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2006-05-16	2.0	AUTOSAR Administration	<ul style="list-style-type: none"> <li>• Document structure adapted to common Release 2.0 SWS Template</li> <li>• clarified development and production error handling and function abortion</li> <li>• multiplexed transmission and TX cancellation</li> <li>• version check</li> <li>• configuration description according template</li> <li>• individual main functions for RX TX and status</li> <li>•</li> </ul>



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2005-05-31	1.0	AUTOSAR Administration	<ul style="list-style-type: none"><li>• Initial release</li></ul>

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## 1 Introduction and functional overview

This specification specifies the functionality, API and the configuration of the AUTOSAR Basic Software module CAN Driver (called “Can module” in this document).

The Can module is part of the lowest layer, performs the hardware access and offers a hardware independent API to the upper layer.

The only upper layer that has access to the Can module is the CanIf module (see also SRS\_SPAL\_12092).

The Can module provides services for initiating transmissions and calls the callback functions of the CanIf module for notifying events, independently from the hardware.

Furthermore, it provides services to control the behavior and state of the CAN controllers that are belonging to the same CAN Hardware Unit.

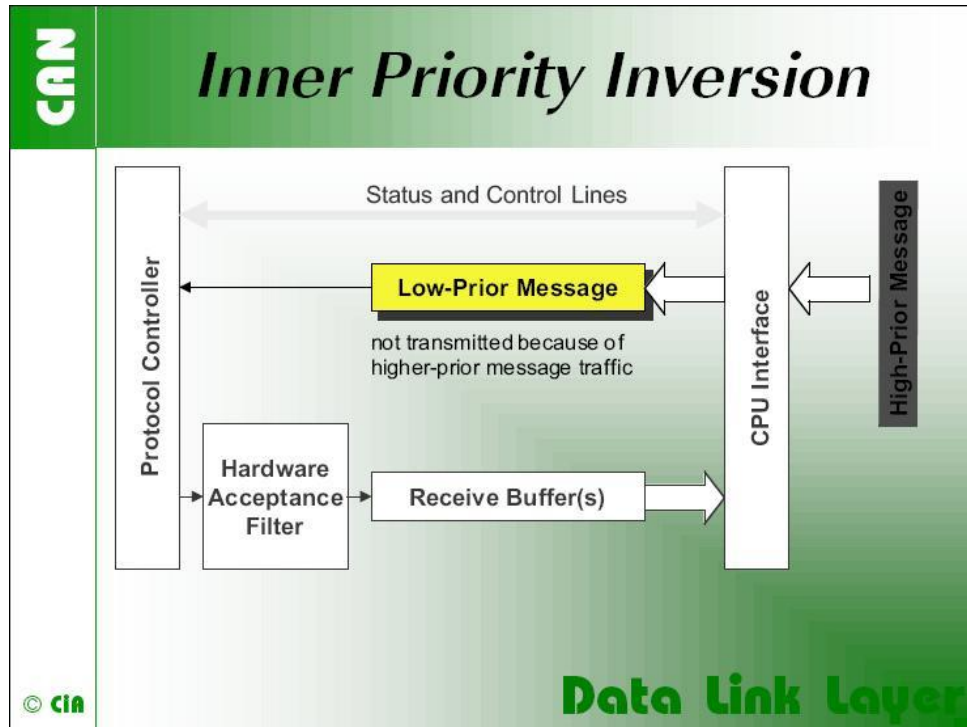
Several CAN controllers can be controlled by a single Can module as long as they belong to the same CAN Hardware Unit.

For a closer description of CAN controller and CAN Hardware Unit see chapter Acronyms and abbreviations and a diagram in [5].

## 2 Acronyms and abbreviations

<b>Abbreviation / Acronym:</b>	<b>Description:</b>
CAN controller	A CAN controller serves exactly one physical channel.
CAN Hardware Unit	A CAN Hardware Unit may consists of one or multiple CAN controllers of the same type and one or multiple CAN RAM areas. The CAN Hardware Unit is either on-chip, or an external device. The CAN Hardware Unit is represented by one CAN driver.
CAN L-PDU	Data Link Layer Protocol Data Unit. Consists of Identifier, Data Length and Data (SDU). (see[18])
CAN L-SDU	Data Link Layer Service Data Unit. Data that is transported inside the L-PDU. (see[18])
DLC	Data Length Code (part of CAN message describes the SDU length)
Hardware Object	A CAN hardware object is defined as a PDU buffer inside the CAN RAM of the CAN hardware unit / CAN controller. A Hardware Object is defined as L-PDU buffer inside the CAN RAM of the CAN Hardware Unit.
Hardware Receive Handle (HRH)	The Hardware Receive Handle (HRH) is defined and provided by the CAN Driver. Each HRH typically represents just one hardware object. The HRH can be used to optimize software filtering.
Hardware Transmit Handle (HTH)	The Hardware Transmit Handle (HTH) is defined and provided by the CAN Driver. Each HTH typically represents just one or multiple hardware objects that are configured as hardware transmit buffer pool.
Inner Priority Inversion	Transmission of a high-priority L-PDU is prevented by the presence of a pending low-priority L-PDU in the same transmit hardware object.
ISR	Interrupt Service Routine
L-PDU Handle	The L-PDU handle is defined and placed inside the CanIf module layer. Typically each handle represents an L-PDU, which is a constant structure with information for Tx/Rx processing.
MCAL	Microcontroller Abstraction Layer
Outer Priority Inversion	A time gap occurs between two consecutive transmit L-PDUs. In this case a lower priority L-PDU from another node can prevent sending the own higher priority L-PDU. Here the higher priority L-PDU cannot participate in arbitration during network access because the lower priority L-PDU already won the arbitration.
Physical Channel	A physical channel represents an interface from a CAN controller to the CAN Network. Different physical channels of the CAN hardware unit may access different networks.
Priority	The Priority of a CAN L-PDU is represented by the CAN Identifier. The lower the numerical value of the identifier, the higher the priority.
SFR	Special Function Register. Hardware register that controls the controller behavior.
SPAL	Standard Peripheral Abstraction Layer
ICOM	Intelligent Communication Controller

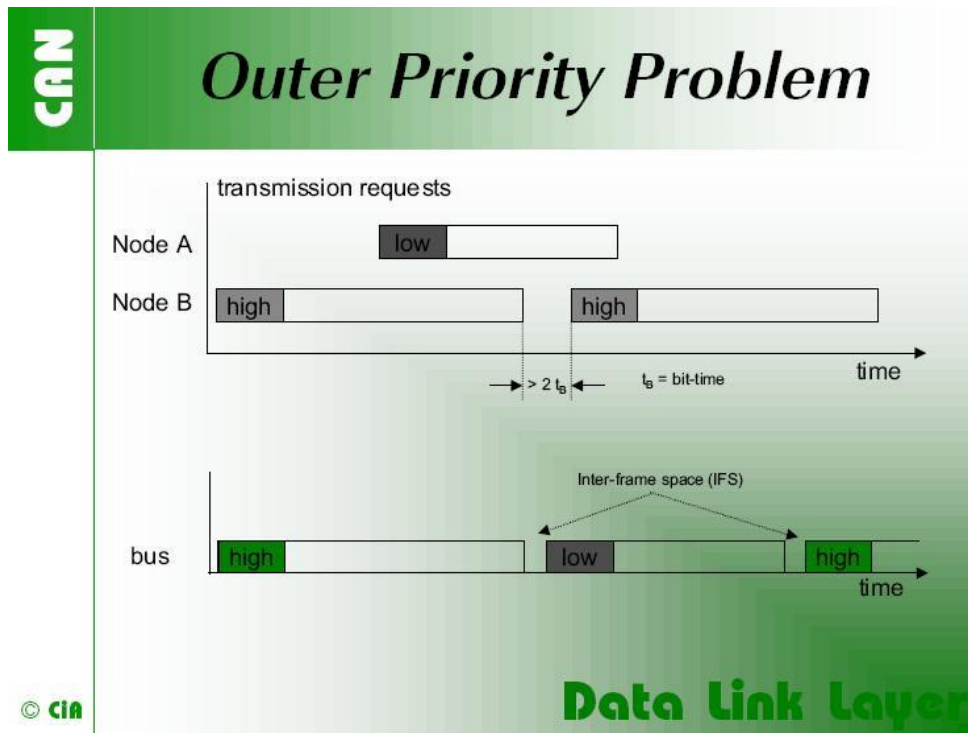
## 2.1 Priority Inversion



“If only a single transmit buffer is used inner priority inversion may occur. Because of low priority a message stored in the buffer waits until the “traffic on the bus calms down”. During the waiting time this message could prevent a message of higher priority generated by the same microcontroller from being transmitted over the bus.”<sup>1</sup>

<sup>1</sup> Picture and text by CiA (CAN in Automation)  
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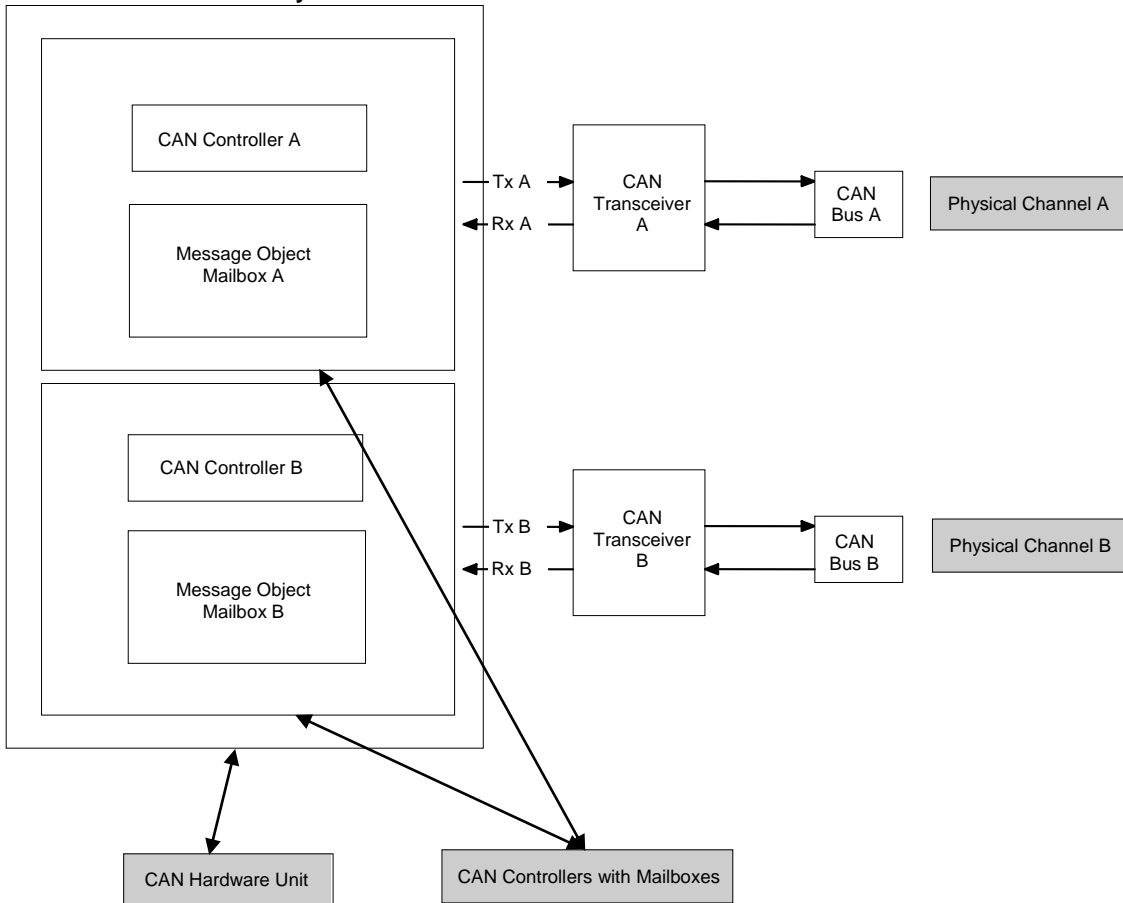
“The problem of outer priority inversion may occur in some CAN implementations. Let us assume that a CAN node wishes to transmit a package of consecutive messages with high priority, which are stored in different message buffers. If the interframe space between these messages on the CAN network is longer than the minimum space defined by the CAN standard, a second node is able to start the transmission of a lower priority message. The minimum interframe space is determined by the Intermission field, which consists of 3 recessive bits. A message, pending during the transmission of another message, is started during the Bus Idle period, at the earliest in the bit following the Intermission field. The exception is that a node with a waiting transmission message will interpret a dominant bit at the third bit of Intermission as Start-of-Frame bit and starts transmission with the first identifier bit without first transmitting an SOF bit. The internal processing time of a CAN module has to be short enough to send out consecutive messages with the minimum interframe space to avoid the outer priority inversion under all the scenarios mentioned.”<sup>2</sup>

<sup>2</sup> Text and image by CiA (CAN in Automation)  
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## 2.2 CAN Hardware Unit

The CAN Hardware Unit combines one or several CAN controllers, which may be located on-chip or as external standalone devices of the same type, with common or separate Hardware Objects.

Following figure shows a CAN Hardware Unit consisting of two CAN controllers connected to two Physical Channels:



## 3 Related documentation

### 3.1 Input documents

- [1] Layered Software Architecture  
AUTOSAR\_EXP\_LayeredSoftwareArchitecture..pdf
- [2] General Requirements on Basic Software Modules  
AUTOSAR\_SRS\_BSWGeneral.pdf
- [3] General Requirements on SPAL  
AUTOSAR\_SRS\_SPALGeneral.pdf
- [4] Requirements on CAN  
AUTOSAR\_SRS\_CAN.pdf
- [5] Specification of CAN Interface  
AUTOSAR\_SWS\_CANInterface.pdf
- [6] Specification of Default Error Tracer  
AUTOSAR\_SWS\_DefaultErrorTracer.pdf
- [7] Specification of ECU State Manager  
AUTOSAR\_SWS\_ECUStateManager.pdf
- [8] Specification of MCU Driver  
AUTOSAR\_SWS\_MCUDriver.pdf
- [9] Specification of Operating System  
AUTOSAR\_SWS\_OS.pdf
- [10] Specification of ECU Configuration  
AUTOSAR\_TPS\_ECUConfiguration.pdf
- [11] Specification of SPI Handler/Driver  
AUTOSAR\_SWS\_SPIHandlerDriver.doc.pdf
- [12] Specification of Memory Mapping  
AUTOSAR\_SWS\_MemoryMapping.pdf
- [13] Specification of BSW Scheduler  
AUTOSAR\_SWS\_BSW\_Scheduler.pdf
- [14] Basic Software Module Description Template  
AUTOSAR\_TPS\_BSWModuleDescriptionTemplate.pdf
- [15] List of Basis Software Modules  
AUTOSAR\_TR\_BSWModuleList.pdf

- [16] General Specification of Basic Software Modules  
[AUTOSAR\\_SWS\\_BSWGeneral.pdf](#)

### 3.2 Related standards and norms

- [17] [ISO11898 – Road vehicles - Controller area network \(CAN\)](#)  
[18] [ISO-IEC 7498-1 – OSI Basic Reference Model](#)

### 3.3 Related specification

[AUTOSAR provides a General Specification on Basic Software modules \[16\] \(SWS BSW General\), which is also valid for CAN Driver.](#)

[Thus, the specification SWS BSW General shall be considered as additional and required specification for CAN Driver.](#)

## 4 Constraints and assumptions

### 4.1 Limitations

A CAN controller always corresponds to one physical channel. It is allowed to connect physical channels on bus side. Regardless the CanIf module will treat the concerned CAN controllers separately.

A few CAN hardware units support the possibility to combine several CAN controllers by using the CAN RAM, to extend the number of message objects for one CAN controller. These combined CAN controller are handled as one controller by the Can module.

The Can module does not support CAN remote frames.

**[SWS\_Can\_00237]** [ The Can module shall not transmit messages triggered by remote transmission requests.] (SRS\_Can\_01147)

**[SWS\_Can\_00236]** [ The Can module shall initialize the CAN HW to ignore any remote transmission requests.] (SRS\_Can\_01147)

### 4.2 Applicability to car domains

The Can module can be used for any application, where the CAN protocol is used.

## 5 Dependencies to other modules

### 5.1 Static Configuration

The configuration elements described in chapter 10 can be referenced by other BSW modules for their configuration.

### 5.2 Driver Services

**[SWS\_Can\_00238]** [ If the CAN controller is on-chip, the Can module shall not use any service of other drivers.] (SRS\_BSW\_00005)

**[SWS\_Can\_00239]** [ The function Can\_Init shall initialize all on-chip hardware resources that are used by the CAN controller. The only exception to this is the digital I/O pin configuration (of pins used by CAN), which is done by the port driver.] (SRS\_BSW\_00377)

**[SWS\_Can\_00240]** [ The Mcu module (SPAL see [8]) shall configure register settings that are 'shared' with other modules.] ()

Implementation hint: The Mcu module shall be initialized before initializing the Can module.

**[SWS\_Can\_00242]** [ If an off-chip CAN controller is used<sup>3</sup>, the Can module shall use services of other MCAL drivers (e.g. SPI).] (SRS\_BSW\_00005)

Implementation hint: If the Can module uses services of other MCAL drivers (e.g. SPI), it must be ensured that these drivers are up and running before initializing the Can module.

The sequence of initialization of different drivers is partly specified in [7].

**[SWS\_Can\_00244]** [ The Can module shall use the synchronous APIs of the underlying MCAL drivers and shall not provide callback functions that can be called by the MCAL drivers.] ()

Thus the type of connection between  $\mu$ C and CAN Hardware Unit has only impact on implementation and not on the API.

### 5.3 System Services

**[SWS\_Can\_00280]** [ In special hardware cases, the Can module shall poll for events of the hardware.] ()

**[SWS\_Can\_00281]** [ The Can module shall use the OsCounter provided by the system service for timeout detection in case the hardware does not react in the expected time (hardware malfunction) to prevent endless loops.] ()

Implementation hint: The blocking time of the Can module function that is waiting for hardware reaction shall be shorter than the CAN main function (i.e. Can\_MainFunction\_Read) trigger period, because the CAN main functions can't be used for that purpose.

---

<sup>3</sup> In this case the CAN driver is not any more part of the  $\mu$ C abstraction layer but part of the ECU abstraction layer. Therefore it is (theoretically) allowed to use any  $\mu$ C abstraction layer driver it needs.

## 5.4 Can module Users

**[SWS\_Can\_00058]** [ The Can module interacts among other modules (eg. Diagnostic Event Manager (DEM), Default Error Tracer (DET), Ecu State Manager (ECUM)) with the CanIf module in a direct way. This document never specifies the actual origin of a request or the actual destination of a notification. The driver only sees the CanIf module as origin and destination.] (SRS\_SPAL\_12092)

## 5.5 File structure

### 5.5.1 Header file structure

[SWS\_Can\_00034] [

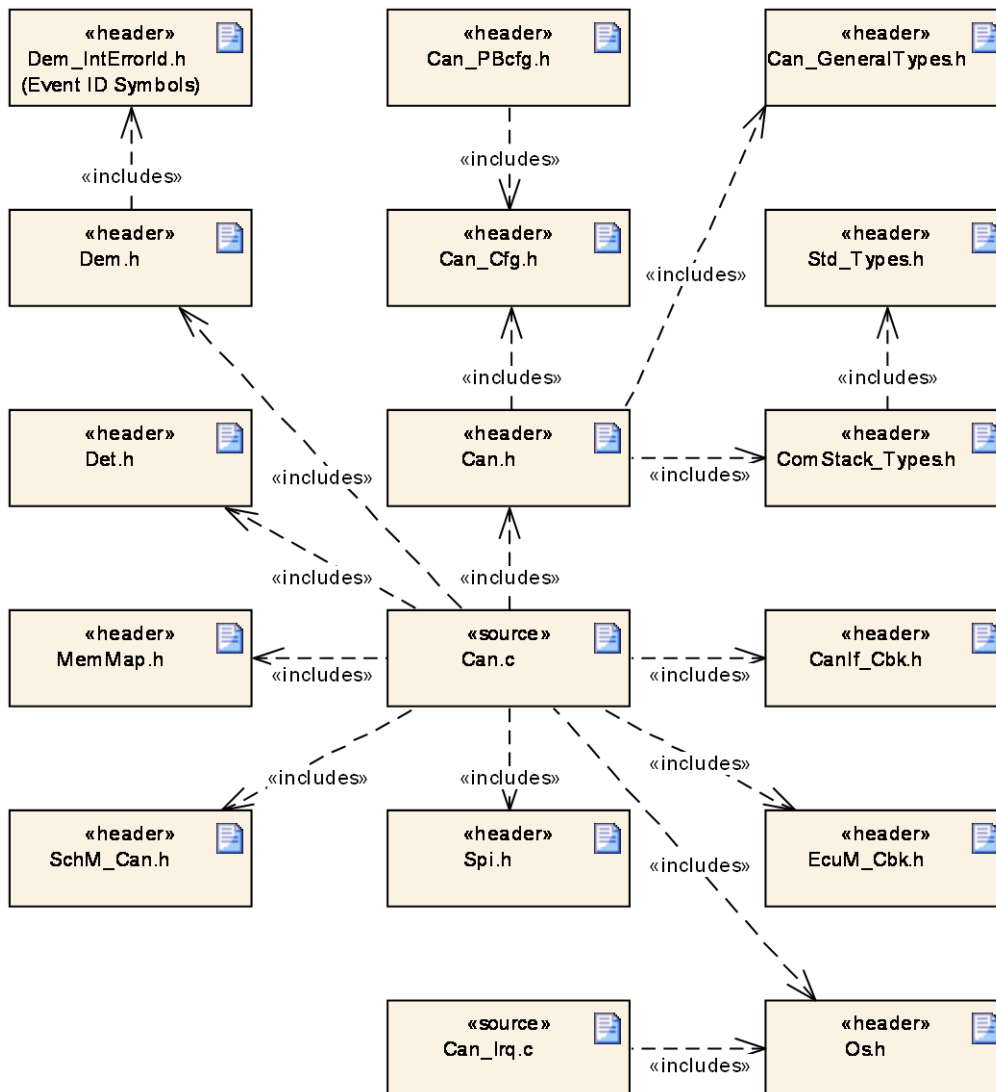


Figure 5-1: File structure for the Can module] (SRS\_BSW\_00381, SRS\_BSW\_00412, SRS\_BSW\_00346, SRS\_BSW\_00158, SRS\_BSW\_00348, SRS\_BSW\_00301)

[SWS\_Can\_00435] [ The Can.h file shall include Can\_GeneralTypes.h.] ( )

[SWS\_Can\_00436] [ Can\_GeneralTypes.h shall contain all types and constants that are shared among the AUTOSAR CAN modules Can, CanIf and CanTrcv.] ( )

[SWS\_Can\_00388] [ The header file Can.h shall include the header file ComStack\_Types.h.] ( )



**[SWS\_Can\_00035]** [

The Can module does not provide callback functions (no Can\_Cbk.h, see also [SWS\\_Can\\_00244](#)) ] ()

**[SWS\_Can\_00390]** [ The Can module shall include the header file EcuM\_Cbk.h, in which the callback functions called by the Can module at the Ecu State Manager module are declared.] ()

**[SWS\_Can\_00391]** [ Can module implementations for off-chip CAN controllers shall include the header file Spi.h. By this inclusion, the APIs to access an external CAN controller by the SPI module [11] are included.] ()

**[SWS\_Can\_00397]** [ The Can module shall include the header file Os.h file. By this inclusion, the API to read a OsCounter value (GetCounterValue) provided by the system service shall be included.] ()

## 6 Requirements traceability

Requirement	Description	Satisfied by
SRS_BSW_00005	Modules of the $\mu$ C Abstraction Layer (MCAL) may not have hard coded horizontal interfaces	SWS_Can_00238, SWS_Can_00242
SRS_BSW_00007	All Basic SW Modules written in C language shall conform to the MISRA C 2012 Standard.	SWS_Can_00079
SRS_BSW_00101	The Basic Software Module shall be able to initialize variables and hardware in a separate initialization function	SWS_Can_00250
SRS_BSW_00158	All modules of the AUTOSAR Basic Software shall strictly separate configuration from implementation	SWS_Can_00034
SRS_BSW_00159	All modules of the AUTOSAR Basic Software shall support a tool based configuration	SWS_Can_00022
SRS_BSW_00162	The AUTOSAR Basic Software shall provide a hardware abstraction layer	SWS_Can_00999
SRS_BSW_00164	The Implementation of interrupt service routines shall be done by the Operating System, complex drivers or modules	SWS_Can_00033
SRS_BSW_00167	All AUTOSAR Basic Software Modules shall provide configuration rules and constraints to enable plausibility checks	SWS_Can_00024
SRS_BSW_00168	SW components shall be tested by a function defined in a common API in the Basis-SW	SWS_Can_00999
SRS_BSW_00170	The AUTOSAR SW Components shall provide information about their dependency from faults, signal qualities, driver demands	SWS_Can_00999
SRS_BSW_00301	All AUTOSAR Basic Software Modules shall only import the necessary information	SWS_Can_00034
SRS_BSW_00306	AUTOSAR Basic Software Modules shall be compiler and platform independent	SWS_Can_00079
SRS_BSW_00307	Global variables naming convention	SWS_Can_00999
SRS_BSW_00308	AUTOSAR Basic Software Modules shall not define global data in their header files, but in the C file	SWS_Can_00079
SRS_BSW_00309	All AUTOSAR Basic Software Modules shall indicate all global data with read-only purposes by explicitly assigning the const keyword	SWS_Can_00079
SRS_BSW_00312	Shared code shall be reentrant	SWS_Can_00214, SWS_Can_00231, SWS_Can_00232, SWS_Can_00233

SRS_BSW_00323	All AUTOSAR Basic Software Modules shall check passed API parameters for validity	SWS_Can_00026, SWS_Can_91006, SWS_Can_91007, SWS_Can_91017, SWS_Can_91018
SRS_BSW_00325	The runtime of interrupt service routines and functions that are running in interrupt context shall be kept short	SWS_Can_00999
SRS_BSW_00330	It shall be allowed to use macros instead of functions where source code is used and runtime is critical	SWS_Can_00079
SRS_BSW_00331	All Basic Software Modules shall strictly separate error and status information	SWS_Can_00039, SWS_Can_00104
SRS_BSW_00336	Basic SW module shall be able to shutdown	SWS_Can_00999, SWS_Can_91002
SRS_BSW_00337	Classification of development errors	SWS_Can_00026, SWS_Can_00104
SRS_BSW_00342	It shall be possible to create an AUTOSAR ECU out of modules provided as source code and modules provided as object code, even mixed	SWS_Can_00999
SRS_BSW_00344	BSW Modules shall support link-time configuration	SWS_Can_00021
SRS_BSW_00346	All AUTOSAR Basic Software Modules shall provide at least a basic set of module files	SWS_Can_00034
SRS_BSW_00347	A Naming separation of different instances of BSW drivers shall be in place	SWS_Can_00077
SRS_BSW_00348	All AUTOSAR standard types and constants shall be placed and organized in a standard type header file	SWS_Can_00034
SRS_BSW_00353	All integer type definitions of target and compiler specific scope shall be placed and organized in a single type header	SWS_Can_00999
SRS_BSW_00357	For success/failure of an API call a standard return type shall be defined	SWS_CAN_00506
SRS_BSW_00358	The return type of init() functions implemented by AUTOSAR Basic Software Modules shall be void	SWS_Can_00223
SRS_BSW_00359	All AUTOSAR Basic Software Modules callback functions shall avoid return types other than void if possible	SWS_Can_00999
SRS_BSW_00361	All mappings of not standardized keywords of compiler specific scope shall be placed and organized in a compiler specific type and keyword header	SWS_Can_00999
SRS_BSW_00369	All AUTOSAR Basic Software Modules shall not return specific development error codes via the API	SWS_Can_00089, SWS_CAN_00506, SWS_Can_91011, SWS_Can_91012
SRS_BSW_00373	The main processing function of each	SWS_Can_00031

	AUTOSAR Basic Software Module shall be named according the defined convention	
SRS_BSW_00375	Basic Software Modules shall report wake-up reasons	SWS_Can_00271, SWS_Can_00364
SRS_BSW_00377	A Basic Software Module can return a module specific types	SWS_Can_00239
SRS_BSW_00378	AUTOSAR shall provide a boolean type	SWS_Can_00999
SRS_BSW_00381	The pre-compile time parameters shall be placed into a separate configuration header file	SWS_Can_00034
SRS_BSW_00383	The Basic Software Module specifications shall specify which other configuration files from other modules they use at least in the description	SWS_Can_00999
SRS_BSW_00385	List possible error notifications	SWS_Can_00104
SRS_BSW_00386	The BSW shall specify the configuration for detecting an error	SWS_Can_00089
SRS_BSW_00395	The Basic Software Module specifications shall list all configuration parameter dependencies	SWS_Can_00999
SRS_BSW_00397	The configuration parameters in pre-compile time are fixed before compilation starts	SWS_Can_00999
SRS_BSW_00398	The link-time configuration is achieved on object code basis in the stage after compiling and before linking	SWS_Can_00999
SRS_BSW_00399	Parameter-sets shall be located in a separate segment and shall be loaded after the code	SWS_Can_00999
SRS_BSW_00400	Parameter shall be selected from multiple sets of parameters after code has been loaded and started	SWS_Can_00999
SRS_BSW_00404	BSW Modules shall support post-build configuration	SWS_Can_00021
SRS_BSW_00405	BSW Modules shall support multiple configuration sets	SWS_Can_00021
SRS_BSW_00406	A static status variable denoting if a BSW module is initialized shall be initialized with value 0 before any APIs of the BSW module is called	SWS_Can_00103, SWS_Can_91005, SWS_Can_91016
SRS_BSW_00409	All production code error ID symbols are defined by the Dem module and shall be retrieved by the other BSW modules from Dem configuration	SWS_Can_00999
SRS_BSW_00412	References to c-configuration parameters shall be placed into a separate h-file	SWS_Can_00034
SRS_BSW_00413	An index-based accessing of the instances of BSW modules shall be done	SWS_Can_00999
SRS_BSW_00414	Init functions shall have a pointer to a configuration structure as single parameter	SWS_Can_00223

SRS_BSW_00415	Interfaces which are provided exclusively for one module shall be separated into a dedicated header file	SWS_Can_00999
SRS_BSW_00416	The sequence of modules to be initialized shall be configurable	SWS_Can_91005, SWS_Can_91016
SRS_BSW_00417	Software which is not part of the SW-C shall report error events only after the DEM is fully operational.	SWS_Can_00999
SRS_BSW_00422	Pre-de-bouncing of error status information is done within the DEM	SWS_Can_00999
SRS_BSW_00423	BSW modules with AUTOSAR interfaces shall be describable with the means of the SW-C Template	SWS_Can_00999
SRS_BSW_00424	BSW module main processing functions shall not be allowed to enter a wait state	SWS_Can_00999
SRS_BSW_00425	The BSW module description template shall provide means to model the defined trigger conditions of schedulable objects	SWS_Can_00999
SRS_BSW_00426	BSW Modules shall ensure data consistency of data which is shared between BSW modules	SWS_Can_00999
SRS_BSW_00427	ISR functions shall be defined and documented in the BSW module description template	SWS_Can_00999
SRS_BSW_00428	A BSW module shall state if its main processing function(s) has to be executed in a specific order or sequence	SWS_Can_00110
SRS_BSW_00429	Access to OS is restricted	SWS_Can_00999
SRS_BSW_00432	Modules should have separate main processing functions for read/receive and write/transmit data path	SWS_Can_00031, SWS_Can_00108, SWS_Can_00112
SRS_BSW_00433	Main processing functions are only allowed to be called from task bodies provided by the BSW Scheduler	SWS_Can_00999
SRS_BSW_00438	Configuration data shall be defined in a structure	SWS_Can_00291
SRS_BSW_00439	Enable BSW modules to handle interrupts	SWS_Can_00999
SRS_BSW_00440	The callback function invocation by the BSW module shall follow the signature provided by RTE to invoke servers via Rte_Call API	SWS_Can_00999
SRS_BSW_00447	Standardizing Include file structure of BSW Modules Implementing Autosar Service	SWS_Can_00999
SRS_BSW_00449	BSW Service APIs used by Autosar Application Software shall return a Std_ReturnType	SWS_CAN_00506, SWS_Can_00999
SRS_BSW_00453	BSW Modules shall be harmonized	SWS_Can_00999
SRS_Can_01005	The CAN Interface shall perform a check for correct DLC of received PDUs	SWS_Can_00218

SRS_Can_01041	The CAN Driver shall implement an interface for initialization	SWS_Can_00245, SWS_Can_00246
SRS_Can_01042	The CAN Driver shall support dynamic selection of configuration sets	SWS_Can_00062
SRS_Can_01043	The CAN Driver shall provide a service to enable/disable interrupts of the CAN Controller.	SWS_Can_00049, SWS_Can_00050
SRS_Can_01045	The CAN Driver shall offer a reception indication service.	SWS_Can_00279, SWS_Can_00396
SRS_Can_01049	The CAN Driver shall provide a dynamic transmission request service	SWS_Can_00212, SWS_Can_00213, SWS_Can_00214
SRS_Can_01051	The CAN Driver shall provide a transmission confirmation service	SWS_Can_00016
SRS_Can_01053	The CAN Driver shall provide a service to change the CAN controller mode.	SWS_Can_00017, SWS_Can_91010
SRS_Can_01054	The CAN Driver shall provide a notification for controller wake-up events	SWS_Can_00235, SWS_Can_00271, SWS_Can_00364
SRS_Can_01055	The CAN Driver shall provide a notification for bus-off state	SWS_Can_00020, SWS_Can_00234
SRS_Can_01059	The CAN Driver shall guarantee data consistency of received L-PDUs	SWS_Can_00011, SWS_Can_00012
SRS_Can_01060	The CAN driver shall not recover from bus-off automatically	SWS_Can_00272, SWS_Can_00273, SWS_Can_00274
SRS_Can_01062	Each event for each CAN Controller shall be configurable to be detected by polling or by an interrupt	SWS_Can_00007
SRS_Can_01122	The CAN driver shall support the situation where a wakeup by bus occurs during the same time the transition to standby/sleep is in progress	SWS_Can_00048
SRS_Can_01125	The CAN stack shall ensure not to lose messages in receive direction	SWS_Can_00999
SRS_Can_01126	The CAN stack shall be able to produce 100% bus load	SWS_Can_00999
SRS_Can_01130	Receive Status Interface of CAN Interface	SWS_CAN_00506
SRS_Can_01132	The CAN driver shall be able to detect notification events message object specific by CAN-Interrupt and polling	SWS_Can_00099
SRS_Can_01134	The CAN Driver shall support multiplexed transmission	SWS_Can_00277, SWS_Can_00401, SWS_Can_00402, SWS_Can_00403
SRS_Can_01135	It shall be possible to configure one or several TX Hardware Objects	SWS_Can_00100
SRS_Can_01139	The CAN Interface and Driver shall offer a CAN Controller specific interface for	SWS_Can_00062

	initialization	
SRS_Can_01147	The CAN Driver shall not support remote frames	SWS_Can_00236, SWS_Can_00237
SRS_Can_01160	Padding of bytes due to discrete CAN FD DLC	SWS_CAN_00502
SRS_Can_01162	The CAN Interface shall support classic CAN and CAN FD frames	SWS_CAN_00501
SRS_Can_01166	The CAN Driver shall implement an interface for de-initialization	noname, SWS_Can_91002, SWS_Can_91010
SRS_CAN_01167	-	SWS_Can_91008
SRS_SPAL_00157	All drivers and handlers of the AUTOSAR Basic Software shall implement notification mechanisms of drivers and handlers	SWS_Can_00026, SWS_Can_00031, SWS_Can_00108, SWS_Can_00112
SRS_SPAL_12056	All driver modules shall allow the static configuration of notification mechanism	SWS_Can_00235
SRS_SPAL_12057	All driver modules shall implement an interface for initialization	SWS_Can_00245, SWS_Can_00246
SRS_SPAL_12063	All driver modules shall only support raw value mode	SWS_Can_00059, SWS_Can_00060
SRS_SPAL_12064	All driver modules shall raise an error if the change of the operation mode leads to degradation of running operations	SWS_Can_00999
SRS_SPAL_12067	All driver modules shall set their wake-up conditions depending on the selected operation mode	SWS_Can_00257
SRS_SPAL_12068	The modules of the MCAL shall be initialized in a defined sequence	SWS_Can_00999
SRS_SPAL_12069	All drivers of the SPAL that wake up from a wake-up interrupt shall report the wake-up reason	SWS_Can_00271, SWS_Can_00364
SRS_SPAL_12075	All drivers with random streaming capabilities shall use application buffers	SWS_Can_00011
SRS_SPAL_12077	All drivers shall provide a non blocking implementation	SWS_Can_00372
SRS_SPAL_12092	The driver's API shall be accessed by its handler or manager	SWS_Can_00058
SRS_SPAL_12125	All driver modules shall only initialize the configured resources	SWS_Can_00053
SRS_SPAL_12129	The ISRs shall be responsible for resetting the interrupt flags and calling the according notification function	SWS_Can_00033
SRS_SPAL_12163	All driver modules shall implement an interface for de-initialization	SWS_Can_00999
SRS_SPAL_12169	All driver modules that provide different operation modes shall provide a service for mode selection	SWS_Can_00017
SRS_SPAL_12263	The implementation of all driver modules	SWS_Can_00021

	shall allow the configuration of specific module parameter types at link time	
SRS_SPAL_12265	Configuration data shall be kept constant	SWS_Can_00021
SRS_SPAL_12448	All driver modules shall have a specific behavior after a development error detection	SWS_Can_00089, SWS_Can_00091
SRS_SPAL_12461	Specific rules regarding initialization of controller registers shall apply to all driver implementations	SWS_Can_00407
SRS_SPAL_12462	The register initialization settings shall be published	SWS_Can_00999
SRS_SPAL_12463	The register initialization settings shall be combined and forwarded	SWS_Can_00024



## 7 Functional specification

On L-PDU transmission, the Can module writes the L-PDU in an appropriate buffer inside the CAN controller hardware.

See chapter 7.5 for closer description of L-PDU transmission.

On L-PDU reception, the Can module calls the RX indication callback function with ID, Data Length and pointer to L-SDU as parameter.

See chapter 7.6 for closer description of L-PDU reception.

The Can module provides an interface that serves as periodical processing function, and which must be called by the Basic Software Scheduler module periodically.

Furthermore, the Can module provides services to control the state of the CAN controllers. Bus-off and Wake-up events are notified by means of callback functions.

The Can module is a Basic Software Module that accesses hardware resources. Therefore, it is designed to fulfill the requirements for Basic Software Modules specified in AUTOSAR\_SRS\_SPAL (see [3]).

**[SWS\_Can\_00033]** [ The Can module shall implement the interrupt service routines for all CAN Hardware Unit interrupts that are needed. ] (SRS\_BSW\_00164, SRS\_SPAL\_12129)

**[SWS\_Can\_00419]** [ The Can module shall disable all unused interrupts in the CAN controller.] ()

**[SWS\_Can\_00420]** [ The Can module shall reset the interrupt flag at the end of the ISR (if not done automatically by hardware). ] ()

Implementation hint: The Can module shall not set the configuration (i.e. priority) of the vector table entry.

**[SWS\_Can\_00079]** [ The Can module shall fulfill all design and implementation guidelines described in [2].] (SRS\_BSW\_00007, SRS\_BSW\_00306, SRS\_BSW\_00308, SRS\_BSW\_00309, SRS\_BSW\_00330)

### 7.1 Driver scope

One Can module provides access to one CAN Hardware Unit that may consist of several CAN controllers.

**[SWS\_Can\_00077]** [ For CAN Hardware Units of different type, different Can modules shall be implemented. ] (SRS\_BSW\_00347)

**[SWS\_Can\_00284]** [ In case several CAN Hardware Units (of same or different vendor) are implemented in one ECU the function names, and global variables of the Can modules shall be implemented such that no two functions with the same name are generated.] ()

The naming convention is as follows:

```
<Can module name>_<vendorID>_<Vendor specific API name><driver abbreviation>()
```

SRS\_BSW\_00347 specifies the naming convention.

**[SWS\_Can\_00385]** [ The naming conventions shall be used only in that case, if multiple different CAN controller types on one ECU have to be supported. ] ()

**[SWS\_Can\_00386]** [ If only one controller type is used, the original naming conventions without any <driver abbreviation> extensions are sufficient.] ()

See [5] for description how several Can modules are handled by the CanIf module.

## 7.2 Driver State Machine

The Can module has a very simple state machine, with the two states CAN\_UNINIT and CAN\_READY. Figure 7.1 shows the state machine.

**[SWS\_Can\_00103]** [ After power-up/reset, the Can module shall be in the state CAN\_UNINIT. ] (SRS\_BSW\_00406)

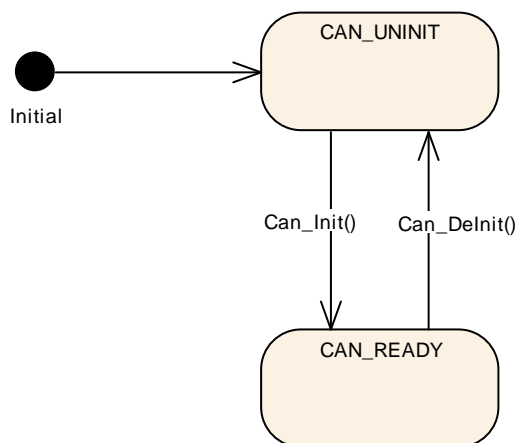


Figure 7-1

**[SWS\_Can\_00246]** [ The function Can\_Init shall change the module state to CAN\_READY, after initializing all controllers inside the HW Unit.] (SRS\_SPAL\_12057, SRS\_Can\_01041)

**[SWS\_Can\_00245]** [ The function Can\_Init shall initialize all CAN controllers according to their configuration.] (SRS\_SPAL\_12057, SRS\_Can\_01041)

Each CAN controller must then be started separately by calling the function Can\_SetControllerMode(CAN\_CS\_STARTED).

Implementation hint:

Hardware register settings that have impact on all CAN controllers inside the HW Unit can only be set in the function Can\_Init.

Implementation hint:

The ECU State Manager module shall call Can\_Init at most once during runtime.

**[SWS\_Can\_91009]** [The function Can\_Delnit shall change the module state to CAN\_UNINIT before de-initializing all controllers inside the HW unit](SRS\_Can\_01166) Refer to [SWS\_Can\_91010]

## 7.3 CAN Controller State Machine

Each CAN controller has complex state machines implemented in hardware. For simplification, the number of states is reduced to the following four basic states in this description: UNINIT, STOPPED, STARTED and SLEEP.

Any CAN hardware access is encapsulated by functions of the Can module, but the Can module does not memorize the state changes.

The Can module offers the services Can\_Init, Can\_SetBaudrate and Can\_SetControllerMode. These services perform the necessary register settings that cause the required change of the hardware CAN controller state.

There are two possibilities for triggering state changes by external events:

- Bus-off event
- HW wakeup event

These events are indicated either by an interrupt or by a status bit that is polled in the Can\_MainFunction\_BusOff or Can\_MainFunction\_Wakeup.

The Can module does the register settings that are necessary to fulfill the required behavior (i.e. no hardware recovery in case of bus off).

Then it notifies the CanIf module with the corresponding callback function. The software state is then changed inside this callback function.

In case development errors are enabled and there is a not allowed transition requested by the upper layer, the Can module shall rise the development error CAN\_E\_TRANSITION.

The Can module does not check the actual state before it performs Can\_Write or raises callbacks.

### **7.3.1 CAN Controller State Description**

This chapter describes the required hardware behavior for the different controller states.

#### **CAN controller state UNINIT**

The CAN controller is not initialized. All registers belonging to the CAN module are in reset state, CAN interrupts are disabled. The CAN Controller is not participating on the CAN bus.

#### **CAN controller state STOPPED**

In this state the CAN Controller is initialized but does not participate on the bus. In addition, error frames and acknowledges must not be sent.

(Example: For many controllers entering an 'initialization'-mode causes the controller to be stopped.)

#### **CAN controller state STARTED**

The controller is in a normal operation mode with complete functionality, which means it participates in the network. For many controllers leaving the 'initialization'-mode causes the controller to be started.

#### **CAN controller state SLEEP**

The hardware settings only differ from state STOPPED for CAN hardware that support a sleep mode (wake-up over CAN bus directly supported by CAN hardware).

**[SWS\_Can\_00257]** [ When the CAN hardware supports sleep mode and is triggered to transition into SLEEP state, the Can module shall set the controller to the SLEEP state from which the hardware can be woken over CAN Bus.] (SRS\_SPAL\_12067)

**[SWS\_Can\_00258]** [ When the CAN hardware does not support sleep mode and is triggered to transition into SLEEP state, the Can module shall emulate a logical SLEEP state from which it returns only, when it is triggered by software to transition into STOPPED state.] ()

**[SWS\_Can\_00404]** [ The CAN hardware shall remain in state STOPPED, while the logical SLEEP state is active.] ()

### 7.3.2 CAN Controller State Transitions

A state transition is triggered by software with the function `Can_SetControllerMode` with the required transition as parameter. A successful state transition triggered by software is notified by the callback function (`CanIf_ControllerModeIndication`). The monitoring whether the requested state is achieved is part of an upper layer module and is not part of the Can module.

Some transitions are triggered by events on the bus (hardware). These transitions cause a notification by means of a callback function (`CanIf_ControllerBusOff`, `EcuM_CheckWakeUp`).

The behavior for invalid transitions in production code is undefined. Figure 7-2 shows all valid state transitions.

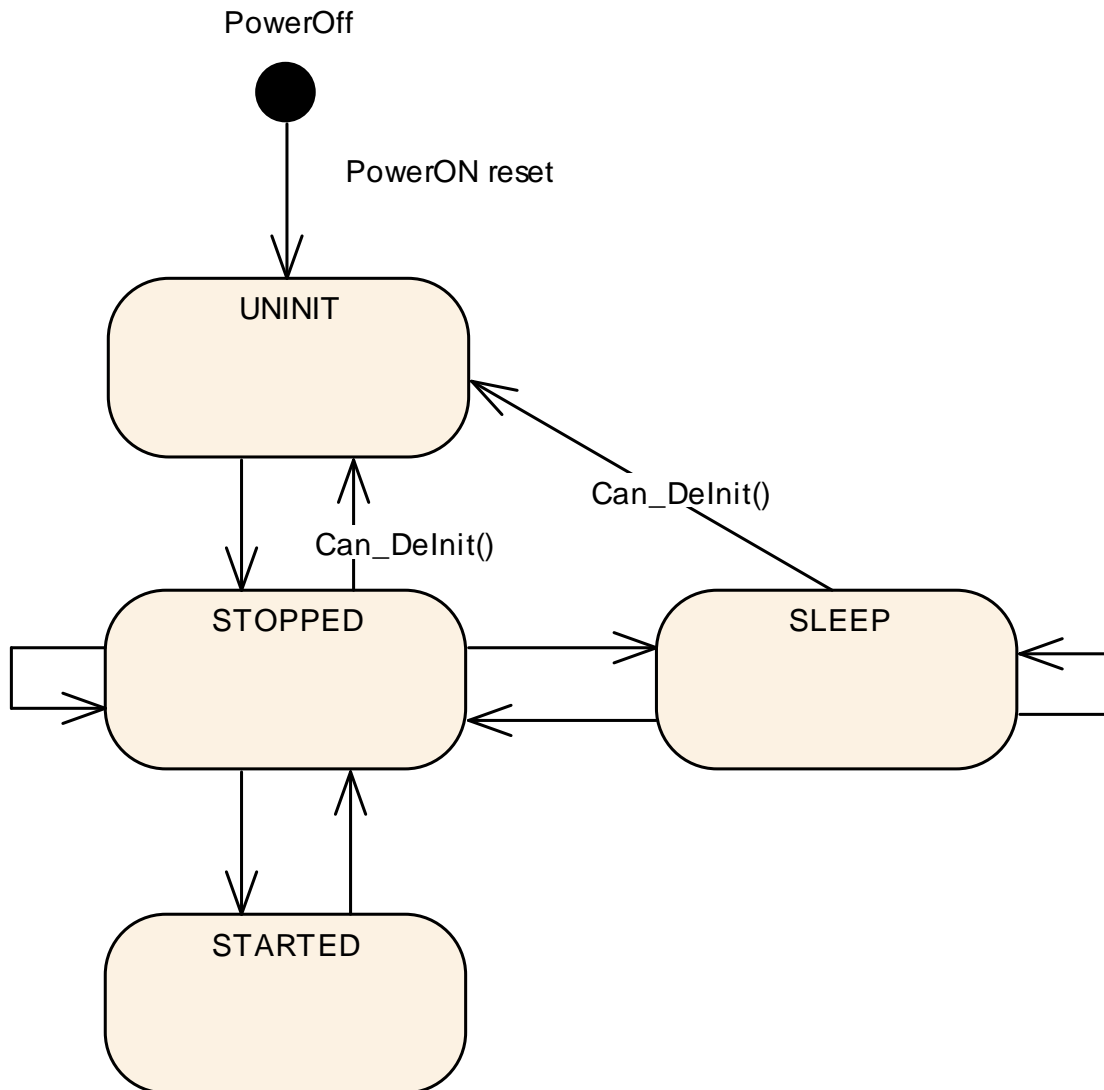


Figure 7-2

### 7.3.3 State transition caused by function Can\_Init

- UNINIT → STOPPED (for all controllers in HW unit)
- software triggered by the function call Can\_Init
- does configuration for all CAN controllers inside HW Unit

All control registers are set according to the static configuration.

**[SWS\_Can\_00259]** [ The function Can\_Init shall set all CAN controllers in the state STOPPED.] ()

When the function Can\_Init is entered and the Can module is not in state CAN\_UNINIT or the CAN controllers are not in state UNINIT, it shall raise the error CAN\_E\_TRANSITION (Compare to [SWS\\_Can\\_00174](#) and [SWS\\_Can\\_00408](#)).

### 7.3.4 State transition caused by function `Can_SetBaudrate`

- STOPPED -> STOPPED; SLEEP -> SLEEP; STARTED -> STARTED
- software triggered by the function call `Can_SetBaudrate`
- changes the CAN controller configuration

CAN controller registers are set according to the static configurations.

**[SWS\_Can\_00256]** [ If the call of `Can_SetBaudrate()` would cause a re-initialization of the CAN Controller and the CAN Controller is not in state STOPPED, it shall return `E_NOT_OK.`] ()

**[SWS\_Can\_00260]** [ If re-initialization is necessary the function `Can_SetBaudrate` shall maintain the CAN controller in the state STOPPED.] ()

**[SWS\_Can\_00422]** [ If re-initialization is necessary the function `Can_SetBaudrate` shall ensure that any settings that will cause the CAN controller to participate in the network are not set.] ()

### 7.3.5 State transition caused by function `Can_SetControllerMode`

The software can trigger a CAN controller state transition with the function `Can_SetControllerMode`. Depending on the CAN hardware, a change of a register setting to transition to a new CAN controller state may take over only after a delay. The Can module notifies the upper layer (`CanIf_ControllerModeIndication`) after a successful state transition about the new state. The monitoring whether the requested state is achieved is part of an upper layer module and is not part of the Can module.

**[SWS\_Can\_00370]** [ The function `Can_Mainfunction_Mode` shall poll a flag of the CAN status register until the flag signals that the change takes effect and notify the upper layer with function `CanIf_ControllerModeIndication` about a successful state transition referring to the corresponding CAN controller with the abstract `CanIf_ControllerId.`] ()

**[SWS\_Can\_00398]** [ The function `Can_SetControllerMode` shall use the system service `GetCounterValue` for timeout monitoring to avoid blocking functions.] ()

**[SWS\_Can\_00372]** [ In case the flag signals that the change takes no effect and the maximum time `CanTimeoutDuration` is elapsed, the function `Can_SetControllerMode` shall be left and the function `Can_Mainfunction_Mode` shall continue to poll the flag.] (SRS\_SPAL\_12077)

**[SWS\_Can\_00373]** [ The function `Can_Mainfunction_Mode` shall call the function `CanIf_ControllerModeIndication` to notify the upper layer about a successful state transition of the corresponding CAN controller referred by abstract `CanIf_ControllerId,` in case the state transition was triggered by function `Can_SetControllerMode.`] ()

### State transition caused by function `Can_SetControllerMode` (CAN\_CS\_STARTED)

- STOPPED → STARTED
- software triggered

**[SWS\_Can\_00261]** [ The function `Can_SetControllerMode(CAN_CS_STARTED)` shall set the hardware registers in a way that makes the CAN controller participating on the network.] ()

**[SWS\_Can\_00262]** [ The function `Can_SetControllerMode(CAN_CS_STARTED)` shall wait for limited time until the CAN controller is fully operational. Compare to [SWS\\_Can\\_00398](#).] ()

Transmit requests that are initiated before the CAN controller is operational get lost. The only indicator for operability is the reception of TX confirmations or RX indications. The sending entities might get a confirmation timeout and need to be able to cope with that.

**[SWS\_Can\_00409]** [ When the function `Can_SetControllerMode(CAN_CS_STARTED)` is entered and the CAN controller is not in state STOPPED it shall detect a invalid state transition (Compare to [SWS\\_Can\\_00200](#)).] ()

#### **State transition caused by function `Can_SetControllerMode(CAN_CS_STOPPED)`**

- STARTED → STOPPED
- SLEEP → STOPPED
- software triggered

**[SWS\_Can\_00263]** [ The function `Can_SetControllerMode(CAN_CS_STOPPED)` shall set the bits inside the CAN hardware such that the CAN controller stops participating on the network.] ()

**[SWS\_Can\_00264]** [ The function `Can_SetControllerMode(CAN_CS_STOPPED)` shall wait for a limited time until the CAN controller is really switched off. Compare to [SWS\\_Can\\_00398](#).] ()

**[SWS\_Can\_00267]** [ If the CAN HW does not support a sleep mode, the transition from SLEEP to STOPPED shall return from the logical sleep mode, but have no effect to the CAN controller state (as the controller is already in stopped state).] ()

**[SWS\_Can\_00268]** [ The function `Can_SetControllerMode(CAN_CS_STOPPED)` shall wait for a limited time until the CAN controller is in STOPPED state. Compare to [SWS\\_Can\\_00398](#).] ()

**[SWS\_Can\_00282]** [ The function `Can_SetControllerMode(CAN_CS_STOPPED)` shall cancel pending messages. ] ()

#### **State transition caused by function `Can_SetControllerMode(CAN_CS_SLEEP)`**

- STOPPED → SLEEP
- software triggered

**[SWS\_Can\_00265]** [ The function `Can_SetControllerMode(CAN_CS_SLEEP)` shall set the controller into sleep mode.] ()

**[SWS\_Can\_00266]** [ If the CAN HW does support a sleep mode, the function Can\_SetControllerMode(CAN\_CS\_SLEEP) shall wait for a limited time until the CAN controller is in SLEEP state and it is assured that the CAN hardware is wake able. Compare to [SWS\\_Can\\_00398](#).] ()

**[SWS\_Can\_00290]** [ If the CAN HW does not support a sleep mode, the function Can\_SetControllerMode(CAN\_CS\_SLEEP) shall set the CAN controller to the logical sleep mode.] ()

**[SWS\_Can\_00405]** [ This logical sleep mode shall left only, if function Can\_SetControllerMode(CAN\_CS\_STOPPED) is called.] ()

**[SWS\_Can\_00411]** [ When the function Can\_SetControllerMode(CAN\_CS\_SLEEP) is entered and the CAN controller is neither in state STOPPED nor in state SLEEP, it shall detect a invalid state transition (Compare to [SWS\\_Can\\_00200](#)).] ()

### 7.3.6 State transition caused by Hardware Events

#### State transition caused by Hardware Wakeup (triggered by wake-up event from CAN bus)

- SLEEP → STOPPED
- triggered by incoming L-PDUs
- The ECU Statemanager module is notified with the function EcuM\_CheckWakeup

This state transition will only occur when sleep mode is supported by hardware.

**[SWS\_Can\_00270]** [ On hardware wakeup (triggered by a wake-up event from CAN bus), the CAN controller shall transition into the state STOPPED.] ()

**[SWS\_Can\_00271]** [ On hardware wakeup (triggered by a wake-up event from CAN bus), the Can module shall call the function EcuM\_CheckWakeup either in interrupt context or in the context of Can\_MainFunction\_Wakeup.] (SRS\_BSW\_00375, SRS\_SPAL\_12069, SRS\_Can\_01054)

**[SWS\_Can\_00269]** [ The Can module shall not further process the L-PDU that caused a wake-up.] ()

**[SWS\_Can\_00048]** [ In case of a CAN bus wake-up during sleep transition, the function Can\_SetControllerMode(CAN\_CS\_STOPPED) shall return E\_NOT\_OK.] (SRS\_Can\_01122)

#### State transition caused by Bus-Off (triggered by state change of CAN controller)

**[SWS\_Can\_00020]** [

- STARTED → STOPPED
- triggered by hardware if the CAN controller reaches bus-off state
- The CanIf module is notified with the function CanIf\_ControllerBusOff after STOPPED state is reached referring to the corresponding CAN controller with the abstract CanIf ControllerId.] (SRS\_Can\_01055)



**[SWS\_Can\_00272]** [ After bus-off detection, the CAN controller shall transition to the state STOPPED and the Can module shall ensure that the CAN controller doesn't participate on the network anymore. ] (SRS\_Can\_01060)

**[SWS\_Can\_00273]** [ After bus-off detection, the Can module shall cancel still pending messages. ] (SRS\_Can\_01060)

**[SWS\_Can\_00274]** [ The Can module shall disable or suppress automatic bus-off recovery.] (SRS\_Can\_01060)

### 7.3.7 State transition caused by function Can\_Delnit

- STOPPED -> UNINIT; SLEEP -> UNINIT (for all controllers in HW unit)
- software triggered by the function call Can\_Delnit
- prepares all CAN controllers inside HW Unit to be re-configured

**[SWS\_Can\_91010]** [The function Can\_Delnit shall set all CAN controllers in the state UNINIT](SRS\_Can\_01166, SRS\_Can\_01053)

When the function Can\_Delnit is entered and the Can module is not in state CAN\_READY or any of the CAN controllers is in state STARTED, it shall raise the error CAN\_E\_TRANSITION (Refer to [SWS\_Can\_91011] and [SWS\_Can\_91012]).

## 7.4 Can module/Controller Initialization

The ECU State Manager module shall initialize the Can module during startup phase by calling the function Can\_Init before using any other functions of the Can module.

**[SWS\_Can\_00250]** [ The function Can\_Init shall initialize:

- static variables, including flags,
- Common setting for the complete CAN HW unit
- CAN controller specific settings for each CAN controller] (SRS\_BSW\_00101)

**[SWS\_Can\_00053]** [ Can\_Init shall not change registers of CAN controller Hardware resources that are not used. ] (SRS\_SPAL\_12125)

The Can module shall apply the following rules regarding initialization of controller registers:

- **[SWS\_Can\_00407]** [ If the hardware allows for only one usage of the register, the Can module implementing that functionality is responsible initializing the register.
- If the register can affect several hardware modules and if it is an I/O register it shall be initialized by the PORT driver.
- If the register can affect several hardware modules and if it is not an I/O register it shall be initialized by the MCU driver.
- One-time writable registers that require initialization directly after reset shall be initialized by the startup code.

- All other registers shall be initialized by the startup code.] (SRS\_SPAL\_12461)

**[SWS\_Can\_00056]** [ Post-Build configuration elements that are marked as ‘multiple’ (‘M’ or ‘x’) in chapter 10 can be selected by passing the pointer ‘Config’ to the init function of the module. ] ()

**[SWS\_Can\_00062]** [ If Can\_SetBaudrate determines that the aimed configuration change requires a re-initialization and the CAN Controller is in STOPPED, the function Can\_SetBaudrate shall re-initialize the CAN controller and the controller specific settings.] (SRS\_Can\_01139, SRS\_Can\_01042)

If re-initialization is necessary, the CAN Controller has to be switched to STOPPED before Can\_SetBaudrate() can be executed and the new baud rate configuration can be applied.

**[SWS\_Can\_00255]** [ The function Can\_SetBaudrate shall only affect register areas that contain specific configuration for a single CAN controller. ] ()

**[SWS\_Can\_00021]** [ The desired CAN controller configuration can be selected with the parameter Config. ] (SRS\_BSW\_00344, SRS\_BSW\_00404, SRS\_BSW\_00405, SRS\_SPAL\_12263, SRS\_SPAL\_12265)

**[SWS\_Can\_00291]** [ Config is a pointer into an array of implementation specific data structure stored in ROM. The different controller configuration sets are located as data structures in ROM.] (SRS\_BSW\_00438)

The possible values for Config are provided by the configuration description (see chapter 10).

The Can module configuration defines the global CAN HW Unit settings and references to the default CAN controller configuration sets.

## 7.5 L-PDU transmission

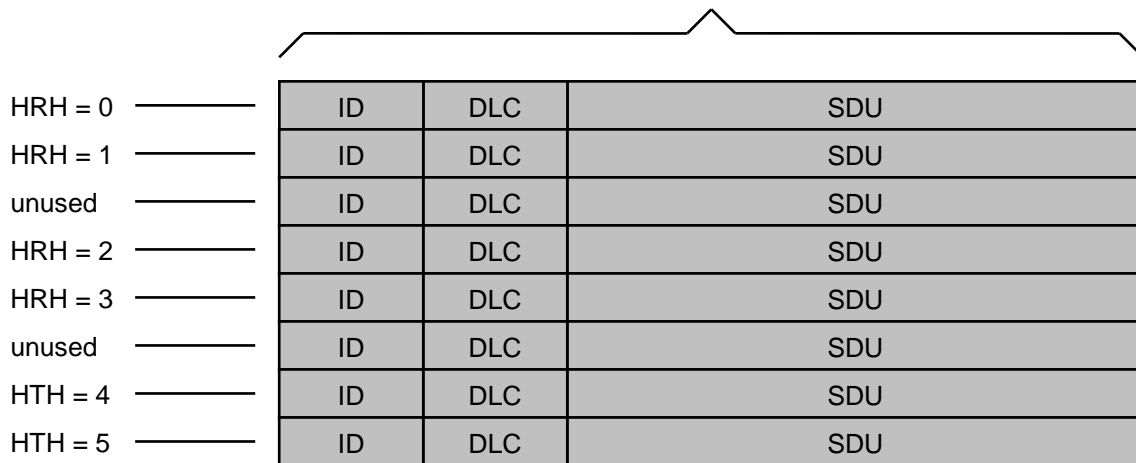
On L-PDU transmission, the Can module converts the L-PDU contents ID and Data Length to a hardware specific format (if necessary) and triggers the transmission.

**[SWS\_Can\_00059]** [ Data mapping by CAN to memory is defined in a way that the CAN data byte which is sent out first is array element 0, the CAN data byte which is sent out last is array element 7 or 63 in case of CAN FD.] (SRS\_SPAL\_12063)

**[SWS\_Can\_00427]** [ If the presentation inside the CAN Hardware buffer differs from AUTOSAR definition, the Can module must provide an adapted SDU-Buffer for the upper layers.] ()

**[SWS\_Can\_00100]** [ Several TX hardware objects with unique HTHs may be configured. The CanIf module provides the HTH as parameter of the TX request. See Figure 7-3 for a possible configuration.] (SRS\_Can\_01135)

Message Objects of CAN Hardware



**Figure 7-3: Example of assignment of HTHs and HRHs to the Hardware Objects. The numbering of HTHs and HRHs are implementation specific. The chosen numbering is only an example.**

**[SWS\_Can\_00276]** [ The function Can\_Write shall store the swPduHandle that is given inside the parameter PduInfo until the Can module calls the CanIf\_TxConfirmation for this request where the swPduHandle is given as parameter. ] ()

The feature of [SWS\\_Can\\_00276](#) is used to reduce time for searching in the CanIf module implementation.

**[SWS\_Can\_00016]** [ The Can module shall call CanIf\_TxConfirmation to indicate a successful transmission. It shall either called by the TX-interrupt service routine of the corresponding HW resource or inside the Can\_MainFunction\_Write in case of polling mode.] (SRS\_Can\_01051)

**7.5.1 Priority Inversion**

Multiplexed transmission is necessary to prevent priority inversion (see chapter 2.1).

**[SWS\_Can\_00277]** [ The Can module shall allow that the functionality “Multiplexed Transmission” is statically configurable (ON | OFF) at pre-compile time.] (SRS\_Can\_01134)

**[SWS\_Can\_00401]** [ Several transmit hardware objects (defined by "CanHwObjectCount") shall be assigned by one HTH to represent one transmit entity to the upper layer.] (SRS\_Can\_01134)

**[SWS\_Can\_00402]** [ The Can module shall support multiplexed transmission mechanisms for devices where either

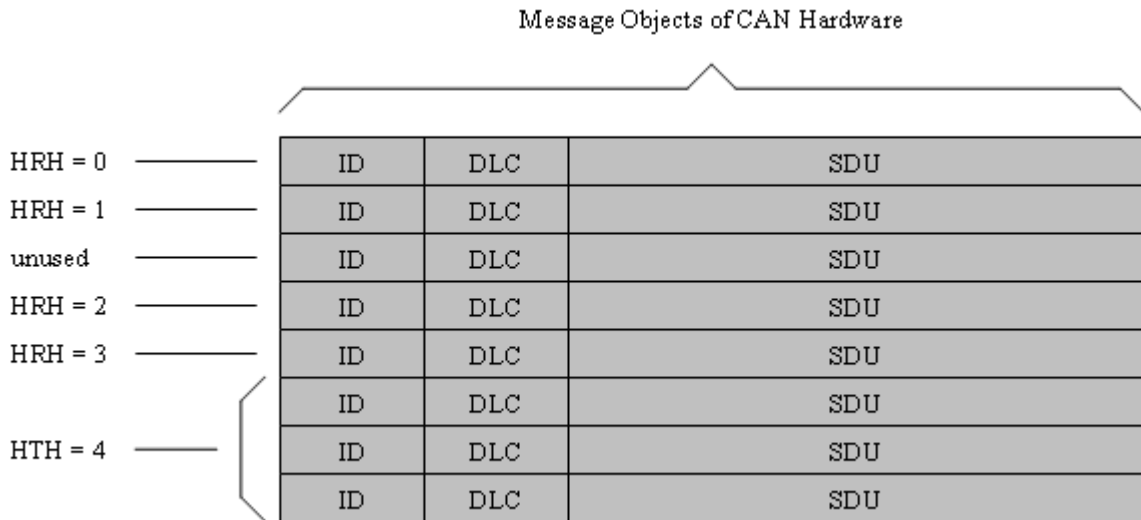
- Multiple transmit hardware objects, which are grouped to a transmit entity can be filled over the same register set, and the microcontroller stores the L-PDU into a free buffer autonomously,

or

- The Hardware provides registers or functions to identify a free transmit hardware object within a transmit entity.] (SRS\_Can\_01134)

**[SWS\_Can\_00403]** [ The Can module shall support multiplexed transmission for devices, which send L-PDUs in order of L-PDU priority.] (SRS\_Can\_01134)

Note: Software emulation of priority handling should be avoided, because the overhead would void the advantage of the multiplexed transmission.



**Figure 7-4: Example of assignment of HTHs and HRHs to the Hardware Objects with multiplexed transmission. The numbering of HTHs and HRHs are implementation specific. The chosen numbering is only an example.**

### 7.5.2 Transmit Data Consistency

**[SWS\_Can\_00011]** [ The Can module shall directly copy the data from the upper layer buffers. It is the responsibility of the upper layer to keep the buffer consistent until return of function call (Can\_Write).] (SRS\_SPAL\_12075, SRS\_Can\_01059)

## 7.6 L-PDU reception

**[SWS\_Can\_00279]** [ On L-PDU reception, the Can module shall call the RX indication callback function `CanIf_RxIndication` with ID, Hoh, abstract `CanIf_ControllerId` in parameter `Mailbox`, and the Data Length and pointer to the L-SDU buffer in parameter `PduInfoPtr`.] (SRS\_Can\_01045)

**[SWS\_Can\_00423]** [ In case of an Extended CAN frame, the Can module shall convert the ID to a standardized format since the Upper layer (CANIF) does not know whether the received CAN frame is a Standard CAN frame or Extended CAN frame. In case of an Extended CAN frame, MSB of a received CAN frame ID needs to be made as '1' to mark the received CAN frame as Extended.] ()

**[SWS\_Can\_00396]** [ The RX-interrupt service routine of the corresponding HW resource or the function `Can_MainFunction_Read` in case of polling mode shall call the callback function `CanIf_RxIndication`.] (SRS\_Can\_01045)

**[SWS\_Can\_00060]** [ Data mapping by CAN to memory is defined in a way that the CAN data byte which is received first is array element 0, the CAN data byte which is received last is array element 7 or 63 in case of CAN FD.

If the presentation inside the CAN Hardware buffer differs from AUTOSAR definition, the Can module must provide an adapted SDU-Buffer for the upper layers.] (SRS\_SPAL\_12063)

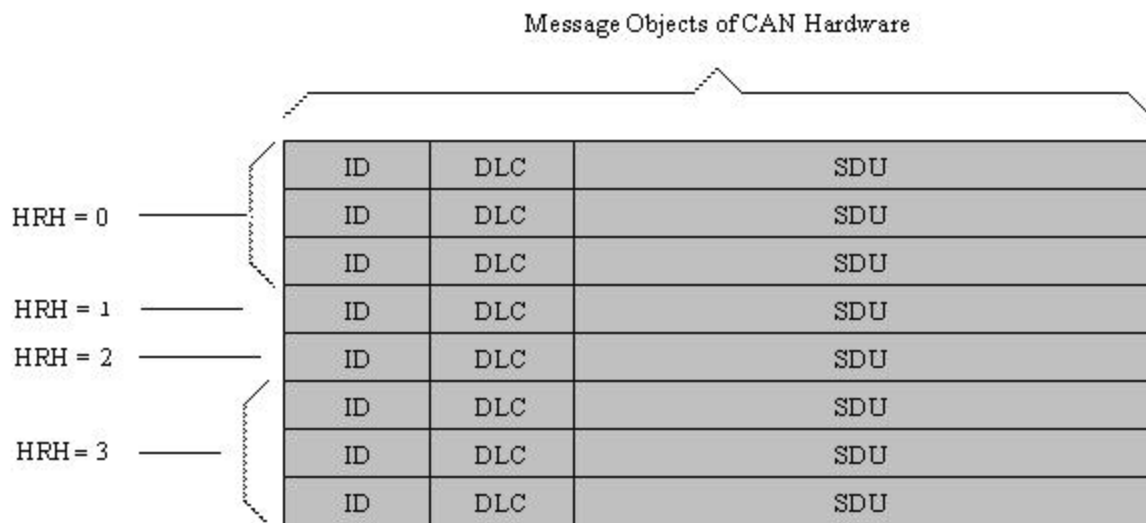
**[SWS\_CAN\_00501]** [ `CanDrv` shall indicate whether the received message is a conventional CAN frame or a CAN FD frame as described in `Can_IdType`.] (SRS\_Can\_01162)

### 7.6.1 Receive Data Consistency

To prevent loss of received messages, some controllers support a FIFO built from a set of hardware objects, while on other controllers it is possible to configure another hardware object with the same properties that works as a shadow buffer and steps in when the main object is busy.

**[SWS\_CAN\_00489]**[ The CAN driver shall support controllers which implement a hardware FIFO. The size of the FIFO is configured via "`CanHwObjectCount`".] ()

**[SWS\_CAN\_00490]**[ Controllers that do not support a hardware FIFO often provide the capabilities to implement a shadow buffer mechanism, where additional hardware objects take over when the primary hardware object is busy. The number of hardware objects is configured via "`CanHwObjectCount`".] ()



**Figure 7-5: Example of assignment of same HRHs to multiple Hardware Objects The chosen numbering is only an example.**

**[SWS\_Can\_00299]** [ The Can module shall copy the L-SDU in a shadow buffer after reception, if the RX buffer cannot be protected (locked) by CAN Hardware against overwriting by a newly received message.] ()

**[SWS\_Can\_00300]** [ The Can module shall copy the L-SDU in a shadow buffer, if the CAN Hardware is not globally accessible.] ()

The complete RX processing (including copying to destination layer, e.g. COM) is done in the context of the RX interrupt or in the context of the Can\_MainFunction\_Read.

**[SWS\_Can\_00012]** [ The Can module shall guarantee that neither the ISRs nor the function Can\_MainFunction\_Read can be interrupted by itself. The CAN hardware (or shadow) buffer is always consistent, because it is written and read in sequence in exactly one function that is never interrupted by itself.] (SRS\_Can\_01059)

If the CAN hardware cannot be configured to lock the RX hardware object after reception (hardware feature), it could happen that the hardware buffer is overwritten by a newly arrived message. In this case, the CAN controller detects an “overwrite” event, if supported by hardware.

If the CAN hardware can be configured to lock the RX hardware object after reception, it could happen that the newly arrived message cannot be stored to the hardware buffer. In this case, the CAN controller detects an “overrun” event, if supported by hardware.

**[SWS\_Can\_00395]** [ Can module shall raise the runtime error CAN\_E\_DATALOST in case of “overwrite” or “overrun” event detection.] ()

Implementation Hint:

The system designer shall assure that the runtime for message reception (interrupt driven or polling) correlates with the fastest possible reception in the system.

## 7.7 Wakeup concept

The Can module handles wakeups that can be detected by the Can controller itself and not via the Can transceiver. There are two possible scenarios: wakeup by interrupt and wakeup by polling.

For wakeup by interrupt, an ISR of the Can module is called when the hardware detects the wakeup.

**[SWS\_Can\_00364]** [ If the ISR for wakeup events is called, it shall call EcuM\_CheckWakeup in turn. The parameter passed to EcuM\_CheckWakeup shall be the ID of the wakeup source referenced by the CanWakeupSourceRef configuration parameter.] (SRS\_BSW\_00375, SRS\_SPAL\_12069, SRS\_Can\_01054)

The ECU State Manager will then set up the MCU and call the Can module back via the Can Interface, resulting in a call to Can\_CheckWakeup.

When wakeup events are detected by polling, the ECU State Manager will cyclically call Can\_CheckWakeup via the Can Interface as before. In both cases, Can\_CheckWakeup will check if there was a wakeup detected by a Can controller and return the result. The CAN driver will then inform the ECU State Manager of the wakeup event via EcuM\_SetWakeupEvent.

The wakeup validation to prevent false wakeup events, will be done by the ECU State Manager and the Can Interface afterwards and without any help from the Can module.

For a general description of the wakeup mechanisms and wakeup sequence diagrams refer to Specification of ECU State Manager [7].

## 7.8 Notification concept

The Can module offers only an event triggered notification interface to the CanIf module. Each notification is represented by a callback function.

**[SWS\_Can\_00099]** [ The hardware events may be detected by an interrupt or by polling status flags of the hardware objects. The configuration possibilities regarding polling is hardware dependent (i.e. which events can be polled, which events need to be polled), and not restricted by this standard. ] (SRS\_Can\_01132)

**[SWS\_Can\_00007]** [ It shall be possible to configure the driver such that no interrupts at all are used (complete polling). ] (SRS\_Can\_01062)

The configuration of what is and is not polled by the Can module is internal to the driver, and not visible outside the module. The polling is done inside the CAN main functions (Can\_MainFunction\_XXX). Also the polled events are notified by the appropriate callback function. Then the call context is not the ISR but the CAN main function. The implementation of all callback functions shall be done as if the call context was the ISR.

For further details see also description of the CAN main functions Can\_MainFunction\_Read, Can\_MainFunction\_Write, Can\_MainFunction\_BusOff and Can\_MainFunction\_Wakeup.

### 7.9 Reentrancy issues

A routine must satisfy the following conditions to be reentrant:

- It uses all shared variables in an atomic way, unless each is allocated to a specific instance of the function.
- It does not call non-reentrant functions.
- It does not use the hardware in a non-atomic way.

Transmit requests are simply forwarded by the CanIf module inside the function CanIf\_Transmit.

The function CanIf\_Transmit is re-entrant. Therefore the function Can\_Write needs to be implemented thread-safe (for example by using mutexes):

Further (preemptive) calls will return with CAN\_BUSY when the write can't be performed re-entrant. (example: write to different hardware TX Handles allowed, write to same TX Handles not allowed)

In case of CAN\_BUSY the CanIf module queues that request. (same behavior as if all hardware objects are busy).

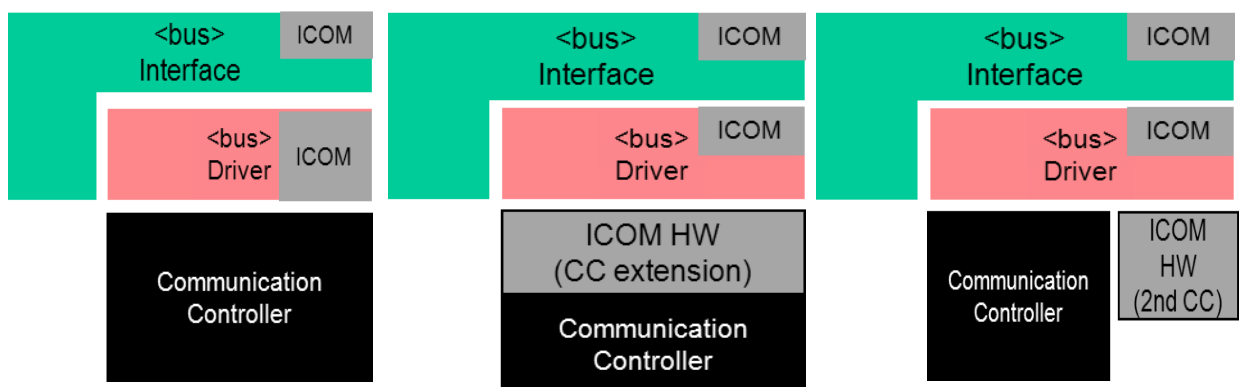
Can\_EnableCanInterrupts and Can\_DisableCanInterrupts may be called inside re-entrant functions. Therefore these functions also need to be reentrant.

All other services don't need to be implemented as reentrant functions.

The CAN main functions (i.e. Can\_MainFunction\_Read) shall not be interrupted by themselves. Therefore these CAN main functions are not reentrant.

### 7.10 Pretended Networking

Optimizing energy efficiency is becoming increasingly important in all automotive domains since energy consumption has direct impact on fuel consumption, CO2 emissions, and range of hybrid or all electric vehicles. The concept of *Pretended Networking* has a high potential for energy reduction on ECU level.



(a) ICOM Software implementation: ICOM features are exclusively implemented in software, reusing the existing Communication Controller

(b) ICOM is a functional hardware extension of the existing Communication Controller

(c) ICOM is a separate hardware component with its own Communication Controller

Figure 7-6: Possible ICOM implementations



The use of *Intelligent Communication Controllers* (ICOM) supports those features (no specific hardware implementation mandatory). If some or all of the functionality of an ECU is temporarily not required, e.g., based on the vehicle state, the ECU can enter a “Pretended Networking” mode. In this mode, the MCU and/or peripherals are switched into a low-power mode. Only the ICOM and the connected transceivers stay active. The ICOM generates a wakeup event, caused by, e.g. a received bus message, when the ECU needs to resume operation.

Depending on the ICOM implementation, message ID and payload of received messages may either be evaluated and filtered completely in hardware, require a callback mechanism in software. As shown in Figure 7-6, the ECU implementation can be divided into three possible variants – Approach (a) software approach, without specific hardware to support Pretended Networking. Approach (b) depicts a functional hardware extension of a communication controller and approach (c) shows a hardware variant with a 2<sup>nd</sup> extended communication controller for wakeup handling. All variants and ICOM implementations shall be supported by Pretended Networking.

Depending on the hardware implementation, the ICOM is also able to send messages. By using the ICOM to continue to send, e.g., status messages, other nodes that rely on that message are not affected by an ECU in Pretended Networking mode.

Furthermore, Pretended Networking aims at reducing wakeup response time, i.e., the time between a wakeup event and valid behavior of an ECU. By using the ICOM to save relevant messages during activated Pretended Networking mode, the application has access to the last valid signal values directly after resuming operation. Therefore, the ECU can immediately respond to a user request after wakeup and does not have to wait until the according message is received again.

### 7.10.1 Support Pretended Networking mode handling

**[SWS\_CAN\_00497]** [ The CAN driver shall deactivate Pretended Networking after initialization of the CAN controller.] ()

#### Activation of Pretended Networking:

**[SWS\_CAN\_00462]** [ Pretended Networking shall be activated by calling `Can_SetIcomConfiguration()` with a configuration ID not set to 0.] ()

**[SWS\_CAN\_00464]** [ `CanDrv` is responsible to perform reconfiguration of the CAN Controller (incl. ICOM) according to the `CanIcomConfig` parameters for the selected configuration (`CanIcomConfigId`).] ()

**[SWS\_CAN\_00467]** [ If activation was successful then `CanIf_CurrentIcomConfiguration` shall be called with the parameter `Error` set to `ICOM_SWITCH_E_OK` referring to the corresponding CAN controller with the abstract `CanIf_ControllerId`. If activation was not successful then `CanIf_CurrentIcomConfiguration` shall be called with the parameter `Error` set to

ICOM\_SWITCH\_E\_FAILED referring to the corresponding CAN controller with the abstract CanIf ControllerId.] ()

**[SWS\_CAN\_00468]** If Pretended Networking is activated CanDrv shall call CanIf\_RxIndication() if and only if the received message matches the wakeup conditions of the CanIcomConfig (see CanIcomWakeupCauses).] ()

**[SWS\_CAN\_00470]** If Pretended Networking is activated CanDrv shall reject Can\_Write() requests with return value CAN\_BUSY.] ()

**[SWS\_CAN\_00498]** The CAN driver shall deactivate Pretended Networking before the CAN Controller is started by SetControllerMode(CAN\_CS\_STARTED)] ()

### Deactivation of Pretended Networking:

**[SWS\_CAN\_00471]** Pretended Networking shall be deactivated (i.e. CanDrv shall behave as when it is configured without Pretended Networking support) by calling Can\_SetIcomConfiguration() with a configuration ID = 0. ] ()

**[SWS\_CAN\_00472]** If Pretended Networking is deactivated CanDrv shall process the messages normally as configured in the normal configuration.] ()

**[SWS\_CAN\_00474]** CAN driver shall inform CanIf about a configuration switch by calling CanIf\_CurrentIcomConfiguration referring to the corresponding CAN controller with the abstract CanIf ControllerId. The error parameter is set to ICOM\_SWITCH\_E\_OK if deactivation is successful and to ICOM\_SWITCH\_E\_FAILED otherwise.] ()

**[SWS\_CAN\_00499]** The CAN driver shall deactivate Pretended Networking before the CAN Controller is stopped by SetControllerMode(CAN\_CS\_STOPPED).] ()

### 7.10.2 Support autonomous sending and receiving of messages

**[SWS\_CAN\_00477]** Autonomous sending of messages in Pretended Networking mode shall be supported only if additional ICOM hardware is available. A configuration parameter defines if there is hardware support or not (Refer to CanIcomVariant).] ()

**[SWS\_CAN\_00478]** If the ICOM is implemented in software the controller shall not send messages in Pretended Networking mode.] ()

**[SWS\_CAN\_00479]** CanDriver shall forward all received messages received during Pretended Networking Mode to CanIf.] ()

## 7.11 Error classification

**[SWS\_Can\_00104]** | The Can module shall be able to detect the following errors and exceptions depending on its configuration (default/production) (SRS\_BSW\_00337, SRS\_BSW\_00385, SRS\_BSW\_00331)

### 7.11.1 Development Errors

<i>Type or error</i>	<i>Relevance</i>	<i>Related error code</i>	<i>Value [hex]</i>
API Service called with wrong parameter	Development	CAN_E_PARAM_POINTER CAN_E_PARAM_HANDLE CAN_E_PARAM_DATA_LENGTH CAN_E_PARAM_CONTROLLER	0x01 0x02 0x03 0x04
API Service used without initialization	Development	CAN_E_UNINIT	0x05
Invalid transition for the current mode	Development	CAN_E_TRANSITION	0x06
Parameter Baudrate has an invalid value	Development	CAN_E_PARAM_BAUDRATE	0x07
Invalid ICOM Configuration Id	Development	CAN_E_ICOM_CONFIG_INVALID	0x08
Invalid configuration set selection	Development	CAN_E_INIT_FAILED	0x09

### 7.11.2 Runtime Errors

<i>Type or error</i>	<i>Relevance</i>	<i>Related error code</i>	<i>Value [hex]</i>
Received CAN message is lost	Runtime	CAN_E_DATA_LOST	0x01

**[SWS\_Can\_00026]** | The Can module shall indicate errors that are caused by erroneous usage of the Can module API. This covers API parameter checks and call sequence errors. | (SRS\_BSW\_00337, SRS\_BSW\_00323, SRS\_SPAL\_00157)

**[SWS\_Can\_00091]** | After return of the DET the Can module's function that raised the development error shall return immediately. | (SRS\_SPAL\_12448)

**[SWS\_Can\_00089]** | The Can module's environment shall indicate development errors only in the return values of a function of the Can module when DET is switched on and the function provides a return value. The returned value is E\_NOT\_OK. | (SRS\_BSW\_00369, SRS\_BSW\_00386, SRS\_SPAL\_12448)

### 7.11.3 Runtime Errors

**[SWS\_CAN\_XXXXX]** Runtime Error Types

<i>Type of error</i>	<i>Related error code</i>	<i>Value [hex]</i>

] ( )

#### 7.11.4 Transient Faults

##### [SWS\_CAN\_XXXXX] Transient Faults Types

<i>Type of error</i>	<i>Related error code</i>	<i>Value [hex]</i>

] ( )

#### 7.11.5 Production Errors

The Can module does not call the Diagnostic Event Manager, because there is no production error code defined for the Can module.

#### 7.11.6 Return Values

CAN\_BUSY is reported via return value of the function Can\_Write. The CanIf module reacts according the sequence diagrams specified for the CanIf module. E\_NOT\_OK is reported via return value in case of a wakeup during transition to sleep mode. Bus-off and Wake-up events are forwarded via notification callback functions.

### 7.12 CAN FD Support

For performance reasons some CAN controllers allow to use a Flexible Data-Rate feature called CAN FD (see "CAN with Flexible Data-Rate" specification). Indicated during the arbitration phase it is possible to switch to a higher baud rate during payload and CRC. This second baud rate has to be configured by extending CanControllerBaudrateConfig with CanControllerFdBaudrateConfig. If a baud rate is active which has a CAN FD configuration (see CanControllerFdBaudrateConfig) the CAN FD feature is enabled for this controller. The specified second baud rate is needed to support reception of CAN FD frames with bit rate switch (BRS). Whether the second baudrate is used for transmission or not depends on configuration parameter CanControllerTxBitRateSwitch (see CanControllerFdBaudrateConfig).

However, there may be cases where conventional CAN 2.0 messages need to be transmitted in networks supporting CAN-FD messages for example to facilitate CAN selective wakeup. In these cases it is necessary to support transmitting interleaved

conventional CAN messages with CAN-FD messages. This can be achieved on frame level by using the two most significant bits of the CanId (see Can\_IdType, SWS\_Can\_00416) passed during Can\_Write to indicate which kind of frame shall be used.

CAN FD also supports an extended payload which allows the transmission of up to 64 bytes. This feature also depends on the CAN FD configuration (see CanControllerFdBaudrateConfig). Therefore, if the CAN Controller is in CAN FD mode (valid CanControllerFdBaudrateConfig) and the CAN FD flag is set in CanId passed to Can\_Write(), CanDrv supports the transmission of PDUs with a length up to 64 bytes. If there is a request to transmit a CAN FD frame and the CAN Controller is not in CAN FD mode (no CanControllerFdBaudrateConfig) the frame is sent as conventional CAN frame as long as the PDU length  $\leq 8$  bytes.

## 8 API specification

The prefix of the function names may be changed in an implementation with several Can modules as described in [SWS Can\\_00284](#).

### 8.1 Imported types

In this chapter all types included from the following files are listed:

[SWS\_Can\_00222] [

<i>Module</i>	<i>Imported Type</i>
Can_GeneralTypes	Can_ControllerStateType
	Can_ErrorStateType
	Can_HwHandleType
	Can_HwType
	Can_IdType
	Can_PduType
ComStack_Types	IcomConfigIdType
	IcomSwitch_ErrorType
	PdulIdType
	PduInfoType
EcuM	EcuM_WakeupSourceType
Icu	Icu_ChannelType
Os	CounterType
	StatusType
	TickRefType
Std_Types	Std_ReturnType
	Std_VersionInfoType

] ()

## 8.2 Type definitions

[SWS\_CAN\_00487] The types specified in Can\_GeneralTypes shall be declared in Can\_GeneralTypes.h | ()

[SWS\_Can\_00439] The content of Can\_GeneralTypes.h shall be protected by a CAN\_GENERAL\_TYPES define. | ()

[SWS\_Can\_00440] If different CAN drivers are used, only one instance of this file has to be included in the source tree. For implementation all Can\_GeneralTypes.h related types in the documents mentioned before shall be considered. | ()

### 8.2.1 Can\_ConfigType

[SWS\_Can\_00413] |

<b>Name:</b>	Can_ConfigType		
<b>Type:</b>	Structure		
<b>Range:</b>	Implementation specific.		
<b>Description:</b>	This is the type of the external data structure containing the overall initialization data for the CAN driver and SFR settings affecting all controllers. Furthermore it contains pointers to controller configuration structures. The contents of the initialization data structure are CAN hardware specific.		

| ()

### 8.2.2 Can\_PduType

[SWS\_Can\_00415] |

<b>Name:</b>	Can_PduType		
<b>Type:</b>	Structure		
<b>Element:</b>	PduIdType	swPduHandle	--
	uint8	length	--
	Can_IdType	id	--
	uint8*	sdu	--
<b>Description:</b>	This type unites PduId (swPduHandle), SduLength (length), SduData (sdu), and CanId (id) for any CAN L-SDU.		

| ()

### 8.2.3 Can\_IdType

[SWS\_Can\_00416] |

<b>Name:</b>	Can_IdType		
<b>Type:</b>	uint32		
<b>Range:</b>	Standard32Bit	--	0..0x400007FF
	Extended32Bit	--	0..0xDFFFFFFF
<b>Description:</b>	Represents the Identifier of an L-PDU. The two most significant bits specify the frame type: 00 CAN message with Standard CAN ID 01 CAN FD frame with Standard CAN ID 10 CAN message with Extended CAN ID		

	11 CAN FD frame with Extended CAN ID
--	--------------------------------------

] ()

### 8.2.4 Can\_HwHandleType

#### [SWS\_Can\_00429] [

<b>Name:</b>	Can_HwHandleType		
<b>Type:</b>	uint8, uint16		
<b>Range:</b>	Standard	--	0..0x0FF
	Extended	--	0..0xFFFF
<b>Description:</b>	Represents the hardware object handles of a CAN hardware unit. For CAN hardware units with more than 255 HW objects use extended range.		

] ()

### 8.2.5 Can\_HwType

#### [SWS\_CAN\_00496] [

<b>Name:</b>	Can_HwType		
<b>Type:</b>	Structure		
<b>Element:</b>	Can_IdType	CanId	Standard/Extended CAN ID of CAN L-PDU
	Can_HwHandleType	Hoh	ID of the corresponding Hardware Object Range
	uint8	ControllerId	ControllerId provided by CanIf clearly identify the corresponding controller
<b>Description:</b>	This type defines a data structure which clearly provides an Hardware Object Handle including its corresponding CAN Controller and therefore CanDrv as well as the specific CanId.		

] ()

### 8.2.6 Can\_ReturnType

#### [SWS\_Can\_00039] [

<b>Range:</b>	CAN_BUSY	0x02	transmit request could not be processed because no transmit object was available
<b>Description:</b>	Overlaid return value of Std_ReturnType for CAN driver API Can_Write()		

] (SRS\_BSW\_00331)

### 8.2.7 Can\_ErrorStateType

#### [SWS\_Can\_91003] [

<b>Name:</b>	Can_ErrorStateType		
<b>Type:</b>	Enumeration		
<b>Range:</b>	CAN_ERRORSTATE_ACTIVE	--	The CAN controller takes fully part in communication.
	CAN_ERRORSTATE_PASSIVE	--	The CAN controller takes part in communication, but does not send active error frames.
	CAN_ERRORSTATE_BUSOFF	--	The CAN controller does not take part in



		communication.
<b>Description:</b>	Error states of a CAN controller.	

] ()

## 8.2.8 Can\_ControllerStateType

[SWS\_Can\_91013] [

<b>Name:</b>	Can_ControllerStateType		
<b>Type:</b>	Enumeration		
<b>Range:</b>	CAN_CS_UNINIT	0x00	CAN controller state UNINIT.
	CAN_CS_STARTED	0x01	CAN controller state STARTED.
	CAN_CS_STOPPED	0x02	CAN controller state STOPPED.
	CAN_CS_SLEEP	0x03	CAN controller state SLEEP.
<b>Description:</b>	States that are used by the several ControllerMode functions.		

] ()

## 8.3 Function definitions

This is a list of functions provided for upper layer modules.

### 8.3.1 Services affecting the complete hardware unit

#### 8.3.1.1 Can\_Init

[SWS\_Can\_00223] [

<b>Service name:</b>	Can_Init	
<b>Syntax:</b>	<pre>void Can_Init(     const Can_ConfigType* Config )</pre>	
<b>Service ID[hex]:</b>	0x00	
<b>Sync/Async:</b>	Synchronous	
<b>Reentrancy:</b>	Non Reentrant	
<b>Parameters (in):</b>	Config	Pointer to driver configuration.
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	None	
<b>Return value:</b>	None	
<b>Description:</b>	This function initializes the module.	

] (SRS\_BSW\_00358, SRS\_BSW\_00414)

Symbolic names of the available configuration sets are provided by the configuration description of the Can module. See chapter 10 about configuration description.

[SWS\_Can\_00174] [ If development error detection for the Can module is enabled: The function Can\_Init shall raise the error CAN\_E\_TRANSITION if the driver is not in state CAN\_UNINIT.] ()

**[SWS\_Can\_00408]** [ If development error detection for the Can module is enabled: The function Can\_Init shall raise the error CAN\_E\_TRANSITION if the CAN controllers are not in state UNINIT.] ()

### 8.3.1.2 Can\_GetVersionInfo

**[SWS\_Can\_00224]** [

<b>Service name:</b>	Can_GetVersionInfo	
<b>Syntax:</b>	void Can_GetVersionInfo( Std_VersionInfoType* versioninfo )	
<b>Service ID[hex]:</b>	0x07	
<b>Sync/Async:</b>	Synchronous	
<b>Reentrancy:</b>	Reentrant	
<b>Parameters (in):</b>	None	
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	versioninfo	Pointer to where to store the version information of this module.
<b>Return value:</b>	None	
<b>Description:</b>	This function returns the version information of this module.	

] ()

**[SWS\_Can\_00177]** [ If development error detection for the Can module is enabled: The function Can\_GetVersionInfo shall raise the error CAN\_E\_PARAM\_POINTER if the parameter versionInfo is a null pointer.] ()

### 8.3.1.3 Can\_DeInit

**[SWS\_Can\_91002]** [

<b>Service name:</b>	Can_DeInit	
<b>Syntax:</b>	void Can_DeInit( void )	
<b>Service ID[hex]:</b>	0x10	
<b>Sync/Async:</b>	Synchronous	
<b>Reentrancy:</b>	Non Reentrant	
<b>Parameters (in):</b>	None	
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	None	
<b>Return value:</b>	None	
<b>Description:</b>	This function de-initializes the module.	

] (SRS\_Can\_01166, SRS\_BSW\_00336)

**Note:** General behavior and constraints on de-initialization functions are specified by [SWS\_BSW\_00152], [SWS\_BSW\_00072], [SWS\_BSW\_00232], [SWS\_BSW\_00233]

**Caveat:** Caller of the Can\_Delnit function has to be sure no CAN controller is in the state STARTED

**[SWS\_Can\_91011]** [If development error detection for the Can module is enabled:  
The function Can\_Delnit shall raise the error CAN\_E\_TRANSITION if the driver is not in state CAN\_READY.](SRS\_BSW\_00369)

**[SWS\_Can\_91012]** [If development error detection for the Can module is enabled:  
The function Can\_Delnit shall raise the error CAN\_E\_TRANSITION if any of the CAN controllers is in state STARTED.](SRS\_BSW\_00369)

## 8.3.2 Services affecting one single CAN Controller

### 8.3.2.1 Can\_SetBaudrate

**[SWS\_CAN\_00491]** [

<b>Service name:</b>	Can_SetBaudrate	
<b>Syntax:</b>	Std_ReturnType Can_SetBaudrate( uint8 Controller, uint16 BaudRateConfigID )	
<b>Service ID[hex]:</b>	0x0f	
<b>Sync/Async:</b>	Synchronous	
<b>Reentrancy:</b>	Reentrant for different Controllers. Non reentrant for the same Controller.	
<b>Parameters (in):</b>	Controller	CAN controller, whose baud rate shall be set
	BaudRateConfigID	references a baud rate configuration by ID (see CanControllerBaudRateConfigID)
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	None	
<b>Return value:</b>	Std_ReturnType	E_OK: Service request accepted, setting of (new) baud rate started E_NOT_OK: Service request not accepted
	<b>Description:</b> This service shall set the baud rate configuration of the CAN controller. Depending on necessary baud rate modifications the controller might have to reset.	

] ( )

There might be several baud rate configurations available. The function Can\_SetBaudrate can be used to switch between different configurations. Depending on the old and new baud rate configuration only a subset of parameters may be changed during runtime and a re-initialization of the CAN Controller might be avoidable.

If the call of Can\_SetBaudrate will cause a re-initialization of the CAN Controller the CAN controller must be in state STOPPED when this function is called (see SWS\_Can\_00256 and SWS\_Can\_00260).

The CAN controller is in state STOPPED after (re-)initialization (see SWS\_Can\_00259).

**[SWS\_CAN\_00492]** [ If development error detection for the Can module is enabled:

The function `Can_SetBaudrate` shall raise the error `CAN_E_UNINIT` and return `E_NOT_OK` if the driver is not yet initialized.] ()

**[SWS\_CAN\_00493]** If development error detection for the Can module is enabled: The function `Can_SetBaudrate` shall raise the error `CAN_E_PARAM_BAUDRATE` and return `E_NOT_OK` if the parameter `BaudRateConfigID` has an invalid value.] ()

**[SWS\_CAN\_00494]** If development error detection for the Can module is enabled the function `Can_SetBaudrate` shall raise the error `CAN_E_PARAM_CONTROLLER` and return `E_NOT_OK` if the parameter `Controller` is out of range.] ()

**[SWS\_CAN\_00500]** If the requested baud rate change can not performed without a re-initialization of the CAN Controller `E_NO_OK` shall be returned.] ()

### 8.3.2.2 Can\_SetControllerMode

**[SWS\_Can\_00230]** [

<b>Service name:</b>	Can_SetControllerMode	
<b>Syntax:</b>	<pre>Std_ReturnType Can_SetControllerMode(     uint8 Controller,     Can_ControllerStateType Transition )</pre>	
<b>Service ID[hex]:</b>	0x03	
<b>Sync/Async:</b>	Asynchronous	
<b>Reentrancy:</b>	Non Reentrant	
<b>Parameters (in):</b>	Controller	CAN controller for which the status shall be changed
	Transition	Transition value to request new CAN controller state
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	None	
<b>Return value:</b>	Std_ReturnType	E_OK: request accepted
		E_NOT_OK: request not accepted, a development error occurred
<b>Description:</b>	This function performs software triggered state transitions of the CAN controller State machine.	

] ()

**[SWS\_Can\_00017]** [ The function `Can_SetControllerMode` shall perform software triggered state transitions of the CAN controller State machine. See also [\[SRS\\_SPAL\\_12169\]](#) ([SRS\\_SPAL\\_12169](#), [SRS\\_Can\\_01053](#))

**[SWS\_Can\_00384]** [ Each time the CAN controller state machine is triggered with the state transition value `CAN_CS_STARTED`, the function `Can_SetControllerMode` shall re-initialize the CAN controller with the same controller configuration set previously used by functions `Can_SetBaudrate` or `Can_Init`.] ()

Refer to [SWS\\_Can\\_00048](#) for the case of a wakeup event from CAN bus occurred during sleep transition.

**[SWS\_Can\_00294]** [ The function `Can_SetControllerMode` shall disable the wake-up interrupt, while checking the wake-up status. ] ()

**[SWS\_Can\_00196]** [ The function `Can_SetControllerMode` shall enable interrupts that are needed in the new state. ] ()

**[SWS\_Can\_00425]** [ Enabling of CAN interrupts shall not be executed, when CAN interrupts have been disabled by function `Can_DisableControllerInterrupts`.] ()

**[SWS\_Can\_00197]** [ The function `Can_SetControllerMode` shall disable interrupts that are not allowed in the new state. ] ()

**[SWS\_Can\_00426]** [ Disabling of CAN interrupts shall not be executed, when CAN interrupts have been disabled by function `Can_DisableControllerInterrupts`.] ()

**[SWS\_Can\_00198]** [ If development error detection for the Can module is enabled: if the module is not yet initialized, the function `Can_SetControllerMode` shall raise development error `CAN_E_UNINIT` and return `E_NOT_OK`.] ()

**[SWS\_Can\_00199]** [ If development error detection for the Can module is enabled: if the parameter `Controller` is out of range, the function `Can_SetControllerMode` shall raise development error `CAN_E_PARAM_CONTROLLER` and return `E_NOT_OK`.] ()

**[SWS\_Can\_00200]** [ If development error detection for the Can module is enabled: if an invalid transition has been requested, the function `Can_SetControllerMode` shall raise the error `CAN_E_TRANSITION` and return `E_NOT_OK`.] ()

### 8.3.2.3 Can\_DisableControllerInterrupts

**[SWS\_Can\_00231]** [

<b>Service name:</b>	Can_DisableControllerInterrupts	
<b>Syntax:</b>	void Can_DisableControllerInterrupts( uint8 Controller )	
<b>Service ID[hex]:</b>	0x04	
<b>Sync/Async:</b>	Synchronous	
<b>Reentrancy:</b>	Reentrant	
<b>Parameters (in):</b>	Controller	CAN controller for which interrupts shall be disabled.
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	None	
<b>Return value:</b>	None	
<b>Description:</b>	This function disables all interrupts for this CAN controller.	

] (SRS\_BSW\_00312)

**[SWS\_Can\_00049]** [The function `Can_DisableControllerInterrupts` shall access the CAN controller registers to disable all interrupts for that CAN controller only, if interrupts for that CAN Controller are enabled. ] (SRS\_Can\_01043)

**[SWS\_Can\_00202]** [ When `Can_DisableControllerInterrupts` has been called several times, `Can_EnableControllerInterrupts` must be called as many times before the interrupts are re-enabled.] ()

Implementation note:

The function `Can_DisableControllerInterrupts` can increase a counter on every execution that indicates how many `Can_EnableControllerInterrupts` need to be called before the interrupts will be enabled (incremental disable).

**[SWS\_Can\_00204]** [ The Can module shall track all individual enabling and disabling of interrupts in other functions (i.e. `Can_SetControllerMode`) , so that the correct interrupt enable state can be restored.] ()

Implementation example:

- in 'interrupts enabled mode': For each interrupt state change does not only modify the interrupt enable bit, but also a software flag.
- in 'interrupts disabled mode': only the software flag is modified.
- `Can_DisableControllerInterrupts` and `Can_EnableControllerInterrupts` do not modify the software flags.
- `Can_EnableControllerInterrupts` reads the software flags to re-enable the correct interrupts.

**[SWS\_Can\_00205]** [ If development error detection for the Can module is enabled: The function `Can_DisableControllerInterrupts` shall raise the error `CAN_E_UNINIT` if the driver not yet initialized.] ()

**[SWS\_Can\_00206]** [ If development error detection for the Can module is enabled: The function `Can_DisableControllerInterrupts` shall raise the error `CAN_E_PARAM_CONTROLLER` if the parameter `Controller` is out of range.] ()

### 8.3.2.4 Can\_EnableControllerInterrupts

**[SWS\_Can\_00232]** [

<b>Service name:</b>	<code>Can_EnableControllerInterrupts</code>	
<b>Syntax:</b>	<pre>void Can_EnableControllerInterrupts(     uint8 Controller )</pre>	
<b>Service ID[hex]:</b>	0x05	
<b>Sync/Async:</b>	Synchronous	
<b>Reentrancy:</b>	Reentrant	
<b>Parameters (in):</b>	Controller	CAN controller for which interrupts shall be re-enabled
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	None	
<b>Return value:</b>	None	
<b>Description:</b>	This function enables all allowed interrupts.	

] (SRS\_BSW\_00312)

**[SWS\_Can\_00050]** [ The function `Can_EnableControllerInterrupts` shall enable all interrupts that must be enabled according the current software status.] (SRS\_Can\_01043)

[SWS\\_Can\\_00202](#) applies to this function.

**[SWS\_Can\_00208]** [ The function `Can_EnableControllerInterrupts` shall perform no action when `Can_DisableControllerInterrupts` has not been called before.] ()

See also implementation example for `Can_DisableControllerInterrupts`.

**[SWS\_Can\_00209]** [ If development error detection for the Can module is enabled: The function `Can_EnableControllerInterrupts` shall raise the error `CAN_E_UNINIT` if the driver not yet initialized.] ()

**[SWS\_Can\_00210]** [ If development error detection for the Can module is enabled: The function `Can_EnableControllerInterrupts` shall raise the error `CAN_E_PARAM_CONTROLLER` if the parameter `Controller` is out of range.] ()

### 8.3.2.5 Can\_CheckWakeup

**[SWS\_Can\_00360]** [

<b>Service name:</b>	Can_CheckWakeup	
<b>Syntax:</b>	Std_ReturnType Can_CheckWakeup( uint8 Controller )	
<b>Service ID[hex]:</b>	0x0b	
<b>Sync/Async:</b>	Synchronous	
<b>Reentrancy:</b>	Non Reentrant	
<b>Parameters (in):</b>	Controller	Controller to be checked for a wakeup.
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	None	
<b>Return value:</b>	Std_ReturnType	E_OK: API call has been accepted E_NOT_OK: API call has not been accepted
<b>Description:</b>	This function checks if a wakeup has occurred for the given controller.	

] ()

**[SWS\_Can\_00361]** [ The function `Can_CheckWakeup` shall check if the requested CAN controller has detected a wakeup. If a wakeup event was successfully detected, reporting shall be done to EcuM via API `EcuM_SetWakeupEvent`.] ()

**[SWS\_CAN\_00485]**[ The function `Can_CheckWakeup` shall be pre compile time configurable On/Off by the configuration parameter: `CanWakeupFunctionalityAPI` ] ()

**[SWS\_Can\_00362]** [ If development error detection for the Can module is enabled: The function `Can_CheckWakeup` shall raise the error `CAN_E_UNINIT` if the driver is not yet initialized.] ()

**[SWS\_Can\_00363]** [ If development error detection for the Can module is enabled: The function `Can_CheckWakeup` shall raise the error `CAN_E_PARAM_CONTROLLER` if the parameter `Controller` is out of range.] ()

### 8.3.2.6 Can\_GetControllerErrorState

**[SWS\_Can\_91004]** [

<b>Service name:</b>	Can_GetControllerErrorState	
<b>Syntax:</b>	Std_ReturnType Can_GetControllerErrorState( uint8 ControllerId, Can_ErrorStateType* ErrorStatePtr )	

<b>Service ID[hex]:</b>	0x11	
<b>Sync/Async:</b>	Synchronous	
<b>Reentrancy:</b>	Non Reentrant for the same ControllerId	
<b>Parameters (in):</b>	ControllerId	Abstracted CanIf ControllerId which is assigned to a CAN controller, which is requested for ErrorState.
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	ErrorStatePtr	Pointer to a memory location, where the error state of the CAN controller will be stored.
<b>Return value:</b>	Std_ReturnType	E_OK: Error state request has been accepted. E_NOT_OK: Error state request has not been accepted.
<b>Description:</b>	This service obtains the error state of the CAN controller.	

] ()

**[SWS\_Can\_91005]** [ If development error detection for the Can module is enabled: if the module is not yet initialized, the function Can\_GetControllerErrorState shall raise development error CAN\_E\_UNINIT and return E\_NOT\_OK.] (SRS\_BSW\_00406, SRS\_BSW\_00416)

**[SWS\_Can\_91006]** [ If development error detection for the Can module is enabled: if the parameter ControllerId is out of range, the function Can\_GetControllerErrorState shall raise development error CAN\_E\_PARAM\_CONTROLLER and return E\_NOT\_OK.] (SRS\_BSW\_00323)

**[SWS\_Can\_91007]** [ If development error detection for the Can module is enabled: if the parameter ErrorStatePtr is a null pointer, the function Can\_GetControllerErrorState shall raise development error CAN\_E\_PARAM\_POINTER and return E\_NOT\_OK.] (SRS\_BSW\_00323)

**[SWS\_Can\_91008]** [ When the API Can\_GetControllerErrorState() is called with Controller Id as input parameter then Can driver shall read the error state register of Can Controller and shall return the error status to upper layer.] (SRS\_CAN\_01167)

### 8.3.2.7 Can\_GetControllerMode

**[SWS\_Can\_91014]** [

<b>Service name:</b>	Can_GetControllerMode	
<b>Syntax:</b>	Std_ReturnType Can_GetControllerMode ( uint8 Controller, Can_ControllerStateType* ControllerModePtr )	
<b>Service ID[hex]:</b>	0x12	
<b>Sync/Async:</b>	Synchronous	
<b>Reentrancy:</b>	Non Reentrant	
<b>Parameters (in):</b>	Controller	CAN controller for which the status shall be requested.
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	ControllerModePtr	Pointer to a memory location, where the current mode of the CAN controller will be stored.
<b>Return value:</b>	Std_ReturnType	E_OK: Controller mode request has been accepted. E_NOT_OK: Controller mode request has not been



	accepted.
<b>Description:</b>	This service reports about the current status of the requested CAN controller.

] ()

[SWS\_Can\_91015] [ The service Can\_GetControllerMode shall return the mode of the requested CAN controller. ]

[SWS\_Can\_91016] [ If development error detection for the Can module is enabled: The function Can\_GetControllerMode shall raise the error CAN\_E\_UNINIT and return

E\_NOT\_OK if the driver is not yet initialized.] ( SRS\_BSW\_00406,SRS\_BSW\_00416)

[SWS\_Can\_91017] [ If parameter Controller of Can\_GetControllerMode() has an invalid value, the CanDrv shall report development error code CAN\_E\_PARAM\_CONTROLLER to the Det\_ReportError service of the DET. ] (SRS\_BSW\_00323)

[SWS\_Can\_91018] [ If parameter ControllerModePtr of Can\_GetControllerMode() has an null pointer, the CanDrv shall report development error code CAN\_E\_PARAM\_POINTER to the Det\_ReportError service of the DET. ] (SRS\_BSW\_00323)

### 8.3.3 Services affecting a Hardware Handle

#### 8.3.3.1 Can\_Write

[SWS\_Can\_00233] [

<b>Service name:</b>	Can_Write	
<b>Syntax:</b>	Std_ReturnType Can_Write( Can_HwHandleType Hth, const Can_PduType* PduInfo )	
<b>Service ID[hex]:</b>	0x06	
<b>Sync/Async:</b>	Synchronous	
<b>Reentrancy:</b>	Reentrant (thread-safe)	
<b>Parameters (in):</b>	Hth	information which HW-transmit handle shall be used for transmit. Implicitly this is also the information about the controller to use because the Hth numbers are unique inside one hardware unit.
	PduInfo	Pointer to SDU user memory, Data Length and Identifier.
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	None	
<b>Return value:</b>	Std_ReturnType	E_OK: Write command has been accepted
		E_NOT_OK: development error occurred
		CAN_BUSY: No TX hardware buffer available or pre-emptive call of Can_Write that can't be implemented re-entrant (see

	Can_ReturnType)
<b>Description:</b>	This function is called by CanIf to pass a CAN message to CanDrv for transmission.

] (SRS\_BSW\_00312)

The function Can\_Write first checks if the hardware transmit object that is identified by the HTH is free and if another Can\_Write is ongoing for the same HTH.

**[SWS\_Can\_00212]** [ The function Can\_Write shall perform following actions if the hardware transmit object is free:

- The mutex for that HTH is set to 'signaled'
- The ID, Data Length and SDU are put in a format appropriate for the hardware (if necessary) and copied in the appropriate hardware registers/buffers.
- All necessary control operations to initiate the transmit are done
- The mutex for that HTH is released
- The function returns with E\_OK] (SRS\_Can\_01049)

**[SWS\_Can\_00213]** [ The function Can\_Write shall perform no actions if the hardware transmit object is busy with another transmit request for an L-PDU:

1. The transmission of the other L-PDU shall not be cancelled and the function Can\_Write is left without any actions.

2. The function Can\_Write shall return CAN\_BUSY.] (SRS\_Can\_01049).

**[SWS\_Can\_00214]** [ The function Can\_Write shall return CAN\_BUSY if a preemptive call of Can\_Write has been issued, that could not be handled reentrant (i.e. a call with the same HTH).] (SRS\_BSW\_00312, SRS\_Can\_01049)

**[SWS\_Can\_00275]** [ The function Can\_Write shall be non-blocking.] ()

**[SWS\_Can\_00216]** [ If development error detection for the Can module is enabled: The function Can\_Write shall raise the error CAN\_E\_UNINIT and shall return E\_NOT\_OK if the driver is not yet initialized.] ()

**[SWS\_Can\_00217]** [ If development error detection for the Can module is enabled: The function Can\_Write shall raise the error CAN\_E\_PARAM\_HANDLE and shall return E\_NOT\_OK if the parameter Hth is not a configured Hardware Transmit Handle.] ()

**[SWS\_Can\_00218]** [ The function Can\_Write shall return E\_NOT\_OK and if development error detection for the CAN module is enabled shall raise the error CAN\_E\_PARAM\_DATA\_LENGTH:

- If the length is more than 64 byte.
- If the length is more than 8 byte and the CAN controller is not in CAN FD mode (no CanControllerFdBaudrateConfig).
- If the length is more than 8 byte and the CAN controller is in CAN FD mode (valid CanControllerFdBaudrateConfig), but the CAN FD flag in Can\_PduType->id is not set (refer Can\_IdType).] ( SRS\_Can\_01005)

**[SWS\_CAN\_00219]** [ If development error detection for CanDrv is enabled: Can\_Write() shall raise CAN\_E\_PARAM\_POINTER and shall return E\_NOT\_OK if the parameter PduInfo is a null pointer.] ()

**[SWS\_CAN\_00503]** [ `Can_Write()` shall accept a null pointer as SDU (`Can_PduType.Can_SduPtrType = NULL`) if the trigger transmit API is enabled for this hardware object (`CanTriggerTransmitEnable = TRUE`).] ()

**[SWS\_CAN\_00504]** [ If the trigger transmit API is enabled for the hardware object, `Can_Write()` shall interpret a null pointer as SDU (`Can_PduType.Can_SduPtrType = NULL`) as request for using the trigger transmit interface. If so and the hardware object is free, `Can_Write()` shall call `CanIf_TriggerTransmit()` with the maximum size of the message buffer to acquire the PDU's data.] ()

Note: Using the message buffer size allows for late changes of the PDU size, e.g. if a container PDU receives another contained PDU between the call to `Can_Write()` and the call of `CanIf_TriggerTransmit()`.

**[SWS\_CAN\_00505]** [ If development error detection for `CanDrv` is enabled: `Can_Write()` shall raise `CAN_E_PARAM_POINTER` and shall return `E_NOT_OK` if the trigger transmit API is disabled for this hardware object (`CanTriggerTransmitEnable = FALSE`) and the SDU pointer inside `PduInfo` is a null pointer.] ()

**[SWS\_CAN\_00506]** [ `Can_Write()` shall return `E_NOT_OK` if the trigger transmit API (`CanIf_TriggerTransmit()`) returns `E_NOT_OK`.] (SRS\_BSW\_00449, SRS\_BSW\_00357, SRS\_BSW\_00369, SRS\_Can\_01130)

**[SWS\_CAN\_00486]** [ The CAN Frame has to be sent according to the two most significant bits of `Can_PduType->id`. The CAN FD frame bit is only evaluated if CAN Controller is in CAN FD mode (valid `CanControllerFdBaudrateConfig`).] ()

**[SWS\_CAN\_00502]** [ If `PduInfo->SduLength` does not match possible DLC values `CanDrv` shall use the next higher valid DLC for transmission with initialization of unused bytes to the value of the corresponding `CanFdPaddingValue` (see ECUC\_Can\_00485).] (SRS\_Can\_01160)

## 8.4 Call-back notifications

This chapter lists all functions provided by the `Can` module to lower layer modules. The lower layer module of `Can` module is the `SPI` module. The `SPI` module, which is part of the `MCAL`, may used to exchange data between the microcontroller and an external CAN controller.

The `Can` module does not provide callback functions. Only synchronous `MCAL` API may used to access external CAN controllers.

### 8.4.1 Call-out function

The AUTOSAR CAN module supports optional L-PDU callouts on every reception of a L-PDU.

**[SWS\_Can\_00443]** [

<b>Service name:</b>	<LPDU_CalloutName>
<b>Syntax:</b>	boolean <LPDU_CalloutName> (

	<pre>uint8 Hrh, Can_IdType CanId, uint8 CanDataLegth, const uint8* CanSduPtr ) </pre>	
<b>Service ID[hex]:</b>	0x20	
<b>Sync/Async:</b>	Asynchronous	
<b>Reentrancy:</b>	Non Reentrant	
<b>Parameters (in):</b>	Hrh	--
	CanId	--
	CanDataLegth	--
	CanSduPtr	--
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	None	
<b>Return value:</b>	boolean	--
<b>Description:</b>	--	

] ()

where <LPDU\_CalloutName> has to be substituted with the concrete L-PDU callout name which is configurable, see ECUC\_Can\_00434.

**[SWS\_Can\_00444]** [ If the L-PDU callout returns false, the L-PDU shall not be processed any further. ] ()

## 8.4.2 Enabling/Disabling wakeup notification

**[SWS\_Can\_00445]** [ Can driver shall use the following APIs provided by Icu driver, to enable and disable the wakeup event notification:

- Icu\_EnableNotification
- Icu\_DisableNotification] ()

**[SWS\_Can\_00446]** [ Icu\_EnableNotification shall be called when “external” Can controllers have been transitioned to SLEEP state.] ()

**[SWS\_Can\_00447]** [ Icu\_DisableNotification shall be called when “external” Can controllers have been transitioned to STOPPED state.] ()

## 8.5 Scheduled functions

These functions are directly called by Basic Software Scheduler. The following functions shall have no return value and no parameter. All functions shall be non-reentrant.

**[SWS\_Can\_00110]** [ There is no requirement regarding the execution order of the CAN main processing functions.] (SRS\_BSW\_00428)

### 8.5.1.1 Can\_MainFunction\_Write

**[SWS\_Can\_00225]** [

<b>Service name:</b>	Can_MainFunction_Write
----------------------	------------------------

<b>Syntax:</b>	void Can_MainFunction_Write( void )
<b>Service ID[hex]:</b>	0x01
<b>Description:</b>	This function performs the polling of TX confirmation when CAN_TX_PROCESSING is set to POLLING.

] ()

**[SWS\_Can\_00031]** [ The function Can\_MainFunction\_Write shall perform the polling of TX confirmation when CanTxProcessing is set to POLLING or MIXED. In case of MIXED processing only the hardware objects for which CanHardwareObjectUsesPolling is set to TRUE shall be polled.] (SRS\_BSW\_00432, SRS\_BSW\_00373, SRS\_SPAL\_00157)

**[SWS\_Can\_00178]** [ The Can module may implement the function Can\_MainFunction\_Write as empty define in case no polling at all is used.] ()

**[SWS\_Can\_00441]** [ The API name of Can\_MainFunction\_Write() shall obey the following pattern:

- Can\_MainFunction\_Wrtte\_0()
- Can\_MainFunction\_Write\_1()
- Can\_MainFunction\_Write\_2()
- Can\_MainFunction\_Write\_3()
- ... and so on, if more than one period (see ECUC\_Can\_00356) is supported.] ()

### 8.5.1.2 Can\_MainFunction\_Read

**[SWS\_Can\_00226]** [

<b>Service name:</b>	Can_MainFunction_Read
<b>Syntax:</b>	void Can_MainFunction_Read( void )
<b>Service ID[hex]:</b>	0x08
<b>Description:</b>	This function performs the polling of RX indications when CAN_RX_PROCESSING is set to POLLING.

] ()

**[SWS\_Can\_00108]** [ The function Can\_MainFunction\_Read shall perform the polling of RX indications when CanRxProcessing is set to POLLING or MIXED. In case of MIXED processing only the hardware objects for which CanHardwareObjectUsesPolling is set to TRUE shall be polled.] (SRS\_BSW\_00432, SRS\_SPAL\_00157)

**[SWS\_Can\_00180]** [ The Can module may implement the function Can\_MainFunction\_Read as empty define in case no polling at all is used.] ()

**[SWS\_Can\_00442]** [ The API name of Can\_MainFunction\_Read() shall obey the following pattern:

- Can\_MainFunction\_Read\_0()
- Can\_MainFunction\_Read\_1()
- Can\_MainFunction\_Read\_2()
- Can\_MainFunction\_Read\_3()

- ... and so on, if more than one period (see ECUC\_Can\_00358) is supported.] ()

### 8.5.1.3 Can\_MainFunction\_BusOff

[SWS\_Can\_00227] [

<b>Service name:</b>	Can_MainFunction_BusOff
<b>Syntax:</b>	void Can_MainFunction_BusOff( void )
<b>Service ID[hex]:</b>	0x09
<b>Description:</b>	This function performs the polling of bus-off events that are configured statically as 'to be polled'.

] ()

[SWS\_Can\_00109] [ The function Can\_MainFunction\_BusOff shall perform the polling of bus-off events that are configured statically as 'to be polled'.] () (SRS\_BSW\_00432, SRS\_SPAL\_00157)

[SWS\_Can\_00183] [ The Can module may implement the function Can\_MainFunction\_BusOff as empty define in case no polling at all is used.] ()

### 8.5.1.4 Can\_MainFunction\_Wakeup

[SWS\_Can\_00228] [

<b>Service name:</b>	Can_MainFunction_Wakeup
<b>Syntax:</b>	void Can_MainFunction_Wakeup( void )
<b>Service ID[hex]:</b>	0x0a
<b>Description:</b>	This function performs the polling of wake-up events that are configured statically as 'to be polled'.

] ()

[SWS\_Can\_00112] [ The function Can\_MainFunction\_Wakeup shall perform the polling of wake-up events that are configured statically as 'to be polled'.] (SRS\_BSW\_00432, SRS\_SPAL\_00157)

[SWS\_Can\_00185] [ The Can module may implement the function Can\_MainFunction\_Wakeup as empty define in case no polling at all is used.] ()

### 8.5.1.5 Can\_MainFunction\_Mode

[SWS\_Can\_00368] [

<b>Service name:</b>	Can_MainFunction_Mode
<b>Syntax:</b>	void Can_MainFunction_Mode( void )
<b>Service ID[hex]:</b>	0x0c
<b>Description:</b>	This function performs the polling of CAN controller mode transitions.

] ()

[SWS\_Can\_00369] | The function Can\_MainFunction\_Mode shall implement the polling of CAN status register flags to detect transition of CAN Controller state. Compare to chapter 7.3.2.] ()

## 8.6 Expected Interfaces

In this chapter all interfaces required from other modules are listed.

### 8.6.1 Mandatory Interfaces

This chapter defines all interfaces which are required to fulfill the core functionality of the module. All callback functions that are called by the Can module are implemented in the CanIf module. These callback functions are not configurable.

[SWS\_Can\_00234] |

API function	Description
CanIf_ControllerBusOff	This service indicates a Controller BusOff event referring to the corresponding CAN Controller with the abstract CanIf ControllerId.
CanIf_ControllerModeIndication	This service indicates a controller state transition referring to the corresponding CAN controller with the abstract CanIf ControllerId.
CanIf_RxIndication	This service indicates a successful reception of a received CAN Rx L-PDU to the CanIf after passing all filters and validation checks.
CanIf_TxConfirmation	This service confirms a previously successfully processed transmission of a CAN TxPDU.
Det_ReportRuntimeError	Service to report runtime errors. If a callout has been configured then this callout shall be called.
GetCounterValue	This service reads the current count value of a counter (returning either the hardware timer ticks if counter is driven by hardware or the software ticks when user drives counter).

] (SRS\_Can\_01055)

### 8.6.2 Optional Interfaces

This chapter defines all interfaces that are required to fulfill an optional functionality of the module.

[SWS\_Can\_00235] |

API function	Description
CanIf_CurrentIcomConfiguration	This service shall inform about the change of the Icom Configuration of a CAN controller using the abstract CanIf ControllerId.
CanIf_TriggerTransmit	Within this API, the upper layer module (called module) shall check whether the available data fits into the buffer size reported by PduInfoPtr->SduLength. If it fits, it shall copy its data into the buffer provided by PduInfoPtr->SduDataPtr and update the length of the actual copied data in PduInfoPtr->SduLength. If not, it returns E_NOT_OK without changing PduInfoPtr.
Det_ReportError	Service to report development errors.
EcuM_CheckWakeup	This callout is called by the EcuM to poll a wakeup source. It shall also be called by the ISR of a wakeup source to set up the PLL and check other wakeup sources that may be connected to the same interrupt.

EcuM_SetWakeupEvent	Sets the wakeup event.
Icu_DisableNotification	This function disables the notification of a channel.
Icu_EnableNotification	This function enables the notification on the given channel.

] (SRS\_SPAL\_12056, SRS\_Can\_01054)

### 8.6.3 Configurable interfaces

There is no configurable target for the Can module. The Can module always reports to CanIf module.

## 8.7 API supporting Pretended Networking

[SWS\_CAN\_91001] [

<b>Service name:</b>	Can_SetIcomConfiguration	
<b>Syntax:</b>	Std_ReturnType Can_SetIcomConfiguration( uint8 Controller, IcomConfigIdType ConfigurationId )	
<b>Service ID[hex]:</b>	0xf	
<b>Sync/Async:</b>	Asynchronous	
<b>Reentrancy:</b>	Reentrant only for different controller Ids	
<b>Parameters (in):</b>	Controller	CAN controller for which the status shall be changed.
	ConfigurationId	Requested Configuration
<b>Parameters (inout):</b>	None	
<b>Parameters (out):</b>	None	
<b>Return value:</b>	Std_ReturnType	E_OK: CAN driver succeeded in setting a configuration with a valid Configuration id. E_NOT_OK: CAN driver failed to set a configuration with a valid Configuration id.
<b>Description:</b>	This service shall change the Icom Configuration of a CAN controller to the requested one.	

] ()

[SWS\_CAN\_00480] The interface Can\_SetIcomConfiguration() shall activate or deactivate Pretended Networking and load the requested ICOM configuration for a given controller.] ()

[SWS\_CAN\_00481] If the requested ConfigurationId is not 0, the function Can\_SetIcomConfiguration() shall reconfigure the controller with the ICOM configuration parameters of the CanIcomConfig container which CanIcomConfigId matches the requested ConfigurationId.] ()

[SWS\_CAN\_00495] Can\_SetIcomConfiguration() shall be pre compile time configurable ON/OFF by the configuration parameter CAN\_PUBLIC\_ICOM\_SUPPORT.] ()



**[SWS\_CAN\_00475]** If development error detection for CanDrv is enabled, then function `Can_SetIcomConfiguration()` shall report the development error `CAN_E_ICOM_CONFIG_INVALID` if it is called with an invalid `ConfigurationId` (i.e. neither 0 nor any of the configured `CanIcomConfigId`).] ()

## 9 Sequence diagrams

### 9.1 Interaction between Can and CanIf module

For sequence diagrams see the CanIf module Specification [5].  
There are described the sequences for Transmission, Reception and Error Handling.

### 9.2 Wakeup sequence

For Wakeup sequence diagrams refer to Specification of ECU State Manager [7].

## 10 Configuration specification

This chapter defines configuration parameters and their clustering into containers. In order to support the specification Chapter 10.1 describes fundamentals. It also specifies a template (table) you shall use for the parameter specification. We intend to leave Chapter 10.1 in the specification to guarantee comprehension.

Chapter 10.2 specifies the structure (containers) and the parameters of the Can module.

Chapter 10.3 specifies published information of the Can module.

### 10.1 How to read this chapter

For details refer to the chapter 10.1 “Introduction to configuration specification” in *SWS\_BSWGeneral*

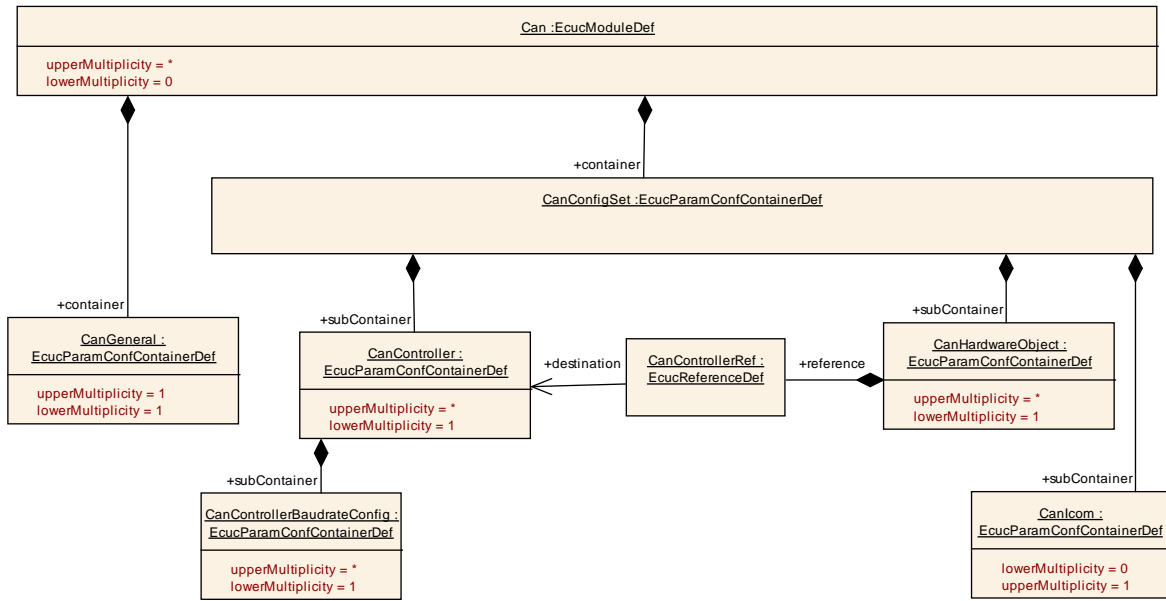
### 10.2 Containers and configuration parameters

The following chapters summarize all configuration parameters. The detailed meanings of the parameters describe Chapters 7 and Chapter 8.

The described parameters are input for the Can module configurator.

**[SWS\_Can\_00022]** [ The code configuration of the Can module is CAN controller specific. If the CAN controller is sited on-chip, the code generation tool for the Can module is  $\mu$ Controller specific. If the CAN controller is an external device, the generation tool must not be  $\mu$ Controller specific.] (SRS\_BSW\_00159)

**[SWS\_Can\_00024]** [ The valid values that can be configured are hardware dependent. Therefore the rules and constraints can't be given in the standard. The configuration tool is responsible to do a static configuration checking, also regarding dependencies between modules (i.e. Port driver, MCU driver etc.)] (SRS\_BSW\_00167, SRS\_SPAL\_12463)



**Figure 10-1: Can Module Configuration Layout**

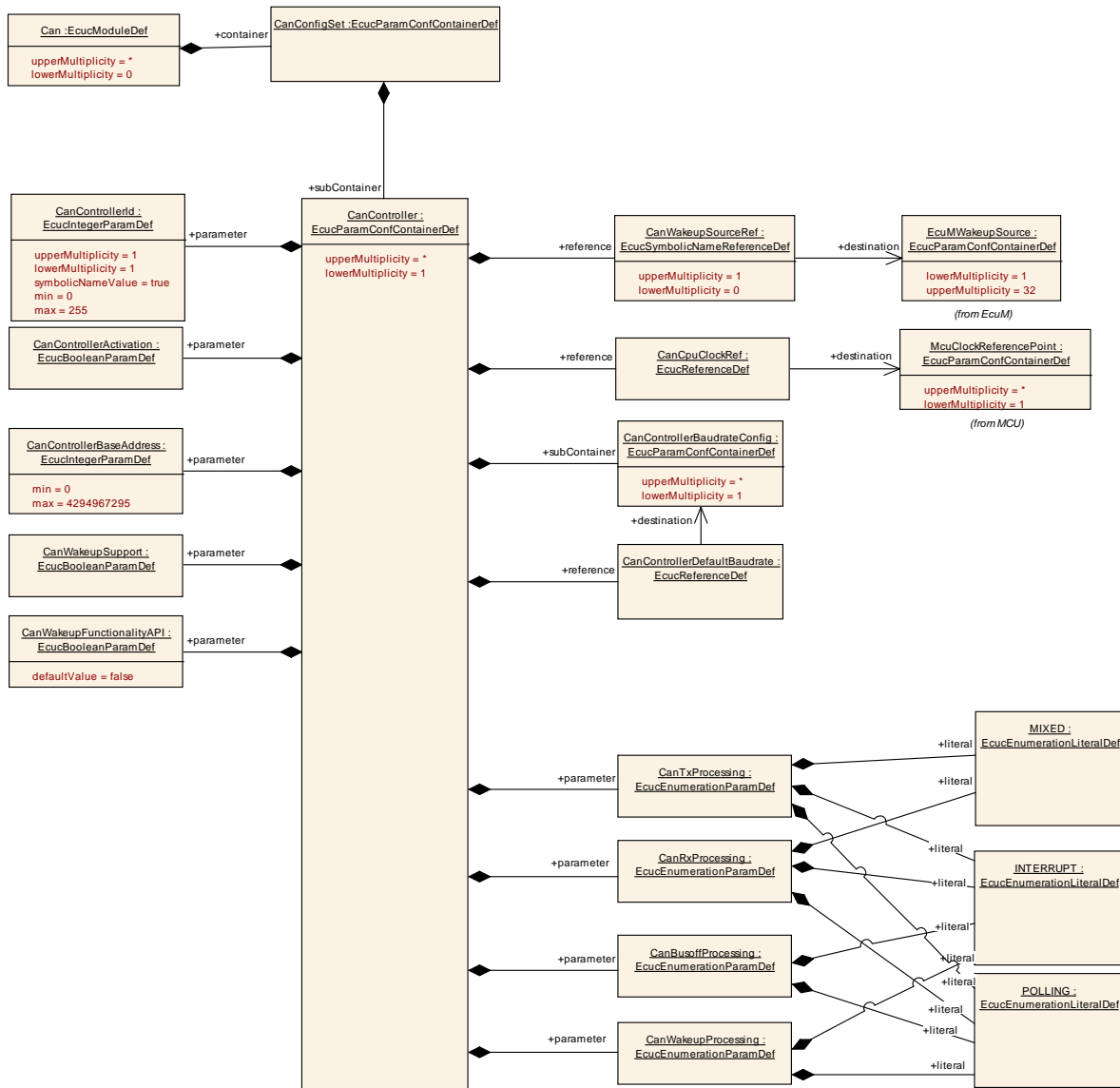
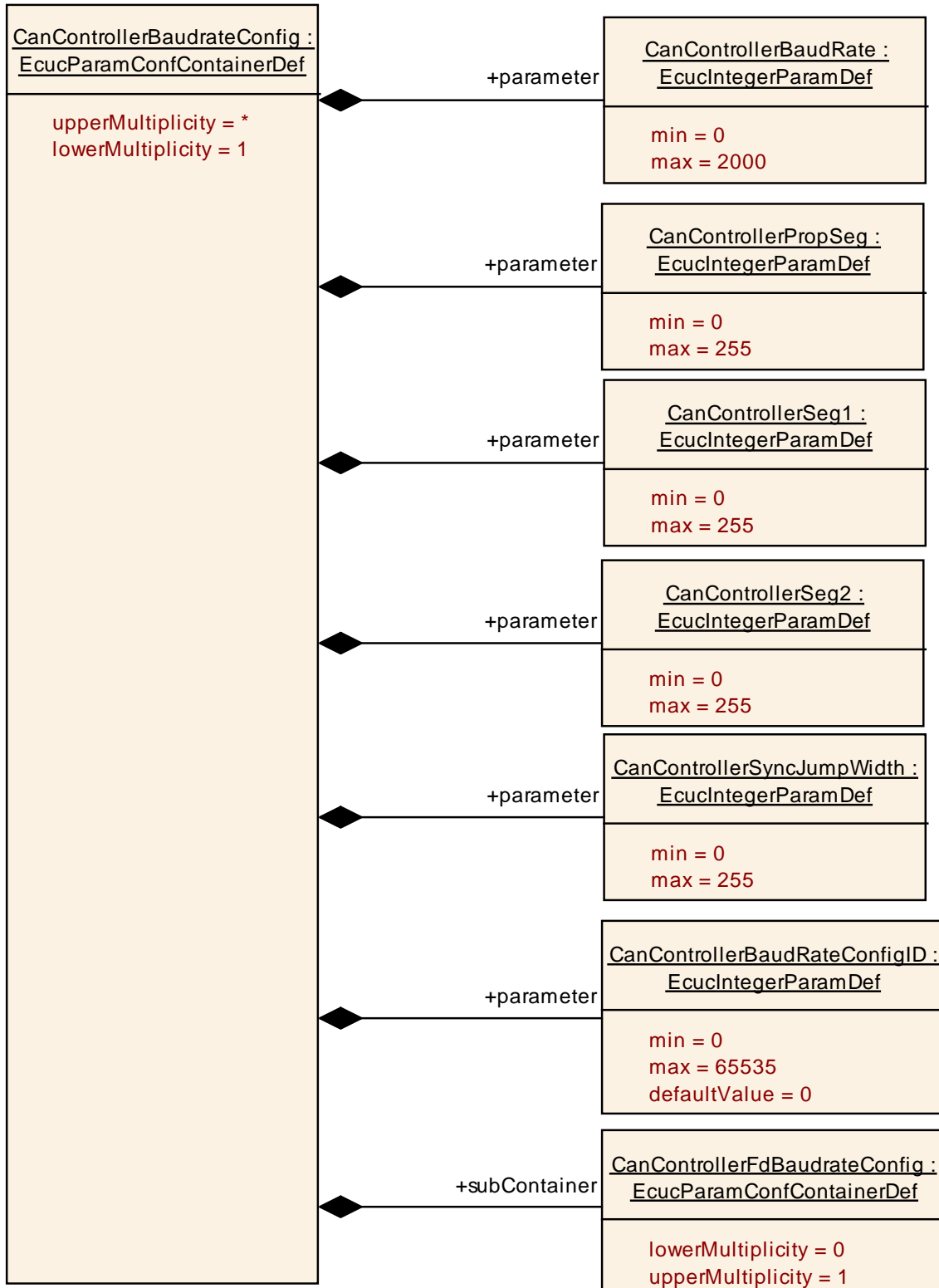


Figure 10-2: Can Controller Configuration Layout



**Figure 10-3: Can Controller Baud Rate Configuration Layout**

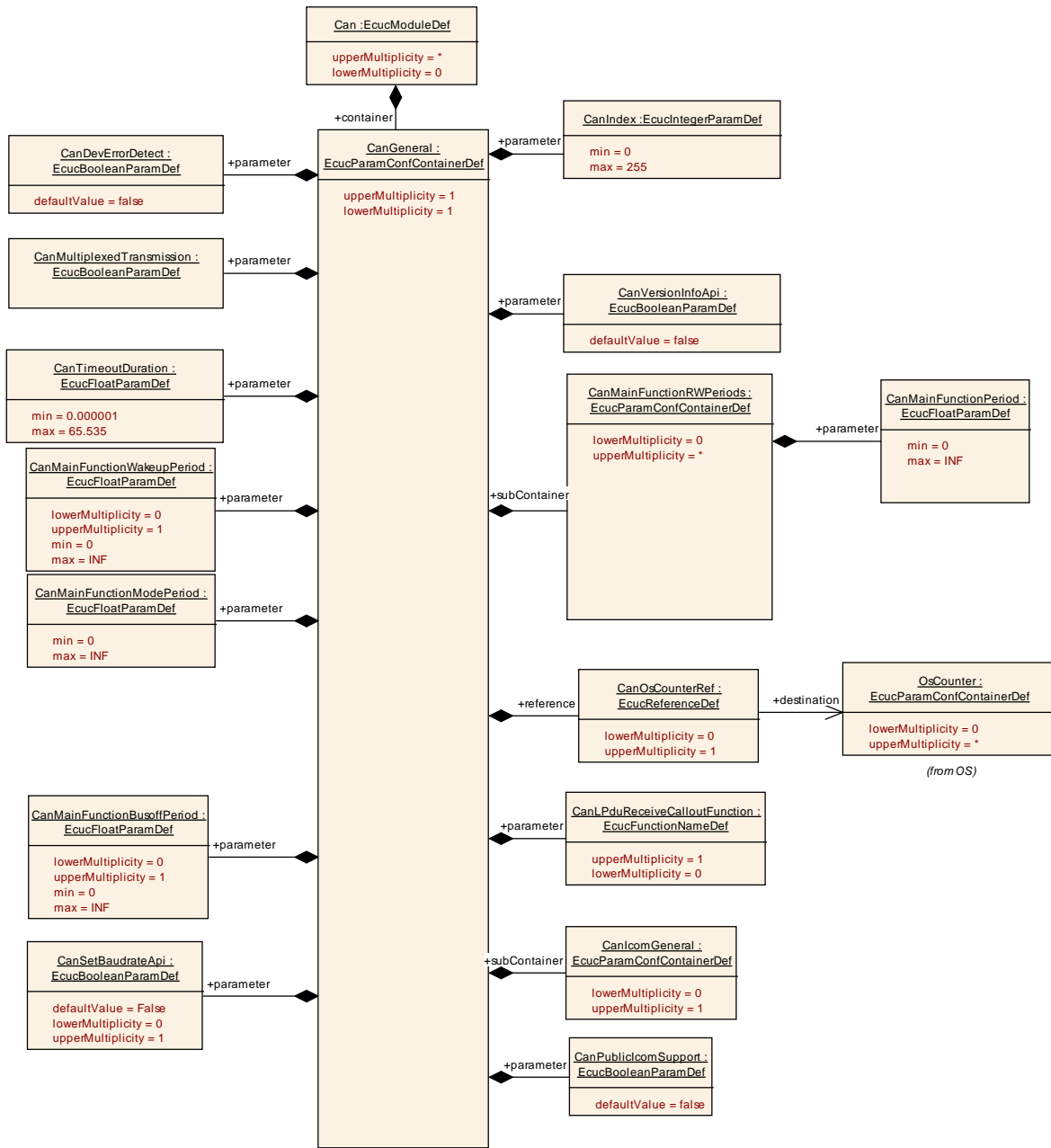


Figure 10-4: Can General Configuration Layout

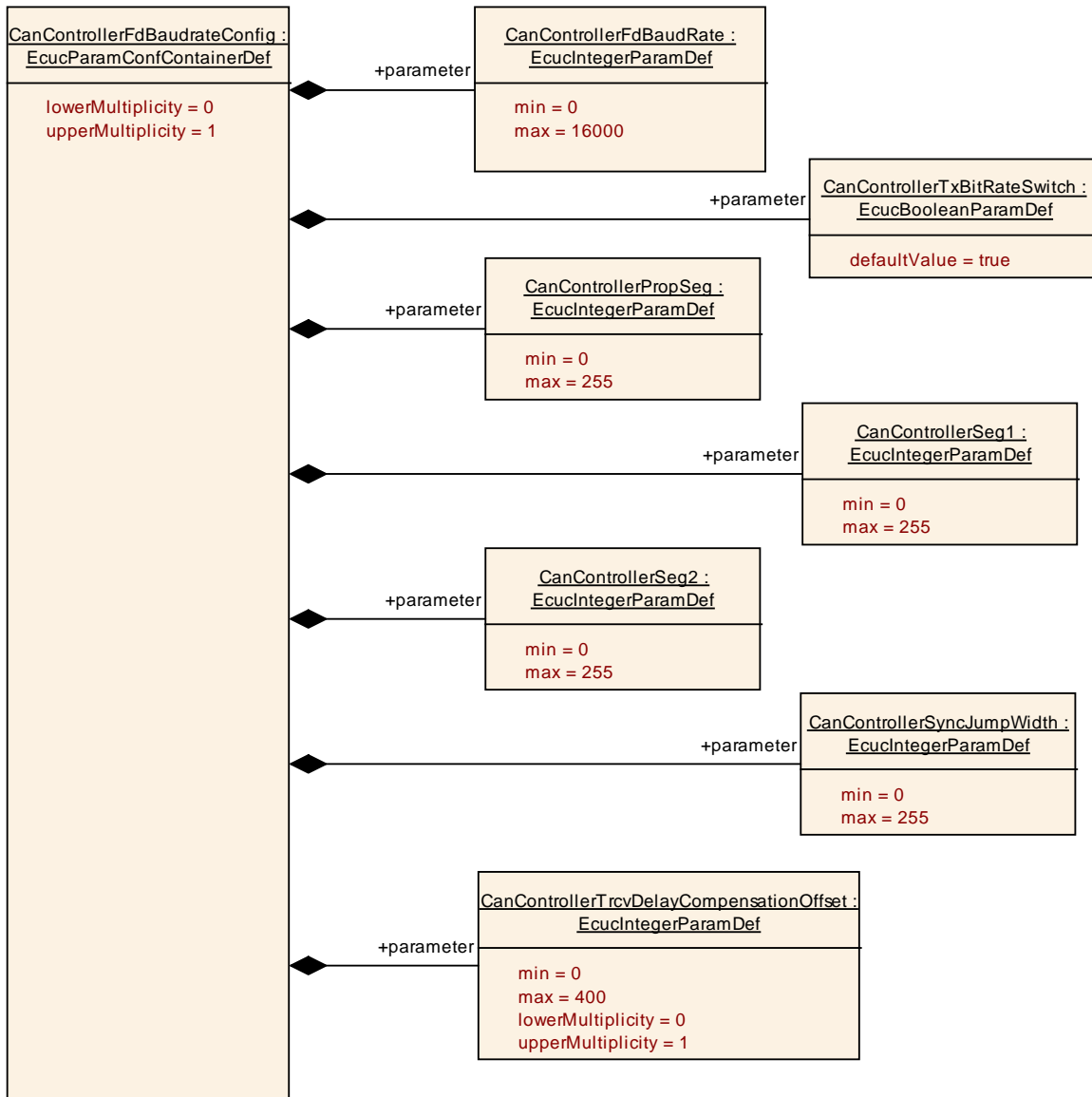


Figure 10-5: CanControllerFdBaudrateConfig



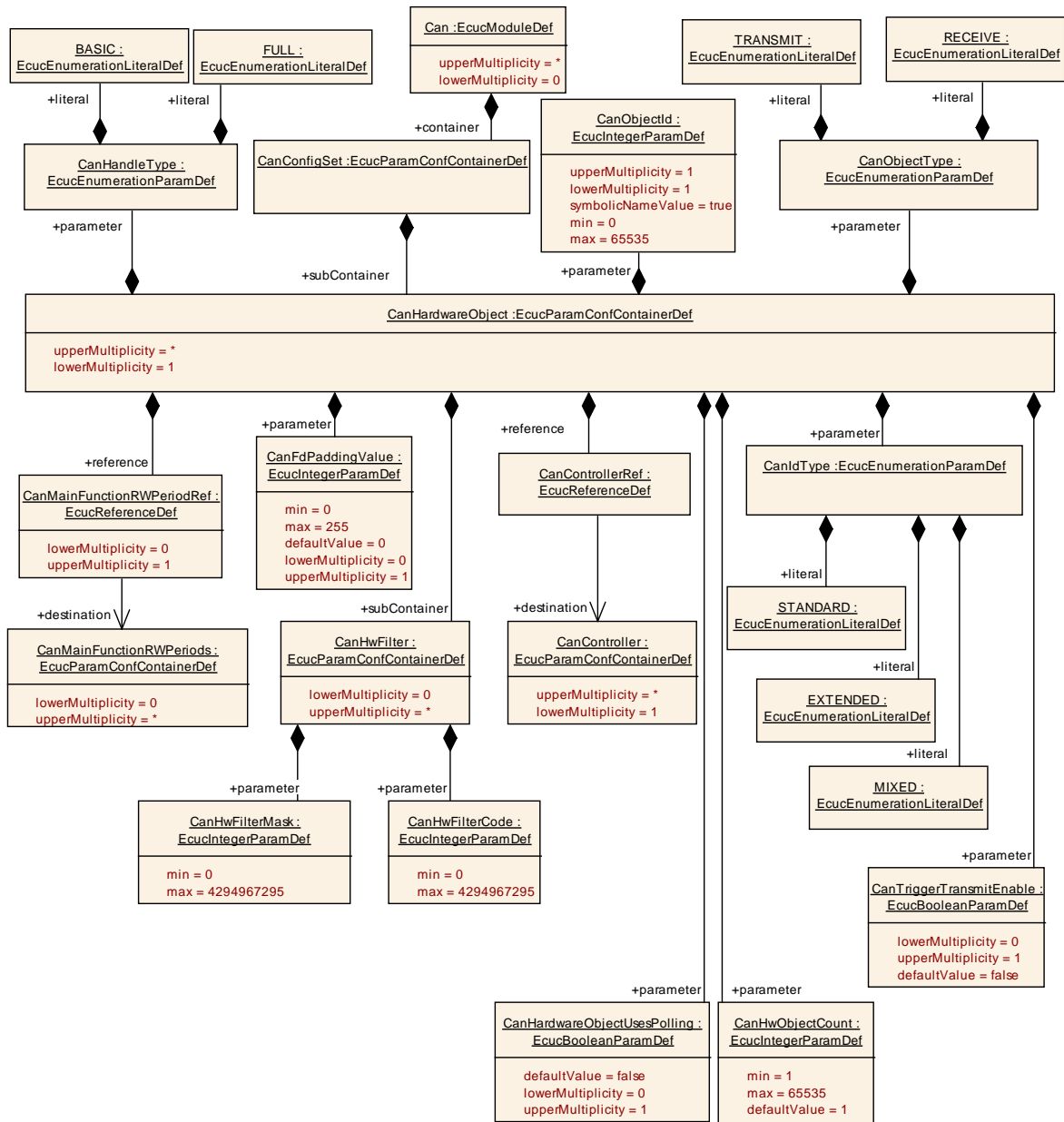
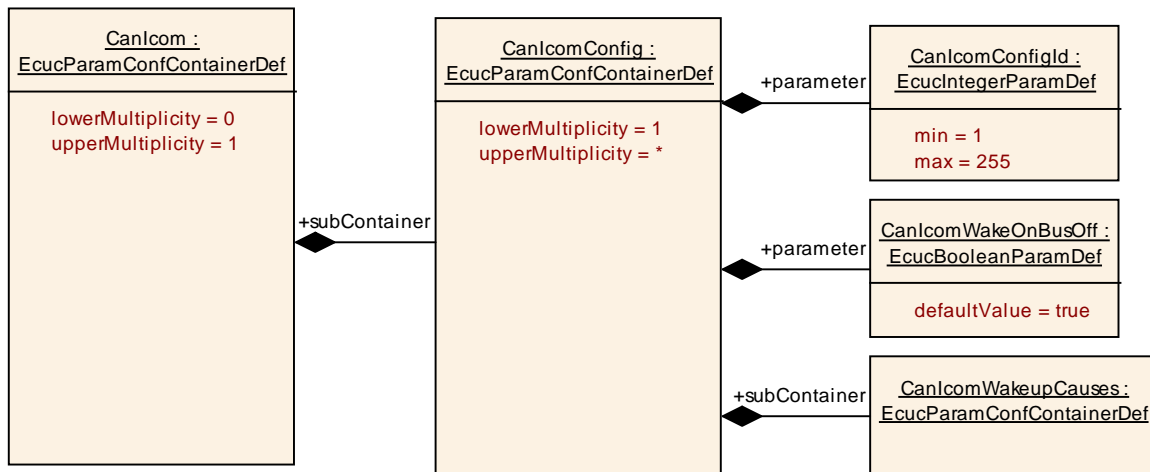
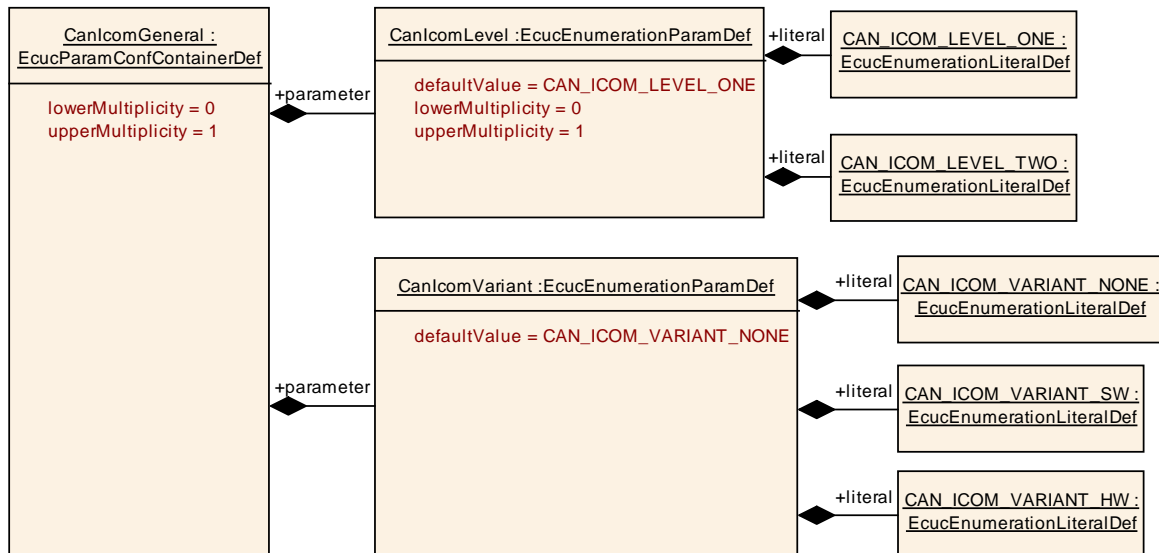


Figure 10-6: Can Hardware Object Configuration Layout



**Figure 10-7: CanIcom Layout**



**Figure 10-8: CanIcom General Configuration Layout**

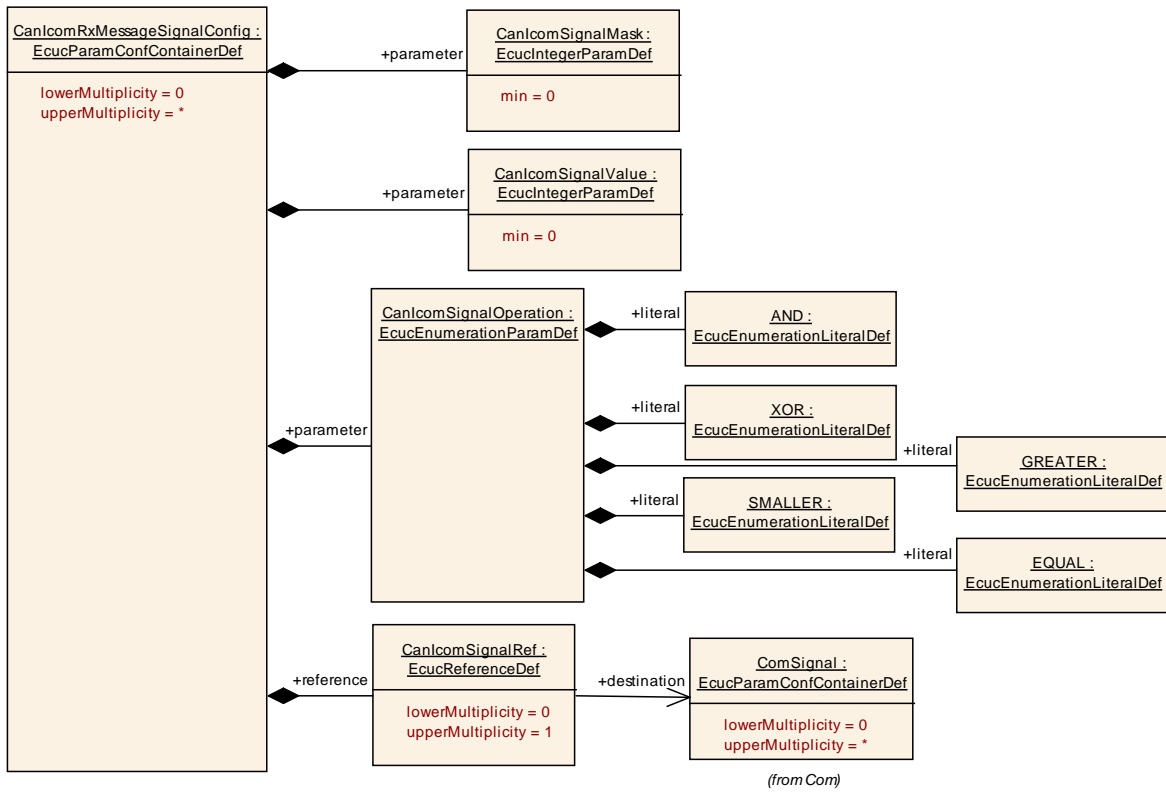


Figure 10-9: CanIcomRxMessageSignal Configuration Layout

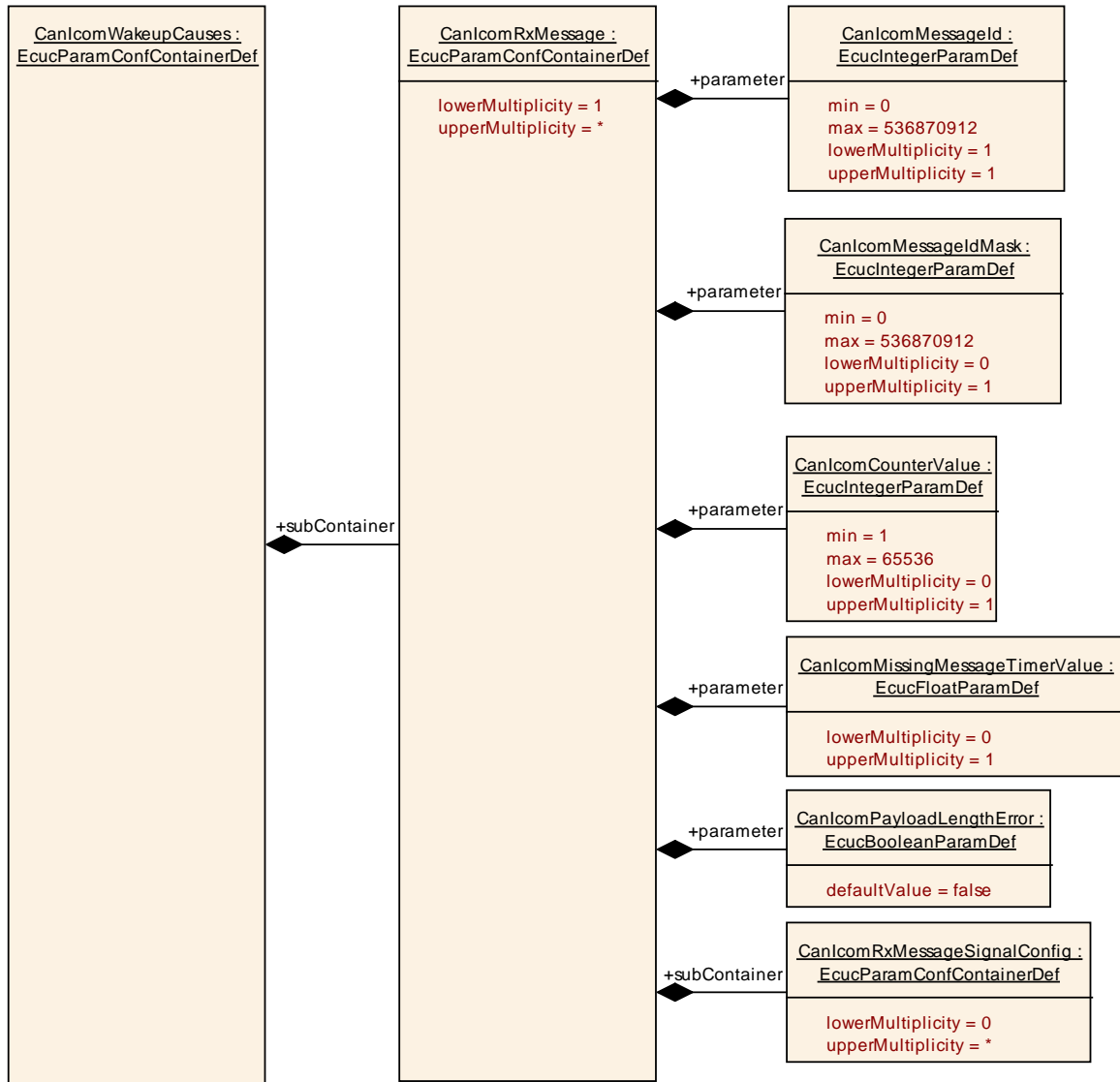


Figure 10-10: CanIcomWakeupCauses Configuration Layout

### 10.2.1 Can

<b>SWS Item</b>	<b>ECUC_Can_00489 :</b>
<b>Module Name</b>	Can
<b>Module Description</b>	This container holds the configuration of a single CAN Driver.
<b>Post-Build Variant Support</b>	true
<b>Supported Config Variants</b>	VARIANT-POST-BUILD, VARIANT-PRE-COMPILE

<b>Included Containers</b>		
<b>Container Name</b>	<b>Multiplicity</b>	<b>Scope / Dependency</b>
CanConfigSet	1	This container contains the configuration parameters and sub containers of the AUTOSAR Can module.
CanGeneral	1	This container contains the parameters related each CAN Driver Unit.

### 10.2.2 CanGeneral

<b>SWS Item</b>	<b>ECUC_Can_00328 :</b>
<b>Container Name</b>	CanGeneral
<b>Description</b>	This container contains the parameters related each CAN Driver Unit.
<b>Configuration Parameters</b>	

<b>SWS Item</b>	<b>ECUC_Can_00064 :</b>		
<b>Name</b>	CanDevErrorDetect		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	Switches the development error detection and notification on or off. <ul style="list-style-type: none"> <li>true: detection and notification is enabled.</li> <li>false: detection and notification is disabled.</li> </ul>		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00320 :</b>		
<b>Name</b>	CanIndex		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	Specifies the InstanceId of this module instance. If only one instance is present it shall have the Id 0.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 255		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		

<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00434 :</b>		
<b>Name</b>	CanLPduReceiveCalloutFunction		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	This parameter defines the existence and the name of a callout function that is called after a successful reception of a received CAN Rx L-PDU. If this parameter is omitted no callout shall take place.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	EcucFunctionNameDef		
<b>Default value</b>	--		
<b>maxLength</b>	--		
<b>minLength</b>	--		
<b>regularExpression</b>	--		
<b>Post-Build Variant Multiplicity</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00355 :</b>		
<b>Name</b>	CanMainFunctionBusoffPeriod		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	This parameter describes the period for cyclic call to Can_MainFunction_Busoff. Unit is seconds.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	EcucFloatParamDef		
<b>Range</b>	]0 .. INF[		
<b>Default value</b>	--		
<b>Post-Build Variant Multiplicity</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>			

<b>SWS Item</b>	<b>ECUC_Can_00376 :</b>		
<b>Name</b>	CanMainFunctionModePeriod		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	This parameter describes the period for cyclic call to Can_MainFunction_Mode. Unit is seconds.		
<b>Multiplicity</b>	1		

<b>Type</b>	EcucFloatParamDef		
<b>Range</b>	]0 .. INF[		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>			

<b>SWS Item</b>	<b>ECUC_Can_00357 :</b>		
<b>Name</b>	CanMainFunctionWakeupPeriod		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	This parameter describes the period for cyclic call to Can_MainFunction_Wakeup. Unit is seconds.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	EcucFloatParamDef		
<b>Range</b>	]0 .. INF[		
<b>Default value</b>	--		
<b>Post-Build Variant Multiplicity</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>			

<b>SWS Item</b>	<b>ECUC_Can_00095 :</b>		
<b>Name</b>	CanMultiplexedTransmission		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	Specifies if multiplexed transmission shall be supported.ON or OFF		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU dependency: CAN Hardware Unit supports multiplexed transmission		

<b>SWS Item</b>	<b>ECUC_Can_00483 :</b>		
<b>Name</b>	CanPublicIcomSupport		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	Selects support of Pretended Network features in Can driver. True: Enabled False: Disabled		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	

	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00482 :</b>		
<b>Name</b>	CanSetBaudrateApi		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	The support of the Can_SetBaudrate API is optional. If this parameter is set to true the Can_SetBaudrate API shall be supported. Otherwise the API is not supported.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	false		
<b>Post-Build Variant Multiplicity</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00113 :</b>		
<b>Name</b>	CanTimeoutDuration		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	Specifies the maximum time for blocking function until a timeout is detected. Unit is seconds.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucFloatParamDef		
<b>Range</b>	[1E-6 .. 65.535]		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00106 :</b>		
<b>Name</b>	CanVersionInfoApi		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	Switches the Can_GetVersionInfo() API ON or OFF.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00431 :</b>		
<b>Name</b>	CanOsCounterRef		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	This parameter contains a reference to the OsCounter, which is used by		



	the CAN driver.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	Reference to [ OsCounter ]		
<b>Post-Build Variant Multiplicity</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00430 :</b>		
<b>Name</b>	CanSupportTTCANRef		
<b>Parent Container</b>	CanGeneral		
<b>Description</b>	The parameter refers to CanIfSupportTTCAN parameter in the CAN Interface Module configuration. The CanIfSupportTTCAN parameter defines whether TTCAN is supported.		
<b>Multiplicity</b>	1		
<b>Type</b>	Reference to [ CanIfPrivateCfg ]		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>Included Containers</b>		
<b>Container Name</b>	<b>Multiplicity</b>	<b>Scope / Dependency</b>
CanIcomGeneral	0..1	This container contains the general configuration parameters of the ICOM Configuration.
CanMainFunctionRWPeriods	0..*	This container contains the parameter for configuring the period for cyclic call to Can_MainFunction_Read or Can_MainFunction_Write depending on the referring item.

### 10.2.3 CanController

<b>SWS Item</b>	<b>ECUC_Can_00354 :</b>	
<b>Container Name</b>	CanController	
<b>Description</b>	This container contains the configuration parameters of the CAN controller(s).	
<b>Configuration Parameters</b>		

<b>SWS Item</b>	<b>ECUC_Can_00314 :</b>	
<b>Name</b>	CanBusoffProcessing	
<b>Parent Container</b>	CanController	
<b>Description</b>	Enables / disables API Can_MainFunction_BusOff() for handling busoff events in polling mode.	
<b>Multiplicity</b>	1	
<b>Type</b>	EcucEnumerationParamDef	
<b>Range</b>	INTERRUPT	Interrupt Mode of operation.
	POLLING	Polling Mode of operation.

<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00315 :</b>		
<b>Name</b>	CanControllerActivation		
<b>Parent Container</b>	CanController		
<b>Description</b>	Defines if a CAN controller is used in the configuration.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00382 :</b>		
<b>Name</b>	CanControllerBaseAddress		
<b>Parent Container</b>	CanController		
<b>Description</b>	Specifies the CAN controller base address.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 4294967295		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00316 :</b>		
<b>Name</b>	CanControllerId		
<b>Parent Container</b>	CanController		
<b>Description</b>	This parameter provides the controller ID which is unique in a given CAN Driver. The value for this parameter starts with 0 and continue without any gaps.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef (Symbolic Name generated for this parameter)		
<b>Range</b>	0 .. 255		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00317 :</b>		
<b>Name</b>	CanRxProcessing		
<b>Parent Container</b>	CanController		
<b>Description</b>	Enables / disables API Can_MainFunction_Read() for handling PDU reception		

	events in polling mode.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucEnumerationParamDef		
<b>Range</b>	INTERRUPT	Interrupt Mode of operation.	
	MIXED	Mixed Mode of operation	
	POLLING	Polling Mode of operation.	
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00318 :</b>		
<b>Name</b>	CanTxProcessing		
<b>Parent Container</b>	CanController		
<b>Description</b>	Enables / disables API Can_MainFunction_Write() for handling PDU transmission events in polling mode.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucEnumerationParamDef		
<b>Range</b>	INTERRUPT	Interrupt Mode of operation.	
	MIXED	Mixed Mode of operation	
	POLLING	Polling Mode of operation.	
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00466 :</b>		
<b>Name</b>	CanWakeupFunctionalityAPI		
<b>Parent Container</b>	CanController		
<b>Description</b>	Adds / removes the service Can_CheckWakeup() from the code. True: Can_CheckWakeup can be used. False: Can_CheckWakeup cannot be used.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local dependency: H/W should support the wakeup functionality to enable this parameter.		

<b>SWS Item</b>	<b>ECUC_Can_00319 :</b>		
<b>Name</b>	CanWakeupProcessing		
<b>Parent Container</b>	CanController		
<b>Description</b>	Enables / disables API Can_MainFunction_Wakeup() for handling wakeup events in polling mode.		
<b>Multiplicity</b>	1		

<b>Type</b>	EcucEnumerationParamDef		
<b>Range</b>	INTERRUPT	Interrupt Mode of operation.	
	POLLING	Polling Mode of operation.	
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00330 :</b>		
<b>Name</b>	CanWakeupSupport		
<b>Parent Container</b>	CanController		
<b>Description</b>	CAN driver support for wakeup over CAN Bus.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>			

<b>SWS Item</b>	<b>ECUC_Can_00435 :</b>		
<b>Name</b>	CanControllerDefaultBaudrate		
<b>Parent Container</b>	CanController		
<b>Description</b>	Reference to baudrate configuration container configured for the Can Controller.		
<b>Multiplicity</b>	1		
<b>Type</b>	Reference to [ CanControllerBaudrateConfig ]		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00313 :</b>		
<b>Name</b>	CanCpuClockRef		
<b>Parent Container</b>	CanController		
<b>Description</b>	Reference to the CPU clock configuration, which is set in the MCU driver configuration		
<b>Multiplicity</b>	1		
<b>Type</b>	Reference to [ McuClockReferencePoint ]		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00359 :</b>		
<b>Name</b>	CanWakeupSourceRef		
<b>Parent Container</b>	CanController		
<b>Description</b>	This parameter contains a reference to the Wakeup Source for this controller as defined in the ECU State Manager.		

	Implementation Type: reference to EcuM_WakeupSourceType		
<b>Multiplicity</b>	0..1		
<b>Type</b>	Symbolic name reference to [ EcuMWakeupSource ]		
<b>Post-Build Variant Multiplicity</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>Included Containers</b>		
<b>Container Name</b>	<b>Multiplicity</b>	<b>Scope / Dependency</b>
CanControllerBaudrateConfig	1..*	This container contains bit timing related configuration parameters of the CAN controller(s).
CanTTController	0..1	CanTTController is specified in the SWS TTCAN and contains the configuration parameters of the TTCAN controller(s) (which are needed in addition to the configuration parameters of the CAN controller(s)). This container is only included and valid if TTCAN is supported by the controller, enabled (see CanSupportTTCANRef, ECUC_Can_00430), and used.

### 10.2.4 CanControllerBaudrateConfig

<b>SWS Item</b>	<b>ECUC_Can_00387 :</b>
<b>Container Name</b>	CanControllerBaudrateConfig
<b>Description</b>	This container contains bit timing related configuration parameters of the CAN controller(s).
<b>Configuration Parameters</b>	

<b>SWS Item</b>	<b>ECUC_Can_00005 :</b>		
<b>Name</b>	CanControllerBaudRate		
<b>Parent Container</b>	CanControllerBaudrateConfig		
<b>Description</b>	Specifies the baudrate of the controller in kbps.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcuIntegerParamDef		
<b>Range</b>	0 .. 2000		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00471 :</b>
<b>Name</b>	CanControllerBaudRateConfigID
<b>Parent Container</b>	CanControllerBaudrateConfig
<b>Description</b>	Uniquely identifies a specific baud rate configuration. This ID is used by SetBaudrate API.

<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 65535		
<b>Default value</b>	0		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: ECU dependency: CanSetBaudrateApi		

<b>SWS Item</b>	<b>ECUC_Can_00073 :</b>		
<b>Name</b>	CanControllerPropSeg		
<b>Parent Container</b>	CanControllerBaudrateConfig		
<b>Description</b>	Specifies propagation delay in time quantas.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 255		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00074 :</b>		
<b>Name</b>	CanControllerSeg1		
<b>Parent Container</b>	CanControllerBaudrateConfig		
<b>Description</b>	Specifies phase segment 1 in time quantas.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 255		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00075 :</b>		
<b>Name</b>	CanControllerSeg2		
<b>Parent Container</b>	CanControllerBaudrateConfig		
<b>Description</b>	Specifies phase segment 2 in time quantas.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 255		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00383 :</b>		
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<b>Name</b>	CanControllerSyncJumpWidth		
<b>Parent Container</b>	CanControllerBaudrateConfig		
<b>Description</b>	Specifies the synchronization jump width for the controller in time quantas.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 255		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>Included Containers</b>		
<b>Container Name</b>	<b>Multiplicity</b>	<b>Scope / Dependency</b>
CanControllerFdBaudrateConfig	0..1	This optional container contains bit timing related configuration parameters of the CAN controller(s) for payload and CRC of a CAN FD frame. If this container exists the controller supports CAN FD frames.

### 10.2.5 CanControllerFdBaudrateConfig

<b>SWS Item</b>	<b>ECUC_Can_00473 :</b>		
<b>Container Name</b>	CanControllerFdBaudrateConfig		
<b>Description</b>	This optional container contains bit timing related configuration parameters of the CAN controller(s) for payload and CRC of a CAN FD frame. If this container exists the controller supports CAN FD frames.		
<b>Configuration Parameters</b>			

<b>SWS Item</b>	<b>ECUC_Can_00481 :</b>		
<b>Name</b>	CanControllerFdBaudRate		
<b>Parent Container</b>	CanControllerFdBaudrateConfig		
<b>Description</b>	Specifies the data segment baud rate of the controller in kbps.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 16000		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00476 :</b>		
<b>Name</b>	CanControllerPropSeg		
<b>Parent Container</b>	CanControllerFdBaudrateConfig		
<b>Description</b>	Specifies propagation delay in time quantas.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 255		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	true		

<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00477 :</b>		
<b>Name</b>	CanControllerSeg1		
<b>Parent Container</b>	CanControllerFdBaudrateConfig		
<b>Description</b>	Specifies phase segment 1 in time quantas.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 255		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00478 :</b>		
<b>Name</b>	CanControllerSeg2		
<b>Parent Container</b>	CanControllerFdBaudrateConfig		
<b>Description</b>	Specifies phase segment 2 in time quantas.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 255		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00479 :</b>		
<b>Name</b>	CanControllerSyncJumpWidth		
<b>Parent Container</b>	CanControllerFdBaudrateConfig		
<b>Description</b>	Specifies the synchronization jump width for the controller in time quantas.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 255		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00480 :</b>		
<b>Name</b>	CanControllerTrcvDelayCompensationOffset		
<b>Parent Container</b>	CanControllerFdBaudrateConfig		
<b>Description</b>	Specifies the Transceiver Delay Compensation Offset in ns. If not specified Transceiver Delay Compensation is disabled.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	EcucIntegerParamDef		



<b>Range</b>	0 .. 400		
<b>Default value</b>	--		
<b>Post-Build Variant Multiplicity</b>	true		
<b>Post-Build Variant Value</b>	true		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00475 :</b>		
<b>Name</b>	CanControllerTxBitRateSwitch		
<b>Parent Container</b>	CanControllerFdBaudrateConfig		
<b>Description</b>	Specifies if the bit rate switching shall be used for transmissions. If FALSE: CAN FD frames shall be sent without bit rate switching.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	true		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

**No Included Containers**

## 10.2.6 CanHardwareObject

<b>SWS Item</b>	<b>ECUC_Can_00324 :</b>		
<b>Container Name</b>	CanHardwareObject		
<b>Description</b>	This container contains the configuration (parameters) of CAN Hardware Objects.		
<b>Configuration Parameters</b>			

<b>SWS Item</b>	<b>ECUC_Can_00485 :</b>		
<b>Name</b>	CanFdPaddingValue		
<b>Parent Container</b>	CanHardwareObject		
<b>Description</b>	Specifies the value which is used to pad unspecified data in CAN FD frames > 8 bytes for transmission. This is necessary due to the discrete possible values of the DLC if > 8 bytes. If the length of a PDU which was requested to be sent does not match the allowed DLC values, the remaining bytes up to the next possible value shall be padded with this value.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 255		
<b>Default value</b>	0		
<b>Post-Build Variant Multiplicity</b>	true		

<b>Post-Build Variant Value</b>	true		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00323 :</b>		
<b>Name</b>	CanHandleType		
<b>Parent Container</b>	CanHardwareObject		
<b>Description</b>	Specifies the type (Full-CAN or Basic-CAN) of a hardware object.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucEnumerationParamDef		
<b>Range</b>	BASIC	For several L-PDUs are hadled by the hardware object	
	FULL	For only one L-PDU (identifier) is handled by the hardware object	
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: ECU dependency: This configuration element is used as information for the CAN Interface only. The relevant CAN driver configuration is done with the filter mask and identifier.		

<b>SWS Item</b>	<b>ECUC_Can_00490 :</b>		
<b>Name</b>	CanHardwareObjectUsesPolling		
<b>Parent Container</b>	CanHardwareObject		
<b>Description</b>	Enables polling of this hardware object.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	false		
<b>Scope / Dependency</b>	dependency: This parameter shall exist if CanRxProcessing/CanTxProcessing is set to Mixed.		

<b>SWS Item</b>	<b>ECUC_Can_00467 :</b>		
<b>Name</b>	CanHwObjectCount		
<b>Parent Container</b>	CanHardwareObject		
<b>Description</b>	Number of hardware objects used to implement one HOH. In case of a HRH this parameter defines the number of elements in the hardware FIFO or the number of shadow buffers, in case of a HTH it defines the number of hardware objects used for multiplexed transmission or for a hardware FIFO used by a FullCAN HTH.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	1 .. 65535		
<b>Default value</b>	1		
<b>Post-Build Variant Multiplicity</b>	true		
<b>Post-Build Variant Value</b>	true		
<b>Multiplicity Configuration</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE

<b>Class</b>	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00065 :</b>		
<b>Name</b>	CanIdType		
<b>Parent Container</b>	CanHardwareObject		
<b>Description</b>	<p>Specifies whether the IdValue is of type</p> <ul style="list-style-type: none"> <li>▪ standard identifier</li> </ul> <p>- extended identifier - mixed mode</p> <p>ImplementationType: Can_IdType</p>		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucEnumerationParamDef		
<b>Range</b>	EXTENDED	All the CANIDs are of type extended only (29 bit).	
	MIXED	The type of CANIDs can be both Standard or Extended.	
	STANDARD	All the CANIDs are of type standard only (11bit).	
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00326 :</b>		
<b>Name</b>	CanObjectId		
<b>Parent Container</b>	CanHardwareObject		
<b>Description</b>	<p>Holds the handle ID of HRH or HTH. The value of this parameter is unique in a given CAN Driver, and it should start with 0 and continue without any gaps.</p> <p>The HRH and HTH Ids share a common ID range.</p> <p>Example: HRH0-0, HRH1-1, HTH0-2, HTH1-3</p>		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef (Symbolic Name generated for this parameter)		
<b>Range</b>	0 .. 65535		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00327 :</b>		
<b>Name</b>	CanObjectType		
<b>Parent Container</b>	CanHardwareObject		

<b>Description</b>	Specifies if the HardwareObject is used as Transmit or as Receive object		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucEnumerationParamDef		
<b>Range</b>	RECEIVE	Receive HOH	
	TRANSMIT	Transmit HOH	
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00486 :</b>		
<b>Name</b>	CanTriggerTransmitEnable		
<b>Parent Container</b>	CanHardwareObject		
<b>Description</b>	This parameter defines if or if not Can supports the trigger-transmit API for this handle.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00322 :</b>		
<b>Name</b>	CanControllerRef		
<b>Parent Container</b>	CanHardwareObject		
<b>Description</b>	Reference to CAN Controller to which the HOH is associated to.		
<b>Multiplicity</b>	1		
<b>Type</b>	Reference to [ CanController ]		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00438 :</b>		
<b>Name</b>	CanMainFunctionRWPeriodRef		
<b>Parent Container</b>	CanHardwareObject		
<b>Description</b>	Reference to CanMainFunctionPeriod		
<b>Multiplicity</b>	0..1		
<b>Type</b>	Reference to [ CanMainFunctionRWPeriods ]		
<b>Post-Build Variant Multiplicity</b>	true		
<b>Post-Build Variant Value</b>	true		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	scope: local		

<b>Included Containers</b>		
<b>Container Name</b>	<b>Multiplicity</b>	<b>Scope / Dependency</b>
CanHwFilter	0..*	This container is only valid for HRHs and contains the configuration (parameters) of one hardware filter.
CanTTHardwareObjectTrigger	0..*	CanTTHardwareObjectTrigger is specified in the SWS TTCAN and contains the configuration (parameters) of TTCAN triggers for Hardware Objects, which are additional to the configuration (parameters) of CAN Hardware Objects. This container is only included and valid if TTCAN is supported by the controller and, enabled (see CanSupportTTCANRef, ECUC_Can_00430), and used.

### 10.2.7 CanHwFilter

<b>SWS Item</b>	<b>ECUC_Can_00468 :</b>		
<b>Container Name</b>	CanHwFilter		
<b>Description</b>	This container is only valid for HRHs and contains the configuration (parameters) of one hardware filter.		
<b>Configuration Parameters</b>			

<b>SWS Item</b>	<b>ECUC_Can_00469 :</b>		
<b>Name</b>	CanHwFilterCode		
<b>Parent Container</b>	CanHwFilter		
<b>Description</b>	Specifies (together with the filter mask) the identifiers range that passes the hardware filter.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 4294967295		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	
	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>			

<b>SWS Item</b>	<b>ECUC_Can_00470 :</b>		
<b>Name</b>	CanHwFilterMask		
<b>Parent Container</b>	CanHwFilter		
<b>Description</b>	Describes a mask for hardware-based filtering of CAN identifiers. The CAN identifiers of incoming messages are masked with the appropriate CanFilterMaskValue. Bits holding a 0 mean don't care, i.e. do not compare the message's identifier in the respective bit position. The mask shall be build by filling with leading 0. In case of CanIdType EXTENDED or MIXED a 29 bit mask shall be build. In case of CanIdType STANDARD a 11 bit mask shall be build		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 4294967295		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	true		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	VARIANT-PRE-COMPILE
	<b>Link time</b>	--	

	<b>Post-build time</b>	X	VARIANT-POST-BUILD
<b>Scope / Dependency</b>	dependency: The filter mask settings must be known by the CanIf configuration for optimization of the SW filters.		

**No Included Containers**

### 10.2.8 CanConfigSet

<b>SWS Item</b>	<b>ECUC_Can_00343 :</b>
<b>Container Name</b>	CanConfigSet
<b>Description</b>	This container contains the configuration parameters and sub containers of the AUTOSAR Can module.
<b>Configuration Parameters</b>	

<b>Included Containers</b>		
<b>Container Name</b>	<b>Multiplicity</b>	<b>Scope / Dependency</b>
CanController	1..*	This container contains the configuration parameters of the CAN controller(s).
CanHardwareObject	1..*	This container contains the configuration (parameters) of CAN Hardware Objects.
Canlcom	0..1	This container contains the parameters for configuring pretended networking

### 10.2.9 CanMainFunctionRWPeriods

<b>SWS Item</b>	<b>ECUC_Can_00437 :</b>
<b>Container Name</b>	CanMainFunctionRWPeriods
<b>Description</b>	This container contains the parameter for configuring the period for cyclic call to Can_MainFunction_Read or Can_MainFunction_Write depending on the referring item.
<b>Configuration Parameters</b>	

<b>SWS Item</b>	<b>ECUC_Can_00484 :</b>		
<b>Name</b>	CanMainFunctionPeriod		
<b>Parent Container</b>	CanMainFunctionRWPeriods		
<b>Description</b>	This parameter describes the period for cyclic call to Can_MainFunction_Read or Can_MainFunction_Write depending on the referring item. Unit is seconds. Different poll-cycles will be configurable if more than one CanMainFunctionPeriod is configured. In this case multiple Can_MainFunction_Read() or Can_MainFunction_Write() will be provided by the CAN Driver module.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucFloatParamDef		
<b>Range</b>	]0 .. INF[		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>No Included Containers</b>
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### 10.2.10 Canlcom

<b>SWS Item</b>	<b>ECUC_Can_00440 :</b>
<b>Container Name</b>	Canlcom
<b>Description</b>	This container contains the parameters for configuring pretended networking
<b>Configuration Parameters</b>	

<b>Included Containers</b>		
<b>Container Name</b>	<b>Multiplicity</b>	<b>Scope / Dependency</b>
CanlcomConfig	1..*	This container contains the configuration parameters of the ICOM Configuration.

### 10.2.11 CanlcomConfig

<b>SWS Item</b>	<b>ECUC_Can_00459 :</b>
<b>Container Name</b>	CanlcomConfig
<b>Description</b>	This container contains the configuration parameters of the ICOM Configuration.
<b>Configuration Parameters</b>	

<b>SWS Item</b>	<b>ECUC_Can_00441 :</b>		
<b>Name</b>	CanlcomConfigId		
<b>Parent Container</b>	CanlcomConfig		
<b>Description</b>	This parameter identifies the ID of the ICOM configuration.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	1 .. 255		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00442 :</b>		
<b>Name</b>	CanlcomWakeOnBusOff		
<b>Parent Container</b>	CanlcomConfig		
<b>Description</b>	This parameter defines that the MCU shall wake if the bus off is detected or not.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	true		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	

<b>Scope / Dependency</b>	scope: ECU
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<b>Included Containers</b>		
<b>Container Name</b>	<b>Multiplicity</b>	<b>Scope / Dependency</b>
CanIcomWakeupCauses	1	This container contains the configuration parameters of the wakeup causes to leave the power saving mode.

### 10.2.12 CanIcomGeneral

<b>SWS Item</b>	<b>ECUC_Can_00444 :</b>
<b>Container Name</b>	CanIcomGeneral
<b>Description</b>	This container contains the general configuration parameters of the ICOM Configuration.
<b>Configuration Parameters</b>	

<b>SWS Item</b>	<b>ECUC_Can_00445 :</b>		
<b>Name</b>	CanIcomLevel		
<b>Parent Container</b>	CanIcomGeneral		
<b>Description</b>	Defines the level of Pretended Networking. This parameter is reserved for future implementations (Pretended Networking level 2).		
<b>Multiplicity</b>	0..1		
<b>Type</b>	EcucEnumerationParamDef		
<b>Range</b>	CAN_ICOM_LEVEL_ONE	--	
	CAN_ICOM_LEVEL_TWO	--	
<b>Default value</b>	CAN_ICOM_LEVEL_ONE		
<b>Post-Build Variant Multiplicity</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00446 :</b>		
<b>Name</b>	CanIcomVariant		
<b>Parent Container</b>	CanIcomGeneral		
<b>Description</b>	Defines the variant, which is supported by this CanController		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucEnumerationParamDef		
<b>Range</b>	CAN_ICOM_VARIANT_HW	--	
	CAN_ICOM_VARIANT_NONE	--	
	CAN_ICOM_VARIANT_SW	--	
<b>Default value</b>	CAN_ICOM_VARIANT_NONE		
<b>Post-Build Variant Value</b>	false		
<b>Value</b>	<b>Pre-compile time</b>	X	All Variants



<b>Configuration Class</b>	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

**No Included Containers**

### 10.2.13 CanlcomRxMessage

<b>SWS Item</b>	<b>ECUC_Can_00447 :</b>		
<b>Container Name</b>	CanlcomRxMessage		
<b>Description</b>	<p>This container contains the configuration parameters for the wakeup causes for matching received messages. It has to be configured as often as received messages are defined as wakeup cause.</p> <p>constraint: For all CanlcomRxMessage instances the Message IDs which are defined in CanlcomMessageld and in CanlcomRxMessageldMask shall not overlap.</p>		
<b>Configuration Parameters</b>			

<b>SWS Item</b>	<b>ECUC_Can_00448 :</b>		
<b>Name</b>	CanlcomCounterValue		
<b>Parent Container</b>	CanlcomRxMessage		
<b>Description</b>	This parameter defines that the MCU shall wake if the message with the ID is received n times on the communication channel.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	EcuIntegerParamDef		
<b>Range</b>	1 .. 65536		
<b>Default value</b>	--		
<b>Post-Build Variant Multiplicity</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00449 :</b>		
<b>Name</b>	CanlcomMessageld		
<b>Parent Container</b>	CanlcomRxMessage		
<b>Description</b>	This parameter defines the message ID the wakeup causes of this CanlcomRxMessage are configured for. In addition a mask (CanlcomMessageldMask) can be defined, in that case it is possible to define a range of rx messages, which can create a wakeup condition.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcuIntegerParamDef		
<b>Range</b>	0 .. 536870912		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		

<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00465 :</b>		
<b>Name</b>	CanlcomMessageldMask		
<b>Parent Container</b>	CanlcomRxMessage		
<b>Description</b>	Describes a mask for filtering of CAN identifiers. The CAN identifiers of incoming messages are masked with this CanlcomMessageldMask. If the masked identifier matches the masked value of CanlcomMessageld, it can create a wakeup condition for this CanlcomRxMessage. Bits holding a 0 mean don't care, i.e. do not compare the message's identifier in the respective bit position. The mask shall be build by filling with leading 0.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 536870912		
<b>Default value</b>	--		
<b>Post-Build Variant Multiplicity</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU dependency: CanlcomMessageldMask and CanlcomRxMessageSignalConfig shall not be defined together.		

<b>SWS Item</b>	<b>ECUC_Can_00450 :</b>		
<b>Name</b>	CanlcomMissingMessageTimerValue		
<b>Parent Container</b>	CanlcomRxMessage		
<b>Description</b>	This parameter defines that the MCU shall wake if the message with the ID is not received for a specific time in s on the communication channel.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	EcucFloatParamDef		
<b>Range</b>	[-INF .. INF]		
<b>Default value</b>	--		
<b>Post-Build Variant Multiplicity</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00451 :</b>		
<b>Name</b>	CanlcomPayloadLengthError		
<b>Parent Container</b>	CanlcomRxMessage		

<b>Description</b>	This parameter defines that the MCU shall wake if a payload error occurs		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucBooleanParamDef		
<b>Default value</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>Included Containers</b>		
<b>Container Name</b>	<b>Multiplicity</b>	<b>Scope / Dependency</b>
CanlcomRxMessageSignalConfig	0..*	This container contains the configuration parameters for the wakeup causes for matching signals. It has to be configured as often as a signal is defined as wakeup cause. If at least one Signal conditions defined in a CanlcomRxMessageSignalConfig evaluates to true or if no CanlcomRxMessageSignalConfig are defined, the whole wakeup condition is considered to be true. All instances of this container refer to the same frame/pdu (see CanlcomMessageId).

### 10.2.14 CanlcomRxMessageSignalConfig

<b>SWS Item</b>	<b>ECUC_Can_00452 :</b>
<b>Container Name</b>	CanlcomRxMessageSignalConfig
<b>Description</b>	This container contains the configuration parameters for the wakeup causes for matching signals. It has to be configured as often as a signal is defined as wakeup cause. If at least one Signal conditions defined in a CanlcomRxMessageSignalConfig evaluates to true or if no CanlcomRxMessageSignalConfig are defined, the whole wakeup condition is considered to be true. All instances of this container refer to the same frame/pdu (see CanlcomMessageId).
<b>Configuration Parameters</b>	

<b>SWS Item</b>	<b>ECUC_Can_00487 :</b>		
<b>Name</b>	CanlcomSignalMask		
<b>Parent Container</b>	CanlcomRxMessageSignalConfig		
<b>Description</b>	This parameter shall be used to mask a signal in the payload of a CAN message. The mask is binary AND with the signal payload. The result will be used in combination of the operations defined in CanlcomSignalOperation with the CanlcomSignalValue.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 18446744073709551615		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	

	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00462 :</b>		
<b>Name</b>	CanlcomSignalOperation		
<b>Parent Container</b>	CanlcomRxMessageSignalConfig		
<b>Description</b>	This parameter defines the operation, which shall be used to verify the signal value creates a wakeup condition.		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucEnumerationParamDef		
<b>Range</b>	AND	The received signal value masked by CanlcomSignalMask has at least one bit set in common with CanlcomSignalValue (binary AND).	
	EQUAL	The received signal value masked by CanlcomSignalMask is equal to CanlcomSignalValue.	
	GREATER	The received signal value masked by CanlcomSignalMask is strictly greater than CanlcomSignalValue. Values are interpreted as unsigned integers.	
	SMALLER	The received signal value masked by CanlcomSignalMask is strictly smaller than CanlcomSignalValue. Values are interpreted as unsigned integers.	
	XOR	The received signal value masked by CanlcomSignalMask then XORed to CanlcomSignalValue is not null.	
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU		

<b>SWS Item</b>	<b>ECUC_Can_00488 :</b>		
<b>Name</b>	CanlcomSignalValue		
<b>Parent Container</b>	CanlcomRxMessageSignalConfig		
<b>Description</b>	This parameter shall be used to define a signal value which shall be compared (CanlcomSignalOperation) with the masked CanlcomSignalMask value of the received signal (CanlcomSignalRef).		
<b>Multiplicity</b>	1		
<b>Type</b>	EcucIntegerParamDef		
<b>Range</b>	0 .. 18446744073709551615		
<b>Default value</b>	--		
<b>Post-Build Variant Value</b>	false		
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: local		

<b>SWS Item</b>	<b>ECUC_Can_00456 :</b>		
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<b>Name</b>	CanlcomSignalRef		
<b>Parent Container</b>	CanlcomRxMessageSignalConfig		
<b>Description</b>	This parameter defines a reference to the signal which shall be checked additional to the message id (CanlcomMessageld). This reference is used for documentation to define which ComSignal originates this filter setting. All signals being referred by this reference shall point to the same PDU.		
<b>Multiplicity</b>	0..1		
<b>Type</b>	Reference to [ ComSignal ]		
<b>Post-Build Variant Multiplicity</b>	false		
<b>Post-Build Variant Value</b>	false		
<b>Multiplicity Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Value Configuration Class</b>	<b>Pre-compile time</b>	X	All Variants
	<b>Link time</b>	--	
	<b>Post-build time</b>	--	
<b>Scope / Dependency</b>	scope: ECU dependency: The signal referenced by CanlcomSignalRef shall be included in a ComIPdu which matches with the current CAN Controller and the CAN Identifier (CanlcomMessageld) configured for this CanlcomRxMessage.		

**No Included Containers**

### 10.2.15 CanlcomWakeupCauses

<b>SWS Item</b>	ECUC_Can_00443 :
<b>Container Name</b>	CanlcomWakeupCauses
<b>Description</b>	This container contains the configuration parameters of the wakeup causes to leave the power saving mode.
<b>Configuration Parameters</b>	

<b>Included Containers</b>		
<b>Container Name</b>	<b>Multiplicity</b>	<b>Scope / Dependency</b>
CanlcomRxMessage	1..*	This container contains the configuration parameters for the wakeup causes for matching received messages. It has to be configured as often as received messages are defined as wakeup cause. constraint: For all CanlcomRxMessage instances the Message IDs which are defined in CanlcomMessageld and in CanlcomRxMessageldMask shall not overlap.

## 11 Not applicable requirements

[SWS\_Can\_00999] [ These requirements are not applicable to this specification. ]  
(SRS\_BSW\_00170, SRS\_BSW\_00383, SRS\_BSW\_00395, SRS\_BSW\_00397,  
SRS\_BSW\_00398, SRS\_BSW\_00399, SRS\_BSW\_00400, SRS\_BSW\_00168,  
SRS\_BSW\_00423, SRS\_BSW\_00424, SRS\_BSW\_00425, SRS\_BSW\_00426,  
SRS\_BSW\_00427, SRS\_BSW\_00429, SRS\_BSW\_00433, SRS\_BSW\_00336,  
SRS\_BSW\_00422, SRS\_BSW\_00417, SRS\_BSW\_00409, SRS\_BSW\_00162,  
SRS\_BSW\_00415, SRS\_BSW\_00325, SRS\_BSW\_00342, SRS\_BSW\_00453,  
SRS\_BSW\_00413, SRS\_BSW\_00307, SRS\_BSW\_00447, SRS\_BSW\_00353,  
SRS\_BSW\_00361, SRS\_BSW\_00439, SRS\_BSW\_00449, SRS\_BSW\_00378,  
SRS\_BSW\_00359, SRS\_BSW\_00440, SRS\_SPAL\_12163, SRS\_SPAL\_12462,  
SRS\_SPAL\_12068, SRS\_SPAL\_12064, SRS\_Can\_01125, SRS\_Can\_01126)