

The image displays two top-down views of a custom PCB layout. The top view shows a populated board with components like a LoPy4, 8uOS, and various connectors. The bottom view shows the same board with different component placements and labels like 'A' and '120R'.

Contents

Contents.....	2
Revision History	3
1. Product Introduction	4
1.1 Product Features.....	4
1.2 Product Dimensions.....	4
2. Peripheral Interface	5
2.1 Pinout.....	5
2.2 Interface Description	6
3. Optional Wiring Diagram.....	7
4. Product Display	8
5. Firmware Description.....	10
5.1 Firmware Source Code	10
5.2 Firmware Update.....	10
5.3 Klipper Configuration	10
6. Precautions.....	11

Revision History

Version	Revision Description	Date
01.00	First Draft	2022/04/23
01.01	Add more detailed pinout diagram	2022/11/25

1. Product Introduction

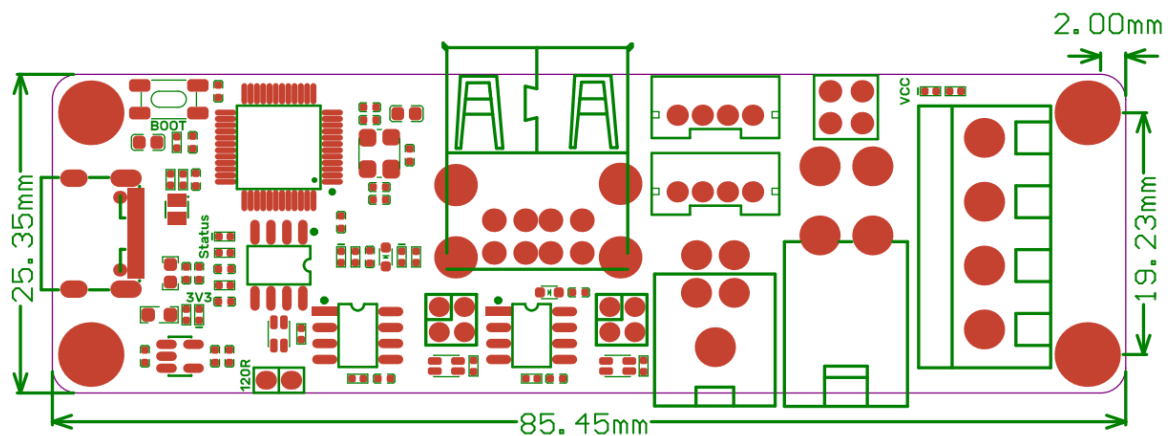
BIGTREETECH U2C is a USB to CAN bus module, which can convert the USB port of Raspberry Pi to the CAN bus, and connect 3D printing motherboard, BIGTREETECH EBB35/36/42 CAN and other products through CAN bus. There are many different forms of CAN interfaces on the board, which are helpful to connect to different boards.

CAN bus has many advantages in the field of industrial control, so our company has launched this USB to CAN module. The CAN bus has a long transmission distance, and a large number of nodes can be mounted on it, so the motherboard, EBB, and other expansion boards can be mounted on the same CAN bus at the same time.

1.1 Product Features

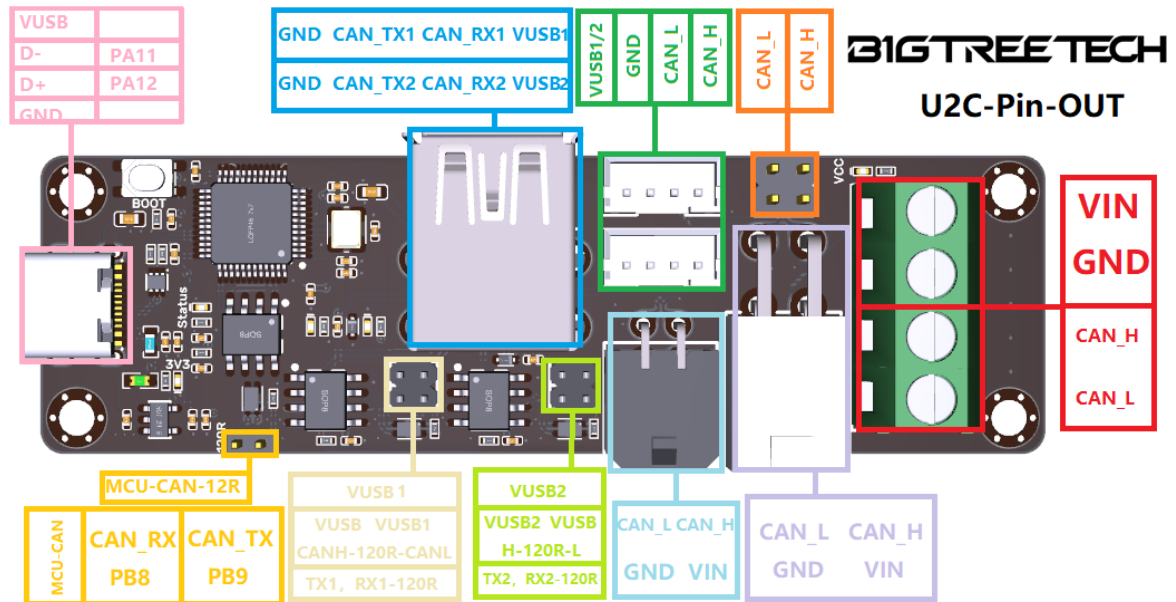
1. Support CAN bus connection, long data transmission, strong anti-noise ability, strong real-time performance and high reliability.
2. The surface of the PCB adopts the ENIG process.
3. The TYPE-C port is equipped with ESD protection to prevent static electricity from damaging the hardware.
4. Support firmware update for the motherboard through SWD or hardware DFU.
5. More than on CAN interface.

1.2 Product Dimensions

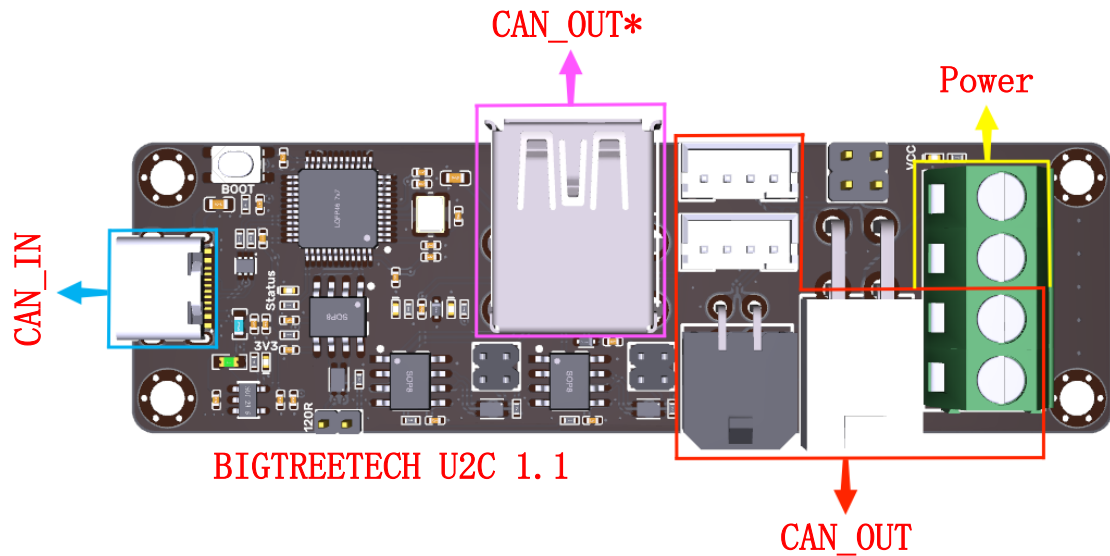


2. Peripheral Interface

2.1 Pinout



2.2 Interface Description



CAN_IN: USB to CAN interface for connecting to Raspberry Pi.

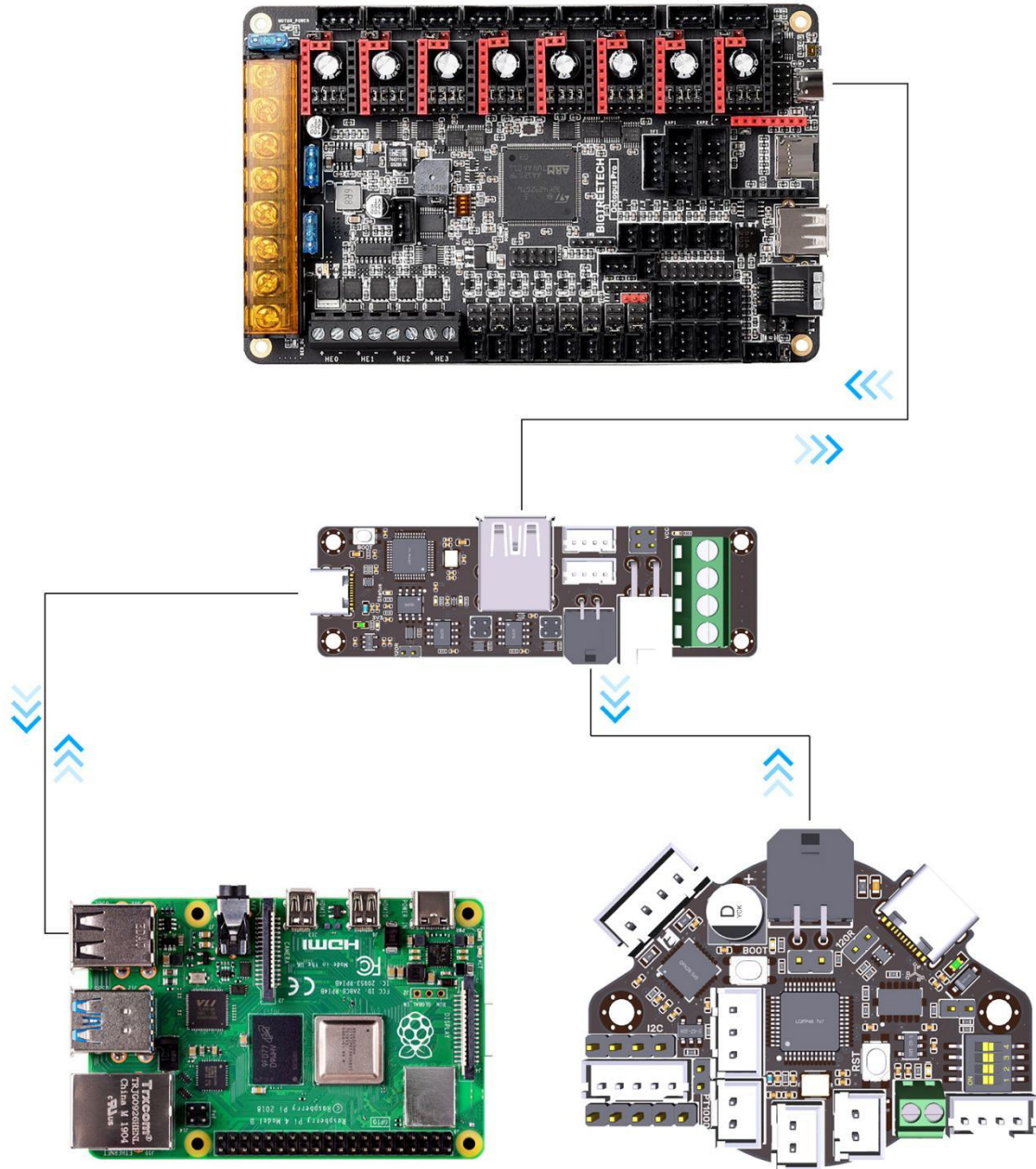
CAN_OUT*: It is used to connect an interface without CAN transceiver but with CAN function, such as connecting to the USB port of the motherboard, where the pin connecting the USB port of the motherboard to the main controller must have CAN function. E. g.:

B12	70	C8	44	32	C1	PA11	I/O	FT	(3)	CAN_RX USART1_CTS, TIM1_CH4, COMP1_OUT, TSC_G4_IO3, EVENTOUT	USB_DM
A12	71	B8	45	33	C3	PA12	I/O	FT	(3)	CAN_TX USART1_RTS, TIM1_ETR, COMP2_OUT, TSC_G4_IO4, EVENTOUT	USB_DP

CAN_OUT: Used to connect BIGTREETECH EBB CAN or other boards with CAN transceivers.

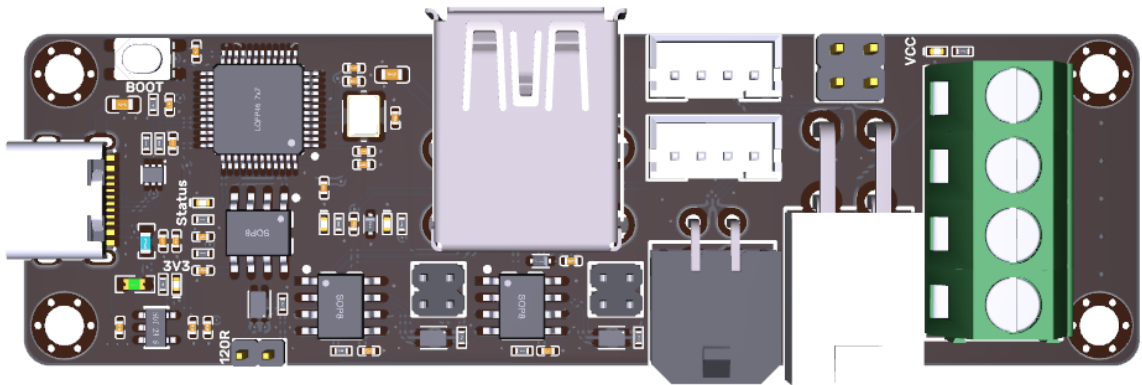
Power: Power Supply.

3. Optional Wiring Diagram

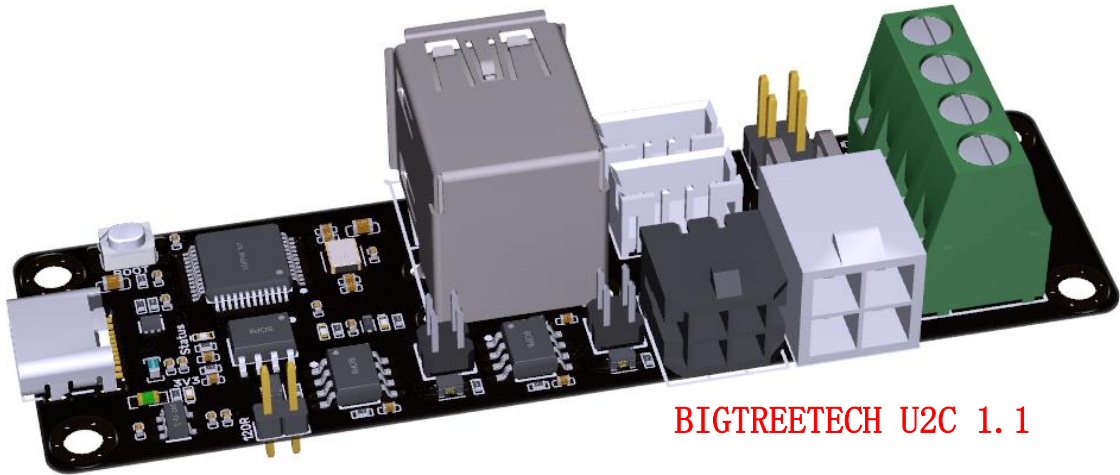


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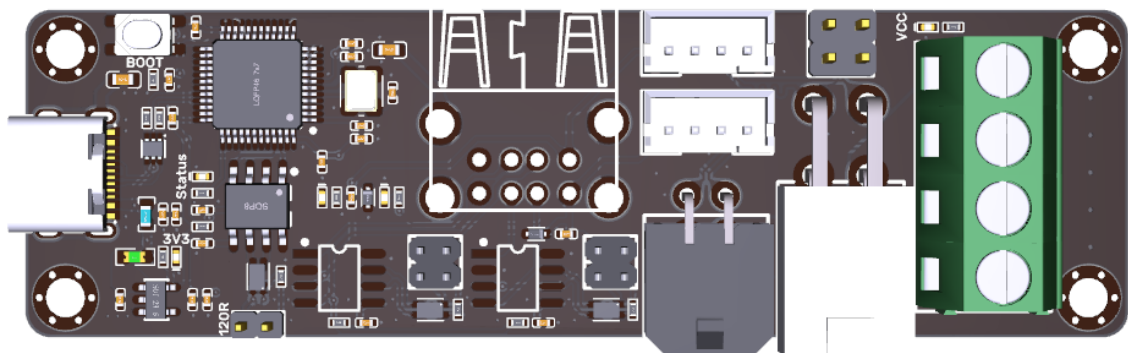
4. Product Display



BIGTREETECH U2C 1.1

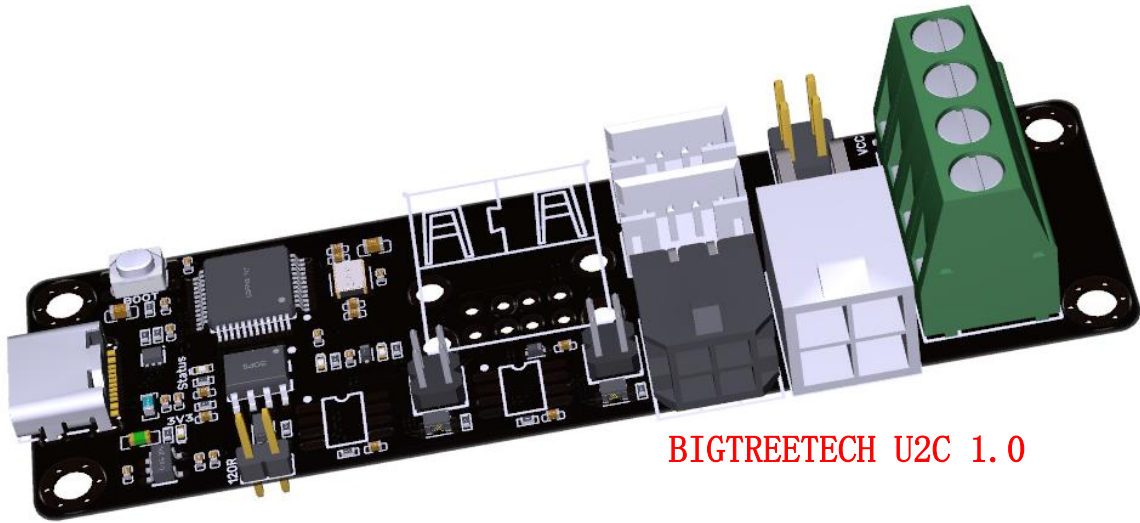


BIGTREETECH U2C 1.1

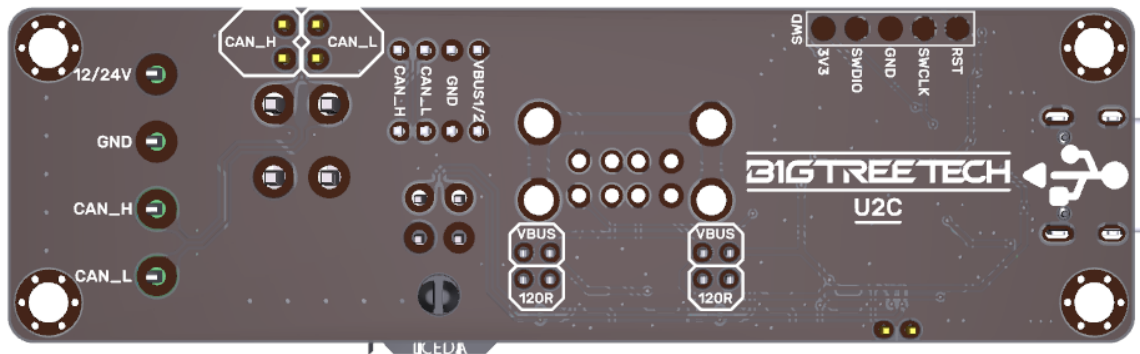


BIGTREETECH U2C 1.0

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BOTTOM

5. Firmware Description

5.1 Firmware Source Code

V1.0/1.1 use the open source CandleLight firmware:

https://github.com/candle-usb/candleLight_fw

MCU Model: STM32F072C8

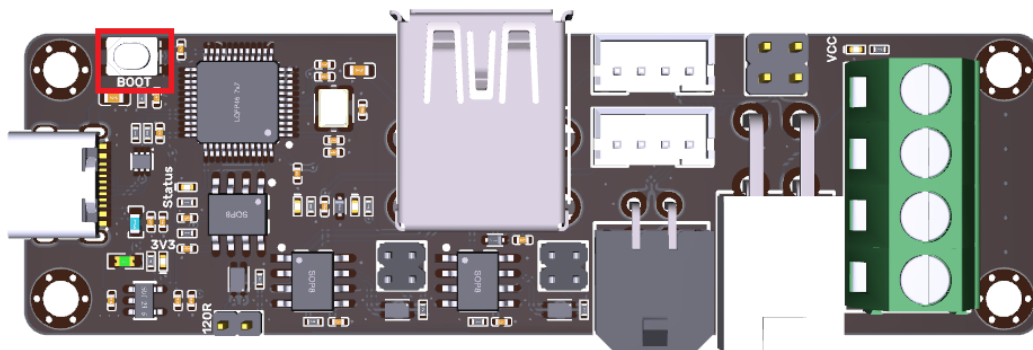
V2.0/2.1 STM32G0 support is added on the basis of open source CandleLight:

https://github.com/bigtreetech/candleLight_fw/tree/stm32g0_support

MCU Model: STM32G0B1C8

5.2 Firmware Update

After the module is completely powered off, press and hold the Boot button, plug the Type-C data cable to power the module, enter the DFU mode, and use the STM32CubeProgrammer software to update the firmware.



5.3 Klipper Configuration

Firmware Configuration Reference: <https://www.klipper3d.org/CANBUS.html>

1. Enter command in ssh terminal `sudo nano /etc/network/interfaces.d/can0` and execute

```
auto can0
```

```
iface can0 can static
```

```
    bitrate 500000
```

```
    up ifconfig $IFACE txqueuelen 1024
```

Set the CANBus speed to 500K (must be the same as the speed set in the firmware **(500000) CAN bus speed**), save after modification (Ctrl + S) and exit (Ctrl + X), enter `sudo reboot` to restart the Raspberry Pi.

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2. Every device on CANBus generates a `canbus_uuid` based on the MCU's UID, to find each microcontroller device ID, make sure the hardware is powered on and wired correctly, then run:

```
~/klippy-env/bin/python ~/klipper/scripts/canbus_query.py can0
```

3. If an uninitialized CAN device is detected, the above command will report the device's `canbus_uuid`:

```
Found canbus_uuid=0e0d81e4210c
```

4. If Klipper is already running and connected to this device, the `canbus_uuid` will not be reported, which is normal.

6. Precautions

1. 12/24V and GND should be connected correctly.

2. When using CAN communication, you need to see which CAN node is used as a terminal. If using a terminal, you must plug the jumper cap at the 120R position.