

USB2CAN MODULE User Manual For Linux/Raspbian/Ubuntu system



1. General Description:

USB2CAN module is a 'plug and play' and bi-directional port powered USB to CAN converter which realizes long-distance communication between your Raspberry Pi/SBC/PC and other devices stably through CAN- Bus connection.

With small size and convenient operation, It's a cost-effective solution that are safe and reliable for all your data-conversion / device-protection applications for any experienced engineer interfacing to expensive industrial equipment yet simple enough for home use by an amateur hobbyist.

USB2CAN can also be applied to obtain the data of car via the OBD connector, but you need to configured and secondary development by yourself.

2. Features

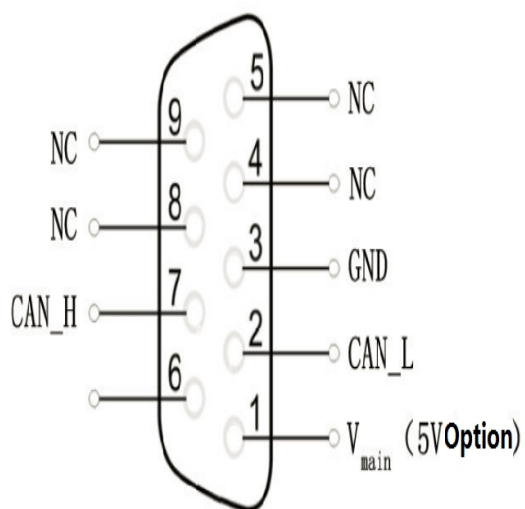
1. Compatible with Raspberry Pi Zero(W)/Pi3B+/Pi4/Beaglebone/Tinker Board and any single board computer .
2. Plug and Play USB device. No external power required. Support wider CAN baud rate, From 20Kbps to 1Mbps can be programmed arbitrarily.
3. On board STM32F0 microcontroller, high speed data transfer with DMA technique. Support for CAN bus 2.0A and 2.0B specification.
4. Power supply isolation, signal input/output isolation, Built-in surge and static protection. 120 Ohm resistor selectable jumper feature.
5. Comes with C/Python demos of Socket-CAN, detailed user manual and friendly technology support.

3. Technical Specification

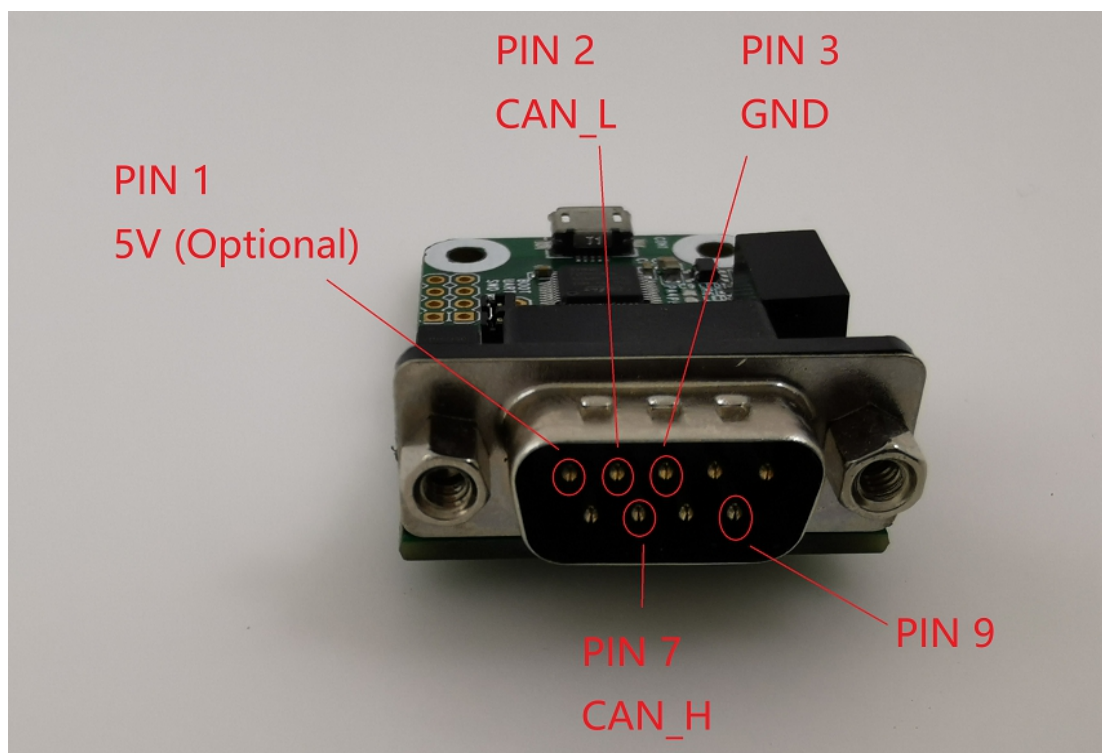
Connector	
CAN	D-SUB, 9 pins
USB	USB 2.0 Full-Speed, Micro USB
CAN Features	
Specification	2.0A (standard format) and 2.0B (extended format), ISO 11898-2 High-speed CAN
Data Rate	From 20kbps to 1Mbps can be programmed arbitrarily.
Isolation Voltage	1.5K VDC/min, 3K VDC/1s
Microcontroller	STM32F0, 48MHz
Termination	120 Ohm resistor selectable jumper
CAN Transceiver	ISO1050DUBR ,Texas Instruments
Other	
Work Temperature	-40° ~ 85°
Relative humidity	15-90%, not condensing
PCBA Size (L * W * H)	56.50mm * 31.20mm * 14.20mm
Weight	15.5 g

4. Hardware Description

4.1 CAN Connector Pinout



Pin	Description
1	5V/150ma output . Weld 0 Ω resistor on R9 to enable this function(close to the jumper).
2	CANL bus line (dominant low)
3	CAN_GND
4	NC
5	NC
6	NC
7	CANH bus line (dominant high)
8	NC
9	NC

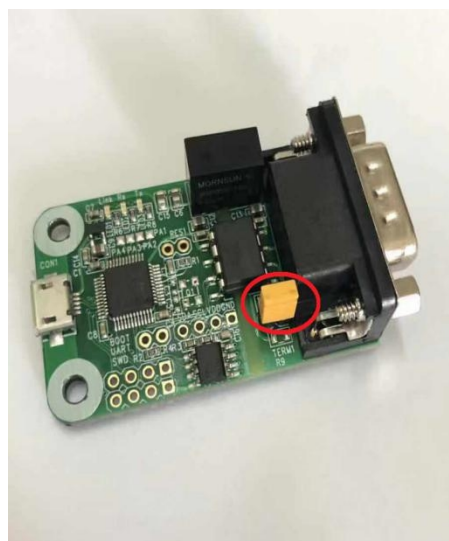


4.2 120 Ohm Resistor Setting.

A High-speed CAN bus (ISO 11898-2) must be terminated on both ends with 120 Ohms. The USB2CAN module with a on-board 120 Ω selectable jumper.

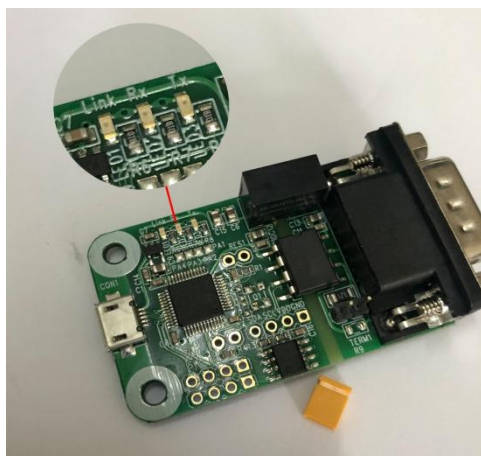


Disable 120 Ohm Resistor.



Enable 120 Ohm Resistor.

4.3 LED Indicate



LED Name	Description
Link	Red led is normally on to indicate the module is started successfully
Tx	Red led flash to indicate send data.
Rx	Red led flash to indicate receive data.

5. Run USB2CAN Test Demo

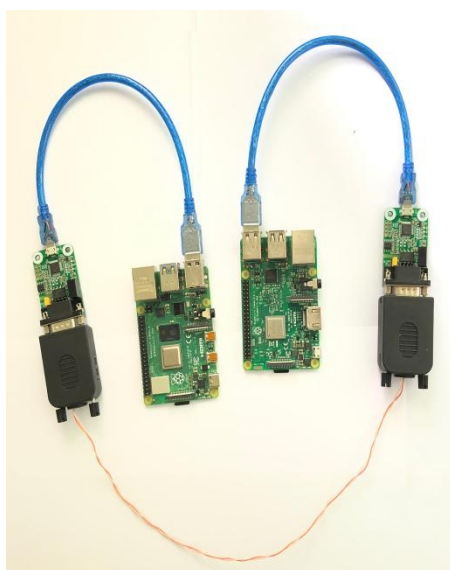
USB2CAN module can run properly without any additional driver request on all Linux system since version 3.9. such as Ubuntu, Debian and Raspbian. If you meet problems in older system, You need to reconfigure the kernel drivers. Enable 'gs_usb.c' and install 'gs_usb.ko' into system. So notice that if you only compile this drivers, It may fail to load in system. At this time, compile fully with new configure.

You can test the USB2CAN module any single board computer or PC with the right Linux version. We take Raspberry Pi 4 as an example to show you how to run the C/Python and can-utils demo.

5.1 Preparatory work

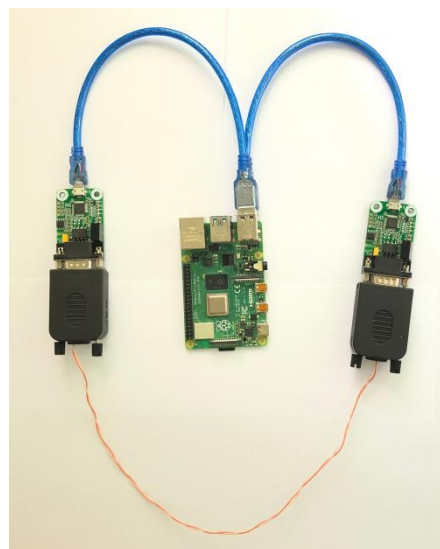
5.1.1 Connection

There are two ways to test the USB2CAN module. One is plug two USB2CAN module into the USB Host of each Raspberry Pi. The other is plug two USB2CAN into one Raspberry Pi. But the codes and commands are a little bit different. And then connect the CAN_H pin and CAN_L pin to each other. No GND pin connection requirement.



Methods A

Use two Raspberry Pi to test USB2CAN

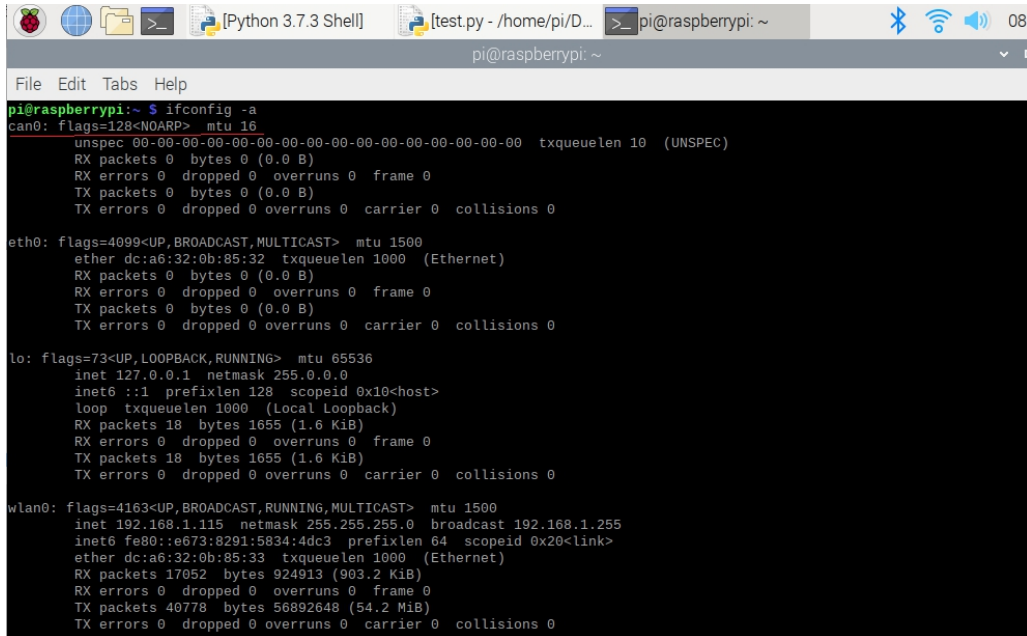


Methods B

Use one Raspberry Pi to test USB2CAN

5.1.2 ifconfig -a

Type command 'ifconfig -a' to check 'can0' device is available in system.



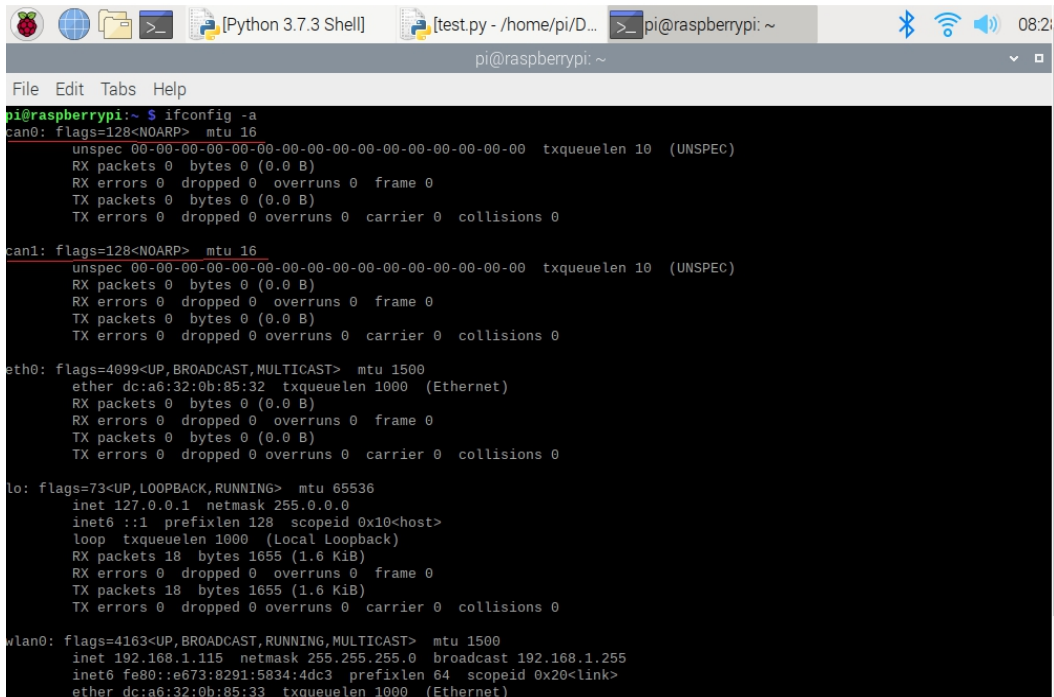
```
pi@raspberrypi:~$ ifconfig -a
can0: flags=128<NOARP> mtu 16
    unspec 00-00-00-00-00-00-00-00-00-00-00-00-00-00-00-00 txqueuelen 10 (UNSPEC)
    RX packets 0 bytes 0 (0.0 B)
    RX errors 0 dropped 0 overruns 0 frame 0
    TX packets 0 bytes 0 (0.0 B)
    TX errors 0 dropped 0 overruns 0 carrier 0 collisions 0

eth0: flags=4099<UP,BROADCAST,MULTICAST> mtu 1500
    ether dc:a6:32:0b:85:32 txqueuelen 1000 (Ethernet)
    RX packets 0 bytes 0 (0.0 B)
    RX errors 0 dropped 0 overruns 0 frame 0
    TX packets 0 bytes 0 (0.0 B)
    TX errors 0 dropped 0 overruns 0 carrier 0 collisions 0

lo: flags=73<UP,LOOPBACK,RUNNING> mtu 65536
    inet 127.0.0.1 netmask 255.0.0.0
    inet6 ::1 prefixlen 128 scopeid 0x10<host>
    loop txqueuelen 1000 (Local Loopback)
    RX packets 18 bytes 1655 (1.6 KiB)
    RX errors 0 dropped 0 overruns 0 frame 0
    TX packets 18 bytes 1655 (1.6 KiB)
    TX errors 0 dropped 0 overruns 0 carrier 0 collisions 0

wlan0: flags=4163<UP,BROADCAST,RUNNING,MULTICAST> mtu 1500
    inet 192.168.1.115 netmask 255.255.255.0 broadcast 192.168.1.255
    inet6 fe80::e673:8291:5834:4dc3 prefixlen 64 scopeid 0x20<link>
    ether dc:a6:32:0b:85:33 txqueuelen 1000 (Ethernet)
    RX packets 17052 bytes 924913 (903.2 KiB)
    RX errors 0 dropped 0 overruns 0 frame 0
    TX packets 40778 bytes 56892648 (54.2 MiB)
    TX errors 0 dropped 0 overruns 0 carrier 0 collisions 0
```

If you plug two USB2CAN into one Raspberry PI, You will see one more 'can1' device.



```
pi@raspberrypi:~$ ifconfig -a
can0: flags=128<NOARP> mtu 16
    unspec 00-00-00-00-00-00-00-00-00-00-00-00-00-00-00-00 txqueuelen 10 (UNSPEC)
    RX packets 0 bytes 0 (0.0 B)
    RX errors 0 dropped 0 overruns 0 frame 0
    TX packets 0 bytes 0 (0.0 B)
    TX errors 0 dropped 0 overruns 0 carrier 0 collisions 0

can1: flags=128<NOARP> mtu 16
    unspec 00-00-00-00-00-00-00-00-00-00-00-00-00-00-00-00 txqueuelen 10 (UNSPEC)
    RX packets 0 bytes 0 (0.0 B)
    RX errors 0 dropped 0 overruns 0 frame 0
    TX packets 0 bytes 0 (0.0 B)
    TX errors 0 dropped 0 overruns 0 carrier 0 collisions 0

eth0: flags=4099<UP,BROADCAST,MULTICAST> mtu 1500
    ether dc:a6:32:0b:85:32 txqueuelen 1000 (Ethernet)
    RX packets 0 bytes 0 (0.0 B)
    RX errors 0 dropped 0 overruns 0 frame 0
    TX packets 0 bytes 0 (0.0 B)
    TX errors 0 dropped 0 overruns 0 carrier 0 collisions 0

lo: flags=73<UP,LOOPBACK,RUNNING> mtu 65536
    inet 127.0.0.1 netmask 255.0.0.0
    inet6 ::1 prefixlen 128 scopeid 0x10<host>
    loop txqueuelen 1000 (Local Loopback)
    RX packets 18 bytes 1655 (1.6 KiB)
    RX errors 0 dropped 0 overruns 0 frame 0
    TX packets 18 bytes 1655 (1.6 KiB)
    TX errors 0 dropped 0 overruns 0 carrier 0 collisions 0

wlan0: flags=4163<UP,BROADCAST,RUNNING,MULTICAST> mtu 1500
    inet 192.168.1.115 netmask 255.255.255.0 broadcast 192.168.1.255
    inet6 fe80::e673:8291:5834:4dc3 prefixlen 64 scopeid 0x20<link>
    ether dc:a6:32:0b:85:33 txqueuelen 1000 (Ethernet)
```

5.1.3 dmesg

You can type command 'dmesg' for see more information about USB2CAN module at the bottom.

```
1.691578] usb 1-1.4: new full-speed USB device number 4 using xhci_hcd
1.828772] usb 1-1.4: New USB device found, idVendor=1d50, idProduct=606f, bcdDevice= 0.00
1.828789] usb 1-1.4: New USB device strings: Mfr=1, Product=2, SerialNumber=3
1.828801] usb 1-1.4: Product: USB2CAN v1
1.828813] usb 1-1.4: Manufacturer: Geschwister Schneider Technologie-,Entwicklungs-und Vertriebs UG.
1.828824] usb 1-1.4: SerialNumber: 004400285753511220303139
```

5.2 Use can-utils Tool

This tool is a very easy way to test USB2CAN module communication. There is only a simple use instruction. For more details, please refer to can-utils usermanual.

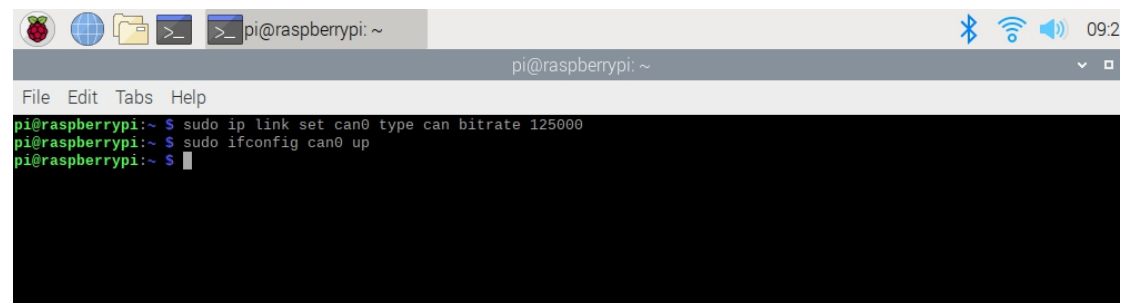
5.2.1 Install Tools

```
sudo apt-get install can-utils
```

5.2.2 Send And Receive Test

(1) Initialize CAN port

```
sudo ip link set can0 type can bitrate 125000
```



(2) Set one as receiver

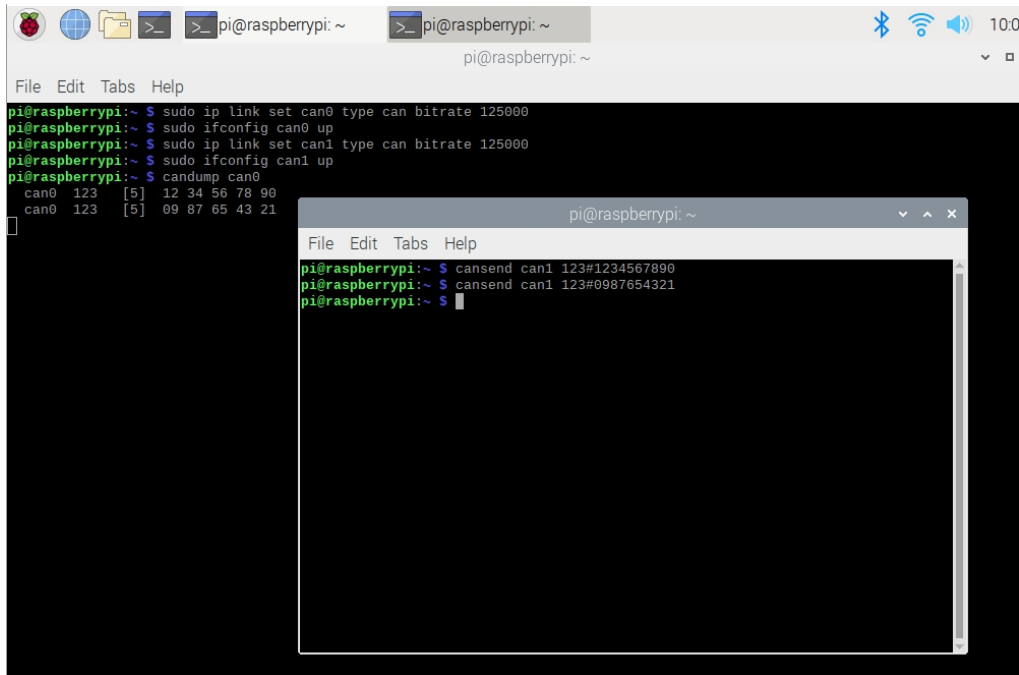
```
candump can0
```

(3) Set the other as sender

```
cansend can0 123#1234567890
```


5.2.3 Test Two USB2CAN Module On One Raspberry Pi

Do as above steps, set 'can0' as receiver and 'can1' as sender.



The screenshot shows a terminal window on a Raspberry Pi. The terminal output is as follows:

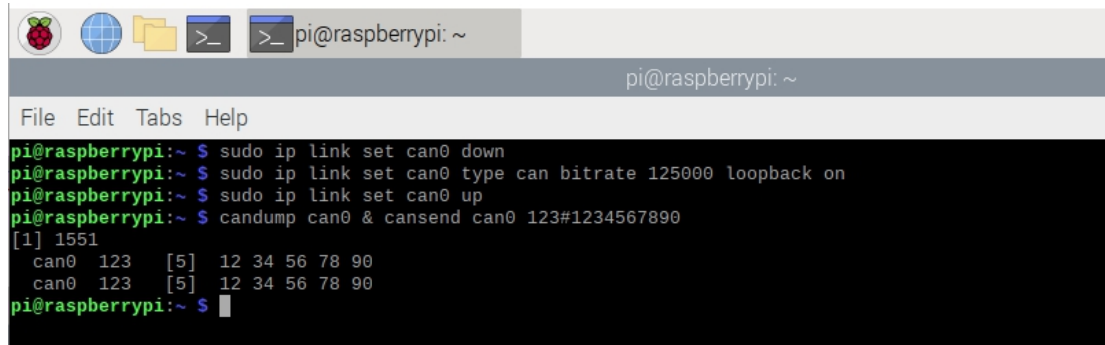
```
pi@raspberrypi:~$ sudo ip link set can0 type can bitrate 125000
pi@raspberrypi:~$ sudo ifconfig can0 up
pi@raspberrypi:~$ sudo ip link set can1 type can bitrate 125000
pi@raspberrypi:~$ sudo ifconfig can1 up
pi@raspberrypi:~$ candump can0
can0 123 [5] 12 34 56 78 90
can0 123 [5] 09 87 65 43 21
```

A second terminal window is open in the foreground, showing the following commands and output:

```
pi@raspberrypi:~$ cansend can1 123#1234567890
pi@raspberrypi:~$ cansend can1 123#0987654321
pi@raspberrypi:~$
```

5.2.4 Loopback Mode Test

```
sudo ip link set can0 down
sudo ip link set can0 type can bitrate 125000 loopback on
sudo ip link set can0 up
candump can0 & cansend can0
```



```

pi@raspberrypi: ~
File Edit Tabs Help
pi@raspberrypi:~ $ sudo ip link set can0 down
pi@raspberrypi:~ $ sudo ip link set can0 type can bitrate 125000 loopback on
pi@raspberrypi:~ $ sudo ip link set can0 up
pi@raspberrypi:~ $ candump can0 & cansend can0 123#1234567890
[1] 1551
can0 123 [5] 12 34 56 78 90
can0 123 [5] 12 34 56 78 90
pi@raspberrypi:~ $

```

5.3 Run C Demo

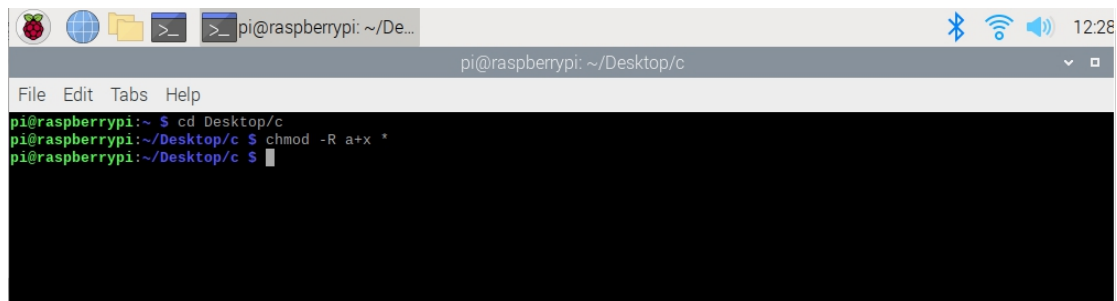
(1) Load C Demo named 'usb2cantest' from our Wiki and up-zip it to the desktop of Rasbian.

http://www.inno-maker.com/wiki/doku.php?id=usb_can

Or <http://www.inno-maker.com/wiki/doku.php>

(2) Go to folder named 'c' and change the permissions.

`chmod -R a+rw *`



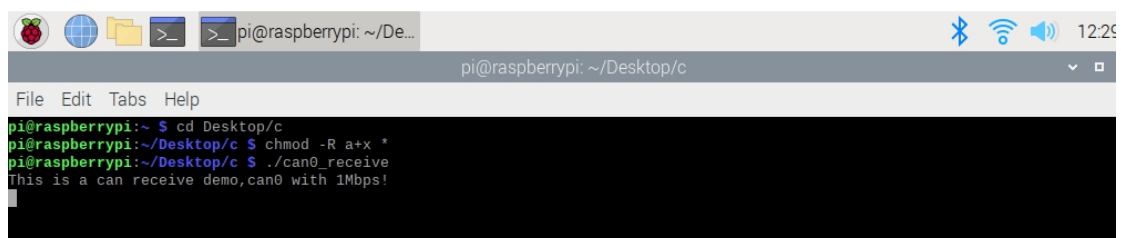
```

pi@raspberrypi: ~/De...
pi@raspberrypi: ~/Desktop/c
File Edit Tabs Help
pi@raspberrypi:~ $ cd Desktop/c
pi@raspberrypi:~/Desktop/c $ chmod -R a+x *
pi@raspberrypi:~/Desktop/c $

```

(3) Set one as receiver, execute following commands in serial terminal. Now this Raspberry pi is blocked.

`./can0_receive`



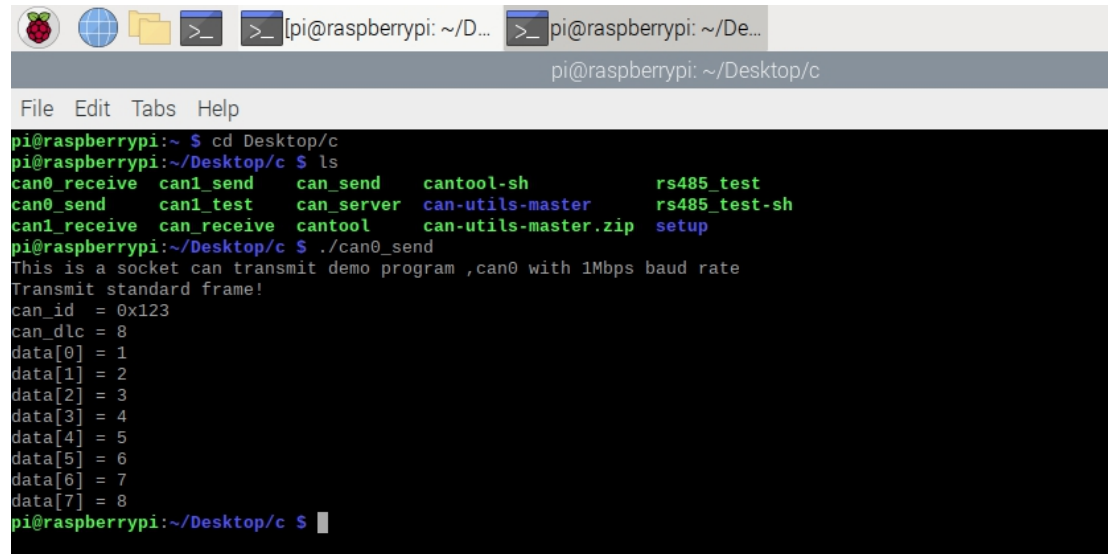
```

pi@raspberrypi: ~/De...
pi@raspberrypi: ~/Desktop/c
File Edit Tabs Help
pi@raspberrypi:~ $ cd Desktop/c
pi@raspberrypi:~/Desktop/c $ chmod -R a+x *
pi@raspberrypi:~/Desktop/c $ ./can0_receive
This is a can receive demo, can0 with 1Mbps!

```

(4) Set the other Pi as sender, execute following commands.

./can0_send

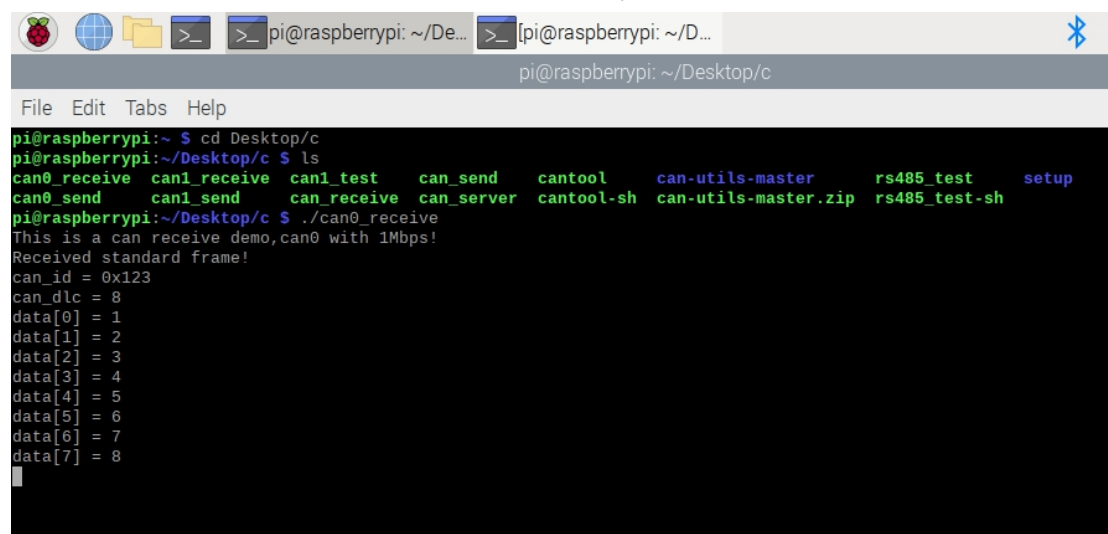


```

pi@raspberrypi: ~/Desktop/c
File Edit Tabs Help
pi@raspberrypi:~ $ cd Desktop/c
pi@raspberrypi:~/Desktop/c $ ls
can0_receive  can1_send    can_send     cantool-sh    rs485_test
can0_send     can1_test    can_server   can-utils-master  rs485_test-sh
can1_receive  can_receive  cantool      can-utils-master.zip  setup
pi@raspberrypi:~/Desktop/c $ ./can0_send
This is a socket can transmit demo program ,can0 with 1Mbps baud rate
Transmit standard frame!
can_id = 0x123
can_dlc = 8
data[0] = 1
data[1] = 2
data[2] = 3
data[3] = 4
data[4] = 5
data[5] = 6
data[6] = 7
data[7] = 8
pi@raspberrypi:~/Desktop/c $

```

(5) You should see that the receiver has received the packet.

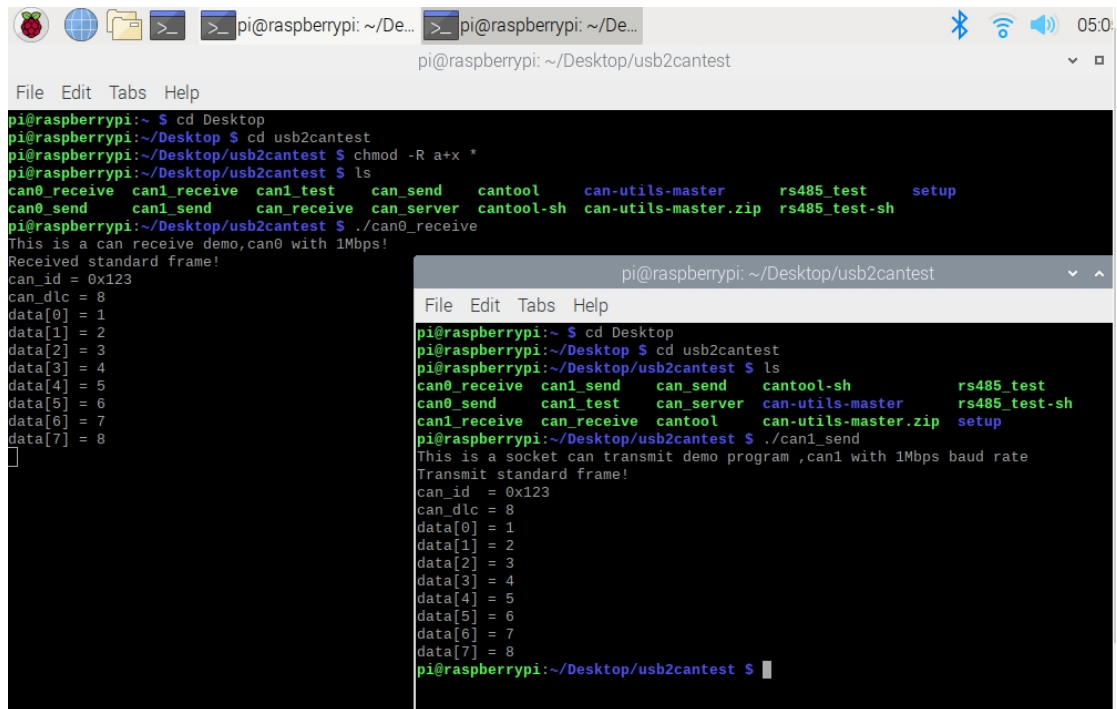


```

pi@raspberrypi: ~/Desktop/c
File Edit Tabs Help
pi@raspberrypi:~ $ cd Desktop/c
pi@raspberrypi:~/Desktop/c $ ls
can0_receive  can1_receive  can1_test    can_send     cantool    can-utils-master  rs485_test  setup
can0_send     can1_send     can_receive  can_server   cantool-sh  can-utils-master.zip  rs485_test-sh
pi@raspberrypi:~/Desktop/c $ ./can0_receive
This is a can receive demo,can0 with 1Mbps!
Received standard frame!
can_id = 0x123
can_dlc = 8
data[0] = 1
data[1] = 2
data[2] = 3
data[3] = 4
data[4] = 5
data[5] = 6
data[6] = 7
data[7] = 8

```

(6) You also can plug two USB2CAN module on one Raspberry PI board to test. You should see two can socket “can 0” and “can 1” devices. So notice that you need to change “can 0” to “can 1” when you use “can 1” device.



The screenshot shows a terminal window on a Raspberry Pi. The user is in the directory ~/Desktop/usb2cantest. They run a series of commands to set up and test the CAN bus. The output shows a standard frame being received on can0 and then transmitted on can1.

```

pi@raspberrypi: ~/Desktop/usb2cantest
File Edit Tabs Help

pi@raspberrypi:~ $ cd Desktop
pi@raspberrypi:~/Desktop $ cd usb2cantest
pi@raspberrypi:~/Desktop/usb2cantest $ chmod -R a+x *
pi@raspberrypi:~/Desktop/usb2cantest $ ls
can0_receive  can1_receive  can1_test     can_send      cantool       can-utils-master  rs485_test  setup
can0_send     can1_send     can_receive   can_server    cantool-sh    can-utils-master.zip  rs485_test-sh
pi@raspberrypi:~/Desktop/usb2cantest $ ./can0_receive
This is a can receive demo, can0 with 1Mbps!
Received standard frame!
can_id = 0x123
can_dlc = 8
data[0] = 1
data[1] = 2
data[2] = 3
data[3] = 4
data[4] = 5
data[5] = 6
data[6] = 7
data[7] = 8

```

The second terminal window shows the user running ./can1_send, which transmits a standard frame on can1.

```

pi@raspberrypi: ~/Desktop/usb2cantest
File Edit Tabs Help

pi@raspberrypi:~ $ cd Desktop
pi@raspberrypi:~/Desktop $ cd usb2cantest
pi@raspberrypi:~/Desktop/usb2cantest $ ls
can0_receive  can1_send     can_send      cantool-sh    rs485_test
can0_send     can1_test     can_server    can-utils-master  rs485_test-sh
can1_receive  can_receive   cantool       can-utils-master.zip  setup
pi@raspberrypi:~/Desktop/usb2cantest $ ./can1_send
This is a socket can transmit demo program ,can1 with 1Mbps baud rate
Transmit standard frame!
can_id = 0x123
can_dlc = 8
data[0] = 1
data[1] = 2
data[2] = 3
data[3] = 4
data[4] = 5
data[5] = 6
data[6] = 7
data[7] = 8
pi@raspberrypi:~/Desktop/usb2cantest $

```

5.4 Run Python3 Demo

Download Python Demo named 'python3' from our Wiki and up-zip it to Desktop(or wherever you want put it).

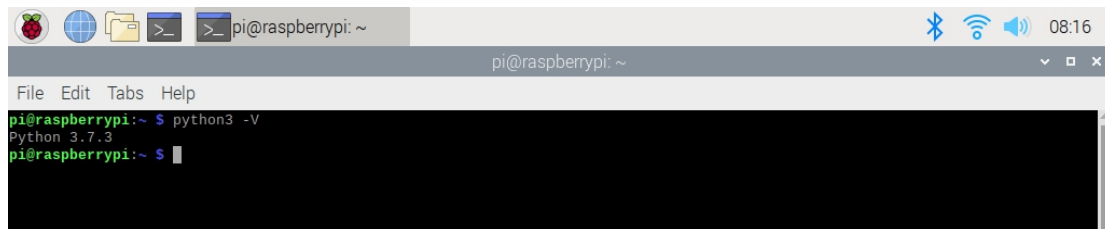
http://www.inno-maker.com/wiki/doku.php?id=usb_can

Or <http://www.inno-maker.com/wiki/doku.php>

There are three files in the folder. 'send.py' and 'receive.py' is for you use two Raspberry Pi to test, and 'test.py' is for you use one Raspberry Pi and two USB2CAN module to test.

(1) Check the Python version of your Raspbian. Python 3.7.3 default in 2019-09-26-Raspbian.img. Our Demo can run on any Python3 version.

`python3 -V`



```
pi@raspberrypi: ~
python3 -V
Python 3.7.3
```

(2) If you can't find the Python3 in system. Install the Python3

`sudo apt-get install python3-pip`

(3) If you are use Ubuntu system, It may can't use the 'ifconfig' command. Please install the net tools.

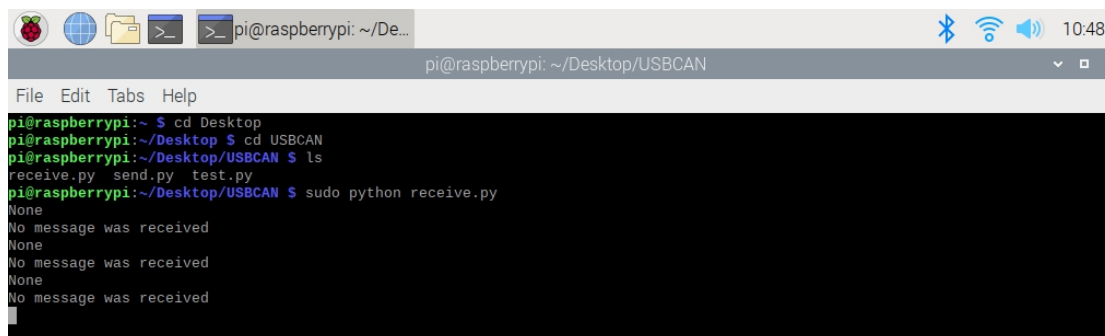
`sudo apt install net-tools`

(4) Install Python CAN library.

`sudo pip3 install python-can`

(5) Set one Raspberry Pi as receiver.

`sudo python3 receive.py`



```
pi@raspberrypi: ~/Desktop/USBCAN
sudo python3 receive.py
None
No message was received
None
No message was received
None
No message was received
```

(6) Set the other as sender.

`sudo python3 receive.py`

```

pi@raspberrypi: ~/Desktop/USBCAN
File Edit Tabs Help
pi@raspberrypi:~ $ cd Desktop
pi@raspberrypi:~/Desktop $ cd USBCAN
pi@raspberrypi:~/Desktop/USBCAN $ ls
receive.py send.py test.py
pi@raspberrypi:~/Desktop/USBCAN $ sudo python send.py
pi@raspberrypi:~/Desktop/USBCAN $
  
```

(7) You will see the data received.

```

pi@raspberrypi: ~/Desktop/USBCAN
File Edit Tabs Help
None
No message was received
None
No message was received
None
No message was received
None
No message was received
None
No message was received
None
No message was received
None
No message was received
None
No message was received
Timestamp: 1567158754.555561 ID: 0123 S DLC: 4 00 01 02 03 Channel: can0
None
  
```

(8) If you use one Raspberry Pi and two USB2CAN module for testing. Run 'test.py' and check the result.

`sudo python3 test.py`

```

pi@raspberrypi: ~/Desktop/python3
File Edit Tabs Help
pi@raspberrypi:~ $ cd Desktop/python3
pi@raspberrypi:~/Desktop/python3 $ ls
receive.py send.py test.py
pi@raspberrypi:~/Desktop/python3 $ sudo python3 test.py
Timestamp: 0.000000 ID: 0123 S DLC: 4 55 aa 5a a5
Timestamp: 1575116121.400328 ID: 0123 S DLC: 4 55 aa 5a a5 Channel: can0
Both USB2CAN module communication test successful
pi@raspberrypi:~/Desktop/python3 $
  
```


6. Software Description

Now with previous demo's code to show you how to program socket can in Raspbian with C and Python . The socket can is an implementation of CAN protocols (Controller Area Network) for Linux. CAN is a networking technology which has widespread use in automation, embedded devices, and automotive fields. While there have been other CAN implementations for Linux based on character devices, Socket CAN uses the Berkeley socket API, the Linux network stack and implements the CAN device drivers as network interfaces. The CAN socket API has been designed as similar as possible to the TCP/IP protocols to allow programmers, familiar with network programming, to easily learn how to use CAN sockets.

For more Socket CAN detail please refer to below link:

<https://www.kernel.org/doc/Documentation/networking/can.txt>

https://elinux.org/CAN_Bus

6.1 Programming in C

6.1.1 For Sender's codes

(1): Create the socket, If an error occurs then the return result is -1.

```
/*Create socket*/
s = socket(PF_CAN, SOCK_RAW, CAN_RAW);
if (s < 0) {
    perror("Create socket PF_CAN failed");
    return 1;
}
```

(2): Locate the interface to "can0" or other name you wish to use. The name will show when you execute `"/ifconfig -a"`.

```
/*Specify can0 device*/
strcpy(ifr.ifr_name, "can0");
ret = ioctl(s, SIOCGIFINDEX, &ifr);
if (ret < 0) {
    perror("ioctl interface index failed!");
    return 1;
}
```

(3): Bind the socket to "can0".

```
/*Bind the socket to can0*/
addr.can_family = PF_CAN;
addr.can_ifindex = ifr.ifr_ifindex;
ret = bind(s, (struct sockaddr *)&addr, sizeof(addr));
if (ret < 0) {
    perror("bind failed");
    return 1;
}
```

(4): Disable sender's filtering rules, this program only send message do not receive packets.

```
/*Disable filtering rules, this program only send message do not receive packets */
setsockopt(s, SOL_CAN_RAW, CAN_RAW_FILTER, NULL, 0);
```

(5): Assembly data to send.

```
/*assembly message data! */
frame.can_id = 0x123;
frame.can_dlc = 8;
frame.data[0] = 1;
frame.data[1] = 2;
frame.data[2] = 3;
frame.data[3] = 4;
frame.data[4] = 5;
frame.data[5] = 6;
frame.data[6] = 7;
frame.data[7] = 8;
//if(frame.can_id&CAN_EFF_FLAG==0)
if(!(frame.can_id&CAN_EFF_FLAG))
    printf("Transmit standard frame!\n");
else
    printf("Transmit extended frame!\n");
```

(6): Send message to the can bus. You can use the return value of write() to check whether all data has been sent successfully .

```
/*Send message out */
nbytes = write(s, &frame, sizeof(frame));
if(nbytes != sizeof(frame)) {
    printf("Send frame incompletely!\r\n");
    system("sudo ifconfig can0 down");
}
```

(7): Close can0 device and disable socket.

```
/*Close can0 device and destroy socket!*/
close(s);
```

6.2.3 For Receiver's codes

(1) step 1 and (2) is same as Sender's code.

(3): It's different from Sender's.

```
/*Bind the socket to can0*/
addr.can_family = PF_CAN;
addr.can_ifindex = ifr.ifr_ifindex;
ret = bind(s, (struct sockaddr *)&addr, sizeof(addr));
if (ret < 0) {
    perror("bind failed");
    return 1;
}
```

(4): Define receive filter rules, we can set more than one filter rule.

```
/*Define receive filter rules, we can set more than one filter rule!*/
struct can_filter rfilter[2];
rfilter[0].can_id = 0x123; //Standard frame id !
rfilter[0].can_mask = CAN_SFF_MASK;
rfilter[1].can_id = 0x12345678; //extend frame id!
rfilter[1].can_mask = CAN_EFF_MASK;
```

(5): Read data back from can bus.

```
while(1) {
    nbytes = read(s, &frame, sizeof(frame));
```

6.2 Programming in Python

6.2.1 Import

`import os`

The OS module in Python provides a way of using operating system dependent functionality. The functions that the OS module provides allows you to interface with the underlying operating system that Python is running on – be that Windows, Mac or Linux. We usually use `os.system()` function to execute a shell command to set CAN.

`import can`

The python-can library provides Controller Area Network support for Python, providing common abstractions to different hardware devices, and a suite of utilities for sending and receiving messages on a CAN bus.

For more information about python-can, please to below link:

<https://python-can.readthedocs.io/en/stable/index.html>

`ifconfig`

If you are use Ubuntu system, It may can't use the 'ifconfig' command. Please install the net tools.

`sudo apt install net-tools`

6.2.1 Simple common functions

(1) Set bitrate and start up CAN device.

`os.system('sudo ip link set can0 type can bitrate 1000000')`

`os.system('sudo ifconfig can0 up')`

(2) Bind the socket to 'can0'.

`can0 = can.interface.Bus(channel = 'can0', bustype = 'socketcan ctypes')`

(3) Assembly data to send.

`msg = can.Message(arbitration_id=0x123, data=[0, 1, 2, 3], extended_id=False)`

(4) Send data.

`can0.send(msg)`

(5) Receive data.

`msg = can0.recv(30.0)`

(6) Close CAN device

`os.system('sudo ifconfig can0 down')`

Support: support@inno-maker.com <http://wiki.inno-maker.com/display/HOMEPAGE>

Bulk Price: sales@inno-maker.com

7. User Manual Version Descriptions

Version	Description	Date	E-mail
V1.1		2019.02.02	support@inno-maker.com sales@inno-maker.com
V1.2	Add Python Add can-utils	2019.08.26	calvin@inno-maker.com
V1.3	Correct description	2019.08.26	calvin@inno-maker.com
V1.4	Added DB9 Description Added CAN utils tools loopback mode description	2020.10.11	calvin@inno-maker.com
V1.5	Added description for how to install net tools on Ubuntu system	2021.05.01	calvin@inno-maker.com

If you have any suggestions, ideas, codes and tools please feel free to email to me. I will update the user manual and record your name and E-mail in list. Look forward to your letter and kindly share.