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## 1 Scope of document

This document specifies the additional TTCAN requirements for the CAN BSW stack.

## 2 How to read this document

Each requirement has its unique identifier starting with the prefix “BSW” (for “Basic Software”). For any review annotations, remarks or questions, please refer to this unique ID rather than chapter or page numbers!

### 2.1 Conventions used

- The representation of requirements in AUTOSAR documents follows the table specified in [6].
- In requirements, the following specific semantics are used (taken from Request for Comment RFC 2119 from the Internet Engineering Task Force IETF)

The key words "MUST", "MUST NOT", "REQUIRED", "SHALL", "SHALL NOT", "SHOULD", "SHOULD NOT", "RECOMMENDED", "MAY", and "OPTIONAL" in this document are to be interpreted as described in RFC 2119. Note that the requirement level of the document in which they are used modifies the force of these words.

- **MUST:** This word, or the terms "REQUIRED" or "SHALL", mean that the definition is an absolute requirement of the specification.
- **MUST NOT:** This phrase, or the phrase „SHALL NOT“, means that the definition is an absolute prohibition of the specification.
- **SHOULD:** This word, or the adjective "RECOMMENDED", mean that there may exist valid reasons in particular circumstances to ignore a particular item, but the full implications must be understood and carefully weighed before choosing a different course.
- **SHOULD NOT:** This phrase, or the phrase "NOT RECOMMENDED" mean that there may exist valid reasons in particular circumstances when the particular behavior is acceptable or even useful, but the full implications should be understood and the case carefully weighed before implementing any behavior described with this label.
- **MAY:** This word, or the adjective „OPTIONAL“, means that an item is truly optional. One vendor may choose to include the item because a particular marketplace requires it or because the vendor feels that it enhances the product while another vendor may omit the same item. An implementation, which does not include a particular option, **MUST** be prepared to interoperate with another implementation, which does include the option, though perhaps with reduced functionality. In the same vein an implementation, which does include a particular option, **MUST** be prepared to interoperate with another implementation, which does not include the option (except, of course, for the feature the option provides.)

### 3 Acronyms and abbreviations

<b><i>Acronym:</i></b>	<b><i>Description:</i></b>
CAN	Controller Area Network
TTCAN	Time Triggered CAN

## 4 Requirements Specification

### 4.1 Functional requirements

This chapter describes functional requirements that shall be fulfilled to support TTCAN. Only requirements are listed that are additional with respect to the CAN requirements [3].

#### 4.1.1 TTCAN support

##### 4.1.1.1 [SRS\_TtCan\_41001] The CAN stack shall support TTCAN according to ISO11898.

<b>Type:</b>	Valid
<b>Description:</b>	The CAN stack shall additionally support part 4 of ISO11898 Time-triggered communication [7]. TTCAN level 1 and level 2 shall be supported.
<b>Rationale:</b>	--
<b>Use Case:</b>	Time triggered communication, Event synchronized time triggered communication
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	ISO11898-4:2004 [7], RS Features: RS_BRF_00312 [5]

](RS\_BRF\_01744)

#### 4.1.2 CAN Driver with TTCAN functionality

##### 4.1.2.1 Configuration

##### 4.1.2.1.1 [SRS\_TtCan\_41003] The Hardware Object Handles shall be mappable to all types of time windows defined in ISO 11898 by configuration.

<b>Type:</b>	Valid
<b>Description:</b>	The hardware objects (SRS_Can_01039 CAN SRS) shall be mappable to the specific time windows defined in ISO 11898-4:2004. The configuration parameters shall be allowed to be of types Pre-Compile-Time, Link-Time or Post-Build-Time.
<b>Rationale:</b>	A Hardware object shall be configurable to transmit or receive messages in a specific time window.
<b>Use Case:</b>	See Rationale.
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]

]( RS\_BRF\_01560)

##### 4.1.2.1.2 [SRS\_TtCan\_41014] Configuration interfaces defined in ISO 11898-4:2004 shall be configurable.

<b>Type:</b>	Valid
<b>Description:</b>	The “configuration interfaces” of chapter 10 of ISO 11898-4:2004 shall be

	configurable. The configuration parameters shall be allowed to be of types Pre-Compile-Time.
<b>Rationale:</b>	Parameters like e.g. “operation mode” , “master/slave”, “trigger” etc. need to be configured.
<b>Use Case:</b>	See Rationale.
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]

](RS\_BRF\_01744)

#### 4.1.2.1.3 [SRS\_TtCan\_41004] The “Appl\_Watchdog\_Limit” (see chapter 10.1.2.7 of ISO 11898-4:2004) shall be configurable.

<b>Type:</b>	Valid
<b>Description:</b>	Activation of “Application_Watchdog” needs to be configured. The configuration parameter shall be allowed to be of type Pre-Compile-Time, Link-Time or Post-Build-Time.
<b>Rationale:</b>	See description
<b>Use Case:</b>	--
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]

](RS\_BRF\_01464)

### 4.1.2.2 Normal Operation

#### 4.1.2.2.1 [SRS\_TtCan\_41005] The CAN Driver with TTCAN functionality shall provide means for influencing timing parameters and providing information from the TTCAN controller for synchronization purposes.

<b>Type:</b>	Valid
<b>Description:</b>	Timing parameters, synchronization state and master state (see ISO 11898-4:2004 for details) shall be provided by the CAN Driver with TTCAN functionality. If a TTCAN controller is timing master, it shall be possible to adjust the timing parameters during runtime (see ISO 11898-4:2004 for details).
<b>Rationale:</b>	Synchronizing application with communication if required
<b>Use Case:</b>	See Rationale.
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]

](RS\_BRF\_01432)

#### 4.1.2.2.2 [SRS\_TtCan\_41006] The CAN Driver with TTCAN functionality shall support the event synchronized time-triggered communication.

<b>Type:</b>	Valid
<b>Description:</b>	Event-Synchronized communication (see chapter 5.2.3 of ISO 11898-4:2004) shall be supported.
<b>Rationale:</b>	Synchronizing communication with external events.
<b>Use Case:</b>	See Rationale.
<b>Dependencies:</b>	--



<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]
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](RS\_BRF\_01432)

**4.1.2.2.3 [SRS\_TtCan\_41007] The CAN Driver with TTCAN functionality shall indicate occurred events according to chapter 10.2.2 “Interrupt\_Status\_Vector” of ISO 11898-4:2004.**

<b>Type:</b>	Valid
<b>Description:</b>	The events which will be supported by ISO 11898-4 shall be available to application if needed.
<b>Rationale:</b>	See description
<b>Use Case:</b>	Application can react on occurred events.
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]

](RS\_BRF\_01328)

#### 4.1.2.3 Fault Operation

**4.1.2.3.1 [SRS\_TtCan\_41008] The CAN Driver with enabled TTCAN functionality shall provide a notification for severe error (S3).**

<b>Type:</b>	Valid
<b>Description:</b>	The CAN Driver with TTCAN functionality shall notify the CAN Interface with TTCAN functionality if the TTCAN Controller enters error level S3 (Severe Error, see ISO 11898-4:2004 [7]). The notification is done by call of static (non-configurable) callback function implemented inside the CAN Interface with TTCAN functionality.
<b>Rationale:</b>	see ISO 11898-4:2004 [7]
<b>Use Case:</b>	Any state transition is notified to the CAN Interface with TTCAN functionality which forwards this notification to the responsible upper layer.
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]

](RS\_BRF\_02168)

**4.1.2.3.2 [SRS\_TtCan\_41009] The CAN Driver with TTCAN functionality shall not recover from severe error (S3) automatically.**

<b>Type:</b>	Valid
<b>Description:</b>	The severe error (S3, see ISO 11898-4:2004 [7]) recovery shall be software driven.
<b>Rationale:</b>	see ISO 11898-4:2004 chapter 9 Failure handling [7]
<b>Use Case:</b>	See Rationale
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]

](RS\_BRF\_02168)

### 4.1.3 CAN Interface with TTCAN functionality

#### 4.1.3.1 [SRS\_TtCan\_41010] A Job List shall be configurable.

<b>Type:</b>	Valid
<b>Description:</b>	It shall be configurable Pre-Compile-Time and per controller, whether a Job List shall be available.
<b>Rationale:</b>	Handling of BasicCAN hardware objects
<b>Use Case:</b>	--
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]

](RS\_BRF\_01592)

#### 4.1.3.2 [SRS\_TtCan\_41011] If a Job List is available (see SRS\_TtCan\_41010) it shall be executed by a separate Job List Execution Function.

<b>Type:</b>	Valid
<b>Description:</b>	The Job List Execution Function shall be called in task or interrupt context.
<b>Rationale:</b>	Handling of BasicCAN hardware objects
<b>Use Case:</b>	--
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]

](RS\_BRF\_01592)

#### 4.1.3.3 [SRS\_TtCan\_41012] “Time Marks” (see ISO 11898-4:2004 [7]) shall be configurable Pre-Compile-Time.

<b>Type:</b>	Valid
<b>Description:</b>	The “Time Marks” of ISO 11898-4:2004 shall be configurable.
<b>Rationale:</b>	--
<b>Use Case:</b>	--
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]

](RS\_BRF\_01744)

#### 4.1.3.4 [SRS\_TtCan\_41013] An occurred severe error (S3) shall be processed as a BusOff (see SRS\_Can\_01029 of CAN SRS)

<b>Type:</b>	Valid
<b>Description:</b>	Severe Error (see ISO 11898-4:2004 [7]), Handling and recovery is the same as for BusOff events.
<b>Rationale:</b>	The required behaviour for an occurred severe error (see ISO 11898-4_2004 [7]) is the same as the AUTOSAR BSW behaviour of a detected BusOff.
<b>Use Case:</b>	--
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]

](RS\_BRF\_01640)

## 4.2 Non-functional requirements

### 4.2.1 CAN dependence

4.2.1.1 [SRS\_TtCan\_41002] The additional TTCAN components shall be integrated into the CAN stack.

<b>Type:</b>	Valid
<b>Description:</b>	The CAN stack shall be extended by additional APIs, type definitions and functionality to support TTCAN.
<b>Rationale:</b>	TTCAN completely uses the CAN stack. The CAN stack shall not be available twice (code optimization).
<b>Use Case:</b>	--
<b>Dependencies:</b>	--
<b>Supporting Material:</b>	RS Features: RS_BRF_00312 [5]

](RS\_BRF\_01744)

## 5 Requirements Tracing

Requirement	Description	Satisfied by
RS_BRF_01328	AUTOSAR RTE shall support scheduling of executable entities on defined events	SRS_TtCan_41007
RS_BRF_01432	AUTOSAR services shall support system time services	SRS_TtCan_41005, SRS_TtCan_41006
RS_BRF_01464	AUTOSAR services shall support standardized handling of watchdogs	SRS_TtCan_41004
RS_BRF_01560	AUTOSAR communication shall support mapping of signals into transferrable protocol data units	SRS_TtCan_41003
RS_BRF_01592	AUTOSAR communication shall offer data transfer on user request, time based, and requested via the underlying bus	SRS_TtCan_41010, SRS_TtCan_41011
RS_BRF_01640	AUTOSAR communication shall support transmit and receive cancelation	SRS_TtCan_41013
RS_BRF_01744	AUTOSAR communication shall support TTCAN	SRS_TtCan_41001, SRS_TtCan_41002, SRS_TtCan_41012, SRS_TtCan_41014
RS_BRF_02168	AUTOSAR diagnostics shall provide a central classification and handling of abnormal operative conditions	SRS_TtCan_41008, SRS_TtCan_41009

## 6 References

### 6.1 Deliverables of AUTOSAR

- [1] **[Ttcan]** Specification of TTCAN Driver  
AUTOSAR\_SWS\_TTCANDriver.pdf
- [2] **[TtcanIf]** Specification of TTCAN Interface  
AUTOSAR\_SWS\_TTCANInterface.pdf
- [3] **[SrsCan]** Requirements on CAN  
AUTOSAR\_SRS\_CAN.pdf
- [4] **[SrsGeneral]** General Requirements on Basic Software Modules  
AUTOSAR\_SRS\_BSWGeneral.pdf
- [5] **[RS\_Features]** Requirements on AUTOSAR Features,  
AUTOSAR\_RS\_Features.pdf
- [6] **[TPS\_STDT\_0078]** Software Standardization Template  
AUTOSAR\_TPS\_StandardizationTemplate.pdf

### 6.2 Related standard and norms

- [7] ISO 11898-4 (2004-08-01), Road vehicles – Controller Area Network (CAN)  
Part4: Time triggered communication