封面

摘要

ABSTRACT  
 As we all know, now related to the automotive industry has made rapid development, and in  
the automotive industry is applied to a very wide range of CAN bus. Development of CAN bus usedates back to the 1990s, when accompanied by an increasing number of cars in a control unit in the  
form of ad-hoc network cabling in the traditional sense of the emergence of a serious shortcoming,it is replaced by a simpler CAN bus network wiring.  
This article is to simulate the vehicle CAN bus which is designed based on CAN bus driver  
module. The main requirement is the ability to be able to transmit data via CAN bus between the  
host computer and the next crew, the next crew and after obtaining information capable of driving  
DC gear motor rotation.  
Upper and lower main control board paper machine are produced using STM32F103c8t6  
microprocessor. Between the upper and lower machine is the use of CAN bus communication, CAN  
transceiver chip is SN65HVD230; PC design has the key means by pressing different buttons  
represent different information, and then host those machines send information via CAN bus  
protocol packetized data to the network; when the corresponding lower computer receives the data,  
depending on the motor rotation control different information in different ways. Finally, in order to  
make the design more vivid, the lower computer chip driven by a motor driven L9110S 6-channel  
DC motor placed excavator model, it is possible to rotate the motor linkage, and the excavator  
design forward, backward, turn, mining and other activities.  
【 Key words】 CAN bus Network Cabling Motor Linkage STM32F103c8t6 SN65HVD230  
L9110S

目录

前言

# 概述

## 选题意义与设计要求

### 选题意义