

Dr.-Ing. Jens Becker (jens.becker@kit.edu) **Dipl.-Inform. Tanja Harbaum** (harbaum@kit.edu)

Institut für Technik der Informationsverarbeitung (ITIV)

Communication Systems and Protocols

Exercise 6

Controller Area Network (CAN)



- 1981 developed by Bosch and Intel
- Goal: Cross-linkage of complex controllers and control units
- International dissemination in the automobile area, the sector of home appliance, in textile machines, in medical engineering devices, ...
- Can also be applied as sensor/actuator bus if realtime constraints are kept
- Low priced bus transceivers through high volume number

Bus Arbitration

- Participants are connected to the bus via open collector drivers
 - Dominant LOW, logical ,0‘
 - Recessive HIGH, logical ,1‘
→ „Wired-AND“

- Arbitration scheme: CSMA/CA

- Arbitration is done with the help of the identifiers of a message
 - Identifier with the lowest value has got highest priority (dominant ,0‘)
 - Every identifier can exist only once within the whole system

Task 1: CAN bus

Time remaining



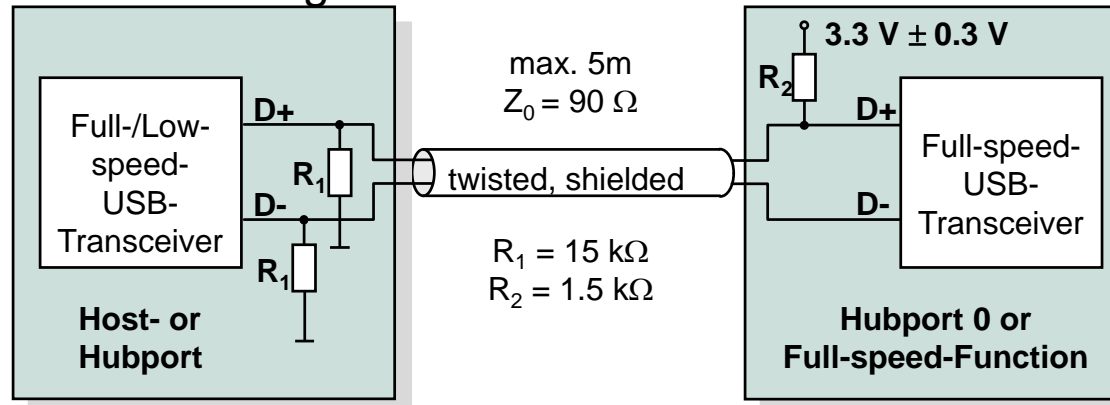
Universal Serial Bus (USB)



- Serial Bus
- NRZ-I Encoding
- Single Master / Multi Slave
- Hot-Plug Capability

Transmission speed detection

- Devices announce their transmission speed using different pull-up resistors at the data wires
- Example for resistor configuration at 12Mbit/s



- At 1.5Mbit/s
 - Low-Speed Transceiver
 - R_2 at D-
 - Cable does not need to be twisted/shielded
 - Z_0 arbitrary
 - Max. 3m wire length
- High-speed devices announce themselves as Full-speed devices (12Mbit/s) first
 - At configuration time, the host is informed about the higher transmission rate possible
 - In normal operation, the resistor is disabled in order to provide symmetrical wire behavior

Energy consumption

- Devices can be supplied with energy (5V) over the bus

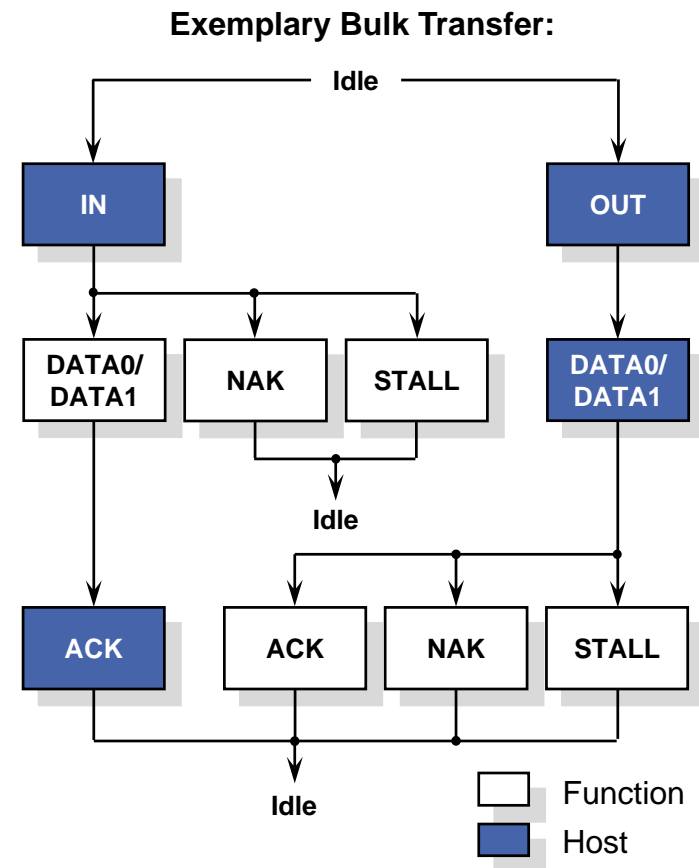
- 3 different classes have to be distinguished
 - Low-power devices: max 100mA
 - High-power devices: max 500mA
 - Self-powered devices: max 100mA from the bus, the rest has to be fetched from their own power supply during operation → otherwise they can be disabled by the host

- Devices have to announce their power consumption at configuration time and are not allowed to go beyond this limit

- Devices have to support standby mode
 - Maximum power consumption of 500 μ A
 - Devices have to go into standby after 3ms of inactivity on the bus or by dedicated command of the host

Transfer process

- The host starts a transfer by sending a corresponding token packet
- Then one ore more data packets are transmitted
- Each packet is acknowledged by a handshake packet
- If errors have occurred during a transmission, no handshake packet is send. The sender has to retransmit the packet
 - For isochronous transfers there is no handshake. Defective data is not transmitted again!



Task 2: Universal Serial Bus (USB)

Time remaining

10

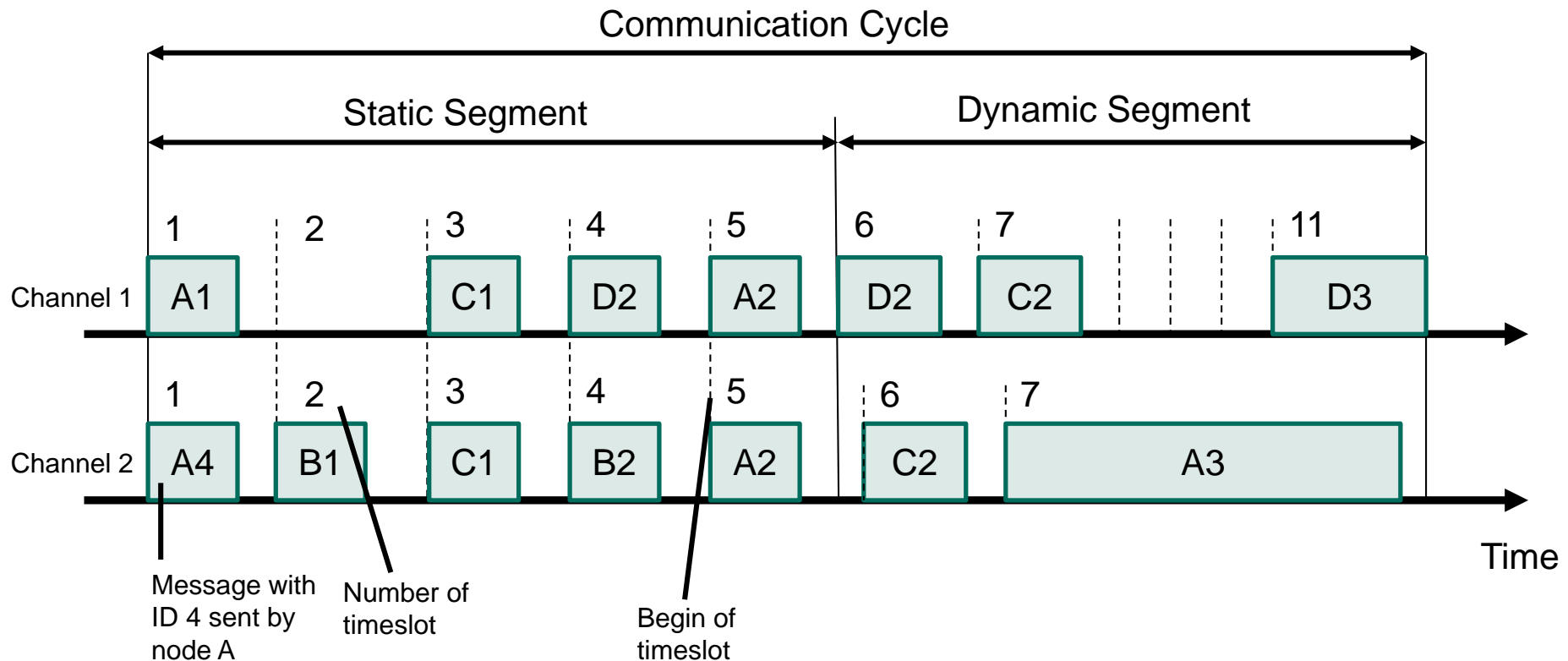
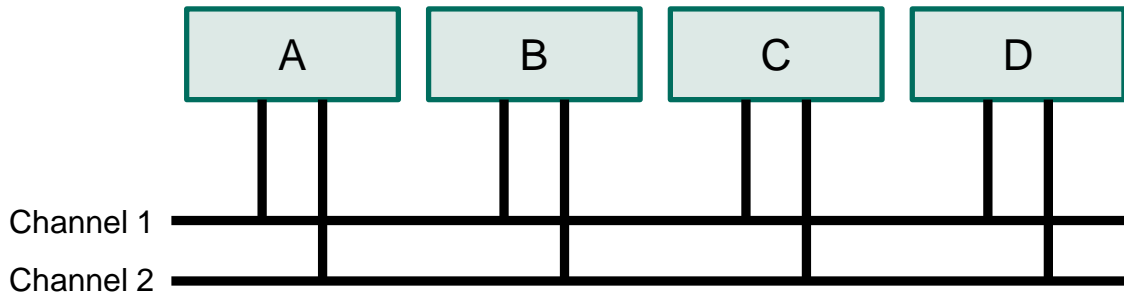


- Consortium founded in 1999
- Motivation: increasing requirements concerning bandwidth and transmission safety within automobiles
- Goal: Development of deterministic, fault tolerant communication system with 10 MBit/s bandwidth
- Basis for X-by-Wire systems
- Actual specification (Version 2.0) specifies protocol, physical layer and the „Bus Guardian“
- Basically the protocol can be used for optical as well as electrical media.

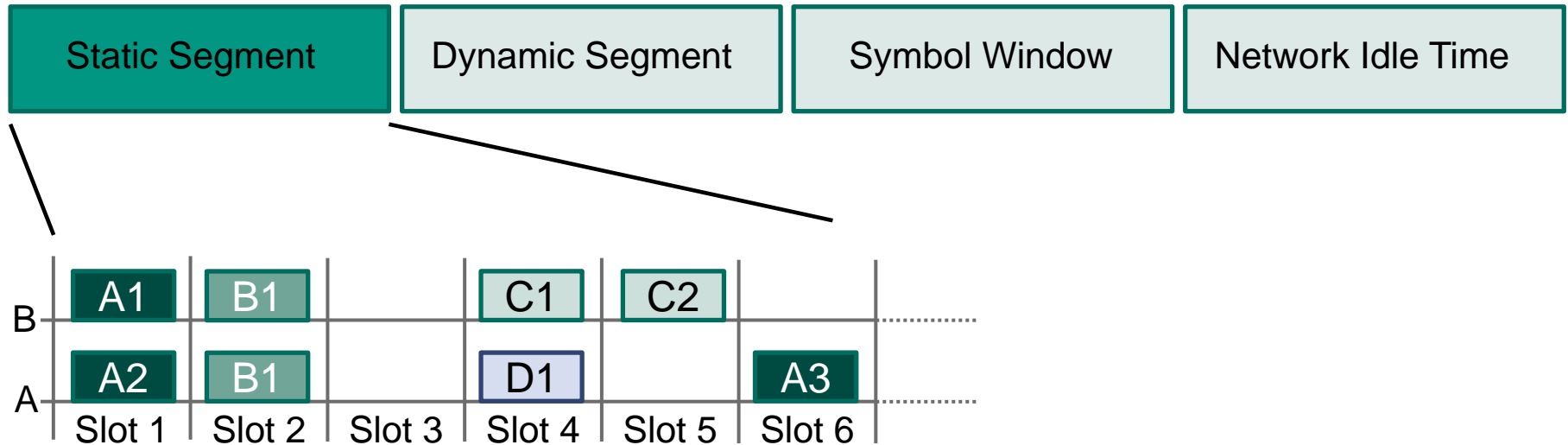
Basic features

- Multi-master system
- Beside basic star like structure also line and bus structures possible
- Allows operation in channel mode with (10 MBit/s) or double channel mode (20 MBit/s)
 - Single channel mode to increase reliability. The second channel is used as a redundancy.
 - Double channel mode to raise throughput but less reliability
- Mechanisms to increase fault tolerance
 - Deactivation of sub-networks in the case of an error
- Deterministic message transmission by using communication cycles
 - Communication cycle is flexibly configurable
 - Global time base for synchronization
- Physical layer: Differential signalization on a twisted pair
- In contrast to CAN „logic 1“ and „logic 0“ are equitable

FlexRay Bus Access

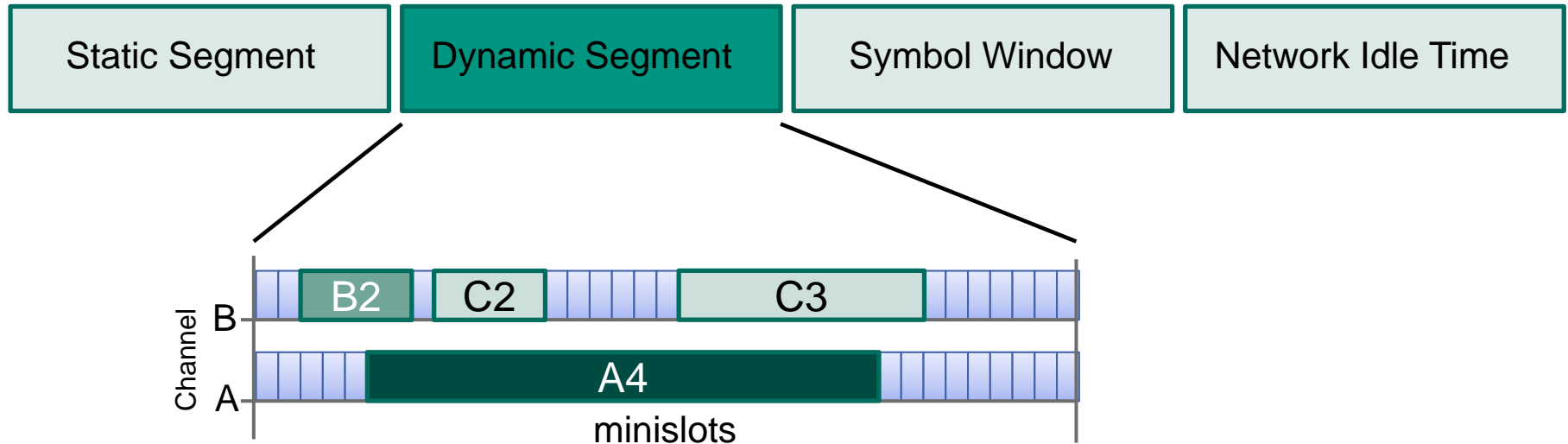


Static Segment (1)



- Nodes are assigned to fix time windows in which frame transmission can be performed
- Bus access within the static segment via TDMA
 - Realization of realtime capability within this segment (deterministic)
 - Every message within this segment is transmitted at defined points in time

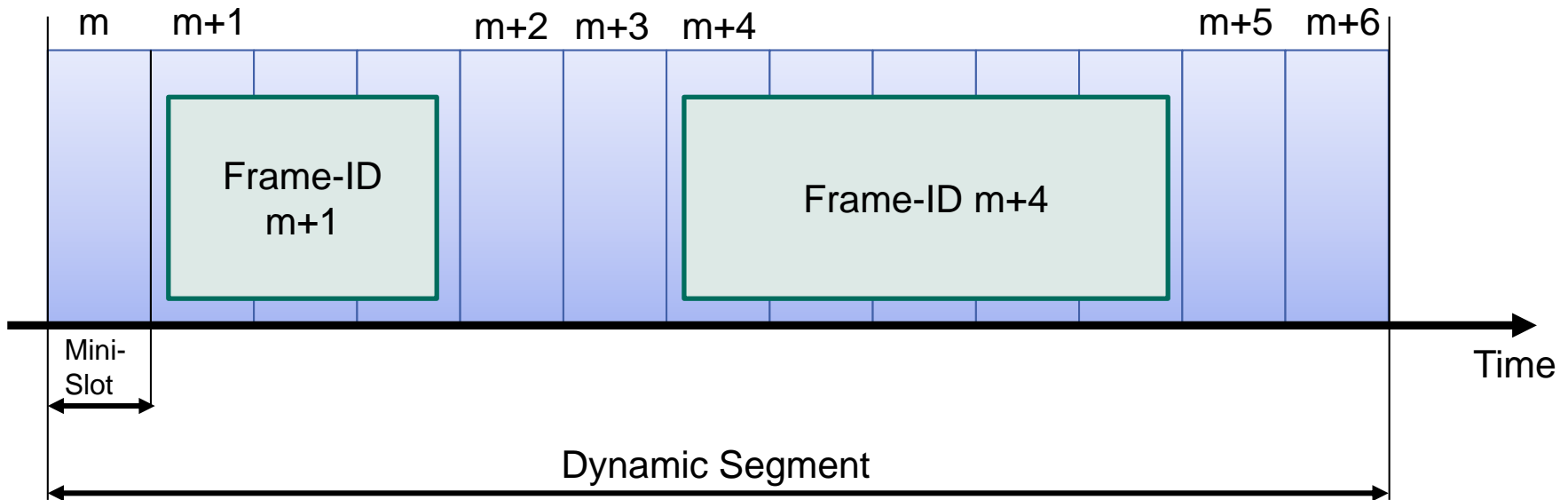
Dynamic Segment



- For frames with lower requirements concerning predictable latency
- Bus access via FTDMA (also called Mini-Slotting)
- Used for event based transmission: Event based data to be transmitted does not depend on a static slot

Mini-Slotting (FTDMA)

- Prioritized bus access within the dynamic segment controlled with a **slot count**
 - If a Minislot is not used the slot counter is incremented and the Minislot elapses unused
 - If the actual slot count corresponds to the Slot-ID of the frame, the frame occupies a certain number of Minislots. After the next free Minislot the slot counter is immediately incremented
- Space within the dynamic segment can be used efficiently that way



Task 3: FlexRay

Time remaining

