

Integration Manual

for S32M27X CANTRCV Driver

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Chapter 1

Revision History

Revision	Date	Author	Description
1.0	31.03.2023	NXP RTD Team	S32K3 Real-Time Drivers AUTOSAR 4.4 & R21-11 Version 3.0.0

Chapter 2

Introduction

- [Supported Derivatives](#)
- [Overview](#)
- [About This Manual](#)
- [acronyms_and_definitions](#)
- [Reference List](#)

This Integration Manual describes the integration requirements for NXP Semiconductors' AUTOSAR CanTrcv Driver for S32M27x.

2.1 Supported Derivatives

The software described in this document is intended to be used with the following microcontroller devices of NXP Semiconductors:

- s32m274_lqfp64
- s32m276_lqfp64

All of the above microcontroller devices are collectively named as S32K3.

2.2 Overview

AUTOSAR (AUTomotive Open System ARchitecture) is an industry partnership working to establish standards for software interfaces and software modules for automobile electronic control systems.

AUTOSAR:

- paves the way for innovative electronic systems that further improve performance, safety and environmental friendliness.
- is a strong global partnership that creates one common standard: "Cooperate on standards, compete on implementation".
- is a key enabling technology to manage the growing electrics/electronics complexity. It aims to be prepared for the upcoming technologies and to improve cost-efficiency without making any compromise with respect to quality.
- facilitates the exchange and update of software and hardware over the service life of the vehicle.

2.3 About This Manual

This Technical Reference employs the following typographical conventions:

- **Boldface** style: Used for important terms, notes and warnings.
- *Italic* style: Used for code snippets in the text. Note that C language modifiers such "const" or "volatile" are sometimes omitted to improve readability of the presented code.

Notes and warnings are shown as below:

Note

This is a note.

Warning

This is a warning

2.4 Reference List

#	Title	Version
1	Specification of Can Transceiver Driver	AUTOSAR Release R21-11
2	Reference Manual	S32M27x Reference Manual, Rev.2, Draft A, — 02/2023
3	Data Sheet	S32M2xx Data Sheet, Rev. 2 RC — 12/2022

Chapter 3

Building the driver

- [Build Options](#)
- [Files required for compilation](#)
- [Setting up the plugins](#)

This section describes the source files and various compilers, linker options used for building the driver. It also explains the EB Tresos Studio plugin setup procedure.

3.1 Build Options

- [GCC Compiler/Assembler/Linker Options](#)
- [DIAB Compiler/Assembler/Linker Options](#)
- [GHS Compiler/Assembler/Linker Options](#)
- [IAR Compiler/Assembler/Linker Options](#)

The RTD driver files are compiled using:

- NXP GCC 10.2.0 20200723 (Build 1728 Revision g5963bc8)
- Wind River Diab Compiler 7.0.4
- Compiler Versions: Green Hills Multi 7.1.6d / Compiler 2021.1.4
- Compiler Versions: IAR ANSI C/C++ Compiler V8.50.10 (safety version)

The compiler, assembler, and linker flags used for building the driver are explained below.

The TS_T40D34M30I0R0 part of the plugin name is composed as follows:

- T = Target_Id (e.g. T40 identifies Cortex-M architecture)
- D = Derivative_Id (e.g. D34 identifies S32K3 platform)
- M = SW_Version_Major and SW_Version_Minor
- I = SW_Version_Patch
- R = Reserved

3.1.1 GCC Compiler/Assembler/Linker Options

3.1.1.1 GCC Compiler Options

Compiler Option	Description
-mcpu=cortex-m7	Targeted ARM processor for which GCC should tune the performance of the code
-mthumb	Generates code that executes in Thumb state
-mlittle-endian	Generate code for a processor running in little-endian mode
-mfpu=fpv5-sp-d16	Specifies the floating-point hardware available on the target
-mfloat-abi=hard	Specifies the floating-point ABI to use. "hard" allows generation of floating-point instructions and uses FPU-specific calling conventions
-std=c99	Specifies the ISO C99 base standard
-Os	Optimize for size. Enables all -O2 optimizations except those that often increase code size
-ggdb3	Produce debugging information for use by GDB using the most expressive format available, including GDB extensions if at all possible. Level 3 includes extra information, such as all the macro definitions present in the program
-Wall	Enables all the warnings about constructions that some users consider questionable, and that are easy to avoid (or modify to prevent the warning), even in conjunction with macros
-Wextra	This enables some extra warning flags that are not enabled by -Wall
-pedantic	Issue all the warnings demanded by strict ISO C. Reject all programs that use forbidden extensions. Follows the version of the ISO C standard specified by the aforementioned -std option
-Wstrict-prototypes	Warn if a function is declared or defined without specifying the argument types
-Wundef	Warn if an undefined identifier is evaluated in an #if directive. Such identifiers are replaced with zero
-Wunused	Warn whenever a function, variable, label, value, macro is unused
-Werror=implicit-function-declaration	Make the specified warning into an error. This option throws an error when a function is used before being declared
-Wsign-compare	Warn when a comparison between signed and unsigned values could produce an incorrect result when the signed value is converted to unsigned.
-Wdouble-promotion	Give a warning when a value of type float is implicitly promoted to double
-fno-short-enums	Specifies that the size of an enumeration type is at least 32 bits regardless of the size of the enumerator values.
-funsigned-char	Let the type char be unsigned by default, when the declaration does not use either signed or unsigned
-funsigned-bitfields	Let a bit-field be unsigned by default, when the declaration does not use either signed or unsigned

Compiler Option	Description
-fno-common	Makes the compiler place uninitialized global variables in the BSS section of the object file. This inhibits the merging of tentative definitions by the linker so you get a multiple-definition error if the same variable is accidentally defined in more than one compilation unit
-fstack-usage	This option is only used to build test for generation Ram/↔ Stack size report. Makes the compiler output stack usage information for the program, on a per-function basis
-fdump-ipa-all	This option is only used to build test for generation Ram/↔ Stack size report. Enables all inter-procedural analysis dumps
-c	Stop after assembly and produce an object file for each source file
-DS32K3XX	Predefine S32K3XX as a macro, with definition 1
-D \$ (DERIVATIVE)	Predefine S32K3's derivative as a macro, with definition 1. For example: Predefine for S32K344 will be -DS32K344.
-DGCC	Predefine GCC as a macro, with definition 1
-DUSE_SW_VECTOR_MODE	Predefine USE_SW_VECTOR_MODE as a macro, with definition 1. By default, the drivers are compiled to handle interrupts in Software Vector Mode
-DD_CACHE_ENABLE	Predefine D_CACHE_ENABLE as a macro, with definition 1. Enables data cache initialization in source file system.↔ c under the Platform driver
-DI_CACHE_ENABLE	Predefine I_CACHE_ENABLE as a macro, with definition 1. Enables instruction cache initialization in source file system.c under the Platform driver
-DENABLE_FPU	Predefine ENABLE_FPU as a macro, with definition 1. Enables FPU initialization in source file system.c under the Platform driver
-DMCAL_ENABLE_USER_MODE_SUPPORT	Predefine MCAL_ENABLE_USER_MODE_SUPPORT↔ RT as a macro, with definition 1. Allows drivers to be configured in user mode.
-sysroot=	Specifies the path to the sysroot, for Cortex-M7 it is /arm-none-eabi/newlib
-specs=nano.specs	Use Newlib nano specs
-specs=nosys.specs	Do not use printf/scanf

3.1.1.2 GCC Assembler Options

Assembler Option	Description
-Xassembler-with-cpp	Specifies the language for the following input files (rather than letting the compiler choose a default based on the file name suffix)
-mcpu=cortexm7	Targeted ARM processor for which GCC should tune the performance of the code
-mfpu=fpv5-sp-d16	Specifies the floating-point hardware available on the target
-mfloat-abi=hard	Specifies the floating-point ABI to use. "hard" allows generation of floating-point instructions and uses FPU-specific calling conventions
-mthumb	Generates code that executes in Thumb state

Assembler Option	Description
-c	Stop after assembly and produce an object file for each source file

3.1.1.3 GCC Linker Options

Linker Option	Description
-Wl,-Map,filename	Produces a map file
-T linkerfile	Use linkerfile as the linker script. This script replaces the default linker script (rather than adding to it)
-entry=Reset_Handler	Specifies that the program entry point is Reset_Handler
-nostartfiles	Do not use the standard system startup files when linking
-mcpu=cortexm7	Targeted ARM processor for which GCC should tune the performance of the code
-mthumb	Generates code that executes in Thumb state
-mfpv=fpv5-sp-d16	Specifies the floating-point hardware available on the target
-mfloat-abi=hard	Specifies the floating-point ABI to use. "hard" allows generation of floating-point instructions and uses FPU-specific calling conventions
-mlittle-endian	Generate code for a processor running in little-endian mode
-ggdb3	Produce debugging information for use by GDB using the most expressive format available, including GDB extensions if at all possible. Level 3 includes extra information, such as all the macro definitions present in the program
-lc	Link with the C library
-lm	Link with the Math library
-lgcc	Link with the GCC library
-specs=nano.specs	Use Newlib nano specs
-specs=nosys.specs	Do not use printf/scanf

3.1.2 DIAB Compiler/Assembler/Linker Options

3.1.2.1 DIAB Compiler Options

Compiler Option	Description
-tARMCORTEXM7MG:simple	Selects target processor (hardware single-precision, software double-precision floating-point)
-mthumb	Selects generating code that executes in Thumb state
-std=c99	Follows the C99 standard for C
-Oz	Like -O2 with further optimizations to reduce code size
-g	Generates DWARF 4.0 debug information
-fstandalone-debug	Emits full debug info for all types used by the program
-Wstrict-prototypes	Warn if a function is declared or defined without specifying the argument types
-Wsign-compare	Produce warnings when comparing signed type with unsigned type
-Wdouble-promotion	Give a warning when a value of type float is implicitly promoted to double

Compiler Option	Description
-Wunknown-pragmas	Issues a warning for unknown pragmas
-Wundef	Warns if an undefined identifier is evaluated in an <code>#if</code> directive. Such identifiers are replaced with zero
-Wextra	Enables some extra warning flags that are not enabled by '-Wall'
-Wall	Enables all of the most useful warnings (for historical reasons this option does not literally enable all warnings)
-pedantic	Emits a warning whenever the standard specified by the -std option requires a diagnostic
-Werror=implicit-function-declaration	Generates an error whenever a function is used before being declared
-fno-common	Compile common globals like normal definitions
-fno-signed-char	Char is unsigned
-fno-trigraphs	Do not process trigraph sequences
-V	Displays the current version number of the tool suite
-c	Stop after assembly and produce an object file for each source file
-DS32K3XX	Predefine S32K3XX as a macro, with definition 1
-D \$ (DERIVATIVE)	Predefine S32K3's derivative as a macro, with definition 1
-DDIAB	Predefine DIAB as a macro, with definition 1
-DUSE_SW_VECTOR_MODE	Predefine USE_SW_VECTOR_MODE as a macro, with definition 1. By default, the drivers are compiled to handle interrupts in Software Vector Mode
-DD_CACHE_ENABLE	Predefine D_CACHE_ENABLE as a macro, with definition 1. Enables data cache initialization in source file system.c under the Platform driver
-DI_CACHE_ENABLE	Predefine I_CACHE_ENABLE as a macro, with definition 1. Enables instruction cache initialization in source file system.c under the Platform driver
-DENABLE_FPU	Predefine ENABLE_FPU as a macro, with definition 1. Enables FPU initialization in source file system.c under the Platform driver
-DMCAL_ENABLE_USER_MODE_SUPPORT	Predefine MCAL_ENABLE_USER_MODE_SUPPORT as a macro, with definition 1. Allows drivers to be configured in user mode

3.1.2.2 DIAB Assembler Options

Assembler Option	Description
-mthumb	Selects generating code that executes in Thumb state
-Xpreprocess-assembly	Invokes C preprocessor on assembly files before running the assembler
-Xassembly-listing	Produces an .lst assembly listing file
-c	Stop after assembly and produce an object file for each source file
-tARMCORTEXM7MG:simple	Selects target processor (hardware single-precision, software double-precision floating-point)

3.1.2.3 DIAB Linker Options

Linker Option	Description
-e Reset_Handler	Make the symbol Reset_Handler be treated as a root symbol and the start label of the application
linker_script_file.dld	Use linker_script_file.dld as the linker script. This script replaces the default linker script (rather than adding to it)
-m30	m2 + m4 + m8 + m16
-Xstack-usage	Gathers and display stack usage at link time
-Xpreprocess-lecl	Perform pre-processing on linker scripts
-Llibrary_path	Points to the libraries location for ARMV7EMMG to be used for linking
-lc	Links with the standard C library
-lm	Links with the math library
-tARMCORTEXM7MG:simple	Selects target processor (hardware single-precision, software double-precision floating-point)

3.1.3 GHS Compiler/Assembler/Linker Options

3.1.3.1 GHS Compiler Options

Compiler Option	Description
-cpu=cortexm7	Selects target processor: Arm Cortex M7
-thumb	Selects generating code that executes in Thumb state
-fpu=vfpv5_d16	Specifies hardware floating-point using the v5 version of the VFP instruction set, with 16 double-precision floating-point registers
-fsingle	Use hardware single-precision, software double-precision FP instructions
-C99	Use (strict ISO) C99 standard (without extensions)
-ghstd=last	Use the most recent version of Green Hills Standard mode (which enables warnings and errors that enforce a stricter coding standard than regular C and C++)
-Osize	Optimize for size
-gnu_asm	Enables GNU extended asm syntax support
-dual_debug	Generate DWARF 2.0 debug information
-G	Generate debug information
-keeptempfiles	Prevents the deletion of temporary files after they are used. If an assembly language file is created by the compiler, this option will place it in the current directory instead of the temporary directory
-Wimplicit-int	Produce warnings if functions are assumed to return int
-Wshadow	Produce warnings if variables are shadowed
-Wtrigraphs	Produce warnings if trigraphs are detected
-Wundef	Produce a warning if undefined identifiers are used in #if preprocessor statements

Compiler Option	Description
-unsigned_chars	Let the type char be unsigned, like unsigned char
-unsigned_fields	Bitfields declared with an integer type are unsigned
-no_commons	Allocates uninitialized global variables to a section and initializes them to zero at program startup
-no_exceptions	Disables C++ support for exception handling
-no_slash_comment	C++ style // comments are not accepted and generate errors
-prototype_errors	Controls the treatment of functions referenced or called when no prototype has been provided
-incorrect_pragma_warnings	Controls the treatment of valid #pragma directives that use the wrong syntax
-c	Stop after assembly and produce an object file for each source file
-DS32K3XX	Predefine S32K3XX as a macro, with definition 1
-D \$ (DERIVATIVE)	Predefine S32K3's derivative as a macro, with definition 1. For example: Predefine for S32K344 will be -DS32K344.
-DGHS	Predefine GHS as a macro, with definition 1
-DUSE_SW_VECTOR_MODE	Predefine USE_SW_VECTOR_MODE as a macro, with definition 1. By default, the drivers are compiled to handle interrupts in Software Vector Mode
-DD_CACHE_ENABLE	Predefine D_CACHE_ENABLE as a macro, with definition 1. Enables data cache initialization in source file system.↵c under the Platform driver
-DI_CACHE_ENABLE	Predefine I_CACHE_ENABLE as a macro, with definition 1. Enables instruction cache initialization in source file system.c under the Platform driver
-DENABLE_FPU	Predefine ENABLE_FPU as a macro, with definition 1. Enables FPU initialization in source file system.c under the Platform driver
-DMCAL_ENABLE_USER_MODE_SUPPORT	Predefine MCAL_ENABLE_USER_MODE_SUPPORT↵RT as a macro, with definition 1. Allows drivers to be configured in user mode

3.1.3.2 GHS Assembler Options

Assembler Option	Description
-cpu=cortexm7	Selects target processor: Arm Cortex M7
-fpu=vfpv5_d16	Specifies hardware floating-point using the v5 version of the VFP instruction set, with 16 double-precision floating-point registers
-fsingle	Use hardware single-precision, software double-precision FP instructions
-preprocess_assembly_files	Controls whether assembly files with standard extensions such as .s and .asm are preprocessed
-list	Creates a listing by using the name and directory of the object file with the .lst extension
-c	Stop after assembly and produce an object file for each source file

3.1.3.3 GHS Linker Options

Linker Option	Description
-e Reset_Handler	Make the symbol Reset_Handler be treated as a root symbol and the start label of the application
-T linker_script_file.ld	Use linker_script_file.ld as the linker script. This script replaces the default linker script (rather than adding to it)
-map	Produce a map file
-keepmap	Controls the retention of the map file in the event of a link error
-Mn	Generates a listing of symbols sorted alphabetically/numerically by address
-delete	Instructs the linker to remove functions that are not referenced in the final executable. The linker iterates to find functions that do not have relocations pointing to them and eliminates them
-ignore_debug_references	Ignores relocations from DWARF debug sections when using -delete. DWARF debug information will contain references to deleted functions that may break some third-party debuggers
-Llibrary_path	Points to library_path (the libraries location) for thumb2 to be used for linking
-larch	Link architecture specific library
-lstartup	Link run-time environment startup routines. The source code for the modules in this library is provided in the src/libstartup directory
-lind_sd	Link language-independent library, containing support routines for features such as software floating point, run-time error checking, C99 complex numbers, and some general purpose routines of the ANSI C library
-v	Prints verbose information about the activities of the linker, including the libraries it searches to resolve undefined symbols
-keep=C40_Ip_AccessCode	Avoid linker remove function C40_Ip_AccessCode from Fls module because it is not referenced explicitly
-nostartfiles	Controls the start files to be linked into the executable

3.1.4 IAR Compiler/Assembler/Linker Options

3.1.4.1 IAR Compiler Options

Compiler Option	Description
-cpu Cortex-M7	Targeted ARM processor for which IAR should tune the performance of the code
-cpu_mode thumb	Generates code that executes in Thumb state
-endian little	Generate code for a processor running in little-endian mode
-fpu VFPv5-SP	Use this option to generate code that performs floating-point operations using a Floating Point Unit (FPU). Single-precision variant.
-e	Enables all IAR C language extensions
-Ohs	Optimize for size. the compiler will emit AEABI attributes indicating the requested optimization goal. This information can be used by the linker to select smaller or faster variants of DLIB library functions
-debug	Makes the compiler include debugging information in the object modules. Including debug information will make the object files larger

Compiler Option	Description
-no_clustering	Disables static clustering optimizations. Static and global variables defined within the same module will not be arranged so that variables that are accessed in the same function are close to each other
-no_mem_idioms	Makes the compiler not optimize certain memory access patterns
-do_explicit_zero_opt_in_named_sections	Disable the exception for variables in user-named sections, and thus treat explicit initializations to zero as zero initializations, not copy initializations
-require_prototypes	Force the compiler to verify that all functions have proper prototypes. Generates an error otherwise
-no_wrap_diagnostics	Does not wrap long lines in diagnostic messages
-diag_suppress Pa050	Suppresses diagnostic message Pa050
-DS32K3XX	Predefine S32K3XX as a macro, with definition 1
-D \$ (DERIVATIVE)	Predefine S32K3's derivative as a macro, with definition 1. For example: Predefine for S32K344 will be -DS32K344.
-DIAR	Predefine IAR as a macro, with definition 1
-DUSE_SW_VECTOR_MODE	Predefine USE_SW_VECTOR_MODE as a macro, with definition 1. By default, the drivers are compiled to handle interrupts in Software Vector Mode.
-DD_CACHE_ENABLE	Predefine D_CACHE_ENABLE as a macro, with definition 1. Enables data cache initialization in source file system.c under the Platform driver
-DI_CACHE_ENABLE	Predefine I_CACHE_ENABLE as a macro, with definition 1. Enables instruction cache initialization in source file system.c under the Platform driver
-DENABLE_FPU	Predefine ENABLE_FPU as a macro, with definition 1. Enables FPU initialization in source file system.c under the Platform driver
-DMCAL_ENABLE_USER_MODE_SUPPORT	Predefine MCAL_ENABLE_USER_MODE_SUPPORT as a macro, with definition 1. Allows drivers to be configured in user mode.

3.1.4.2 IAR Assembler Options

Assembler Option	Description
-cpu Cortex-M7	Targeted ARM processor for which IAR should generate the instruction set
-fpu VFPv5-SP	Use this option to generate code that performs floating-point operations using a Floating Point Unit (FPU). Single-precision variant.
-cpu_mode thumb	Selects the thumb mode for the assembler directive CODE
-g	Disables the automatic search for system include files
-r	Generates debug information

3.1.4.3 IAR Linker Options

Linker Option	Description
-map filename	Produces a map file
-config linkerfile	Use linkerfile as the linker script. This script replaces the default linker script (rather than adding to it)
-cpu=Cortex-M7	Selects the ARM processor variant to link the application for
-fpu VFPv5-SP	Use this option to generate code that performs floating-point operations using a Floating Point Unit (FPU). Single-precision variant.
-entry _start	Treats _start as a root symbol and start label
-enable_stack_usage	Enables stack usage analysis. If a linker map file is produced, a stack usage chapter is included in the map file
-skip_dynamic_initialization	Dynamic initialization (typically initialization of C++ objects with static storage duration) will not be performed automatically during application startup
-no_wrap_diagnostics	Does not wrap long lines in diagnostic messages

3.2 Files required for compilation

This section describes the include files required to compile, assemble and link the AUTOSAR CanTrcv Driver for S32 microcontrollers.

To avoid integration of incompatible files, all the include files from other modules shall have the same AR_MAJOR_VERSION and AR_MINOR_VERSION, i.e. only files with the same AUTOSAR major and minor versions can be compiled.

3.2.0.0.1 CanTrcv Driver Files:

- CanTrcv_43_AE_TS_T40D34M30I0R0\src\AeCanPHY_HwAccess.c
- CanTrcv_43_AE_TS_T40D34M30I0R0\src\AeCanPHY_Ip.c
- CanTrcv_43_AE_TS_T40D34M30I0R0\src\CanTrcv_43_AE.c
- CanTrcv_43_AE_TS_T40D34M30I0R0\src\CanTrcv_43_AE_Ipw.c
- CanTrcv_43_AE_TS_T40D34M30I0R0\include\AeCanPHY_HwAccess.h
- CanTrcv_43_AE_TS_T40D34M30I0R0\include\AeCanPHY_Ip.h
- CanTrcv_43_AE_TS_T40D34M30I0R0\include\AeCanPHY_Ip_Types.h
- CanTrcv_43_AE_TS_T40D34M30I0R0\include\CanTrcv_43_AE.h
- CanTrcv_43_AE_TS_T40D34M30I0R0\include\CanTrcv_43_AE_Ipw.h
- CanTrcv_43_AE_TS_T40D34M30I0R0\include\CanTrcv_43_AE_Ipw_Types.h
- CanTrcv_43_AE_TS_T40D34M30I0R0\include\CanTrcv_43_AE_Types.h

3.2.0.0.2 CanTrcv Driver Generated Files (must be generated by the user using a configuration tool):

- AeCanPHY_Ip_Cfg.h
- AeCanPHY_Ip_CfgDefines.h
- CanTrcv_43_AE_Cfg.h
- CanTrcv_43_AE_Ipw_Cfg.h
- AeCanPHY_Ip_[VariantName]_PBcfg.h
- CanTrcv_43_AE_Ipw_[VariantName]_PBcfg.h
- CanTrcv_43_AE_[VariantName]_PBcfg.h
- AeCanPHY_Ip_[VariantName]_PBcfg.c
- CanTrcv_43_AE_Ipw_[VariantName]_PBcfg.c
- CanTrcv_43_AE_[VariantName]_PBcfg.c

Note

As a deviation from the standard:

- AeCanPHY_Ip_[VariantName]_PBcfg.c, CanTrcv_43_AE_Ipw_[VariantName]_PBcfg.c, CanTrcv_43_AE_[VariantName]_PBcfg.c - These files will contain the definition for all parameters, independent of the configuration class that will be selected (PC, LT, PB)

3.2.0.0.3 Spi Files:

- Spi_TS_T40D34M30I0R0\include\Spi.h
- Spi_TS_T40D34M30I0R0\src\Spi.c
- Spi_TS_T40D34M30I0R0\src\Lpspi_Ip.c
- Spi_TS_T40D34M30I0R0\include\Lpspi_Ip.h

3.2.0.0.4 AE Driver Files:

- Ae_TS_T40D34M30I0R0\src\Ae.c
- Ae_TS_T40D34M30I0R0\src\Ae_Ipw.c
- Ae_TS_T40D34M30I0R0\src\Aec_Ip.c
- Ae_TS_T40D34M30I0R0\src\Ae_Ip_Hw_Access.c
- Ae_TS_T40D34M30I0R0\include\Hvm_Ip_Hw_Access.c
- Ae_TS_T40D34M30I0R0\include\Hvm_Ip.c
- Ae_TS_T40D34M30I0R0\include\Ae.h

- Ae_TS_T40D34M30I0R0\include\Ae_Ipw.h
- Ae_TS_T40D34M30I0R0\include\Aec_Ip.h
- Ae_TS_T40D34M30I0R0\include\Aec_Ip_Types.h
- Ae_TS_T40D34M30I0R0\include\Aec_Ip_Hw_Access.h
- Ae_TS_T40D34M30I0R0\include\Hvm_Ip_Hw_Access.h
- Ae_TS_T40D34M30I0R0\include\Hvm_Ip.h
- Ae_TS_T40D34M30I0R0\include\Hvm_Ip_Types.h

3.2.0.0.5 BaseNXP Files:

- BaseNXP_TS_T40D34M30I0R0\include\Can_GeneralTypes.h
- BaseNXP_TS_T40D34M30I0R0\include\Mcal.h
- BaseNXP_TS_T40D34M30I0R0\include\CanTrcv_43_AE_MemMap.h
- BaseNXP_TS_T40D34M30I0R0\include\Platform_Types.h
- BaseNXP_TS_T40D34M30I0R0\include\Soc_Ips.h
- BaseNXP_TS_T40D34M30I0R0\include\Std_Types.h
- BaseNXP_TS_T40D34M30I0R0\include\OsIf.h
- BaseNXP_TS_T40D34M30I0R0\generate_PC\include\modules.h

3.2.0.0.6 DEM Files:

- Dem_TS_T40D34M30I0R0\include\Dem.h
- Dem_TS_T40D34M30I0R0\include\Dem_Types.h
- Dem_TS_T40D34M30I0R0\generate_PC\include\Dem_IntErrId.h
- Dem_TS_T40D34M30I0R0\src\Dem.c

3.2.0.0.7 DET Files:

- Det_TS_T40D34M30I0R0\include\Det.h
- Det_TS_T40D34M30I0R0\src\Det.c

3.2.0.0.8 RTE Files:

- Rte_TS_T40D34M30I0R0\include\SchM_CanTrcv_43_AE.h
- Rte_TS_T40D34M30I0R0\src\SchM_CanTrcv_43_AE.c

3.2.0.0.9 CanIf Files:

- CanIf_TS_T40D34M30I0R0\include\CanIf_CanTrcv.h

3.2.0.0.10 EcuM Files:

- EcuM_TS_T40D34M30I0R0\include\EcuM.h
- EcuM_TS_T40D34M30I0R0\src\EcuM.c

3.3 Setting up the plugins

The CanTrcv Driver was designed to be configured by using the EB Tresos Studio (version 27.1.0 b200625-0900 or later)

3.3.0.0.1 Location of various files inside the CanTrcv module folder:

- VSMD (Vendor Specific Module Definition) file in EB Tresos Studio XDM format:
 - CanTrcv_43_AE_TS_T40D34M30I0R0\config\CanTrcv_43_AE.xdm
- VSMD (Vendor Specific Module Definition) file(s) in AUTOSAR compliant EPD format:
 - CanTrcv_43_AE_TS_T40D34M30I0R0\autosar\CanTrcv_43_AE_<subderivative_name>.epd
- Code Generation Templates for variant aware parameters:
 - CanTrcv_43_AE_TS_T40D34M30I0R0\generate_PB\src\AeCanPHY_Ip_PBcfg.c
 - CanTrcv_43_AE_TS_T40D34M30I0R0\generate_PB\src\CanTrcv_43_AE_Ipw_PBcfg.c
 - CanTrcv_43_AE_TS_T40D34M30I0R0\generate_PB\src\CanTrcv_43_AE_PBcfg.h
 - CanTrcv_43_AE_TS_T40D34M30I0R0\generate_PB\include\AeCanPHY_Ip_PBcfg.h
 - CanTrcv_43_AE_TS_T40D34M30I0R0\generate_PB\include\CanTrcv_43_AE_Ipw_PBcfg.h
 - CanTrcv_43_AE_TS_T40D34M30I0R0\generate_PB\include\CanTrcv_43_AE_PBcfg.h
- Code Generation Templates for parameters without variation points:
 - CanTrcv_43_AE_TS_T40D34M30I0R0\generate_PC\include\AeCanPHY_Ip_Cfg.h
 - CanTrcv_43_AE_TS_T40D34M30I0R0\generate_PC\include\AeCanPHY_Ip_CfgDefines.h
 - CanTrcv_43_AE_TS_T40D34M30I0R0\generate_PC\include\CanTrcv_43_AE_Cfg.h
 - CanTrcv_43_AE_TS_T40D34M30I0R0\generate_PC\include\CanTrcv_43_AE_Ipw_Cfg.h

3.3.0.0.2 Steps to generate the configuration:

1. Copy the following module folders into the Tresos plugins folder:
 - CanTrcv_43_AE_TS_T40D34M30I0R0
 - Ae_TS_T40D34M30I0R0
 - Spi_TS_T40D34M30I0R0
 - BaseNXP_TS_T40D34M30I0R0
 - Dem_TS_T40D34M30I0R0
 - Det_TS_T40D34M30I0R0
 - EcuC_TS_T40D34M30I0R0
 - Rte_TS_T40D34M30I0R0
 - Resource_TS_T40D34M30I0R0
 - Mcu_TS_T40D34M30I0R0
 - CanIf_TS_T40D34M30I0R0
 - EcuM_TS_T40D34M30I0R0
2. Set the desired Tresos Output location folder for the generated sources and header files.
3. Use the EB Tresos Studio GUI to modify ECU configuration parameters values.
4. Generate the configuration files

Chapter 4

Function calls to module

- [Function Calls during Start-up](#)
- [Function Calls during Shutdown](#)
- [Function Calls during Wake-up](#)

4.1 Function Calls during Start-up

The CanTrcv Driver shall be initialized through the CanTrcv_43_AE_Init API function. The Mcu, Port, Spi, Ae drivers shall be initialized beforehand.

4.2 Function Calls during Shutdown

None.

4.3 Function Calls during Wake-up

If the Transceiver enables Wakeup(CanTrcvWakeupByBusUsed) and CanTrcvWakeupSourceRef, the CanTrcv shall report the wakeup event to EcuM through EcuM_CheckWakeupEvent upon a wakeup event(Wake Up Pattern) by calling of CanTrcv_CheckWakeup and CanTrcv_MainFunction.

The main function CanTrcv_MainFunction shall be called by BSW scheduler and CanTrcv_CheckWakeup by CanIf.

Chapter 5

Module requirements

- Exclusive areas to be defined in BSW scheduler
- unavailable_exclusive_areas
- Peripheral Hardware Requirements
- ISR to configure within AutosarOS - dependencies
- ISR Macro
- Other AUTOSAR modules - dependencies
- Data Cache Restrictions
- User Mode support
- Multicore Support

5.1 Exclusive areas to be defined in BSW scheduler

No exclusive areas have been identified.

5.2 Peripheral Hardware Requirements

None.

5.3 ISR to configure within AutosarOS - dependencies

None.

5.4 ISR Macro

RTD drivers use the ISR macro to define the functions that will process hardware interrupts. Depending on whether the OS is used or not, this macro can have different definitions.

5.4.1 Without an Operating System The macro `USING_OS_AUTOSAROS` must not be defined.

5.4.1.1 Using Software Vector Mode

The macro `USE_SW_VECTOR_MODE` must be defined and the ISR macro is defined as:

```
#define ISR(IsrName) void IsrName(void)
```

In this case, the drivers' interrupt handlers are normal C functions and their prologue/epilogue will handle the context save and restore.

5.4.1.2 Using Hardware Vector Mode

The macro `USE_SW_VECTOR_MODE` must not be defined and the ISR macro is defined as:

```
#define ISR(IsrName) INTERRUPT_FUNC void IsrName(void)
```

In this case, the drivers' interrupt handlers must also handle the context save and restore.

5.4.2 With an Operating System Please refer to your OS documentation for description of the ISR macro.

5.5 Other AUTOSAR modules - dependencies

- **Port:** Needed to configure the pins to be used by the Spi and Ae drivers for accessing(read/write) to CANPHY in AE, and pins of CAN controller which connects fixly to CANPHY in AE.
- **DET:** Needed for detecting and reporting development errors and runtime errors.
- **DEM:** Needed for detecting and reporting extended production errors.
- **RTE:** Needed for implementing data consistency through exclusive areas.
- **MCU:** Needed to configure the clocks to be used by the Spi and Ae drivers for accessing(read/write) to CANPHY in AE.
- **EcuC:** Needed to retrieve information about post-build variants.
- **Base:** Needed for common files/definitions which are used by all RTD modules.
- **OS:** Needed to define a mapping between EcuC partitions and EcuC core ids when multicore support is enabled.
- **CanIf:** The callbacks `CanIf_TrsvModeIndication` are used to notify the upper layer after the requested mode has been reached. The callback `CanIf_CheckTrsvWakeFlagIndication` is used to notify the upper layer when `CanTrsv_43_AE_CheckWakeFlag` was called and no wake flags set.
- **Can:** Needed if expected to work with CANPHY in AE.
- **EcuM:** Gets information about wake up events from CAN transceiver driver via CanIf.
- **Spi:** Used to access CANPHY via Ae driver.
- **Ae:** Uses Spi to access to CANPHY.

5.6 Data Cache Restrictions

None.

5.7 User Mode support

- [User Mode configuration in the module](#)
- [User Mode configuration in AutosarOS](#)

5.7.1 User Mode configuration in the module User mode needs to be configured in SPI driver that is used to access to CANPHY registers.

5.7.2 User Mode configuration in AutosarOS

When User mode is enabled, the driver may has the functions that need to be called as trusted functions in AutosarOS context. Those functions are already defined in driver and declared in the header `<IpName>_IpTrustedFunctions.h`. This header also included all headers files that contains all types definition used by parameters or return types of those functions. Refer the chapter [User Mode configuration in the module](#) for more detail about those functions and the name of header files they are declared inside. Those functions will be called indirectly with the naming convention below in order to AutosarOS can call them as trusted functions.

```
Call_<Function_Name>_TRUSTED(parameter1,parameter2,...)
```

That is the result of macro expansion `OsIf_Trusted_Call` in driver code:

```
#define OsIf_Trusted_Call[1-6params](name,param1,...,param6) Call_##name##_TRUSTED(param1,...,param6)
```

So, the following steps need to be done in AutosarOS:

- Ensure `MCAL_ENABLE_USER_MODE_SUPPORT` macro is defined in the build system or somewhere global.
- Define and declare all functions that need to call as trusted functions follow the naming convention above in Integration/User code. They need to visible in `Os.h` for the driver to call them. They will do the marshalling of the parameters and call `CallTrustedFunction()` in OS specific manner.
- `CallTrustedFunction()` will switch to privileged mode and call `TRUSTED_<Function_Name>()`.
- `TRUSTED_<Function_Name>()` function is also defined and declared in Integration/User code. It will un-marshalling of the parameters to call `<Function_Name>()` of driver. The `<Function_Name>()` functions are already defined in driver and declared in `<IpName>_IpTrustedFunctions.h`. This header should be included in OS for OS call and indexing these functions.

Module requirements

See the sequence chart below for an example calling `Linflexd_Uart_Ip_Init_Privileged()` as a trusted function.

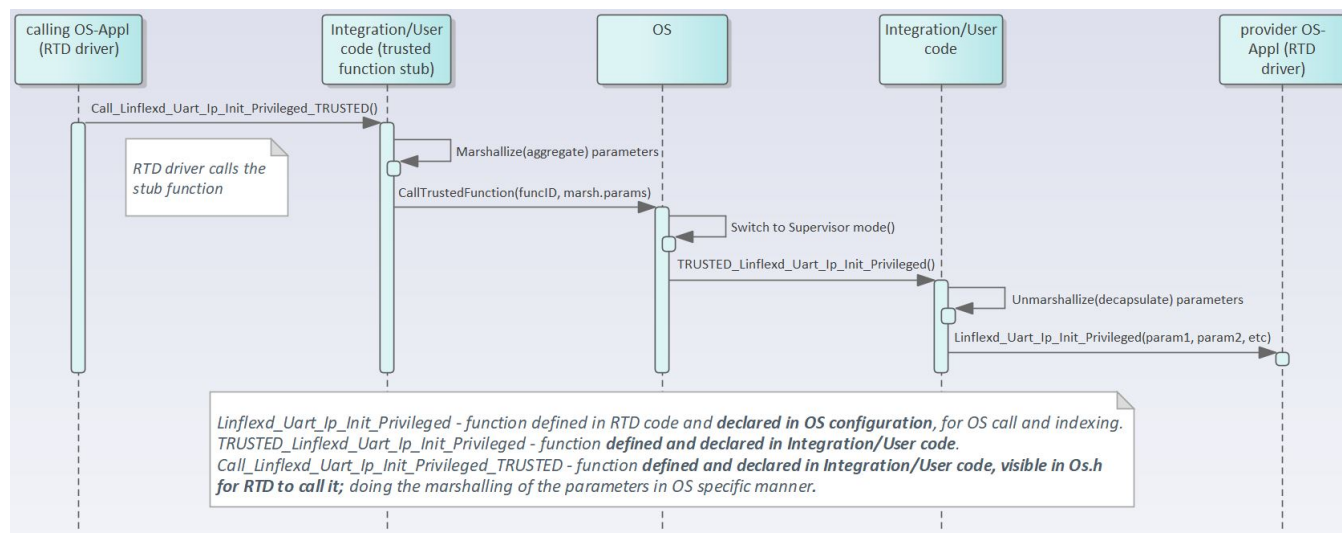


Figure 5.1 Example sequence chart for calling **Linflexd_Uart_Ip_Init_Privileged** as trusted function

5.8 Multicore Support

None.

Chapter 6

Main API Requirements

- [Main function calls within BSW scheduler](#)
- [API Requirements](#)
- [Calls to Notification Functions, Callbacks, Callouts](#)

6.1 Main function calls within BSW scheduler

The CanTrcv Driver supports 2 main functions that can be configured to be scheduled by the BSW Scheduler:

```
void CanTrcv_43_AE_MainFunction(void);
```

This function scans transceivers for wake up event and reports such event. Calls *EcuM_SetWakeupEvent* when wakeup event was detected.

```
void CanTrcv_43_AE_MainFunctionDiagnostics(void);
```

This function scans transceivers for system errors(dominant timeout, invalid state). Calls *Dem_SetEventStatus* to report status of Transceiver.

6.2 API Requirements

None

6.3 Calls to Notification Functions, Callbacks, Callouts

The CanTrcv Driver provides no configurable notification functions, callbacks, or callouts.

Chapter 7

Memory allocation

- [Sections to be defined in CanTrcv_43_AE_MemMap.h](#)
- [Linker command file](#)

7.1 Sections to be defined in CanTrcv_43_AE_MemMap.h

Section Name	Section Type	Description
CANTRCV_43_AE_START_SEC_CONFIG_DATA_UNSPECIFIED↔	Configuration Data	Start of Memory Section for Config Data
CANTRCV_43_AE_STOP_SEC_CONFIG_DATA_UNSPECIFIED↔	Configuration Data	End of Memory Section for Config Data
CANTRCV_43_AE_START_SEC_CODE↔	Code	Start of Memory Section for Code
CANTRCV_43_AE_STOP_SEC_CODE	Code	End of Memory Section for Code
CANTRCV_43_AE_START_SEC_VARIABLES_CLEARED_UNSPECIFIED↔	Variables	Used for variables, structures, arrays when the SIZE (alignment) does not fit the criteria of 8, 16 or 32 bit. These variables are never cleared and never initialized by start-up code
CANTRCV_43_AE_STOP_SEC_VARIABLES_CLEARED_UNSPECIFIED↔	Variables	End of the above section
CANTRCV_43_AE_START_SEC_VARIABLES_CLEARED_UNSPECIFIED_NO_CACHEABLE↔	Variables	Used for variables, structures, arrays when the SIZE (alignment) does not fit the criteria of 8, 16 or 32 bit. Normally, this section is used to store descriptors and data buffers. This section must also be cache inhibited
CANTRCV_43_AE_STOP_SEC_VARIABLES_CLEARED_UNSPECIFIED_NO_CACHEABLE↔	Variables	End of the above section
CANTRCV_43_AE_START_SEC_VARIABLES_CLEARED_32↔	Variables	Used for variables which have to be aligned to 32 bits. For instance used for 32-bits variables or used for composite data types (arrays, structs) containing elements of maximum 32 bits. These variables are cleared to zero by start-up code.

Section Name	Section Type	Description
CANTRCV_43_AE_STOP_SEC_VAR↵ _CLEARED_32	Variables	End of the above section
CANTRCV_43_AE_START_SEC_C↵ ONST_32	Constants	Used for constants that have to be aligned to 32 bits
CANTRCV_43_AE_STOP_SEC_CO↵ NST_32	Constants	End of the above section

7.2 Linker command file

Memory shall be allocated for every section defined in the driver's "<Module>"_MemMap.h.



Chapter 8

Integration Steps

This section gives a brief overview of the steps needed for integrating this module:

1. Generate the required module configuration(s). For more details refer to section [Files Required for Compilation](#)
2. Allocate the proper memory sections in the driver's memory map header file ("`<Module>_MemMap.h`") and linker command file. For more details refer to section [Sections to be defined in `<Module>_MemMap.h`](#)
3. Compile & build the module with all the dependent modules. For more details refer to section [Building the Driver](#)

Chapter 9

External assumptions for driver

The section presents requirements that must be complied with when integrating the CANTRCV_PHY_AE driver into the application.

External Assumption Req ID	External Assumption Text
SWS_CanTrcv_00163	Name: CanTrcv_TrcvModeType Kind: Enumeration Range: CANTRCV_TRCVMODE_SLEEP: -: Transceiver mode SLEEP CANTRCV_TRCVMODE_STANDBY: -: Transceiver mode STANDBY CANTRCV_TRCVMODE_NORMAL: 0x00: Transceiver mode NORMAL Description: Operating modes of the CAN Transceiver Driver. Available via: Can_GeneralTypes.h Note: Implemented in Base module
SWS_CanTrcv_00164	Name: CanTrcv_TrcvWakeupModeType Kind: Enumeration Range: CANTRCV_WUMODE_ENABLE: 0x00: The notification for wakeup events is enabled on the addressed transceiver. CANTRCV_WUMODE_DISABLE: 0x01: The notification for wakeup events is disabled on the addressed transceiver. CANTRCV_WUMODE_CLEAR: 0x02: A stored wakeup event is cleared on the addressed transceiver. Description: This type shall be used to control the CAN transceiver concerning wake up events and wake up notifications. Available via: Can_GeneralTypes.h Note: Implemented in Base module
SWS_CanTrcv_00165	Name: CanTrcv_TrcvWakeupReasonType Kind: Enumeration Range: CANTRCV_WU_ERROR: 0x00: Due to an error wake up reason was not detected. This value may only be reported when error was reported to DEM before. CANTRCV_WU_NOT_SUPPORTED: 0x01: The transceiver does not support any information for the wake up reason. CANTRCV_WU_BY_BUS: 0x02: The transceiver has detected, that the network has caused the wake up of the ECU. CANTRCV_WU INTERNALLY: 0x03: The transceiver has detected, that the network has woken up by the ECU via a request to NORMAL mode. CANTRCV_WU_RESET: 0x04: The transceiver has detected, that the "wake up" is due to an ECU reset. CANTRCV_WU_POWER_ON: 0x05: The transceiver has detected, that the "wake up" is due to an ECU reset after power on. CANTRCV_WU_BY_PIN: 0x06: The transceiver has detected a wake-up event at one of the transceiver's pins (not at the CAN bus). CANTRCV_WU_BY_SYSERR: 0x07: The transceiver has detected, that the wake up of the ECU was caused by a HW related device failure. Description: This type denotes the wake up reason detected by the CAN transceiver in detail. Available via: Can_GeneralTypes.h Note: Implemented in Base module

External assumptions for driver

External Assumption Req ID	External Assumption Text
EA_RTD_00071	If interrupts are locked, a centralized function pair to lock and unlock interrupts shall be used.
EA_RTD_00081	The integrator shall assure that <MSN>_Init() and <MSN>_DeInit() functions do not interrupt each other.
EA_RTD_00082	When caches are enabled and data buffers are allocated in cacheable memory regions the buffers involved in DMA transfer shall be aligned with both start and end to cache line size. Note: Rationale: This ensures that no other buffers/variables compete for the same cache lines.
EA_RTD_00113	When RTD drivers are integrated with AutosarOS and User mode support is enabled, the integrator shall assure that the definition and declaration of all RTD functions needed to be called as trusted functions follow the naming convention Call<Function_Name>TRUSTED(parameter1,parameter2,...) in Integration/User code. They need to be visible in Os.h for the driver to call them. They will call RTD <Function_Name>() as trusted functions in OS specific manner.

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