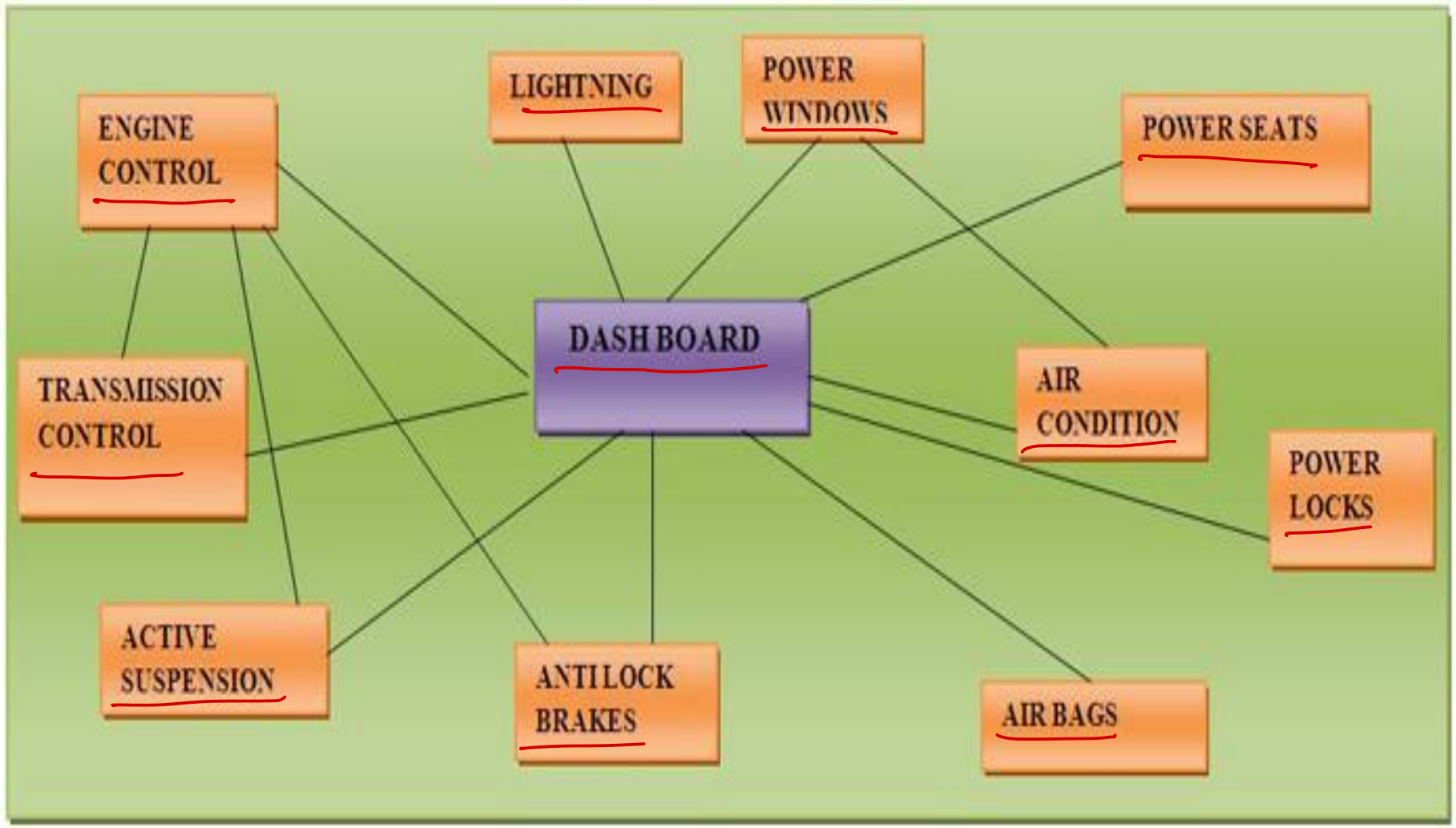
CAN Protocol

Controller Area Network

Introduction

- CAN protocol is method of communication between various electronic devices. It defines set of rules for communication in a network of devices.
- Original idea initiated Robert Bosch in 1983. However first release of CAN protocol is done in 1986.
- Protocol is implemented in hardware and software to communicate between different controllers present in the automobiles.
- Nowadays this protocol is used in various industries including Healthcare (ICUs & Operation Rooms), Entertainment (light control, door control in studios, gambling machines), Science (high energy experiments, astronomical telescopes).

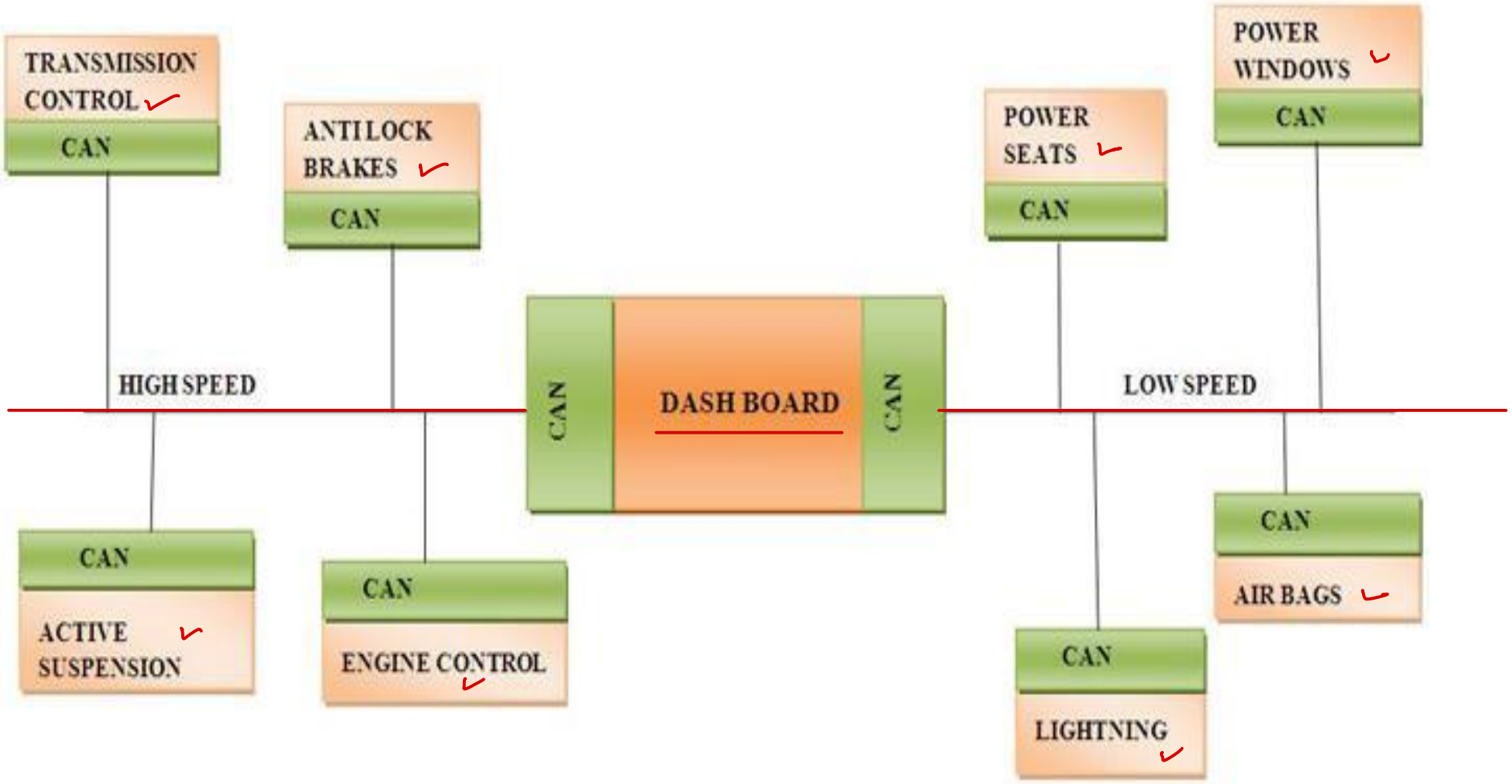
Automobiles – Prior invention of CAN



Drawbacks & Limitations of Wired System

- Number of wires in various subsystem makes the system complicated and difficult to maintain.
- Passing real time information among subsystems was tedious implementation (serial protocols used).
- Asynchronous transmitter/receiver do not support multi-domain communication e.g. communication between air-conditioning system and door/window system.
- Multiple domains in automobiles includes power generation (engine), chassis (driving mechanism), body (climate control/wipers), telemetric (entertainment units) and passive safety (air bags, etc).

Automobile System – with CAN protocol

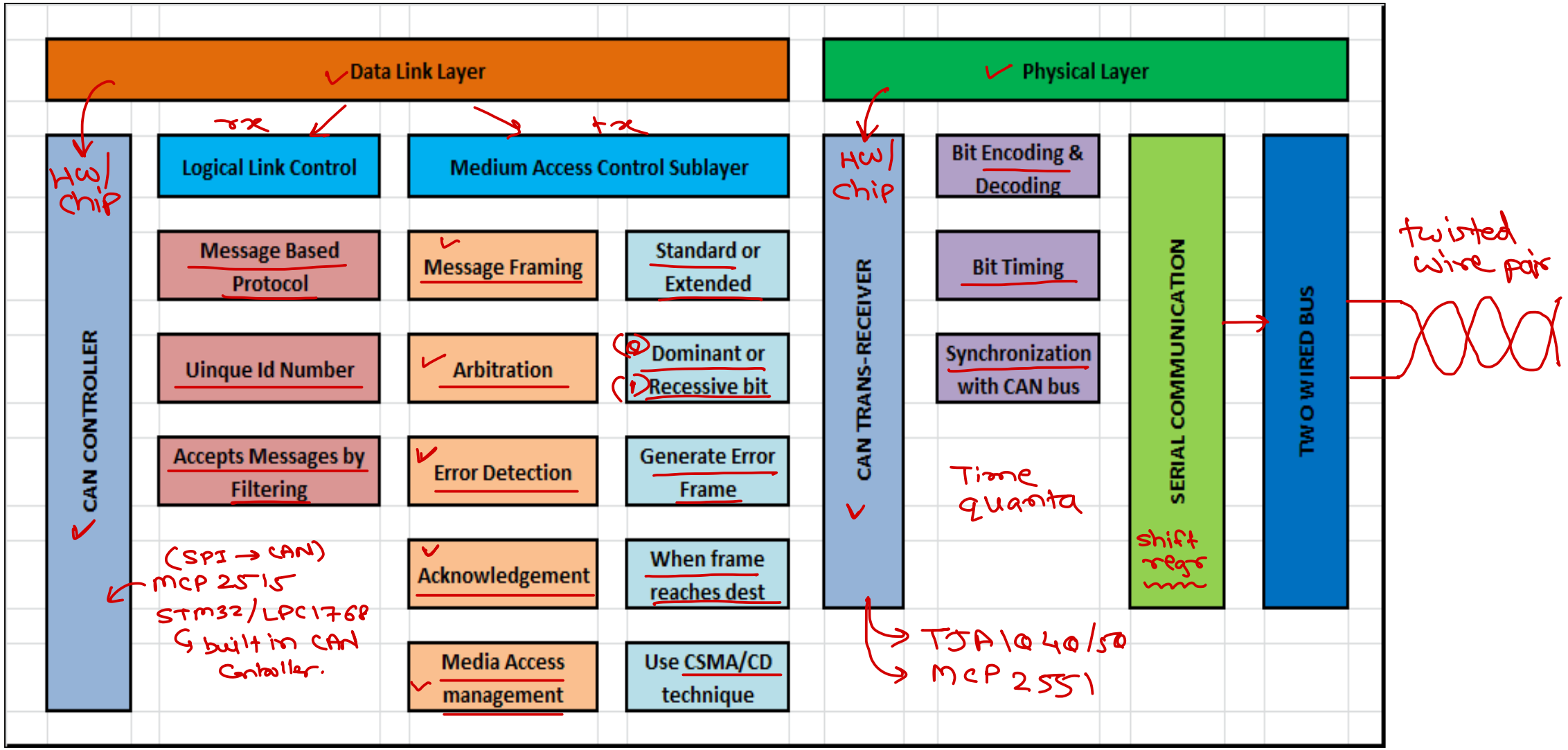


CAN Architecture

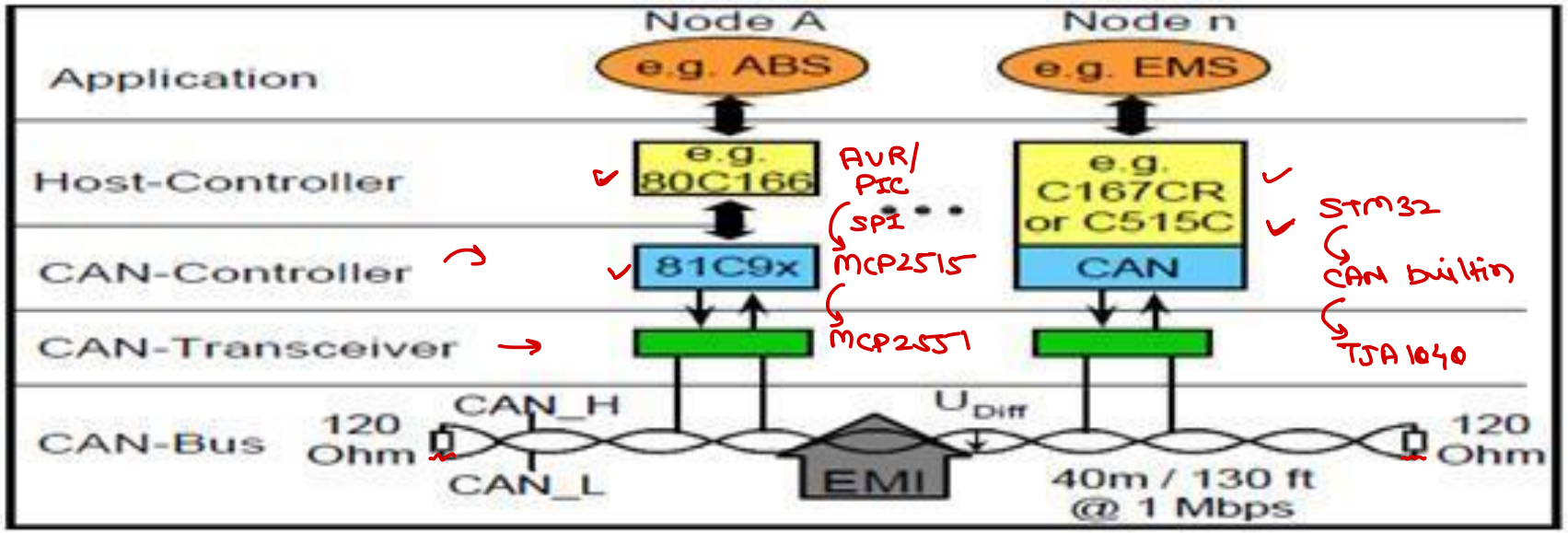
- CAN protocol is implemented with OSI reference model.
- It implements two layers of OSI model and rest are left for implementation specific to the requirement.
- Data Link Layer
  - Logical link control
    - Allows filtering of messages based on UID.
  - Medium access control
    - Prepare message frame and handle arbitration.
- Physical Layer
  - Send bits to the CAN two wire bus as per timing requirements.

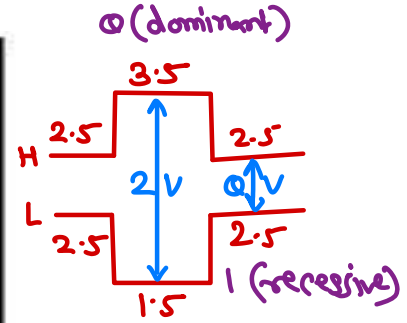
- application layer
- presentation layer
- session layer
- transport layer
- network layer
- data link layer
- physical layer

CAN Architecture



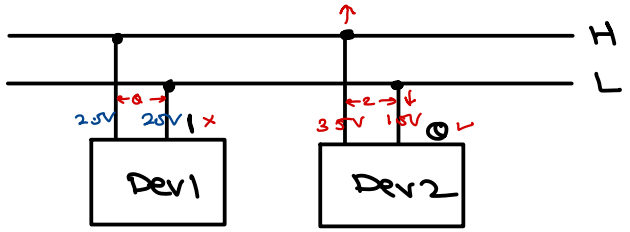
CAN Node

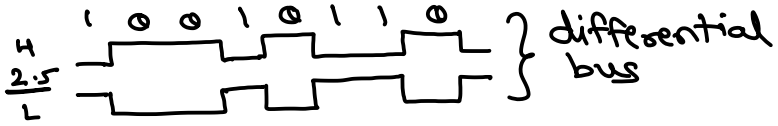


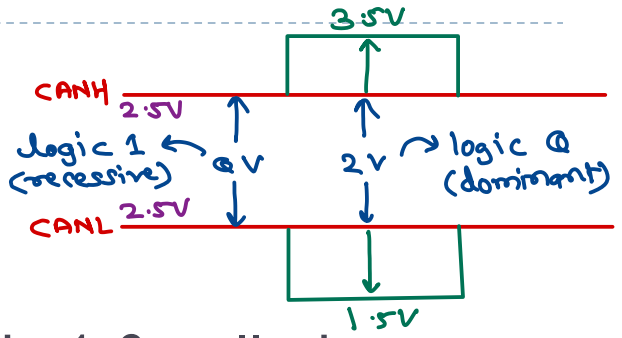


- Each electronic device is called as Node.
- Host-controller is MCU responsible for functioning of node.
- CAN controller converts messages of node as per CAN protocol. Can be a separate chip or embedded in MCU.
- Trans-receiver is to transmit bits on CAN bus.

CAN Bus





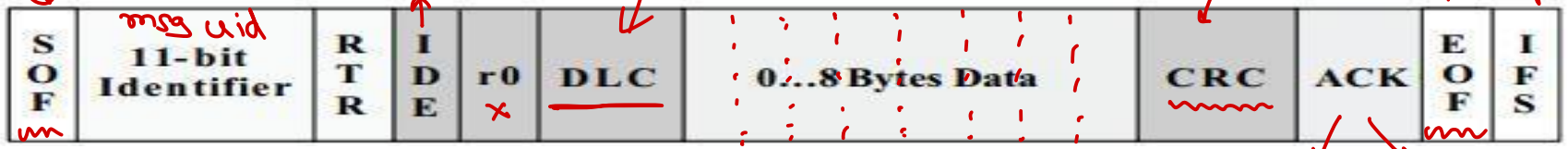


- CAN bus is a two twisted wire bus i.e. CANH & CANL.
  - The passive voltage of each line is 2.5 V.
  - The active voltages are 3.5 V and 1.5 V.
  - When both lines are 2.5 V, difference is 0 V. It represent logic 1 & called as “recessive bit”.
  - When both lines are pulled to 3.5 V and 1.5V respectively, then difference is 2 V. It represent logic 0 & called as “dominant bit”.
  - Note that dominant bit can always overwrite recessive bit.
  - CAN bus is a linear bus terminated with 120 Ω. Also input impedance of each node is 120 Ω.
- CAN bus is not a master slave bus i.e. Any node can write the data on the bus in certain format (frame) provided bus is available.

CAN Frame

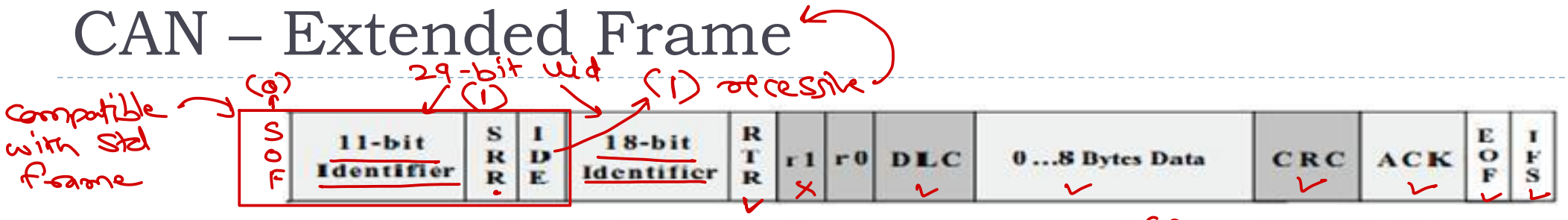
- CAN is a message based protocol (not address based).
- Message contains a pre-defined unique id (rather than addresses).
- Messages are accepted or rejected by any node based on this UID. If multiple nodes send messages at same time, node with highest priority gets bus access.
- CAN message is made up of 10 bytes.
- Each message is coded into meaningful sequence of bits/bytes called as **frame**.
- Framing is done by Medium Access Layer.
- There are two types of frames:
  - Standard CAN Frame
  - Extended CAN Frame

CAN – Standard Frame



- SOF: Start of Frame – Dominant bit – For Sync.
- UID: Type of message and Arbitration.
- RTR: Type of frame i.e. Data Frame [Dominant] or Remote Transmission Request (RTR) Frame [Recessive].
  - RTR frame don't have data, instead request other node to send data.
- IDE: UID Extension. Standard (dominant) or Extended (recessive) frame.
- R0: Reserved for future use.
- DLC: 4-bit data length code [0 to 8 bytes – data length]
- DATA: 0 to 8 bytes
- CRC:15 bits CRC + 1 bit delimiter (recessive)
- ACK: Transmitter sent recessive bit, Rcvr overwrite with dominant. + 1 bit delimiter (recessive)
- EOF: 7-bits (recessive) to indicate End of Frame.
- IFS: 3 recessive bits - Intermission bits – Separation between two frames.

CAN – Extended Frame

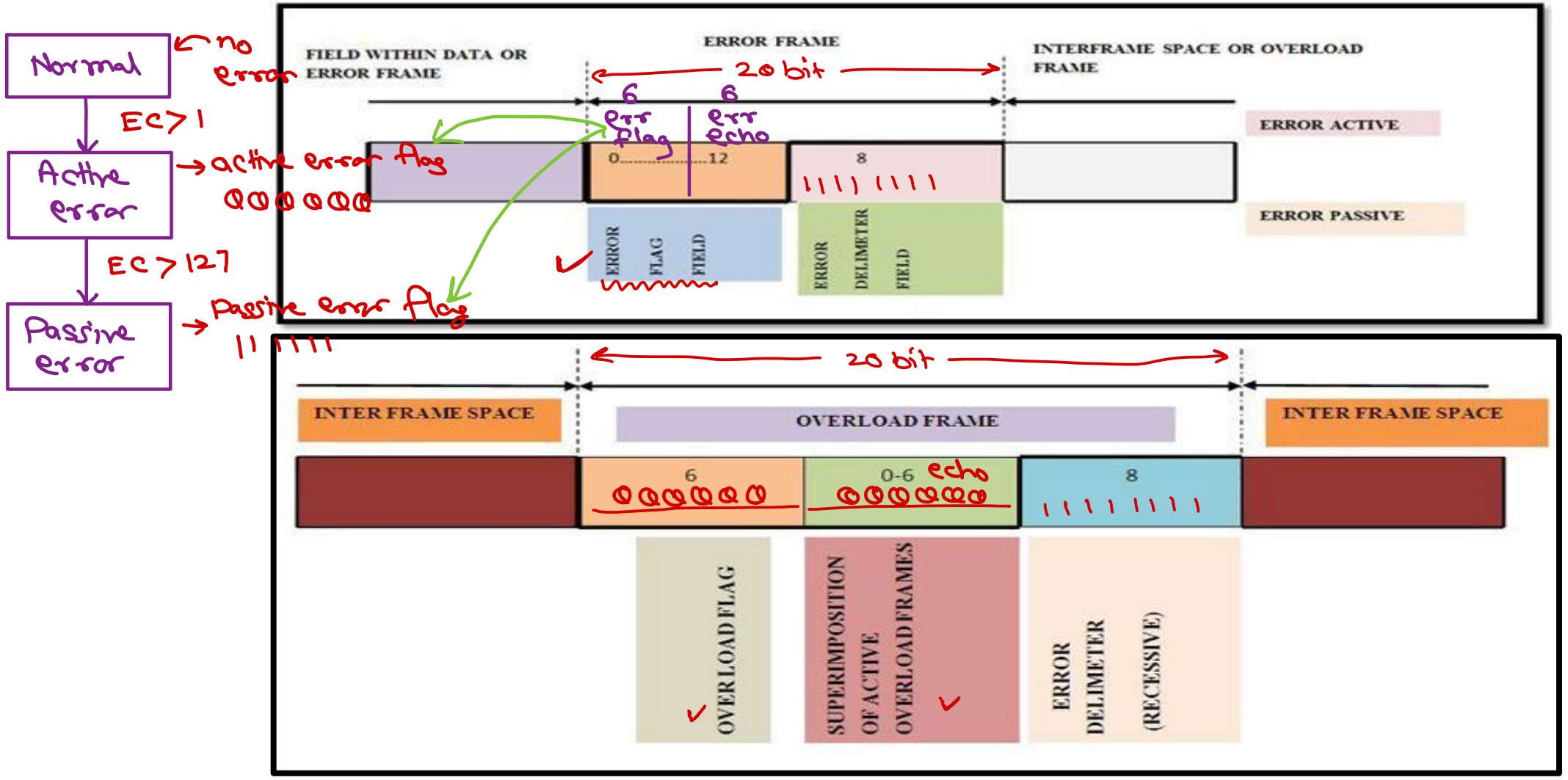


- SRR: Substitute Remote Request : Recessive bit [~~like~~ RTR]
- 11-bit Id + 18 bit Id = 29 bit Id – Extended Message Id.
- R1: Additional reserved bit.
- Types of Frames:
  - Data Frame
  - Remote Frame
  - Error Frame: When error is detected, transmission aborts and send this frame.
  - Overload Frame: Like error frame, sent by node when busy in internal processing.

To request data from other device. RTR = 1. No data sent in RTR frame.

TEC } Tx/Rx
REC } Error Count

CAN – Error and Overload Frames

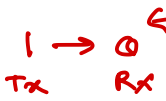


CAN Error Detection & Handling

- There are five methods of error detection.
  - Message Level Error Detection.
    - CRC check
    - ACK slots
    - Form error
  - Bit Level Error Detection.
    - Stuff error
    - Bit error
- If node detects an error, following steps occurs:
  - Transmits error flag.
  - Destroys transmitted frame.
  - Transmitting node resends the frame.

CAN – Error Detection

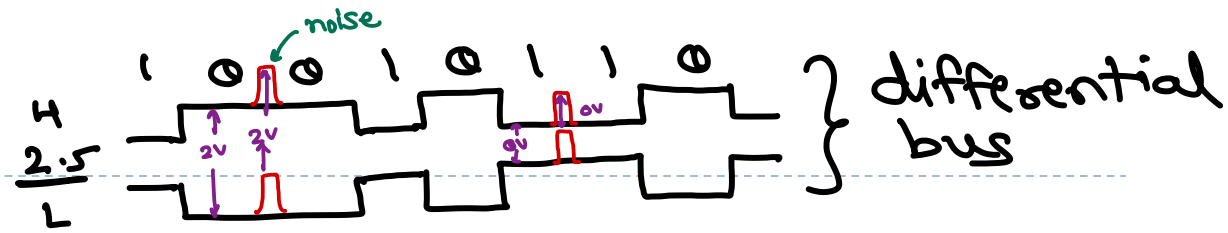
- CRC check:
  - Calculated and sent by transmitter node.
  - Receiver node recalculate CRC and if differs, raise error.
- ACK slots:
  - Transmitter send recessive bit & Receiver overwrite dominant
  - If none of the node overwrite dominant bit, error is raised.
- FORM (FORMAT) error:
  - EOF, IFS, ACK delim bits are always recessive.
  - If dominant bit is found, error is raised.
- BIT error:
  - Transmitter always monitor sent bit.
  - If sent bit is not validated error is generated, except in case of arbitration and acknowledgment bit.



CAN – Error Detection

- Bit Stuff Error:
  - CAN bus is never IDLE as it follows NRZ method (non-returning to zero i.e. 0 & 1 is represented as non-zero values - differential).
  - For sake of synchronization one bit of opposite polarity is added after consecutive 5 bits of same polarity, called as bit-stuffing.
  - Stuffed data frames are de-stuffed by data link layer of receiver.
  - If error is found in stuffing, error is raised.
  - In CAN, 6 consecutive recessive/dominant bits represent error bits.
  - All fields in the frame are stuffed with the exception of the CRC delimiter, ACK field and end of frame which are a fixed size.

CAN protocol – Advantages

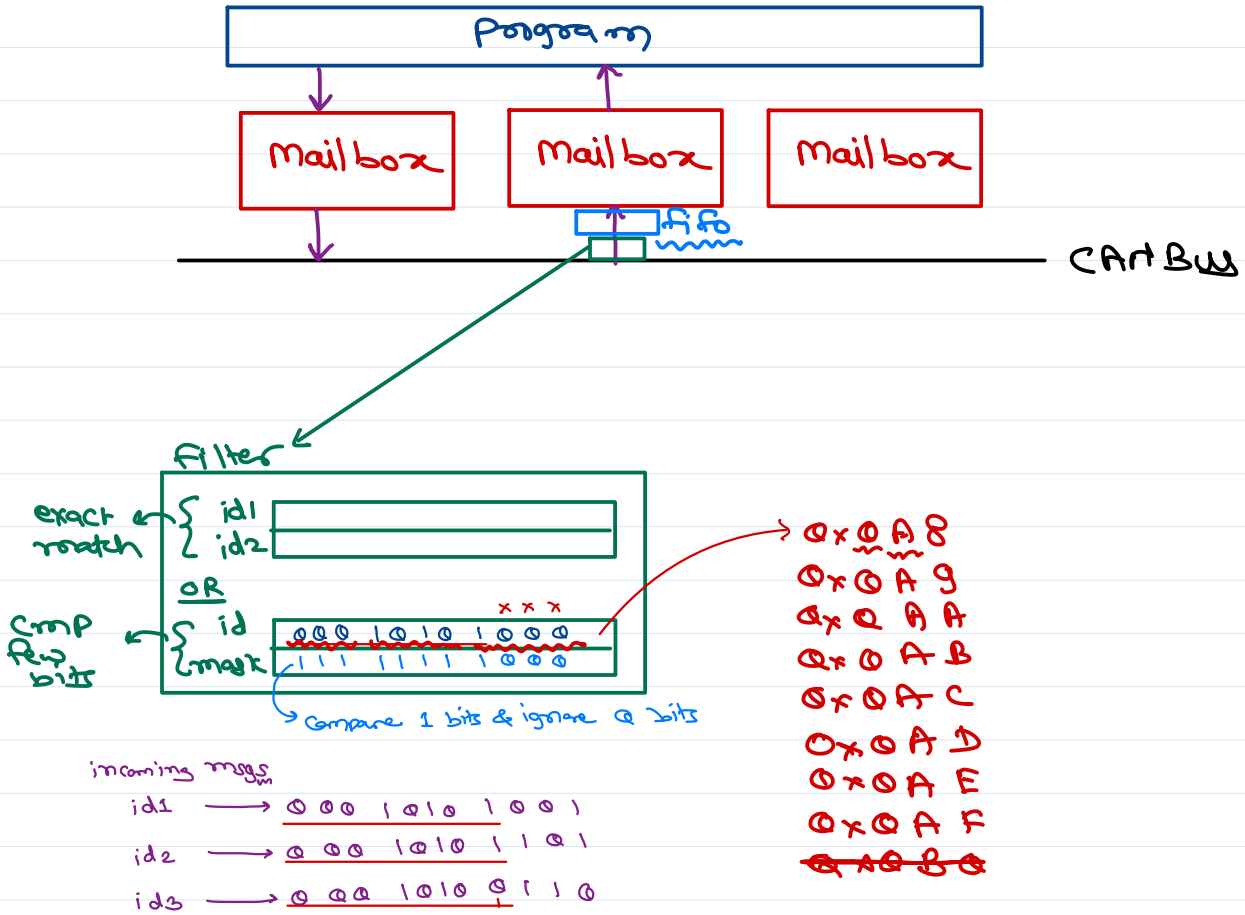


- Low cost: Only two wire serial bus.
- Reliable: Error detection & handling. Immune to noise.
- Flexibility: Nodes can be easily added or deleted.
- High speed: Support data rate of 1 Mbits/sec @ 40m bus.
- Multi-master bus: Any node can access bus.
- Fault confinement: Faulty nodes do not disturb commn.
- Broadcast capability: One to One/Many/All commn.
- Standardization: ISO standardized.
  - ISO-DIS 11898 : High speed communication
  - ISO-DIS 11519-2 : Low speed communication

① Mailbox

② Acceptance Filter

③ Time quanta



CPU clock = 72 MHz

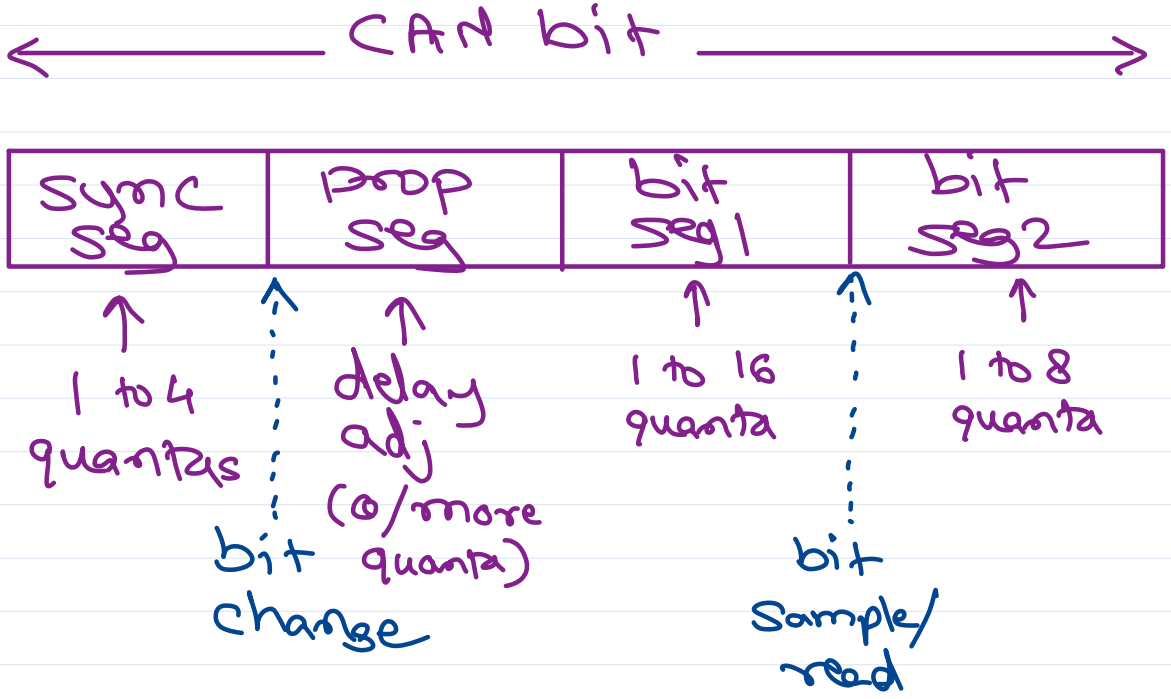
PCLK = 36 MHz (APB1)

CAN Prescalar = 18

$$\text{CAN Time quanta} = \frac{\text{Prescalar}}{\text{PCLK}}$$

$$= \frac{18}{36\ \text{MHz}} = 0.5\ \mu s$$

$$= 500\ ns$$



Our Example :

1 + 0 + 2 + 1

= 4 quantas ← bit nominal time

= 4 × 500 ns = 2000 ns = 2 µs

Bit rate = $\frac{1}{2\ \mu s}$ = 0.5 MBit/s = 500 KBit/s

Thank you!

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