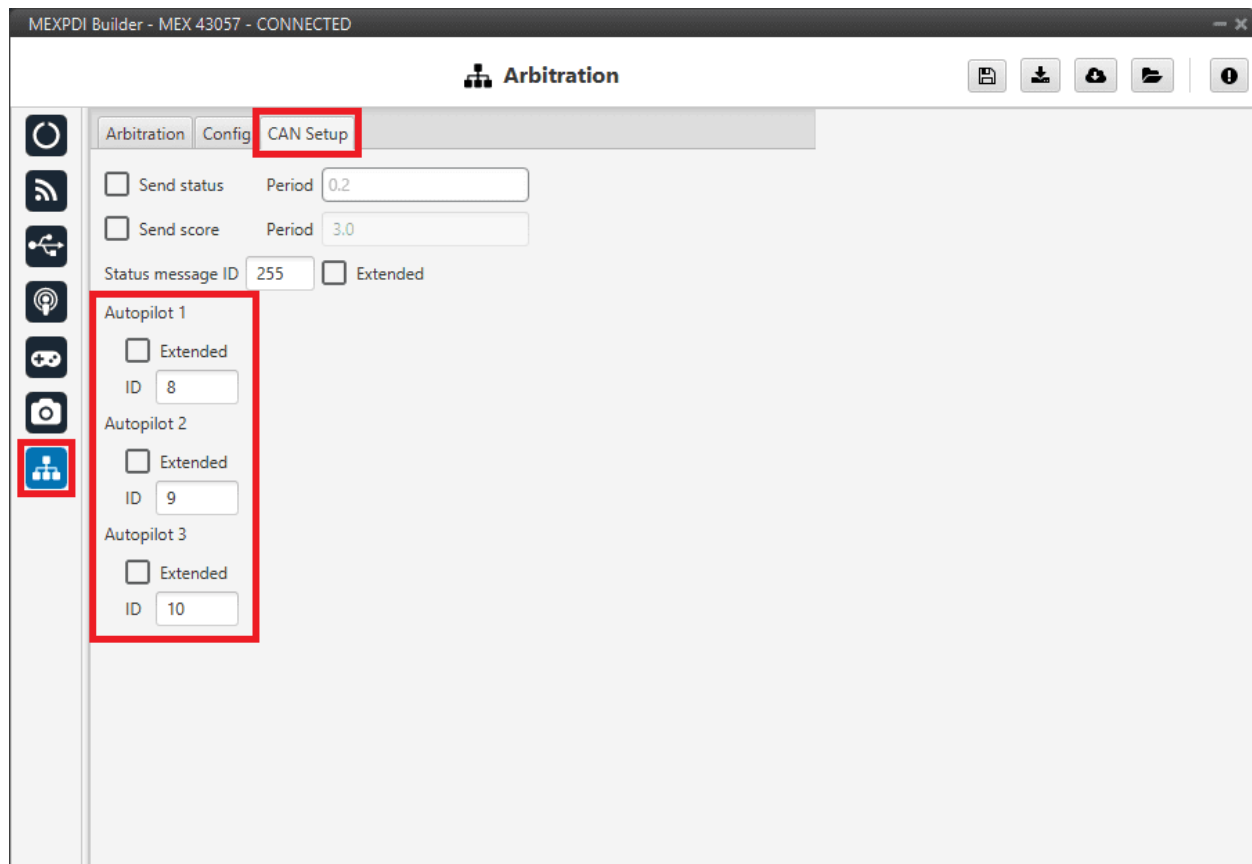


Fig. 74: Arbitration - CAN Reception IDs

Note: If **arbitration is not enabled**, and therefore only an **Autopilot 1x** is being used, no CAN Ids need to be configured here.

3.8.3.2.2 CAN I/O Interconnections

Once CAN IDs are set, users shall configure:

- **CAN Input Filters** to be used (as communication with **MEX** has to be **always** through a **Filter**).
- The connection between input filters and data Consumers.

Go to Input/Output menu → CAN I/O panel → **Configuration** tab:

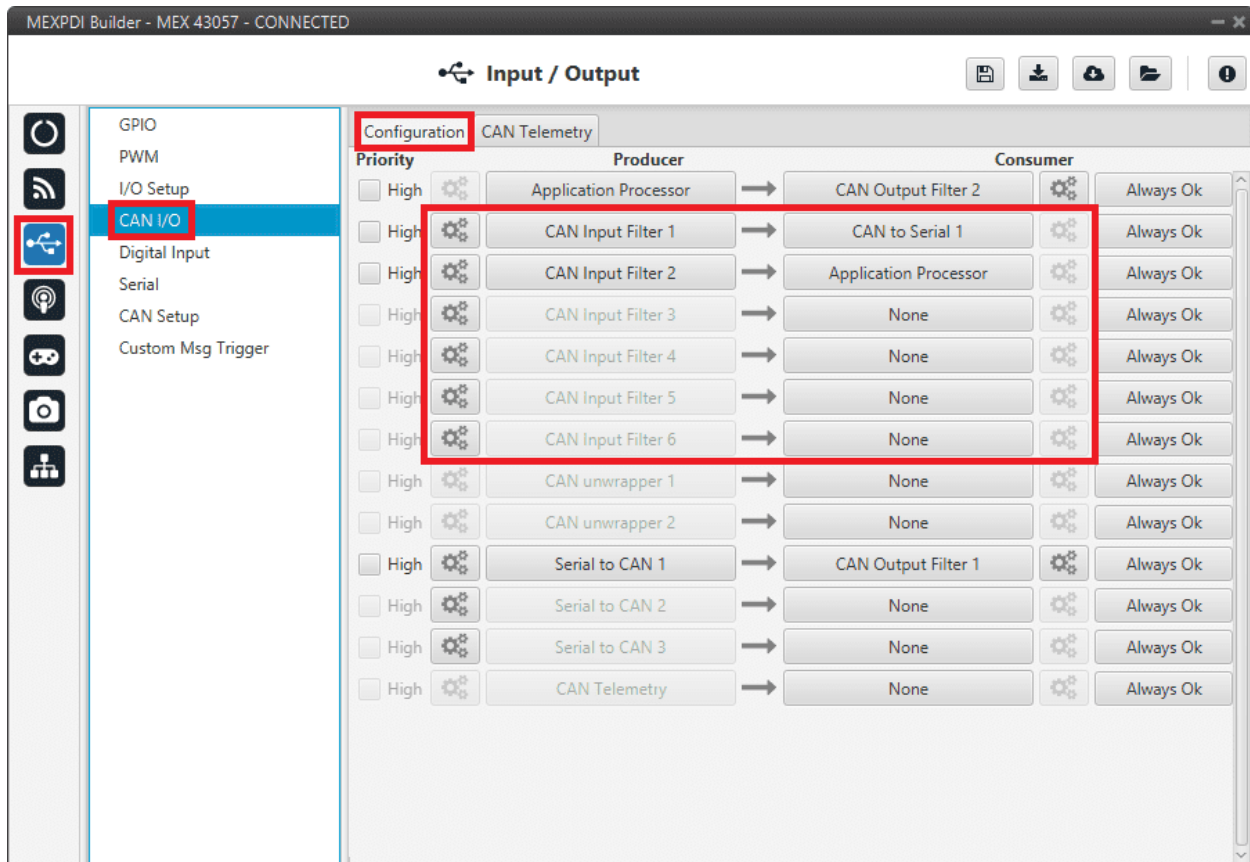


Fig. 75: Arbitration - CAN Input Filters

For more information on CAN I/O configuration, see the [CAN I/O - Input/Output](#) section of the present manual.

Next step is to connect each of the desired data Producers to a **CAN Output Filter**, and configure both, the Producer and the CAN Output Filter:

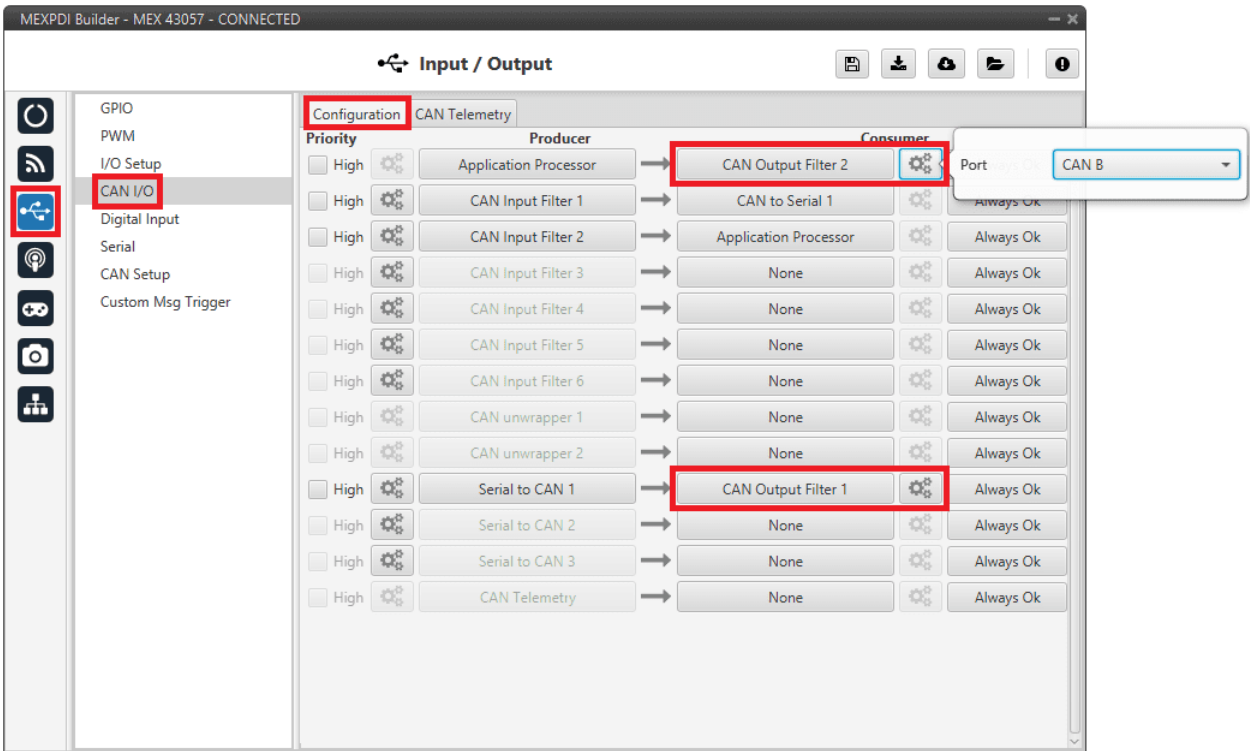


Fig. 76: Arbitration - CAN Output Filters

TROUBLESHOOTING

4.1 Maintenance mode (loaded with errors)

The following error message may appear when trying to save a change or import a configuration.

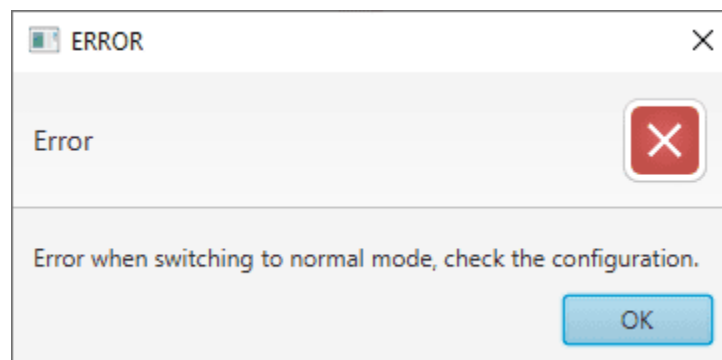


Fig. 1: Error message

Therefore, **MEX** unit will be in 'Maintenance mode (loaded with errors)':

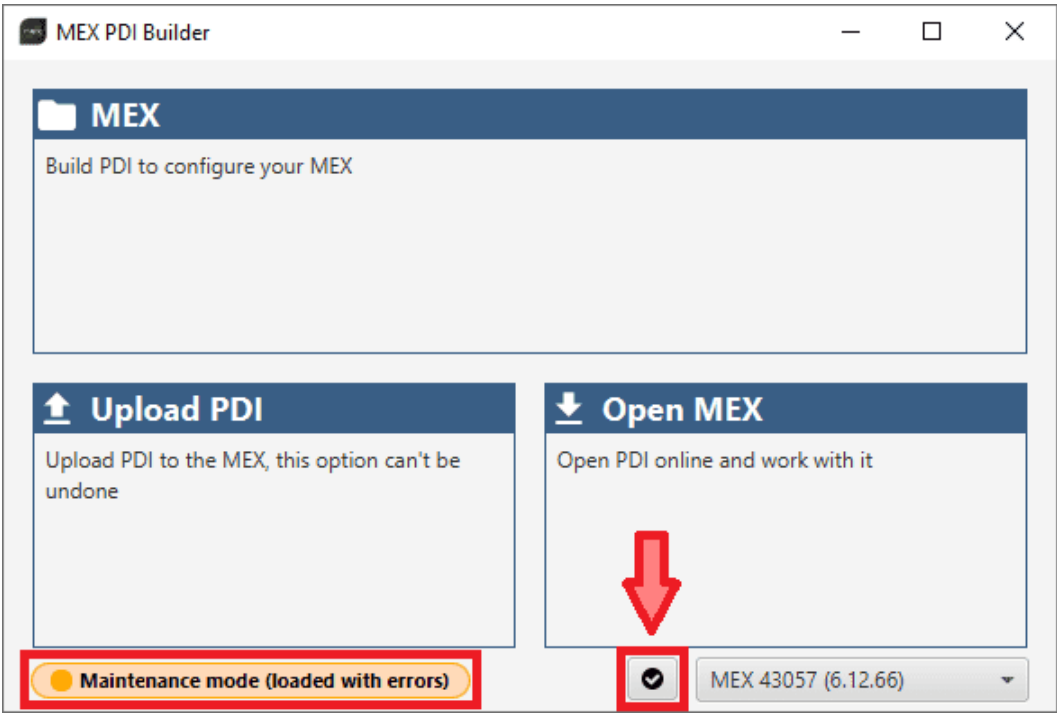



Fig. 2: Maintenance mode (loaded with errors)

To check what the source of the problem is, the user can simply click on the **PDI Error button** , which will show what the PDI Error is:

PDI Errors - Device: 43057

PDI ID	PDI Error Description	Config ID	Config Desc.
502	Invalid CAN id	317	CEX Serial To CAN Producers

Export Close

Fig. 3: Maintenance mode (loaded with errors) - PDI Errors panel

- **PDI ID:** ID of the PDI Error.

- **PDI Error Description:** Description of this PDI Error. A list of all PDI Errors can also be accessed in the [List of PDI errors](#) section of the **1x Software Manual**.
- **Config ID:** ID of the configurable (.xml file) containing the data in which the PDI Error has been caused.
- **Config Description:** Description of the configurable (.xml file) containing the data in which the PDI Error has been caused.

Clicking the **Export** button will export a .csv file with the same information shown in this PDI Errors panel.

Finally, it is possible to access the **MEX** configuration to fix this error.

4.2 Migrate configuration

Warning: When performing automatic migration from a previous version to the current version of the software, errors may occur.

It is then the responsibility of the user to check the subsequent result.

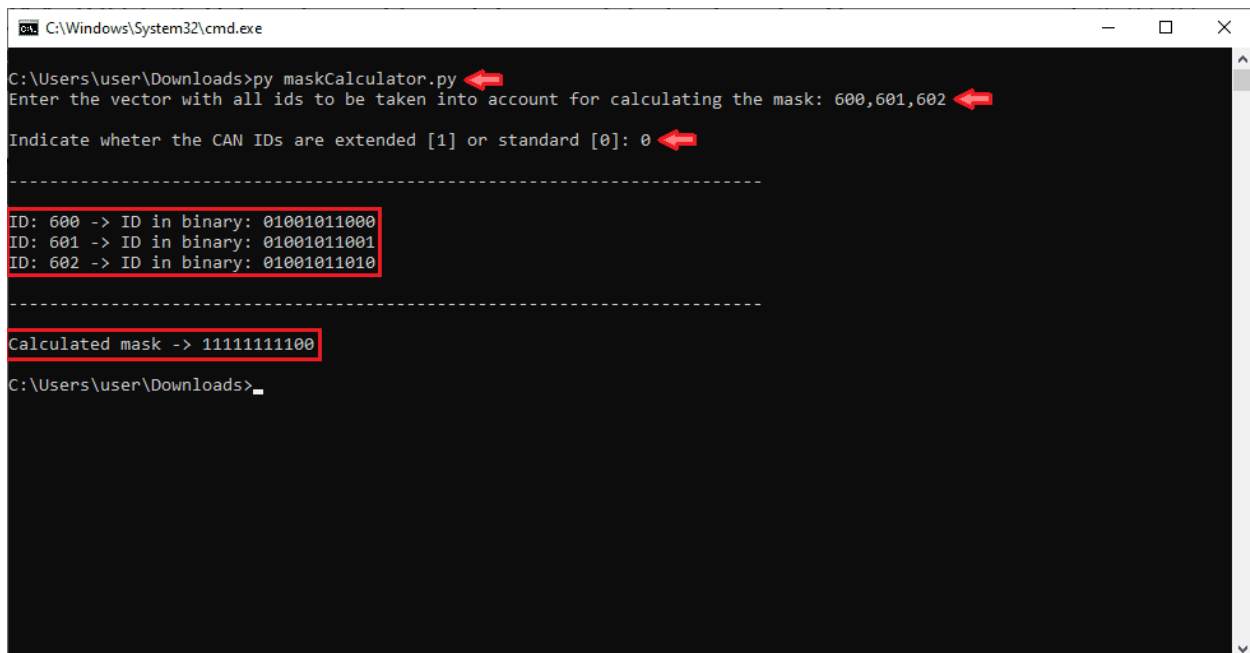
5.1 How to calculate a mask

This section attaches a python program that allows users to easily calculate their mask in standard or extended frame format by simply entering the CAN Ids as a **vector**. In addition, this program also converts each Id entered into binary.



maskCalculator.py

An example of the execution of this program is shown below:



```
C:\Windows\System32\cmd.exe
C:\Users\user\Downloads>py maskCalculator.py
Enter the vector with all ids to be taken into account for calculating the mask: 600,601,602
Indicate wheter the CAN IDs are extended [1] or standard [0]: 0
-----
ID: 600 -> ID in binary: 01001011000
ID: 601 -> ID in binary: 01001011001
ID: 602 -> ID in binary: 01001011010
-----
Calculated mask -> 1111111100
C:\Users\user\Downloads>
```

Fig. 1: Example of maskCalculator program