

# Bosch's CAN bus Investigation of the standard

Meryem Can Stephan Fahrenkrog-Petersen Jakob Rüßler Thomas Schlegel Daniel Titz Duc Anh Tran

July 19, 2016

### **CONTENT**

INTRODUCTION

**DOCUMENTATION** 

**MESSAGES** 

CODING / ERRORS

FAULT CONFINEMENT

**BIT TIMING** 

**CAN OSCILLATOR** 

CONCLUSION

#### INTRODUCTION AND BASIC CONCEPTS

- ► Controller Area Network
- Serial communications protocol/bus system
- ► Supports distributed realtime control with a very high level of security [1]

#### PURPOSE AND CONTEXT

- ► Created by BOSCH
- Used in the automotive industry, automation engineering, medical technology, aerospace engineering
- Connecting automotive electronics, engine control units, sensors, anti-skid-systems
- ► High speed networks to low cost multiplex wiring

#### RELATED STANDARDS

- standardized after ISO 11898.
- ► ISO 11898-2 (Highspeed-CAN) related
- ► ISISO 11898-3 (Lowspeed-CAN)- related
- ► Not compitable with each other

#### **HIGHER STANDARDS**

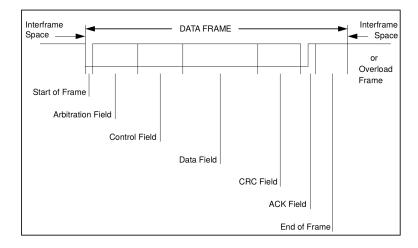
- Þ
- ▶
- Þ
- •

### Message Transfer and Validation – 1

#### Overview:

- ► Information is sent in fixed format messages of different but limited lengths
- When free, any connected unit may send messages over the bus
- ► The content of the message is named by an identifier

#### Message Transfer and Validation – 2



### Message Transfer and Validation – 3

- ► A unit sending a message is the "transmitter" of that message
- ► It stays transmitter, until the bus is idle or it loses arbitration
- ► A unit is called "receiver" of a message, if it is not the transmitter and the bus is not idle

### CODING AND ERROR HANDLING - 1

#### Overview:

- ▶ Bit stuffing → control mechanism
- ▶ Distortions etc. → error handling to achieve error tolerance
- ► 5 different error types (Bit, Stuff, CRC, Form, ACK)

#### CODING AND ERROR HANDLING - 2

- Message passing mechanism, no additional structure needed
- Errors broadcasted when detected
- ► Semantics important for correct transmission
- ► Drivers: reliability, error limitation
- ► Problem: new error types?

### FAULT CONFINEMENT

- ▶ Unit can have 3 states and 2 counters
- ► Strength: Enables extensibility
- ► Drivers: Seperation of concern, reliability, error limitation
- ▶ Problem: More Unit means more errors?

Introduction Documentation Messages Coding / Errors Fault Confinement Bit Timing CAN Oscillator

## BIT TIMING REQUIREMENTS

- ► List of definitions and rules
- ► Strength: short, but includes everything important
- ► Weaknesses: almost text only, hard to read (structure), like a glossary
- ► Improvable by usage of more pictures and examples

## **CAN IMPROVEMENTS**

# CONCLUSION

### REFERENCES



# Robert Bosch GmbH. CAN Specification.

http://www.bosch-semiconductors.de/media/ubk\_semiconductors/pdf\_1/canliteratur/can2spec.pdf. Last accessed: July 16, 2016.