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Revision	3

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Date	Version	Changed by	Change Description
23.11.2011	3.0.0	AUTOSAR Administration	• Added support for Partial Networking • Implemented Production error concept • Updated Baud rate configuration parameter handling • Added support to detect that power-on was caused by CAN communication • Reentrancy attribute is corrected for APIs • Corrections in few requirements • Optional Interfaces Table is corrected
21.10.2010	2.1.0	AUTOSAR Administration	• CanTrcv state names changed and state diagram modified • Usage of SBCs are no longer restricted • Mode switch requests to the current mode are allowed • CanTrvc driver has to invoke CanIf_TrcvModeIndication after each mode switch request, when the requested mode has been reached

04.12.2009	2.0.0	AUTOSAR Administration	• Wakeup event reporting: In R4.0, CanTrcv stores wakeup events. CanIf invokes function CanTrcv_CheckWakeup() periodically to check for wakeup events. • Wakeup modes: In R4.0, wakeup through interrupt mechanism is not supported. Only POLLING and NOT_SUPPORTED wakeup modes are available in CanTrcv. • Sleep Wait Count added: Wait count for transitioning into sleep mode (CanTrcvSleepWaitCount) added. • Legal disclaimer revised
23.06.2008	1.2.1	AUTOSAR Administration	• Legal disclaimer revised
05.12.2007	1.2.0	AUTOSAR Administration	• Changed API name CanIf_TrcvWakeupByBus to CanIf_SetWakeupEvent • New error code CANTRCV_E_PARAM_TRCV_WAKEUP_MODE has been added. • Output parameter in the API's CanTrcv_GetOpMode, CanTrcv_GetBusWuReason and CanTrcv_GetVersionInfo is changed to pointer type. • API CanTrcv_CB_WakeupByBus has been modified • Document meta information extended • Small layout adaptations made
30.01.2007	1.1.0	AUTOSAR Administration	• CAN transceiver driver is below CAN interface. All API access from higher layers are routed through CAN interface. • One CAN transceiver driver used per CAN transceiver hardware type. For different CAN transceiver hardware types different CAN transceiver drivers are used. One CAN transceiver driver supports all CAN transceiver hardware of same type • Legal disclaimer revised • Release Notes added • "Advice for users" revised • "Revision Information" added
16.05.2006	1.0.0	AUTOSAR Administration	Initial release

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Advice for users

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Table of Content

1 Introduction

This specification describes the functionality, APIs and configuration of CAN Transceiver Driver module. The CAN Transceiver Driver module is responsible for handling the CAN transceiver hardware chips on an ECU.

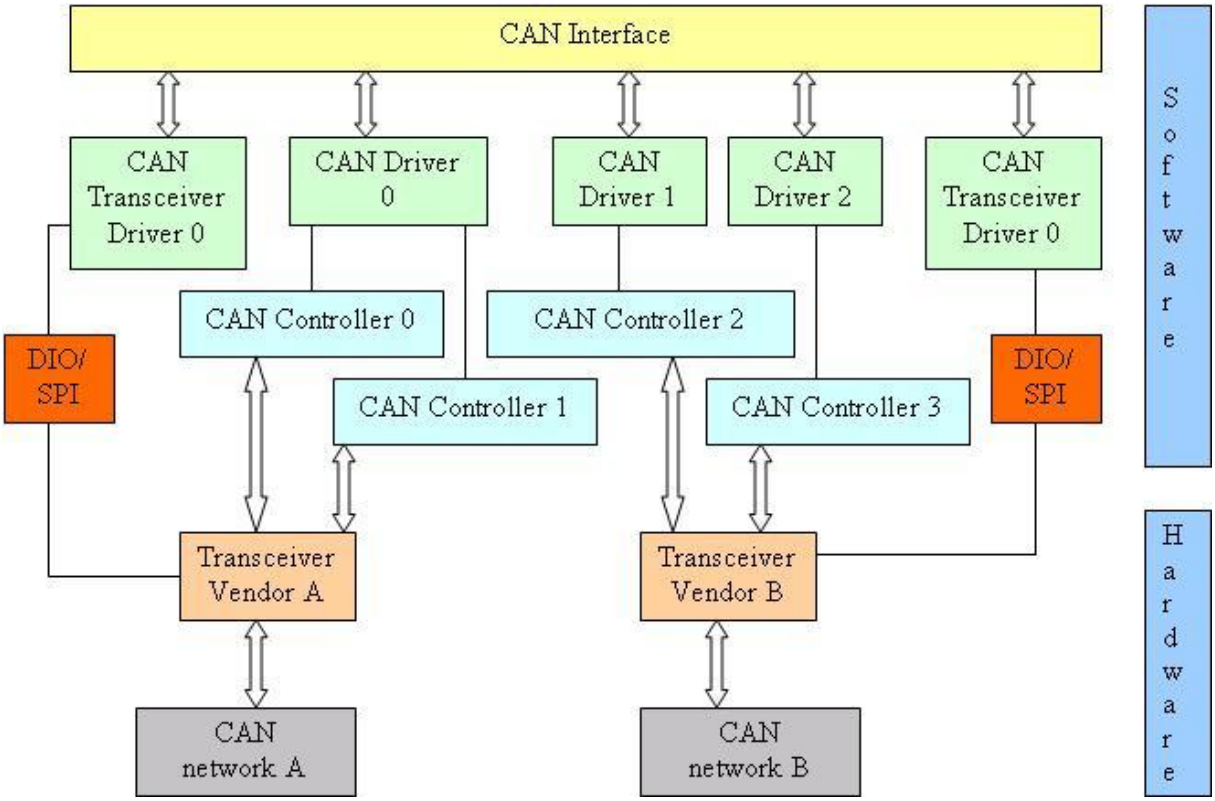
The CAN Transceiver is a hardware device, which adapts the signal levels that are used on the CAN bus to the logical (digital) signal levels recognised by a microcontroller.

In addition, the transceivers are able to detect electrical malfunctions like wiring issues, ground offsets or transmission of long dominant signals. Depending on the interfacing with the microcontroller, they flag the detected error summarized by a single port pin or very detailed by SPI.

Some transceivers support power supply control and wake up via the CAN bus. Different wake up/sleep and power supply concepts are usual on the market.

Within the automotive environment, there are mainly three different CAN bus physics used. These are ISO11898 for high-speed CAN (up to 1Mbits/s), ISO11519 for low-speed CAN (up to 125Kbits/s) and SAE J2411 for single-wire CAN.

Latest developments include System Basis Chips (SBCs) where power supply control and advanced watchdogs are implemented in addition to CAN. These are enclosed in one housing and controlled through single interface (e.g. via SPI).


CAN Interface
CAN Transceiver Driver 0
CAN Driver 0
CAN Driver 1
CAN Driver 2
CAN Transceiver Driver 0
CAN Controller 0
CAN Controller 2
DIO/ SPI
CAN Controller 1
CAN Controller 3
DIO/ SPI
Transceiver Vendor A
Transceiver Vendor B
CAN network A
CAN network B
Software
Hardware

1.1 Goal of CAN Transceiver Driver

The target of this document is to specify the interfaces and behavior which are applicable to most current and future CAN transceiver devices.

The CAN transceiver driver abstracts the CAN transceiver hardware. It offers a hardware independent interface to the higher layers. It abstracts from the ECU layout by using APIs of MCAL layer to access the CAN transceiver hardware.

1.2 Explicitly uncovered CAN transceiver functionality

Some CAN bus transceivers offer additional functionality, for example, ECU self test or error detection capability for diagnostics.

ECU self test and error detection are not defined within AUTOSAR and requiring such functionality would lock out most currently used transceiver hardware chips. Therefore, features like “ground shift detection”, “selective wake up”, “slope control” are not supported.

1.3 Single wire CAN transceivers according SAE J2411

Single wire CAN according SAE J2411 is not supported by AUTOSAR.

2 Acronyms and abbreviations

Abbreviation	*Description*
ComM	Communication Manager
DEM	Diagnostic Event Manager
DET	Development Error Tracer
DIO	Digital Input Output (SPAL module)
EB	Externally Buffered channels. Buffers containing data to transfer are outside the SPI Handler/Driver.
EcuM	ECU State Manager
IB	Internally Buffered channels. Buffers containing data to transfer are inside the SPI Handler/Driver.
ISR	Interrupt Service Routine
MCAL	Micro Controller Abstraction Layer
Port	Port module (SPAL module)
n/a	Not Applicable
SBC	System Basis Chip; a device, which integrates e.g. CAN and/or LIN transceiver, watchdog and power control.
SPAL	Standard Peripheral Abstraction Layer
SPI Channel	A channel is a software exchange medium for data that are defined with the same criteria: configuration parameters, number of data elements with same size and data pointers (source & destination) or location. See specification of SPI driver for more details.
SPI Job	A job is composed of one or several channels with the same chip select. A job is considered to be atomic and therefore cannot be interrupted. A job has also an assigned priority. See specification of SPI driver for more details.
SPI Sequence	A sequence is a number of consecutive jobs to be transmitted. A sequence depends on a static configuration. See specification of SPI driver for more details.
CAN Channel	A physical channel which is connected to a CAN network from a CAN controller through a CAN transceiver.
API	Application Programming Interface

3 Related documentation

3.1 Input documents

[1] List of Basic Software Modules
AUTOSAR_TR_BSWModuleList.pdf

[2] Layered Software Architecture
AUTOSAR_EXP_LayeredSoftwareArchitecture.pdf

[3] Specification of ECU Configuration
AUTOSAR_TPS_ECUConfiguration.pdf

[4] General Requirements on Basic Software
AUTOSAR_SRS_BSWGeneral.pdf

[5] Specification of Specification of CAN Interface
AUTOSAR_SWS_CANInterface.pdf

[6] Basic Software Module Description Template,
AUTOSAR_TPS_BSWModuleDescriptionTemplate.pdf

3.2 Related standards and norms

[7] ISO11898 – Road vehicles - Controller area network (CAN)

4 Constraints and assumptions

4.1 Limitations

[CanTrcv098] ⌈ The CAN bus transceiver hardware shall provide the functionality and an interface which can be mapped to the operation mode model of the AUTOSAR CAN transceiver driver. ⌋(BSW172)

See also Chapter 7.1.

The used APIs of underlying drivers (SPI and DIO) shall be synchronous.

Implementations of underlying drivers which does not support synchronous behavior cannot be used together with CAN transceiver driver.

4.2 Applicability to car domains

This driver might be applicable in all car domains using CAN for communication.

5 Dependencies to other modules

Module	Dependencies
CanIf	All CAN transceiver drivers are arranged below CanIf.
ComM	ComM steers CAN transceiver driver communication modes via CanIf. Each CAN transceiver driver is steered independently.
DET	DET gets development error information from CAN transceiver driver.
DIO	DIO module is used to access CAN transceiver device connected via ports.
EcuM	EcuM gets information about wake up events from CAN transceiver driver via CanIf.
SPI	SPI module is used to access CAN transceiver device connected via SPI.

5.1 File structure

5.1.1 Naming convention for transceiver driver implementation

[CanTrcv070] ⌈ In case different CAN transceiver hardware chips are used in one ECU, the function names of the different CAN transceiver drivers must be modified such that no two functions with the same names are generated. It is the responsibility of the user to take care that no two functions with the same names are configured. The names may be extended with a vendor ID or a type ID. ⌋(BSW00347)

5.1.2 Code file structure

[CanTrcv064] ⌈ The naming convention prescribed by AUTOSAR is applied to all files of the CanTrcv module. ⌋(BSW00300)

[CanTrcv065] ⌈ The CanTrcv module consists of the following files:

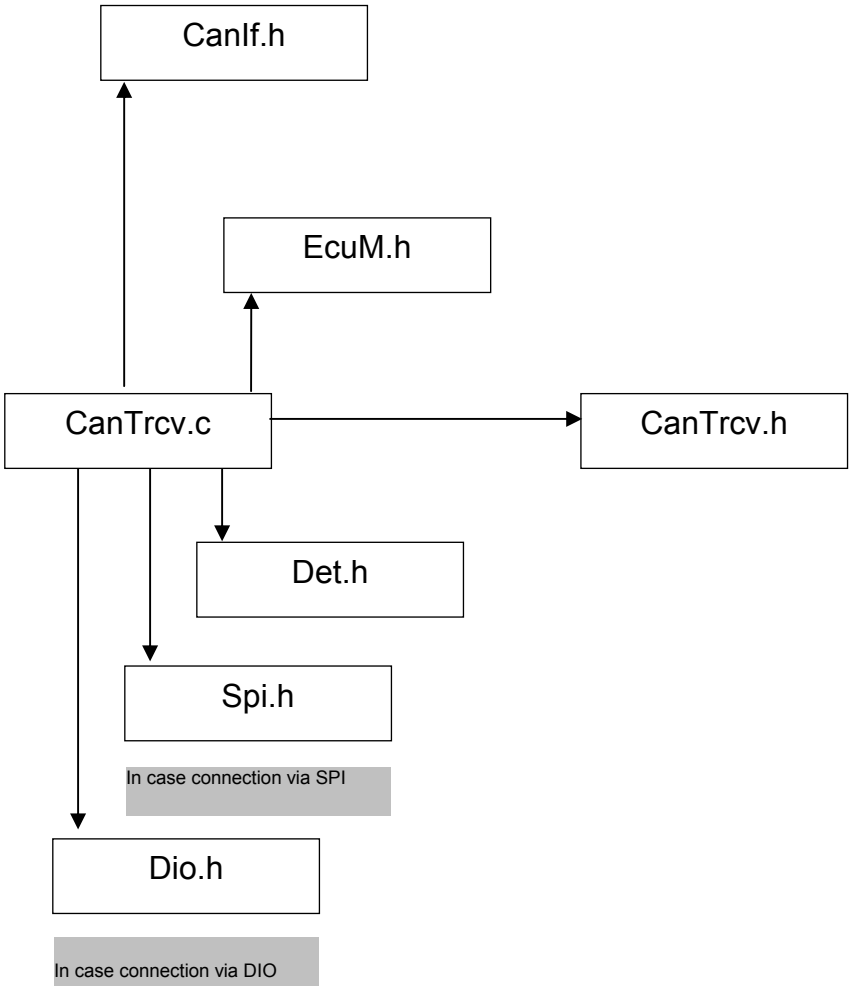
File name	*Requirements*	*Description*
CanTrcv.c	CanTrcv069	The implementation general c file. It does not contain interrupt routines.
CanTrcv.h	CanTrcv052	It contains only information relevant for other BSW modules (API). Differences in API depending in configuration are encapsulated.
CanTrcv_Cfg.h	CanTrcv083	Pre-compile time configuration parameter file. It's generated by the configuration tool.
CanTrcv_Cfg.c	CanTrcv062	Pre-compile time configuration code file. It's generated by the configuration tool.

		⌋(BSW00346, BSW158)

5.1.3 Header file structure

[CanTrcv067]

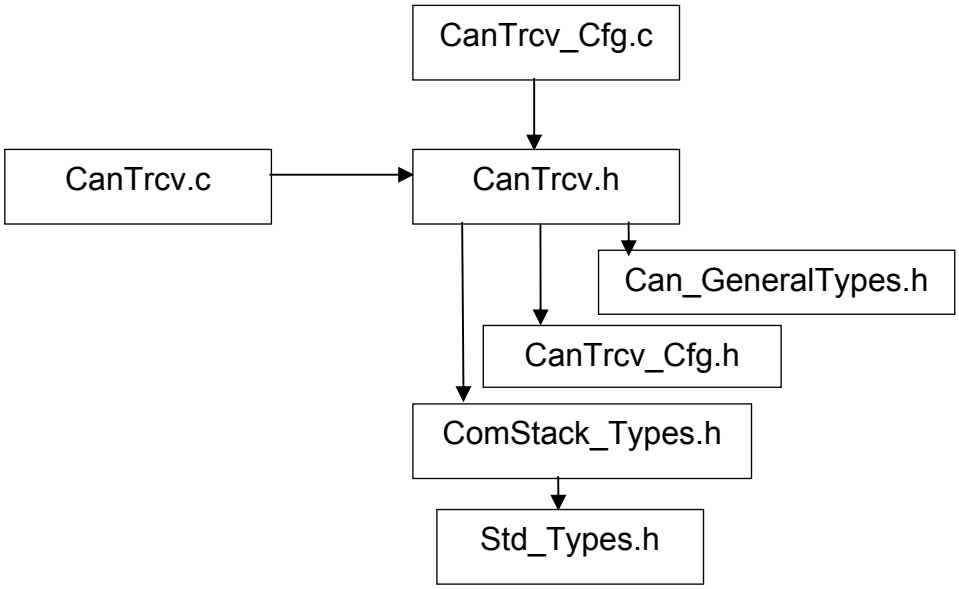
⌈



⌋(BSW00301, BSW00409)

[CanTrcv147]

⌈



」()

[CanTrcv068] 「 For AUTOSAR standard data types, header file `Std_Types.h` is included. 」(BSW00348)

[CanTrcv061] 「 The name of the compiler specific header file is `Compiler.h`. All mappings of not standardized keywords of compiler specific scope shall be placed and organized in this compiler specific type and keyword header. 」(BSW00361)

[CanTrcv063] 「 The name of the platform specific header file is `Platform_Types.h`. All integer type definitions of target and compiler specific scope shall be placed and organized in this single type header. 」(BSW00353)

[CanTrcv156] 「 CanTrcv.h shall include CanTrcv_Cfg.h, for the API pre-compiler switches 」()

[CanTrcv162] 「 CanTrcv.h shall include Can_GeneralTypes.h, for the general CAN type definitions. 」()

[CanTrcv166] 「 The imported types described in CanTrcv163, CanTrcv164 and CanTrcv165 shall be defined in Can_GeneralTypes.h. 」()

6 Requirements Traceability

Document: AUTOSAR requirements on Basic Software, general

Requirement	*Satisfied by*
[BSW003] Version identification	CanTrcv160
[BSW00300] Module naming convention.	CanTrcv064
[BSW00301] Limit imported information	CanTrcv067
[BSW00302] Limit exported information.	CanTrcv052
[BSW00304] AUTOSAR integer data types	not applicable (general implementation requirement)
[BSW00305] Self-defined data types naming convention	not applicable (no self defined data types)
[BSW00306] Avoid direct use of compiler and platform specific keyword	not applicable (general implementation requirement)
[BSW00307] Naming convention for global variables	not applicable (general implementation requirement)
[BSW00308] Definition of global data	not applicable (general implementation requirement)
[BSW00309] Global read only data with read only constraint	not applicable (general implementation requirement)
[BSW00310] API naming convention	CanTrcv001, CanTrcv002, CanTrcv005, CanTrcv007, CanTrcv008, CanTrcv009, CanTrcv013
[BSW00312] Shared code shall be reentrant	not applicable (general implementation requirement)
[BSW00314] Separation of interrupt frames and services routines	CanTrcv069
[BSW00318] Format of module version numbers	CanTrcv160
[BSW00321] Enumeration of module version numbers	not applicable (general implementation requirement)
[BSW00323] API parameter checking	CanTrcv048
[BSW00325] Runtime of interrupt service routines	not applicable (CAN transceiver driver implements no ISRs)
[BSW00326] Transition from ISRs to OS tasks	not applicable (no such transitions are performed)
[BSW00327] Error values naming convention	CanTrcv050
[BSW00328] Avoid duplication of code	not applicable (general implementation requirement)
[BSW00329] Avoidance of generic interfaces	CanTrcv001, CanTrcv002, CanTrcv005, CanTrcv007, CanTrcv008, CanTrcv009, CanTrcv013
[BSW00330] Use of macros and inline functions	not applicable (general implementation requirement)
[BSW00331] Separation of error and status values	not applicable (no such values defined)
[BSW00333] Documentation of callback function context	not applicable (general documentation requirement)
[BSW00334] Provision of XML file	not applicable (general implementation requirement)
[BSW00335] Status values naming convention	not applicable
[BSW00336] Shut down interface	not applicable (no need for such interfaces)
[BSW00337] Classification of errors	CanTrcv057

[BSW00338] Detection and reporting of development errors	CanTrcv040,CanTrcv050
[BSW00339] Reporting of production relevant error status	CanTrcv024,CanTrcv058
[BSW00341] Mircocontroller compatibility documentation	not applicable (general documentation requirement)
[BSW00342] Use of source code and object code	not applicable (general implementation requirement)
[BSW00343] Specification and configuration of time	CanTrcv112
[BSW00344] Reference to link time configuration	not applicable (only Pre-compile time configuration supported)
[BSW00345] Pre-compile time configuration	CanTrcv062, CanTrcv083
[BSW00346] Basic set of module files	CanTrcv065
[BSW00347] Naming separation of different instances of BSW drivers	CanTrcv016, CanTrcv070
[BSW00348] Standard type header	CanTrcv068
[BSW00350] Development error detection keyword	CanTrcv023, CanTrcv050
[BSW00353] Platform specific type header	CanTrcv063
[BSW00355] Do not redefine AUTOSAR integer data types	not applicable (general implementation requirement)
[BSW00357] Standard API return type	CanTrcv002
[BSW00358] Return type of init() functions	CanTrcv001
[BSW00359] Return type of callback functions	not applicable
[BSW00360] Parameters of callback functions	not applicable
[BSW00361] Compiler specific language extension header	CanTrcv061
[BSW00369] Do not return development error codes via API	CanTrcv001, CanTrcv002, CanTrcv005, CanTrcv007, CanTrcv008, CanTrcv009, CanTrcv013
[BSW00370] Separation of callback interfaces from API	CanTrcv085
[BSW00371] Do not pass function pointers via API	CanTrcv001, CanTrcv002, CanTrcv005, CanTrcv007, CanTrcv008, CanTrcv009, CanTrcv013
[BSW00373] Main processing function naming convention	CanTrcv013
[BSW00374] Module vendor identification	CanTrcv108
[BSW00375] Notification of wake-up reason	CanTrcv007
[BSW00376] Return type and parameters of main functions	CanTrcv013
[BSW00377] Module specific API return types	CanTrcv005, CanTrcv007
[BSW00378] AUTOSAR boolean type	not applicable (general implementation requirement)
[BSW00379] Module identification	CanTrcv108
[BSW00380] Separate C file for configuration parameters	CanTrcv062
[BSW00381] Separate configuration H file for Pre-compile time parameters	CanTrcv083
[BSW00383] List dependencies of configuration elements	not applicable (general documentation requirement)
[BSW00384] List dependencies to other modules	not applicable (general documentation requirement)
[BSW00385] List possible error notifications	CanTrcv050
[BSW00386] Configuration for detecting an error	CanTrcv050
[BSW00387] Specify the configuration class of callbacks	not applicable
[BSW00388] Introduce containers	CanTrcv090, CanTrcv091, CanTrcv092CanTrcv093, CanTrcv094CanTrcv095
[BSW00389] Container shall have names	CanTrcv090, CanTrcv091, CanTrcv092CanTrcv093, CanTrcv094 CanTrcv095
[BSW00390] Parameter content unique within the module	CanTrcv090, CanTrcv091, CanTrcv093, CanTrcv095
[BSW00391] Parameters shall have unique names	CanTrcv090, CanTrcv091, CanTrcv093,

	CanTrcv095
[BSW00392] Parameters shall have unique types	CanTrcv090, CanTrcv091, CanTrcv093, CanTrcv095
[BSW00393] Parameters shall have a range	CanTrcv090, CanTrcv091, CanTrcv093, CanTrcv095
[BSW00394] Specify the scope of the parameters	CanTrcv090, CanTrcv091, CanTrcv093, CanTrcv095
[BSW00395] List the required parameters (per parameter)	CanTrcv091, CanTrcv093, CanTrcv094CanTrcv095
[BSW00396] Configuration classes	CanTrcv017
[BSW00397] Pre-compile time parameters	CanTrcv062, CanTrcv083
[BSW00398] Link time parameters	not applicable (only Pre-compile time configuration supported)
[BSW00399] Loadable post build time parameters	not applicable (only Pre-compile time configuration supported)
[BSW004] Version check	CanTrcv160
[BSW00400] Selectable post build time parameters	not applicable (only Pre-compile time configuration supported)
[BSW00401] Documentation of multiple instances of configuration parameters	not applicable (general documentation requirement)
[BSW00402] Published information	CanTrcv001_PI
[BSW00404] Reference to post build time configuration	not applicable (only Pre-compile time configuration supported)
[BSW00405] Reference to multiple configuratin sets	not applicable (only Pre-compile time configuration supported)
[BSW00406] Check module initialization	CanTrcv002, CanTrcv005, CanTrcv007, CanTrcv008, CanTrcv009, CanTrcv013
[BSW00407] Function to read out published parameters	CanTrcv008
[BSW00408] Configuration Parameter naming convention	CanTrcv090, CanTrcv091, CanTrcv093, CanTrcv094CanTrcv095
[BSW00409] Header files for production code error	CanTrcv067
[BSW00410] Compiler switches shall have defined values	not applicable (general implementation requirement)
[BSW00411] Get version information keyword	CanTrcv008
[BSW00412] Separate H file for configuration parameters	CanTrcv083
[BSW00413] Accessing instances of BSW modules	CanTrcv016
[BSW00414] Parameters of init function	CanTrcv001
[BSW00415] User dependent include files	CanTrcv052
[BSW00416] Sequence of initialization	not applicable (this is out of CAN transceiver driver's scope)
[BSW00417] Preporting of error events by non basic software	not applicable (Requirement concerns application components only)
[BSW00419] Separate C file for Pre-compile time configuration parameters	CanTrcv062
[BSW00420] Production relevant error event rate detection	not applicable (it's an Dem requirement)
[BSW00421] Reporting of production relevant error events	CanTrcv058
[BSW00422] Debouncing of production relevant error status	not applicable (it's an Dem requirement)
[BSW00423] Usage of SW C template to describe BSW modules with AUTOSAR interfaces	not applicable (general implementation requirement)
[BSW00424] BSW main processing function task allocation	CanTrcv013

[BSW00425] Trigger condition for schedulable objects	CanTrcv090
[BSW00426] Exclusive areas in BSW modules	not applicable (CAN transceiver driver is part of ECU abstraction layer)
[BSW00427] ISR description for BSW modules	not applicable (No such areas or function in CAN transceiver driver)
[BSW00428] Execution order dependencies of main processing function	CanTrcv013
[BSW00429] Restricted BSW OS functionality access	not applicable (general implementation requirement)
[BSW00431] The BSW scheduler module implements task bodies	not applicable (requirement concerns BSW scheduler module)
[BSW00432] Modules should have separate main processing functions for read/receive and write/transmit data path	not applicable (CAN transceiver driver does not propagate data)
[BSW00433] Calling of main processing functions	not applicable (requirement concerns BSW scheduler module)
[BSW00434] The schedule module shall provide an API for exclusive areas	not applicable (requirement concerns BSW scheduler module)
[BSW005] No hard coded horizontal interfaces within MCAL	not applicable (CAN transceiver driver is part of ECU abstraction layer)
[BSW006] Platform independency	not applicable (general implementation requirement)
[BSW007] HIS Misra C	not applicable (general implementation requirement)
[BSW009] Module user documentation	not applicable (general documentation requirement)
[BSW010] Memory resource documentation	not applicable (general documentation requirement)
[BSW101] Initialization interface	CanTrcv001
[BSW158] Separation of configuration from implementation	CanTrcv065
[BSW159] Tool-based configuration	
[BSW160] Human readable configuration data	CanTrcv090, CanTrcv091, CanTrcv093, CanTrcv094CanTrcv095
[BSW161] Microcontroller abstraction	not applicable (CAN transceiver driver is part of ECU abstraction layer)
[BSW162] ECU layout abstraction	
[BSW164] Implementation of interrupt service routines	not applicable (CAN transceiver driver implements no ISRs)
[BSW167] Static configuration checking	
[BSW168] Diagnostic Interface of SW components	not applicable (CAN transceiver driver has no such needs)
[BSW170] Data for reconfiguration of AUTOSAR SW components	
[BSW171] Configurability of optional functionality	CanTrcv013
[BSW172] Compatibility and documentation of scheduling strategy	CanTrcv001, CanTrcv013, CanTrcv090 CanTrcv091, CanTrcv098, CanTrcv099

Document: AUTOSAR requirements on Basic Software, cluster CAN

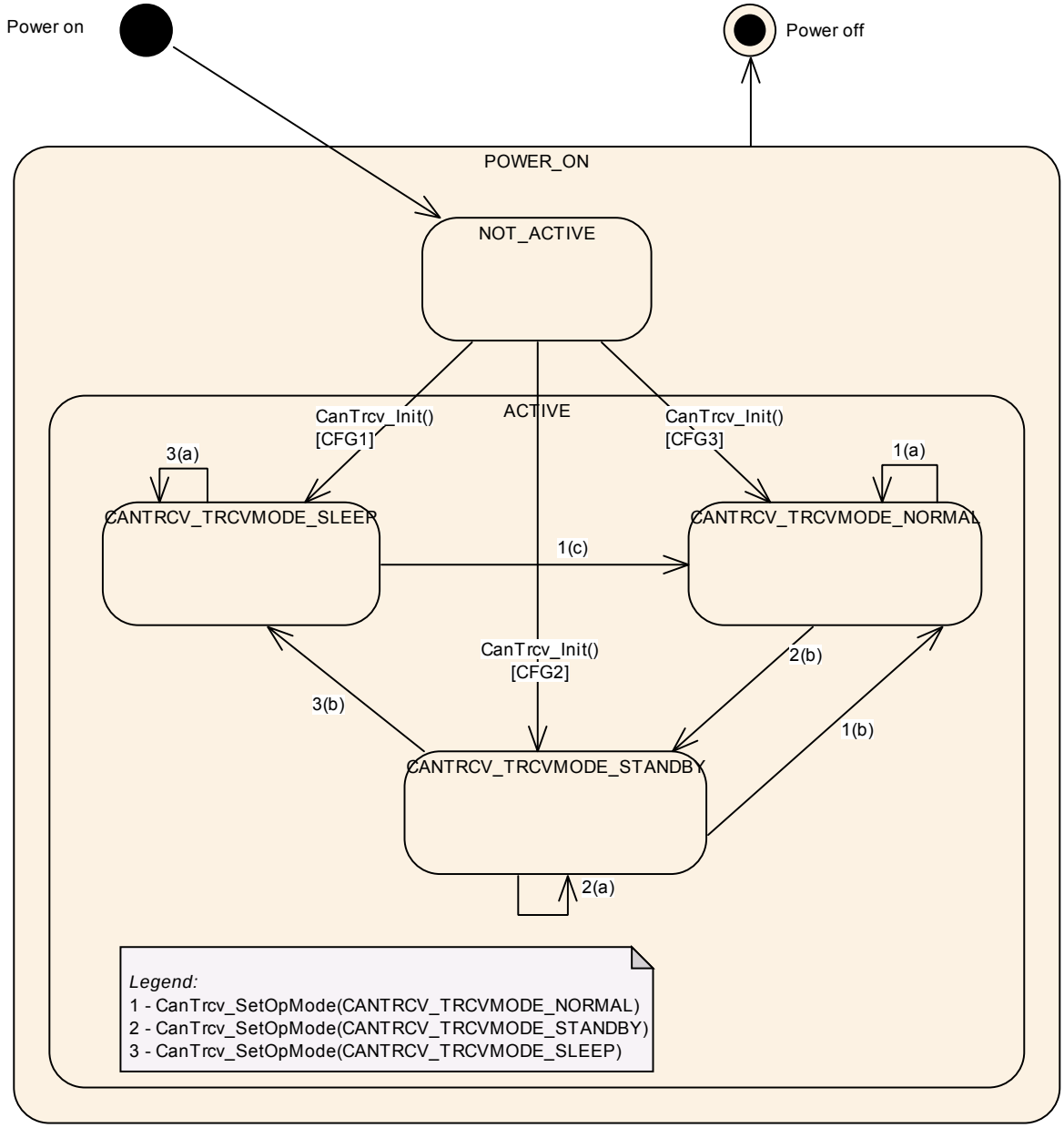
Requirement	***Satisfied by***

[BSW01090] Configuration Data for CAN Bus Transceiver	CanTrcv090, CanTrcv091, CanTrcv093, CanTrcv094CanTrcv095
[BSW01091] Support for more than one CAN transceiver. Only pre-compile time configuration allowed.	CanTrcv002, CanTrcv005, CanTrcv007, CanTrcv009, CanTrcv016, CanTrcv017
[BSW01092] Configuration of bus operation mode after initialization for each CAN bus transceiver	CanTrcv091
[BSW01095] Configuration “Notification for Wakeup by bus”	CanTrcv007
[BSW01096] API to initialize the CAN bus transceiver driver	CanTrcv001
[BSW01097] CAN bus transceiver driver API shall be synchronous	CanTrcv001, CanTrcv002, CanTrcv005, CanTrcv007, CanTrcv009, CanTrcv013
[BSW01098] API to request operation mode Standby	CanTrcv002, CanTrcv055
[BSW01099] API to request operation mode Sleep	CanTrcv002, CanTrcv055
[BSW01100] API to request operation mode Normal	CanTrcv002, CanTrcv055
[BSW01101] API to read out current operation mode	CanTrcv005
[BSW01103] API to read out wake up reason	CanTrcv007
[BSW01106] Wake up by bus notification to upper layer	CanTrcv007
[BSW01107] Support for wake up during sleep transition	not applicable
[BSW01109] CAN bus transceiver driver must check transceiver control	CanTrcv001, CanTrcv002, CanTrcv005, CanTrcv007, CanTrcv009, CanTrcv013
[BSW01110] Handle timing requirements of transceiver	CanTrcv001, CanTrcv002, CanTrcv005, CanTrcv007, CanTrcv009, CanTrcv013
[BSW01115] Support API for enable/disable and clear wake up event	CanTrcv009
[BSW01138] Wake up by bus callback for lower layers	not applicable
BSW01108] Safe system start up and shut down for CAN bus transceiver driver	CanTrcv001, CanTrcv002

7 Functional specification

7.1 CAN transceiver driver operation modes

[CanTrcv055] ⌈ The CanTrcv module shall implement the state diagram shown below, independently for each configured transceiver. ⌋(BSW01098, BSW01099, BSW01100)



The main idea intended by this diagram, is to support a lot of up to now available CAN bus transceivers in a generic view. Depending on the CAN transceiver hardware, the model may have one or two states more than necessary for a given CAN

transceiver hardware but this will clearly decouple the ComM and EcuM from the used hardware.

[CanTrcv148] ⌈ The function `CanTrcv_Init` causes a state change to either CANTRCV_TRCVMODE_SLEEP, CANTRCV_TRCVMODE _NORMAL or CANTRCV_TRCVMODE _STANDBY. This depends on the configuration and is independently configurable for each transceiver. ⌋()

State	Description
POWER_ON	ECU is fully powered.
NOT_ACTIVE	State of CAN transceiver hardware depends on ECU hardware and on Dio and Port driver configuration. CAN transceiver driver is not initialized and therefore not active.
ACTIVE	The function CanTrcv_Init has been called. It carries CAN transceiver driver to active state. Depending on configuration CAN transceiver driver enters the state CANTRCV_TRCVMODE_SLEEP, CANTRCV_TRCVMODE_STANDBY or CANTRCV_TRCVMODE_NORMAL.
CANTRCV_TRCVMODE_NORMAL	Full bus communication. If CAN transceiver hardware controls ECU power supply, ECU is fully powered. The CAN transceiver driver detects no further wake up information.
CANTRCV_TRCVMODE_STANDBY	No communication is possible. ECU is still powered if CAN transceiver hardware controls ECU power supply. A transition to CANTRCV_TRCVMODE_SLEEP is only valid from this mode. A wake up by bus or by a local wake up event is possible.
CANTRCV_TRCVMODE_SLEEP	No communication is possible. ECU may be unpowered depending on responsibility to handle power supply. A wake up by bus or by a local wake up event is possible.

If a CAN transceiver driver covers more than one CAN transceiver (configured as channels), all transceivers (channels) are either in the state NOT_ACTIVE or in the state ACTIVE.

In state ACTIVE, each transceiver may be in a different sub state.

7.1.1 Operation mode switching

A mode switch is requested with a call to the function `CanTrcv_SetOpMode`.

[CanTrcv161] ⌈ A mode switch request to the current mode is allowed and shall not lead to an error, even if DET is enabled. ⌋()

[CanTrcv158] ⌈ The CanTrcv module shall invoke the callback function `CanIf_TrcvModeIndication`, for each mode switch request with call to `CanTrcv_SetOpMode`, after the requested mode has been reached. ⌋()

7.2 CAN transceiver hardware operation modes

The CAN transceiver hardware may support more mode transitions than shown in the state diagram above. The dependencies and the recommended implementations behaviour are explained in this chapter.

It is implementation specific to decide which CAN transceiver hardware state is covered by which CAN transceiver driver software state. An implementation has to guarantee that the whole functionality of the described CAN transceiver driver software state is realized by the implementation.

7.2.1 Example for temporary “Go-To-Sleep” mode

The mode often referred to as "Go-to-sleep” is a temporary mode when switching from Normal to Sleep. The driver encapsulates such a temporary mode within one of the CAN transceiver driver software states. In addition, the CAN transceiver driver switches first from Normal to Standby and then with an additional API call from Standby to Sleep.

7.2.2 Example for “PowerOn/ListenOnly” mode

The mode often referred to as “PowerOn“ or “ListenOnly” is a mode where the CAN transceiver hardware is only able to receive messages but not able to send messages. Also, transmission of the acknowledge bit during reception of a message is suppressed. This mode is not supported because it is outside of the CAN standard and not supported by all CAN transceiver hardware chips.

7.3 CAN transceiver wake up types

There are three different scenarios which are often called wake up:

Scenario 1:

- MCU is not powered.
- Parts of ECU including CAN transceiver hardware are powered.
- The considered CAN transceiver is in SLEEP mode.
- A wake up event on CAN bus is detected by CAN transceiver hardware.
- The CAN transceiver hardware causes powering of MCU.

In terms of AUTOSAR, this is kept as a cold start and NOT as a wake up.

Scenario 2:

- MCU is in low power mode.
- Parts of ECU including CAN transceiver hardware are powered.
- The considered CAN transceiver is in STANDBY mode.
- A wake up event on CAN bus is detected by CAN transceiver hardware.
- The CAN transceiver hardware causes a SW interrupt for waking up.

In terms of AUTOSAR, this is kept as a wake up of the CAN channel and of the MCU.

Scenario 3:

- MCU is in full power mode.
- At least parts of ECU including CAN transceiver hardware are powered.
- The considered CAN transceiver is in STANDBY mode.
- A wake up event on CAN is detected by CAN transceiver hardware.
- The CAN transceiver hardware either causes a SW interrupt for waking up or is polled cyclically for wake up events.

In terms of AUTOSAR, this is kept as a wake up of the CAN channel.

7.4 Enabling/Disabling wakeup notification

CanTrcv171: CanTrcv driver shall use the following APIs provided by ICU driver, to enable and disable the wakeup event notification:

- `Icu_EnableNotification`
- `Icu_DisableNotification`

CanTrcv driver shall ensure the following to avoid the loss of wakeup events:

CanTrcv172: It shall enable the ICU channels when the transceiver transitions to the Standby mode (`CANTRCV_STANDBY`).

CanTrcv173: It shall disable the ICU channels when the transceiver transitions to the Normal mode (`CANTRCV_NORMAL`).

7.5 CAN transceiver wake up modes

CAN transceiver driver offers two wake up modes:

[CanTrcv090] ⌈ **NOT_SUPPORTED mode** ⌋(BSW00388, BSW00389, BSW00390, BSW00391, BSW00392, BSW00393, BSW00394, BSW00408, BSW00425, BSW160, BSW172, BSW01090)

In mode NOT_SUPPORTED, no wake ups are generated by CAN transceiver driver. This mode is supported by all CAN transceiver hardware types.

[CanTrcv091] ⌈ **POLLING mode** ⌋(BSW00388, BSW00389, BSW00390, BSW00391, BSW00392, BSW00393, BSW00394, BSW00395, BSW00408, BSW160, BSW172, BSW01090, BSW01092)

In mode POLLING, wake ups generated by CAN transceiver driver may cause CAN channel wake ups. In this mode, no MCU wake ups are possible. This mode presumes a support by used CAN transceiver hardware type. Wake up mode POLLING requires function `CanTrcv_CheckWakeup` and main function `CanTrcv_MainFunction` to be present in source code.
The main function `CanTrcv_MainFunction` shall be called by BSW scheduler and `CanTrcv_CheckWakeup` by CanIf.

The selection of the wake up mode is done by the configuration parameter `CanTrcvWakeUpSupport`. The support of wake ups may be switched on and off for each CAN transceiver individually by the configuration parameter `CanTrcvWakeupByBusUsed`.

Note: In both modes the function `CanTrcv_CheckWakeup` shall be present, but the functionality shall be based on the configured wakeup mode (NOT_SUPPORTED OR POLLING).

Implementation Hint:

If a CAN transceiver needs a specific state transition (e.g. Sleep -> Normal) initiated by the software after detection of a wake-up, this may be accomplished by the CanTrcv module, during the execution of `CanTrcv_CheckWakeup`. This behaviour is implementation specific.

It has to be assured by configuration of modules, which are involved in wake-up process (EcuM, CanIf, ICU etc…) that `CanTrcv_CheckWakeup` is called, when a transceiver needs a specific state transition.

7.6 Error classification

[CanTrcv057] ⌈ Development error values are of type uint8. ⌋(BSW00337)

[CanTrcv050]
⌈

Type or error	*Relevance*	*Related error code*	*Value [hex]*
API called with wrong parameter for the CAN transceiver	Development	CANTRCV_E_INVALID_TRANSCEIVER	1
API called with null	Development	CANTRCV_E_PARAM_POINTER	2

pointer parameter			
API service used without initialization	Development	CANTRCV_E_UNINIT	11
API service called in wrong transceiver operation mode	Development	CANTRCV_E_TRCV_NOT_STANDBY CANTRCV_E_TRCV_NOT_NORMAL	21 22
API service called with invalid parameter for TrcvWakeupMode	Development	CANTRCV_E_PARAM_TRCV_WAKEUP_MODE	23
API service called with invalid parameter for OpMode	Development	CANTRCV_E_PARAM_TRCV_OPMODE	24
Configured baud rate is not supported by the transceiver	Development	CANTRCV_E_BAUDRATE_NOT_SUPPORTED	25
No/incorrect communication to transceiver.	Development	CANTRCV_E_NO_TRCV_CONTROL	26

」(BSW00327, BSW00338, BSW00350, BSW00385, BSW00386)

7.7 Error detection

[CanTrcv023] 「 The detection of all development errors is configurable (ON/OFF) at Pre-compile time. The switch `CanTrcvDevErrorDetect` shall activate or deactivate the detection of all development errors. 」(BSW00350)

[CanTrcv048] 「 If the `CanTrcvDevErrorDetect` switch is enabled API parameter checking is enabled. The detailed description of the detected errors can be found in chapter 7.6. 」(BSW00323)

[CanTrcv058] 「 The detection of production code errors cannot be switched off. 」(BSW00339, BSW00421)

Note: Currently no production error are specified for the CAN Transceiver Driver.

[CanTrcv040] 「 Detected development errors will be reported to the error hook of the Development Error Tracer (Det) if the pre-processor switch `CanTrcvDevErrorDetect` is set. 」(BSW00338)

[CanTrcv024] 「 Production errors shall be reported to Diagnostic Event Manager (Dem). Only error cases are reported to the Dem. 」(BSW00339)

Note: Currently no production error are specified for the CAN Transceiver Driver.

7.8 Preconditions for driver initialization

[CanTrcv099]「 The environment of the CanTrcv module shall make sure that all necessary BSW drivers (used by the CanTrcv module) have been initialized and are usable before `CanTrcv_Init` is called. 」(BSW172)

The CAN bus transceiver driver uses drivers for Spi and Dio to control the CAN bus transceiver hardware. Thus, these drivers must be available and ready to operate before the CAN bus transceiver driver is initialized.

The CAN transceiver driver may have timing requirements for the initialization sequence and the access to the transceiver device which must be fulfilled by these used underlying drivers.

The timing requirements might be that
1) The call of the CAN bus transceiver driver initialization has to be performed very early after power up to be able to read all necessary information out of the transceiver hardware in time for all other users within the ECU.
2) The runtime of the used underlying services is very short and synchronous to enable the driver to keep his own timing requirements limited by the used hardware device.
3) The runtime of the driver may be enlarged due to some hardware devices configuring the port pin level to be valid for e.g. 50µs before changing it again to reach a specific state (e.g. sleep).

7.9 Instance concept

[CanTrcv016]「 For each different CAN transceiver hardware type, an ECU has one CAN transceiver driver instance. One instance serves all CAN transceiver hardware of same type. 」(BSW00347, BSW00413, BSW01091)

7.10 Wait states

For changing operation modes, the CAN transceiver hardware may have to perform wait states.

The wait states can be realized with the configuration parameter: `CanTrcvWaitCount`.

7.11 Debugging

[CanTrcv151]「 All type definitions of variables which shall be debugged, shall be accessible by the header file CanTrcv.h 」()

[CanTrcv152] ⌈ Each variable that shall be accessible by AUTOSAR Debugging, shall be defined as a global variable. ⌋()

[CanTrcv153] ⌈ The declaration of variables in the header file shall be such, that it is possible to calculate the size of the variables by C-“sizeof”. ⌋()

[CanTrcv154] ⌈ Variables available for debugging shall be described in the respective Basic Software Module Description. ⌋()

[CanTrcv155] ⌈ The states of CAN Transceiver Driver state machine shall be available for debugging. ⌋()

7.12 Version checking

[CanTrcv160] ⌈ The CanTrcv module shall perform Inter-Module checks to avoid integration of incompatible files. ⌋(BSW003, BSW00318, BSW004)

The imported include files shall be checked by pre-processor directives.

The following version numbers shall be verified:

- `<MODULENAME>_AR_RELEASE_MAJOR_VERSION`
- `<MODULENAME>_AR_RELEASE_MINOR_VERSION`

Where `<MODULENAME>` is the module short name of the other (external) modules which provide header files, included by the CanTrcv module.

If the values are not identical to the expected values, an error shall be reported.

7.13 Transceivers with selective wakeup functionality

This section describes requirements for CAN transceivers with selective wakeup functionality.

Partial Networking is a state in a CAN system where some nodes are in low power mode while other nodes are communicating. This reduces the power consumption by the entire network. Nodes in the low-power modes are woken up by pre-defined wakeup frames.

Transceivers which support selective wakeup can be woken up by Wake Up Frame/ Frames (WUF), in addition to the wakeup by Wake Up Pattern (WUP) offered by normal transceivers.

CanTrcv174: If selective wakeup is supported by the transceiver hardware, it shall be indicated with the configuration parameter `CanTrcvHwPnSupport`.

CanTrcv175: The configuration container for selective wakeup functionality (`CanTrcvPartialNetwork`) and
for the following APIs:

- `8.4.7 CanTrcv_GetTrcvSystemData,`
- `8.4.8 CanTrcv_ClearTrcvWufFlag,`
- `8.4.9 CanTrcv_ReadTrcvTimeoutFlag,`
- `8.4.10 CanTrcv_ClearTrcvTimeoutFlag` and
- `8.4.11 CanTrcv_ReadTrcvSilenceFlag`

shall exist only if `CanTrcvHwPnSupport = TRUE.`

CanTrcv177: If selective wakeup is supported, CAN transceivers shall be configured to wake up on a particular CAN frame or a group of CAN frames using the parameters `CanTrcvPnFrameCanId`, `CanTrcvPnFrameCanIdMask` and `CanTrcvPnFrameDataMask`.

CanTrcv178: If the transceiver has the ability to identify bus failures (and distinguish between bus failures and other hardware failures), it shall be indicated using the configuration parameter `CanTrcvBusErrFlag` for bus diagnostic purposes.

Note:

For CAN transceivers supporting selective wakeup functionality, detection of wakeup frames is possible during Normal mode (`CANTRCV_TRCVMODE_NORMAL`). Detected wakeup frames are signaled by the transceiver WUF flag. This ensures that no wakeup frame is lost during a transition to Standby mode (`CANTRCV_TRCVMODE_STANDBY`).

8 API specification

8.1 Imported types

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

[CanTrcv084]

⌈

Module	*Imported Type*
Can_GeneralTypes	CanTrcv_TrcvModeType
	CanTrcv_TrcvWakeupModeType
	CanTrcv_TrcvWakeupReasonType
Dio	Dio_ChannelType
	Dio_LevelType
	Dio_PortLevelType
	Dio_PortType
	Dio_ChannelGroupType
Icu	Icu_ChannelType
Spi	Spi_ChannelType
	Spi_DataType
	Spi_NumberOfDataType
	Spi_SequenceType
	Spi_StatusType
Std_Types	Std_ReturnType
	Std_VersionInfoType

⌋()

[CanTrcv163]

⌈

Name:	CanTrcv_TrcvModeType	
Type:	Enumeration	
Range:	CANTRCV_TRCVMODE_NORMAL	= 0 Transceiver mode NORMAL
	CANTRCV_TRCVMODE_SLEEP	Transceiver mode SLEEP
	CANTRCV_TRCVMODE_STANDBY	Transceiver mode STANDBY
Description:	Operating modes of the CAN Transceiver Driver.	

⌋()

[CanTrcv164]

⌈

Name:	CanTrcv_TrcvWakeupModeType	
Type:	Enumeration	
Range:	CANTRCV_WUMODE_CLEAR	A stored wakeup event is cleared on the addressed transceiver.
	CANTRCV_WUMODE_DISABLE	The notification for wakeup events is disabled on the addressed transceiver.

	CANTRCV_WUMODE_ENABLE	= 0 The notification for wakeup events is enabled on the addressed transceiver.
Description:	This type shall be used to control the CAN transceiver concerning wake up events and wake up notifications.	

⌋()

[CanTrcv165]

⌈

Name:	CanTrcv_TrcvWakeupReasonType	
Type:	Enumeration	
Range:	CANTRCV_WU_BY_BUS	The transceiver has detected, that the network has caused the wake up of the ECU.
	CANTRCV_WU_BY_PIN	The transceiver has detected a wake-up event at one of the transceiver's pins (not at the CAN bus).
	CANTRCV_WU_ERROR	= 0 Due to an error wake up reason was not detected. This value may only be reported when error was reported to DEM before.
	CANTRCV_WU_INTERNALLY	The transceiver has detected, that the network has woken up by the ECU via a request to NORMAL mode.
	CANTRCV_WU_NOT_SUPPORTED	The transceiver does not support any information for the wake up reason.
	CANTRCV_WU_POWER_ON	The transceiver has detected, that the "wake up" is due to an ECU reset after power on.
	CANTRCV_WU_RESET	The transceiver has detected, that the "wake up" is due to an ECU reset.
	CANTRCV_WU_BY_SYSERR	The transceiver has detected, that the wake up of the ECU was caused by a HW related device failure.
Description:	This type denotes the wake up reason detected by the CAN transceiver in detail.	

⌋()

8.2 Type definitions

[CanTrcv209]

Name:	CanTrcv_ConfigType	
Type:	Structure	
Range:	Implementation specific	--
Description:	This is the type of the external data structure containing the overall initialization data for the CAN transceiver driver and settings affecting all transceivers. Furthermore it contains pointers to transceiver configuration structures. The contents of the initialization data structure are CAN transceiver hardware specific.	

[CanTrcv210]

Name:	CanTrcv_PNActivationType

Type:	Enumeration	
Range:	PN_ENABLED	PN wakeup functionality in CanTrcv is enabled.
	PN_DISABLED	PN wakeup functionality in CanTrcv is disabled.
Description:	Datatype used for describing whether PN wakeup functionality in CanTrcv is enabled or disabled.	

[**CanTrcv211**]

Name:	CanTrcv_TrcvFlagStateType	
Type:	Enumeration	
Range:	CANTRCV_FLAG_SET	The flag is set in the transceiver hardware.
	CANTRCV_FLAG_CLEARED	The flag is cleared in the transceiver hardware.
Description:	Provides the state of a flag in the transceiver hardware.	

8.3 Function definitions

8.3.1 CanTrcv_Init

[CanTrcv001]

⌈

Service name:	CanTrcv_Init	

Syntax:	`void CanTrcv_Init(`
	`  const CanTrcv_ConfigType* ConfigPtr`
	`)`	

Service ID[hex]:	0x00	
Sync/Async:	Synchronous	
Reentrancy:	Non Reentrant	
Parameters (in):	ConfigPtr	Pointer to driver configuration.
Parameters (in-out):	None	
Parameters (out):	None	
Return value:	None	
Description:	Initializes the CanTrcv module.	

⌋(BSW00310, BSW00329, BSW00358, BSW00369, BSW00371, BSW00414, BSW101, BSW172, BSW01096, BSW01097, BSW01109, BSW01110, BSW01108)

[**CanTrcv180**]: The function `CanTrcv_Init` shall initialize all the connected CAN transceivers based on their initialization sequences and configuration (provided by parameter `ConfigPtr`). Meanwhile, it shall support the configuration sequence of the AUTOSAR stack also.

[CanTrcv100] ⌈ The function `CanTrcv_Init` shall set the CAN transceiver hardware to the state configured by the configuration parameter `CanTrcvInitState`. ⌋()

Note that in the time span between power up and the call to `CanTrcv_Init`, the CAN transceiver hardware may be in a different state. This depends on hardware and SPAL driver configuration.

The initialization sequence after reset (e.g. power up) is a critical phase for the CAN transceiver driver.

This API shall store the wake up event, if any, during initialization time.

See also requirement CanTrcv099.

[CanTrcv167] ⌈ If supported by hardware, `CanTrcv_Init` shall validate whether there has been a wake up due to transceiver activity and if TRUE, reporting shall be done to EcuM via API `EcuM_SetWakeupEvent`. ⌋()

[**CanTrcv181**]: If selective wakeup is enabled and supported by hardware: POR and SYSERR flags of the transceiver status shall be checked by `CanTrcv_Init` API.

[CanTrcv182]: If the POR flag or SYSERR flag is set, transceiver shall be re-configured for selective wakeup functionality by running the configuration sequence.

If the POR flag or SYSERR flag is not set, the configuration stored in the transceiver memory will be still valid and re-configuration is not necessary.

[CanTrcv183]: If the POR flag is set, wakeup shall be reported to EcuM through API `EcuM_SetWakeupEvent` with `CANIF_TRCV_WU_POWERON` as the wakeup reason.

[CanTrcv184]: If the SYSERR flag is set, wakeup shall be reported to EcuM through API `EcuM_SetWakeupEvent` with `CANIF_TRCV_WU_BY_SYSERR` as the wakeup reason.

[CanTrcv113] ⌈ If there is no/incorrect communication towards the transceiver, the function `CanTrcv_Init` shall report the development error `CANTRCV_E_NO_TRCV_CONTROL`.
For Eg., there are different transceiver types and different access ways (port connection, SPI). This development error should be signaled if you detect any miscommunication with your hardware. Depending on connection type and depending on your transceiver hardware you may not run in situations where you have to signal this error. ⌋()

[CanTrcv168] ⌈ If DET is enabled for CanTrcv module: the function `CanTrcv_Init` shall raise the development error `CANTRCV_E_BAUDRATE_NOT_SUPPORTED`, if the configured baud rate is not supported by the transceiver. ⌋()

[CanTrcv185]: If DET is enabled for CanTrcv module: the function `CanTrcv_Init` shall raise the development error `CANTRCV_E_PARAM_POINTER`, if NULL pointer is passed as `ConfigPtr` parameter.

8.3.2 CanTrcv_SetOpMode

[CanTrcv002]

⌈

Service name:	CanTrcv_SetOpMode	
Syntax:	`Std_ReturnType CanTrcv_SetOpMode( uint8 Transceiver, CanTrcv_TrcvModeType OpMode )`	
Service ID[hex]:	0x01	
Sync/Async:	Asynchronous	
Reentrancy:	Reentrant for different transceivers	
Parameters (in):	Transceiver	CAN transceiver to which API call has to be applied.
	OpMode	This parameter contains the desired operating mode
Parameters (in-out):	None	
Parameters (out):	None	

Return value:	Std_ReturnType	E_OK: will be returned if the request for transceiver mode change has been accepted. E_NOT_OK: will be returned if the request for transceiver mode change has not been accepted or any parameter is out of the allowed range.
Description:	Sets the mode of the Transceiver to the value OpMode.	

」(BSW00310, BSW00329; BSW00357, BSW00369, BSW00371, BSW00406, BSW01091, BSW01097, BSW01098, BSW01099, BSW01100, BSW01109, BSW01110, BSW01108)

[CanTrcv102] 「 The function `CanTrcv_SetOpMode` shall switch the internal state of Transceiver to the value of the parameter OpMode, which can be CANTRCV_TRCVMODE_NORMAL, CANTRCV_TRCVMODE_STANDBY or CANTRCV_TRCVMODE_SLEEP. 」()

[CanTrcv103] 「 The user of the CanTrcv module shall call the function `CanTrcv_SetOpMode` with OpMode = CANTRCV_TRCVMODE_STANDBY or CANTRCV_TRCVMODE_NORMAL, if the Transceiver is in mode CANTRCV_TRCVMODE_NORMAL. 」()

[CanTrcv104] 「 The user of the CanTrcv module shall call the function `CanTrcv_SetOpMode` with OpMode = CANTRCV_TRCVMODE_SLEEP or CANTRCV_TRCVMODE_STANDBY, if the Transceiver is in mode CANTRCV_TRCVMODE_STANDBY. 」()

This API is applicable to each transceiver with each value for parameter `CanTrcv_SetOpMode`, regardless of whether the transceiver hardware supports these modes or not. This is to simplify the view of the CanIf to the assigned bus.

[CanTrcv105] 「 If the requested mode is not supported by the underlying transceiver hardware, the function `CanTrcv_SetOpMode` shall return E_NOT_OK. 」()

The number of supported busses is set up in the configuration phase.

[CanTrcv186]: If selective wakeup is supported by hardware: the flags POR and SYSERR of the transceiver status shall be checked by `CanTrcv_SetOpMode` API.

[CanTrcv187]: If the POR flag is set, transceiver shall be re-initialized to run the transceiver's configuration sequence.

[CanTrcv188]: If the SYSERR flag is NOT set and the requested mode is `CANTRCV_NORMAL`, transceiver shall call the API `CanIf_ConfirmPnAvailability()` for the corresponding `TransceiverId`.

`CanIf_ConfirmPnAvailability` informs CanNm (through CanIf and CanSm) that selective wakeup is enabled.

[CanTrcv114] ⌈ If there is no/incorrect communication to the transceiver, the function `CanTrcv_SetOpMode` shall report development error `CANTRCV_E_NO_TRCV_CONTROL` and return `E_NOT_OK`. ⌋()

[CanTrcv120] ⌈ If development error detection for the module CanTrcv is enabled: If the function `CanTrcv_SetOpMode` is called with OpMode = CANTRCV_TRCVMODE_STANDBY, and the Transceiver is not in mode CANTRCV_TRCVMODE_NORMAL or CANTRCV_TRCVMODE_STANDBY, the function `CanTrcv_SetOpMode` shall raise the development error `CANTRCV_E_TRCV_NOT_NORMAL` and return `E_NOT_OK`. ⌋()

[CanTrcv121] ⌈ If development error detection for the module CanTrcv is enabled: If the function `CanTrcv_SetOpMode` is called with OpMode = CANTRCV_TRCVMODE_SLEEP, and the Transceiver is not in mode CANTRCV_TRCVMODE_STANDBY or CANTRCV_TRCVMODE_SLEEP, the function `CanTrcv_SetOpMode` shall raise the development error `CANTRCV_E_TRCV_NOT_STANDBY` and return `E_NOT_OK`. ⌋()

[CanTrcv122] ⌈ If development error detection for the module CanTrcv is enabled: If called before the CanTrcv module has been initialized, the function `CanTrcv_SetOpMode` shall raise the development error `CANTRCV_E_UNINIT` and return `E_NOT_OK`. ⌋()

[CanTrcv123] ⌈ If development error detection for the module CanTrcv is enabled: If called with an invalid Transceiver number, the function `CanTrcv_SetOpMode` shall raise the development error `CANTRCV_E_INVALID_TRANSCEIVER` and return `E_NOT_OK`. ⌋()

[CanTrcv087] ⌈ If development error detection for the module CanTrcv is enabled: If called with an invalid OpMode, the function `CanTrcv_SetOpMode` shall raise the development error `CANTRCV_E_PARAM_TRCV_OPMODE` and return `E_NOT_OK`. ⌋()

8.3.3 CanTrcv_GetOpMode

[CanTrcv005]

⌈

Service name:	CanTrcv_GetOpMode	
Syntax:	`Std_ReturnType CanTrcv_GetOpMode( uint8 Transceiver, CanTrcv_TrcvModeType* OpMode )`	
Service ID[hex]:	0x02	
Sync/Async:	Synchronous	
Reentrancy:	Reentrant	
Parameters (in):	Transceiver	CAN transceiver to which API call has to be applied.
Parameters (in-out):	None	
Parameters (out):	OpMode	Pointer to operation mode of the bus the API is applied to.
Return value:	Std_ReturnType	E_OK: will be returned if the operation mode was detected. E_NOT_OK: will be returned if the operation mode was not detected.
Description:	Gets the mode of the Transceiver and returns it in OpMode.	

⌋(BSW00310, BSW00329, BSW00369, BSW00371, BSW00377, BSW00406, BSW01091, BSW01097, BSW01101, BSW01109, BSW01110)

[CanTrcv106] ⌈ The function CanTrcv_GetOpMode shall collect the actual state of the CAN transceiver driver in the out parameter OpMode. ⌋()

See function `CanTrcv_Init` for the provided state after the CAN transceiver driver initialization till the first operation mode change request.

The number of supported busses is statically set in the configuration phase.

[CanTrcv115] ⌈ If there is no/incorrect communication to the transceiver, the function `CanTrcv_GetOpMode` shall report the development error `CANTRCV_E_NO_TRCV_CONTROL` and return `E_NOT_OK`. ⌋()

[CanTrcv124] ⌈ If development error detection for the module CanTrcv is enabled: If called before the CanTrcv module has been initialized, the function `CanTrcv_GetOpMode` shall raise the development error `CANTRCV_E_UNINIT` and return `E_NOT_OK`. ⌋()

[CanTrcv129] ⌈ If development error detection for the module CanTrcv is enabled: If called with an invalid Transceiver number, the function `CanTrcv_GetOpMode` shall raise the development error `CANTRCV_E_INVALID_TRANSCEIVER` and return `E_NOT_OK.` ⌋()

[CanTrcv132] ⌈ If development error detection for the module CanTrcv is enabled: If called with OpMode = NULL, the function `CanTrcv_GetOpMode` shall raise the development error `CANTRCV_E_PARAM_POINTER` and return `E_NOT_OK`. ⌋()

8.3.4 CanTrcv_GetBusWuReason

[CanTrcv007]

⌈

Service name:	CanTrcv_GetBusWuReason	
Syntax:	`Std_ReturnType CanTrcv_GetBusWuReason( uint8 Transceiver, CanTrcv_TrcvWakeupReasonType* reason )`	
Service ID[hex]:	0x03	
Sync/Async:	Synchronous	
Reentrancy:	Reentrant	
Parameters (in):	Transceiver	CAN transceiver to which API call has to be applied.
Parameters (in-out):	None	
Parameters (out):	reason	Pointer to wake up reason of the bus the API is applied to.
Return value:	Std_ReturnType	E_OK: will be returned if the transceiver wakeup reason was provided. E_NOT_OK: will be returned if the service request failed due to development errors OR the transceiver wakeup reason is not defined in CanTrcv_TrcvWakeupReasonType.
Description:	Gets the wakeup reason for the Transceiver and returns it in parameter Reason.	

⌋(BSW00310, BSW00329, BSW00369, BSW00371, BSW00375, BSW00377, BSW00406, BSW01091, BSW01095, BSW01097, BSW01103, BSW01106, BSW01109, BSW01110)

[CanTrcv107] ⌈ The function CanTrcv_GetBusWuReason shall collect the reason for the wake up that the CAN transceiver has detected in the parameter Reason. ⌋()

The ability to detect and differentiate the possible wake up reasons depends strongly on the CAN transceiver hardware.

Be aware if more than one bus is available, each bus may report a different wake up reason. E.g. if an ECU has CAN, a wake up by CAN may occur and the incoming data may cause an internal wake up for another CAN bus.
The CAN transceiver driver has a “per bus” view and does not vote the more important reason or sequence internally. The same may be true if e.g. one transceiver controls the power supply and the other is just powered or un-powered.

The number of supported busses is statically set in the configuration phase.

[CanTrcv116] ⌈ If there is no/incorrect communication to the transceiver, the function `CanTrcv_GetBusWuReason` shall report the development error `CANTRCV_E_NO_TRCV_CONTROL` and return `E_OK`. ⌋()

[CanTrcv125] ⌈ If development error detection for the module CanTrcv is enabled: If called before the CanTrcv module has been initialized, the function `CanTrcv_GetBusWuReason` shall raise development error `CANTRCV_E_UNINIT` and return `E_NOT_OK`. ⌋()

[CanTrcv130] ⌈ If development error detection for the module CanTrcv is enabled: If called with an invalid Transceiver number, the function `CanTrcv_GetBusWuReason` shall raise development error `CANTRCV_E_INVALID_TRANSCEIVER` and return `E_NOT_OK.` ⌋()

[CanTrcv133] ⌈ If development error detection for the module CanTrcv is enabled: If called with Reason = NULL, the function `CanTrcv_GetBusWuReason` shall raise the development error `CANTRCV_E_PARAM_POINTER` and return `E_NOT_OK`. ⌋()

8.3.5 CanTrcv_GetVersionInfo

[CanTrcv008]

⌈

Service name:	CanTrcv_GetVersionInfo	
Syntax:	`void CanTrcv_GetVersionInfo( Std_VersionInfoType* versioninfo )`	
Service ID[hex]:	0x04	
Sync/Async:	Synchronous	
Reentrancy:	Reentrant	
Parameters (in):	None	
Parameters (in-out):	None	
Parameters (out):	versioninfo	Pointer to version information of this module.
Return value:	None	
Description:	Gets the version of the module and returns it in VersionInfo.	

⌋(BSW00310, BSW00329, BSW00369, BSW00371, BSW00406, BSW00407, BSW00411)

[CanTrcv108] ⌈ The function `CanTrcv_GetVersionInfo` shall return the version information of this module. The version information includes:

- Module Id
- Vendor Id
- Vendor specific version numbers ⌋(BSW00374, BSW00379)

[CanTrcv109] ⌈ The function `CanTrcv_GetVersionInfo` shall be pre-compile time configurable On/Off by the configuration parameter `CanTrcvGetVersionInfo`. ⌋()

[CanTrcv110] ⌈ If source code for caller and callee of this function is available, the CanTrcv module should realize this function as a macro defined in the module's header file. ⌋()

[CanTrcv134] ⌈ If development error detection for the module CanTrcv is enabled: If called with VersionInfo = NULL, the function `CanTrcv_GetVersionInfo` shall raise development error `CANTRCV_E_PARAM_POINTER`. ⌋()

8.3.6 CanTrcv_ SetWakeupMode

[CanTrcv009]

⌈

Service name:	CanTrcv_SetWakeupMode	
Syntax:	`Std_ReturnType CanTrcv_SetWakeupMode( uint8 Transceiver, CanTrcv_TrcvWakeupModeType TrcvWakeupMode )`	
Service ID[hex]:	0x05	
Sync/Async:	Synchronous	
Reentrancy:	Reentrant for different transceivers	
Parameters (in):	Transceiver	CAN transceiver to which API call has to be applied.
	TrcvWakeupMode	Requested transceiver wakeup reason
Parameters (in-out):	None	
Parameters (out):	None	
Return value:	Std_ReturnType	E_OK: Will be returned, if the wakeup state has been changed to the requested mode. E_NOT_OK: Will be returned, if the wakeup state change has failed or the parameter is out of the allowed range. The previous state has not been changed.
Description:	Enables, disables or clears wake-up events of the Transceiver according to TrcvWakeupMode.	

⌋(BSW00310, BSW00329, BSW00369, BSW00371, BSW00406, BSW01091, BSW01097, BSW01109, BSW01110, BSW01115)

[CanTrcv111] ⌈ **Enabled:** If the function `CanTrcv_SetWakeupMode` is called with TrcvWakupMode = CANTRCV_ WUMODE_ENABLE and if the CanTrcv module has a stored wakeup event pending for the addressed bus, the CanTrcv module shall update its wakeup event as 'present'. ⌋()

[CanTrcv093] ⌈ **Disabled:** If the function `CanTrcv_SetWakeupMode` is called with

TrcvWakeupMode = CANTRCV_ WUMODE_DISABLE, the wakeup events are disabled on the addressed transceiver. It is required by the transceiver device and the transceiver driver to detect the wakeup events and store it internally, in order to raise the wakeup events when the wakeup mode is enabled again. ⌋(BSW00388, BSW00389, BSW00390, BSW00391, BSW00392, BSW00393, BSW00394, BSW00395, BSW00408, BSW160, BSW01090)

[CanTrcv094] ⌈ **Clear:** If the function `CanTrcv_SetWakeupMode` is called with TrcvWakeupMode = CANTRCV_ WUMODE_CLEAR, then a stored wakeup event is cleared on the addressed transceiver. ⌋()

[CanTrcv150] ⌈ Clearing of wakeup events have to be used when the wake up notification is disabled to clear all stored wake up events under control of the higher layer. ⌋()

[CanTrcv095] ⌈ The implementation can enable, disable or clear wake up events from the last communication cycle. It is very important not to lose wake up events during the disabled period. ⌋(BSW00388, BSW00389, BSW00390, BSW00391, BSW00392, BSW00393, BSW00394, BSW00395, BSW00408, BSW160, BSW01090)

The number of supported busses is statically set in the configuration phase.

[CanTrcv117] ⌈ If there is no/incorrect communication to the transceiver, the function `CanTrcv_SetWakeupMode` shall report the development error `CANTRCV_E_NO_TRCV_CONTROL` and return `E_NOT_OK`. ⌋()

[CanTrcv127] ⌈ If development error detection for the module CanTrcv is enabled: If called before the CanTrcv has been initialized, the function `CanTrcv_SetWakeupMode` shall raise development error `CANTRCV_E_UNINIT` and return `E_NOT_OK`. ⌋()

[CanTrcv131] ⌈ If development error detection for the module CanTrcv is enabled: If called with an invalid Transceiver number, the function `CanTrcv_SetWakeupMode` shall raise development error `CANTRCV_E_INVALID_TRANSCEIVER` and return `E_NOT_OK`. ⌋()

[CanTrcv089] ⌈ If development error detection for the module CanTrcv is enabled: If called with an invalid TrcvWakeupMode, the function `CanTrcv_SetWakeupMode` shall raise the development error CANTRCV_E_PARAM_TRCV_WAKEUP_MODE and return `E_NOT_OK`. ⌋()

8.3.7 CanTrcv_GetTrcvSystemData

[**CanTrcv213**]

Service name:	CanTrcv_GetTrcvSystemData	

Syntax:	`Std_ReturnType CanTrcv_GetTrcvSystemData(`
	`  uint8 Transceiver,`
	`  const uint32* TrcvSysData`
	`)`	

Service ID[hex]:	0x09	
Sync/Async:	Synchronous	
Reentrancy:	Non Reentrant	
Parameters (in):	Transceiver	CAN transceiver ID.
Parameters (in-out):	None	
Parameters (out):	TrcvSysData	Configuration/Status data of the transceiver.
Return value:	Std_ReturnType	E_OK: will be returned if the transceiver status is successfully read. E_NOT_OK: will be returned if the transceiver status data is not available or a development error occurs.
Description:	Reads the transceiver configuration/status data and returns it through parameter TrcvSysData. This API shall exist only if CanTrcvHwPnSupport = TRUE.	

[CanTrcv189]: The function `CanTrcv_GetTrcvSystemData` shall read the configuration/status of the CAN transceiver and store the read data in the out parameter `TrcvSysData`. If this is successful, `E_OK` shall be returned.

Hint: This API can be invoked through diagnostic services or during initialization to determine the transceiver status and its availability.

Note: Currently an agreement on the parameter set for the transceiver HW specification has not been reached. For this reason, the diagnostic data is now returned as a uint32 (as stored in the transceiver registers). When a definitive and standard parameter set is defined, a data structure may be defined for abstracting the diagnostic data.

[CanTrcv190]: If there is no/incorrect communication to the transceiver, the function `CanTrcv_GetTrcvSystemData` shall report the development error `CANTRCV_E_NO_TRCV_CONTROL` and return `E_NOT_OK`.

[CanTrcv191]: If DET is enabled for the CanTrcv module: if called before the CanTrcv has been initialized, the function `CanTrcv_GetTrcvSystemData` shall raise development error `CANTRCV_E_UNINIT` and return `E_NOT_OK`.

[CanTrcv192]: If DET is enabled for the CanTrcv module: if called with an invalid transceiver ID for parameter `Transceiver`, function `CanTrcv_GetTrcvSystemData` shall raise the development error `CANTRCV_E_INVALID_TRANSCEIVER` and return `E_NOT_OK`.

[CanTrcv193]: If DET is enabled for the CanTrcv module: if called with NULL pointer for parameter `TrcvSysData`, function `CanTrcv_GetTrcvSystemData` shall raise the development error `CANTRCV_E_PARAM_POINTER` and return `E_NOT_OK`.

8.3.8 CanTrcv_ClearTrcvWufFlag

[**CanTrcv214**]

Service name:	CanTrcv_ClearTrcvWufFlag	
Syntax:	`Std_ReturnType CanTrcv_ClearTrcvWufFlag( uint8 Transceiver )`	
Service ID[hex]:	0x0a	
Sync/Async:	Synchronous	
Reentrancy:	Reentrant for different transceivers	
Parameters (in):	Transceiver	CAN Transceiver ID.
Parameters (in-out):	None	
Parameters (out):	None	
Return value:	Std_ReturnType	E_OK: will be returned if the WUF flag has been cleared. E_NOT_OK: will be returned if the WUF flag has not been cleared or a development error occurs.
Description:	Clears the WUF flag in the transceiver hardware. This API shall exist only if CanTrcvHwPnSupport = TRUE.	

[CanTrcv194]: The function `CanTrcv_ClearTrcvWufFlag` shall clear the wakeup flag in the CAN transceiver. If successful, `E_OK` shall be returned.

Implementation Hints:

This API shall be used by the CanSM module for ensuring that no frame wakeup event is lost, during entering a low-power mode. This API clears the WUF flag.

The CAN transceiver shall be shall be put into Standby mode (`CANTRCV_STANDBY`) after clearing of the WUF flag.

If a system error (SYSERR, e.g. configuration error) occurs while selective wakeup functionality is being enabled, transceiver will disable the functionality. Transceiver will wake up on the next CAN wake pattern (WUP).
In case of any other hardware error (e.g. frame detection error), transceiver will wake up if the error counter inside the transceiver overflows.

[CanTrcv195]: CanTrcv shall inform CanIf that the wakeup flag has been cleared for the requested `Transceiver`, through the callback notification `CanIf_ClearTrcvWufFlagIndication`.

[CanTrcv196]: If there is no/incorrect communication to the transceiver, the function `CanTrcv_ClearTrcvWufFlag` shall report the development error `CANTRCV_E_NO_TRCV_CONTROL` and return `E_NOT_OK`.

[CanTrcv197]: If DET is enabled for the CanTrcv module: if called before the CanTrcv has been initialized, the function `CanTrcv_ClearTrcvWufFlag` shall raise development error `CANTRCV_E_UNINIT` and return `E_NOT_OK`

[CanTrcv198]: If DET is enabled for the CanTrcv module: if called with an invalid transceiver ID for parameter `Transceiver`, function `CanTrcv_ClearTrcvWufFlag` shall raise the development error `CANTRCV_E_INVALID_TRANSCEIVER` and return `E_NOT_OK`.

8.3.9 CanTrcv_ReadTrcvTimeoutFlag

[**CanTrcv215**]

Service name:	CanTrcv_ReadTrcvTimeoutFlag	
Syntax:	`Std_ReturnType CanTrcv_ReadTrcvTimeoutFlag( uint8 Transceiver, CanTrcv_TrcvFlagStateType* FlagState )`	
Service ID[hex]:	0x0b	
Sync/Async:	Synchronous	
Reentrancy:	Non Reentrant	
Parameters (in):	Transceiver	CAN transceiver ID.
Parameters (in-out):	None	
Parameters (out):	FlagState	State of the timeout flag.
Return value:	Std_ReturnType	E_OK: Will be returned, if status of the timeout flag is successfully read. E_NOT_OK: Will be returned, if status of the timeout flag could not be read.
Description:	Reads the status of the timeout flag from the transceiver hardware. This API shall exist only if CanTrcvHwPnSupport = TRUE.	

[CanTrcv199]: If DET for the module CanTrcv is enabled: If called with an invalid transceiver ID `Transceiver`, the function `CanTrcv_ReadTrcvTimeoutFlag` shall raise the development error `CANTRCV_E_INVALID_TRANSCEIVER` and return `E_NOT_OK.`

[CanTrcv200]: If DET for the module CanTrcv is enabled: If called with `FlagState = NULL`, the function `CanTrcv_ReadTrcvTimeoutFlag` shall raise the development error `CANTRCV_E_PARAM_POINTER` and return `E_NOT_OK`.

8.3.10 CanTrcv_ClearTrcvTimeoutFlag

[**CanTrcv216**]

Service name:	CanTrcv_ClearTrcvTimeoutFlag
Syntax:	`Std_ReturnType CanTrcv_ClearTrcvTimeoutFlag(`

	`uint8 Transceiver`)	
Service ID[hex]:	0x0c	
Sync/Async:	Synchronous	
Reentrancy:	Non Reentrant	
Parameters (in):	Transceiver	CAN transceiver ID.
Parameters (in-out):	None	
Parameters (out):	None	
Return value:	Std_ReturnType	E_OK: Will be returned, if the timeout flag is successfully cleared. E_NOT_OK: Will be returned, if the timeout flag could not be cleared.
Description:	Clears the status of the timeout flag in the transceiver hardware. This API shall exist only if CanTrcvHwPnSupport = TRUE.	

[CanTrcv201]: If DET for the module CanTrcv is enabled: If called with an invalid transceiver ID `Transceiver`, the function `CanTrcv_ClearTrcvTimeoutFlag` shall raise the development error `CANTRCV_E_INVALID_TRANSCEIVER` and return `E_NOT_OK`.

8.3.11 CanTrcv_ReadTrcvSilenceFlag

[**CanTrcv217**]

Service name:	CanTrcv_ReadTrcvSilenceFlag	

Syntax:	`Std_ReturnType CanTrcv_ReadTrcvSilenceFlag(`
	`  uint8 Transceiver,`
	`  CanTrcv_TrcvFlagStateType* FlagState`
	)	

Service ID[hex]:	0x0d	
Sync/Async:	Synchronous	
Reentrancy:	Non Reentrant	
Parameters (in):	Transceiver	CAN transceiver ID.
Parameters (in-out):	None	
Parameters (out):	FlagState	State of the silence flag.
Return value:	Std_ReturnType	E_OK: Will be returned, if status of the silence flag is successfully read. E_NOT_OK: Will be returned, if status of the silence flag could not be read.
Description:	Reads the status of the silence flag from the transceiver hardware. This API shall exist only if CanTrcvHwPnSupport = TRUE.	

[CanTrcv202]: If DET for the module CanTrcv is enabled: If called with an invalid transceiver ID `Transceiver`, the function `CanTrcv_ReadTrcvSilenceFlag` shall raise the development error `CANTRCV_E_INVALID_TRANSCEIVER` and return `E_NOT_OK`.

[CanTrcv203]: If DET for the module CanTrcv is enabled: If called with `FlagState = NULL`, the function `CanTrcv_ReadTrcvSilenceFlag` shall raise the development error `CANTRCV_E_PARAM_POINTER` and return `E_NOT_OK`.

8.3.12 CanTrcv_CheckWakeup

[CanTrcv143]

⌜

Service name:	CanTrcv_CheckWakeup	
Syntax:	`Std_ReturnType CanTrcv_CheckWakeup( uint8 Transceiver )`	
Service ID[hex]:	0x07	
Sync/Async:	Synchronous	
Reentrancy:	Reentrant	
Parameters (in):	Transceiver	CAN transceiver to which API call has to be applied.
Parameters (in-out):	None	
Parameters (out):	None	
Return value:	Std_ReturnType	E_OK when a valid interrupt is detected E_NOT_OK when a no interrupt is detected
Description:	Service is called by underlying CANIF in case a wake up interrupt is detected.	

⌟()

[CanTrcv144] ⌜ If development error detection for the module CanTrcv is enabled: If called before the CanTrcv module has been initialized, the function `CanTrcv_CheckWakeup` shall raise the development error `CANTRCV_E_UNINIT` and return `E_NOT_OK`. ⌟()

[CanTrcv145] ⌜ If development error detection for the module CanTrcv is enabled: If called with an invalid Transceiver number, the function `CanTrcv_CheckWakeup` shall raise the development error `CANTRCV_E_INVALID_TRANSCEIVER` and return `E_NOT_OK`. ⌟()

[CanTrcv146] ⌜ This function notifies the calling function if a wakeup is detected in the Transceiver by returning E_OK else returns E_NOT_OK. ⌟()

8.3.13 CanTrcv_SetPNActivationState

[**CanTrcv219**]

Service name:	CanTrcv_SetPNActivationState
Syntax:	`Std_ReturnType CanTrcv_SetPNActivationState( CanTrcv_PNActivationType ActivationState )`

Service ID[hex]:	0x0f	
Sync/Async:	Synchronous	
Reentrancy:	Non Reentrant	
Parameters (in):	ActivationState	PN_ENABLED: PN wakeup functionality in CanTrcv shall be enabled. PN_DIABLED: PN wakeup functionality in CanTrcv shall be disabled.
Parameters (in-out):	None	
Parameters (out):	None	
Return value:	Std_ReturnType	E_OK: Will be returned, if the PN has been changed to the requested configuration. E_NOT_OK: Will be returned, if the PN configuration change has failed. The previous configuration has not been changed.
Description:	The API configures the wake-up of the transceiver for Standby and Sleep Mode: Either the CAN transceiver is woken up by a remote wake-up pattern (standard CAN wake-up) or by the configured remote wake-up frame.	

[**CanTrcv220**] If development error detection for the module CanTrcv is enabled: If called before the CanTrcv module has been initialized, the function CanTrcv_SetPNActivationState shall raise the development error CANTRCV_E_UNINIT and return E_NOT_OK.

[**CanTrcv221**] CanTrcv shall enable the PN wakeup functionality when function CanTrcv_SetPNActivationState is called with ActivationState= PN_ENABLED and return E_OK.

[**CanTrcv222**] CanTrcv shall disable the PN wakeup functionality when function CanTrcv_SetPNActivationState is called with ActivationState= PN_DISABLED and return E_OK.

8.3.14 CanTrcv_CheckWakeFlag

[**CanTrcv223**]「」()

Service name:	CanTrcv_CheckWakeFlag	

Syntax:	`Std_ReturnType CanTrcv_CheckWakeFlag(`
	`  uint8 Transceiver`
	`)`	

Service ID[hex]:	0x0e	
Sync/Async:	Synchronous	
Reentrancy:	Non Reentrant	
Parameters (in):	Transceiver	CAN transceiver ID.
Parameters (in-out):	None	
Parameters (out):	None	
Return value:	Std_ReturnType	E_OK: Will be returned, if the request for checking the wakeup flag has been accepted. E_NOT_OK: Will be returned, if the request for checking the wakeup flag has not been accepted.
Description:	Requests to check the status of the wakeup flag from the transceiver hardware.	

[**CanTrcv224**]⌈ ⌋() CanTrcv shall inform CanIf that a wakeup has been detected in the requested `Transceiver`, through the callback notification `CanIf_CheckTrcvWakeFlagIndication`.

[**CanTrcv225**]⌈ ⌋() If DET for the module CanTrcv is enabled: If called with an invalid transceiver ID Transceiver, the function `CanTrcv_CheckWakeFlag` shall raise the development error `CANTRCV_E_INVALID_TRANSCEIVER` and return `E_NOT_OK`.

8.4 Scheduled functions

This chaper lists all functions provided by the CanTrcv module and called directly by the Basic Software Module Scheduler.

8.4.1 CanTrcv_MainFunction

[CanTrcv013]

⌈

Service name:	CanTrcv_MainFunction

Syntax:	`void CanTrcv_MainFunction(`
	`  void`
	`)`

Service ID[hex]:	0x06
Timing:	FIXED_CYCLIC
Description:	Service to scan all busses for wake up events and perform these event.

⌋(BSW00310, BSW00329, BSW00369, BSW00371, BSW00373, BSW00376, BSW00406, BSW00424, BSW00428, BSW171, BSW172, BSW01097, BSW01109, BSW01110)

The CAN bus transceiver driver may have cyclic jobs like polling for wake up events (if configured).

[CanTrcv112] ⌈ The `CanTrcv_MainFunction` shall scan all busses in STANDBY and SLEEP for wake up events.
This function shall set a wake-up event flag to perform these events. ⌋(BSW00343)

According to [BSW00424], main processing functions shall be allocated by basic tasks. No special call order to be kept. This function is directly called by Basic Software Scheduler.

See configuration parameter `CanTrcvWakeUpSupport`.

[CanTrcv128] ⌈ If development error detection for the module CanTrcv is enabled: If called before the CanTrcv has been initialized, the function `CanTrcv_MainFunction` shall raise development error `CANTRCV_E_UNINIT`. ⌋()

8.4.2 CanTrcv_MainFunctionDiagnostics

[CanTrcv218]

Service name:	CanTrcv_MainFunctionDiagnostics
Syntax:	`void CanTrcv_MainFunctionDiagnostics( void )`
Service ID[hex]:	0x08
Timing:	FIXED_CYCLIC
Description:	Reads the transceiver diagnostic status periodically and sets product/development accordingly.

[CanTrcv204]: The cyclic function `CanTrcv_MainFunctionDiagnostics` shall read the transceiver status periodically and report production/development errors accordingly.

[CanTrcv205]: The cyclic function `CanTrcv_MainFunctionDiagnostics` shall exist only if `CanTrcvBusErrFlag = TRUE`.

[CanTrcv206]: If configured and supported by hardware: if the BUSERR flag is set, function `CanTrcv_MainFunctionDiagnostics` shall set the production error `CANTRCV_E_BUS_ERROR`.

[CanTrcv207]: If DET for the module CanTrcv is enabled: If called before the CanTrcv has been initialized, the function `CanTrcv_MainFunctionDiagnostics` shall raise development error `CANTRCV_E_UNINIT`.

8.5 Call-back notifications

Since the CanTrcv is a driver module, it doesn't provide any callback functions for lower layer modules.

8.6 Expected Interfaces

This chapter lists all functions the module CanTrcv requires from other modules.

8.6.1 Mandatory Interfaces

This chapter defines all interfaces which are required to fulfill the core functionality of the module.

[CanTrcv085]

⌈

API function	*Description*
CanIf_TrcvModeIndication	This service indicates a transceiver state transition referring to the corresponding CAN transceiver.

⌋(BSW00370)

8.6.2 Optional Interfaces

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

[CanTrcv086]

⌈

API function	*Description*
CanIf_CheckTrcvWakeFlagIndication	This service indicates the reason for the wake up that the CAN transceiver has detected.
CanIf_ClearTrcvWufFlagIndication	This service indicates that the transceiver has cleared the Wuf-Flag.
CanIf_ConfirmPnAvailability	This service indicates that the transceiver is running in PN communication mode.
Det_ReportError	Service to report development errors.
Dio_ReadChannel	Returns the value of the specified DIO channel.
Dio_ReadChannelGroup	This Service reads a subset of the adjoining bits of a port.
Dio_ReadPort	Returns the level of all channels of that port.
Dio_WriteChannel	Service to set a level of a channel.
Dio_WriteChannelGroup	Service to set a subset of the adjoining bits of a port to a specified level.
Dio_WritePort	Service to set a value of the port.
Icu_DisableNotification	This function disables the notification of a channel.
Icu_EnableNotification	This function enables the notification on the given channel.
Spi_GetStatus	Service returns the SPI Handler/Driver software module status.
Spi_ReadIB	Service for reading synchronously one or more data from an IB SPI Handler/Driver Channel specified by parameter.
Spi_SetupEB	Service to setup the buffers and the length of data for the EB SPI Handler/Driver Channel specified.
Spi_SyncTransmit	Service to transmit data on the SPI bus
Spi_WriteIB	Service for writing one or more data to an IB SPI Handler/Driver Channel specified by parameter.

⌋()

1. The interfaces of the SPI module are used by the CanTrcv module if there are instances of the container CanTrcvSpiSequence.

2. The interfaces of the DIO module are used by the CanTrcv module if there are instances of the container CanTransceiverDIOAccess.

Note: If the Can transceiver is controlled via Dio/Spi, the Dio/Spi interfaces are required to fulfill the core functionality of the module. Which interfaces are needed exactly shall not be detailed further in this specification

8.6.3 Configurable interfaces

There are no configurable interfaces for CAN transceiver driver.

9 Sequence diagram

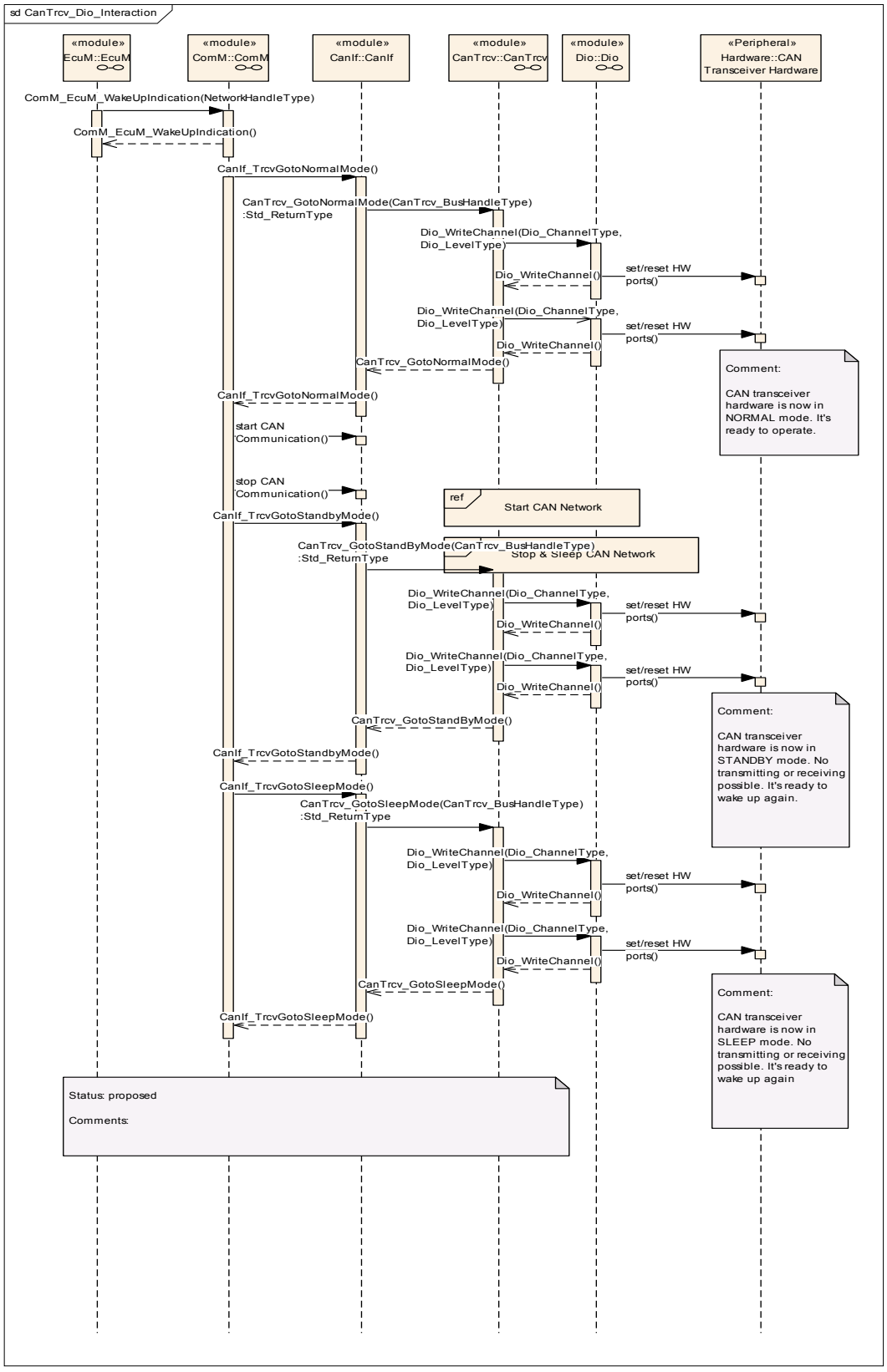
The focus of the following diagrams is on the interaction between the CAN transceiver driver and the BSW modules CanIf, ComM, EcuM and Dio. Depending on the CAN transceiver hardware, one or more calls to `Dio_WriteChannels` may be necessary.

Depending on the transceiver hardware, there may be a need of wait states for some transitions.

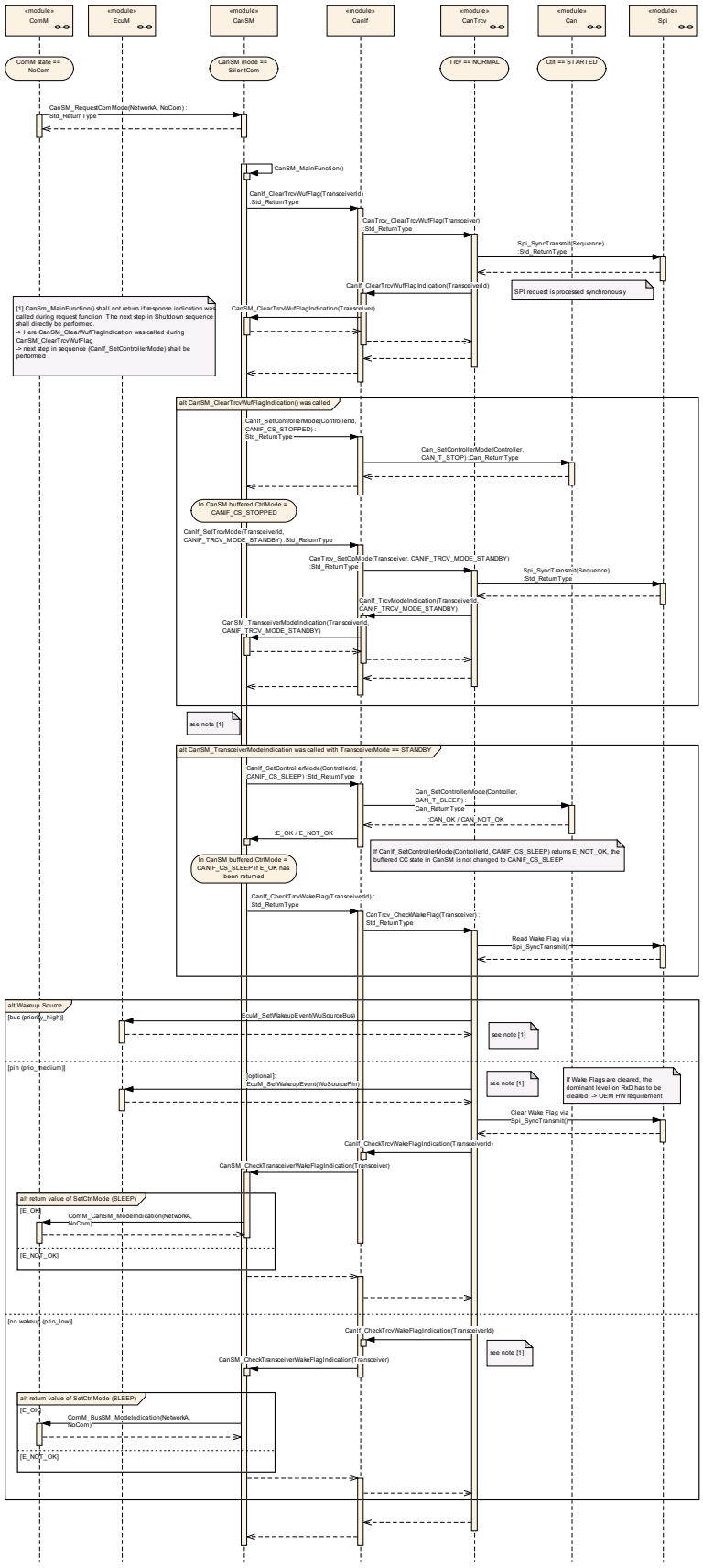
9.1 Wake up with valid validation

For all wakeup related sequence diagrams please refer to chapter 9 of ECU State Manager.

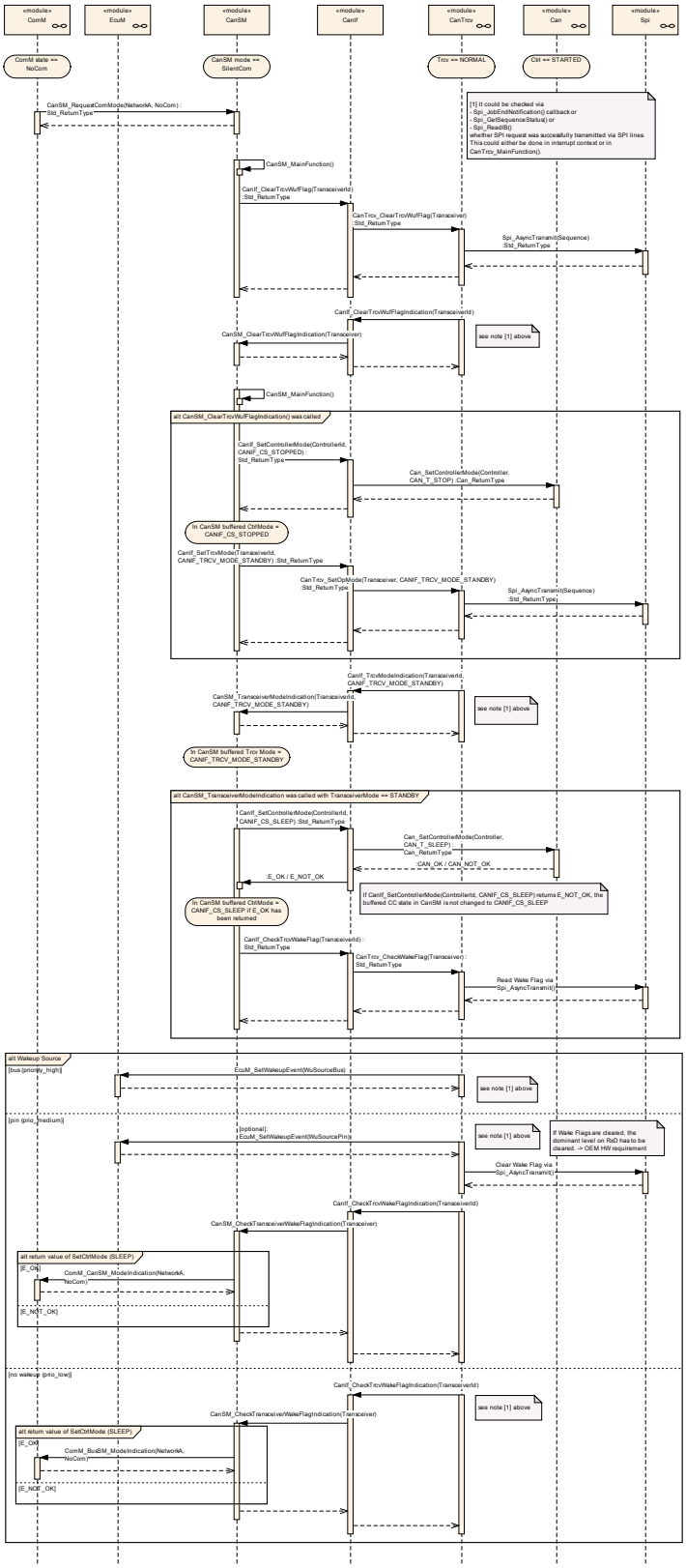
9.2 Interaction with DIO module



9.3 De-Initialization (SPI Synchronous)



9.4 De-Initialization (SPI Asynchronous)



10 Configuration specification

In general this chapter defines configuration parameters and their clustering into containers. In order to support the specification Chapter 10.1 describes fundamentals.

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

Chapter 0 specifies published information of the module CanTrcv.

10.1 How to read this chapter

In addition to this section, it is highly recommended to read the documents:

- AUTOSAR Layered Software Architecture [2]
- AUTOSAR ECU Configuration Specification [3]
  This document describes the AUTOSAR configuration methodology and the AUTOSAR configuration metamodel in detail.

The following is only a short survey of the topic and it will not replace the ECU Configuration Specification document.

10.1.1 Configuration class and configuration parameters

Configuration parameters define the variability of the generic part(s) of an onfiguretation of a module. This means that only generic or configurable module implementation can be adapted to the environment (software/hardware) in use during system and/or ECU configuration.

The configuration of parameters can be achieved at different times during the software process: before compile time, before link time or after build time. In the following, the term “configuration class” (of a parameter) shall be used in order to refer to a specific configuration point in time.

10.1.2 Variants

Variants describe sets of configuration parameters. E.g., variant 1: only pre-compile time configuration parameters; variant 2: mix of pre-compile- and post build time-configuration parameters. In one variant a parameter can only be of one onfiguretion class.

Each Variant must have a unique name which could be referenced to in later chapters. The maximum number of allowed variants is 3.

10.1.3 Containers

Containers structure the set of configuration parameters. This means:

- *all* configuration parameters are kept in containers.
- (sub-) containers can reference (sub-) containers. It is possible to assign a multiplicity to these references. The multiplicity then defines the possible number of instances of the contained parameters.

Configuration parameters shall be clustered into a container whenever

- the configuration parameters logically belong together (e.g. general parameters which are valid for the entire module NVRAM manager)
- the configuration parameters need to be instantiated (e.g. parameters of the memory block specification of the NVRAM manager – those parameters must be instantiated for each memory block)

10.2 Containers and configuration parameters

The following chapters summarize all configuration parameters. The detailed meanings of the parameters are described in preeding hapters.

10.2.1 Variants

Currently VARIANT-PRE-COMPILE variant is defined for CanTrcv.

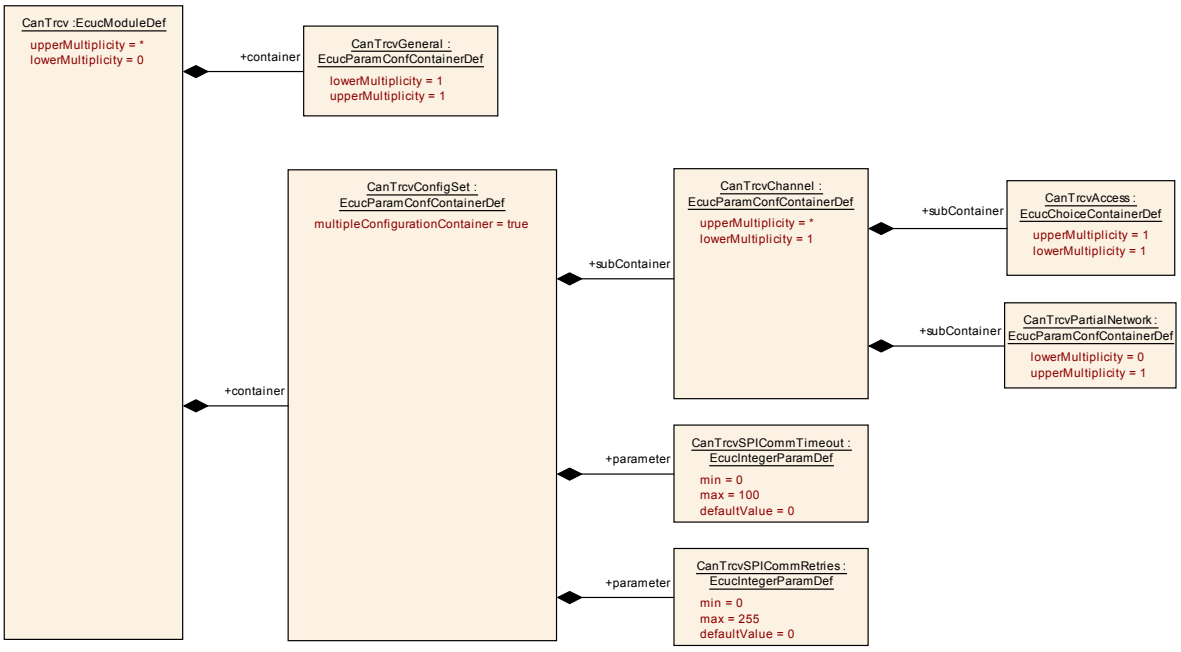
VARIANT-PRE-COMPILE:Only parameters with “Pre-compile time" configuration are allowed in this variant

[CanTrcv017] ⌈ Only Pre-compile time configuration is allowed. Thus only VARIANT-PRE-COMPILE is allowed. ⌋(BSW00396, BSW01091)

10.2.2 CanTrcv

Module Name	*CanTrcv*
Module Description	Configuration of the CanTrcv (CAN Transceiver driver) module.

Included Containers		
Container Name	***Multiplicity***	***Scope / Dependency***
CanTrcvConfigSet	1	This is the multiple configuration set container for CAN Transceiver.
CanTrcvGeneral	1	Container gives CAN transceiver driver basic information.



10.2.3 CanTrcvGeneral

SWS Item	**CanTrcv090_Conf :**		
Container Name	CanTrcvGeneral		
Description	Container gives CAN transceiver driver basic information.		
Configuration Parameters			

SWS Item	**CanTrcv152_Conf :**		
Name	CanTrcvDevErrorDetect {CANTRCV_DEV_ERROR_DETECT}		
Description	Switches development error detection and notification on and off. If switched on, #define CANTRCV_DEV _ERROR_DETECT ON shall be generated. If switched off, #define CANTRCV_DEV_ERROR _DETECT OFF shall be generated. Define shall be part of file CanTrcv_Cfg.h.		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	--		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Module		

SWS Item	**CanTrcv153_Conf :**		
Name	CanTrcvGetVersionInfo {CANTRCV_GET_VERSION_INFO}		
Description	Switches version information API on and off. If switched off, function need not be present in compiled code.		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	false		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Module		

SWS Item	**CanTrcv179_Conf :**		
Name	CanTrcvSPICommRetries		
Description	Indicates the maximal number of communication retries in case of failed SPI communication (applies both to timed out communication and to errors/NACK in the response data). (0 ... 255 times, 0 means no retry allowed, communication must succeed at first try)		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 255		
Default value	0		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Local dependency: This parameter exists inly if a SPI Sequence is referenced in SPIREF.		

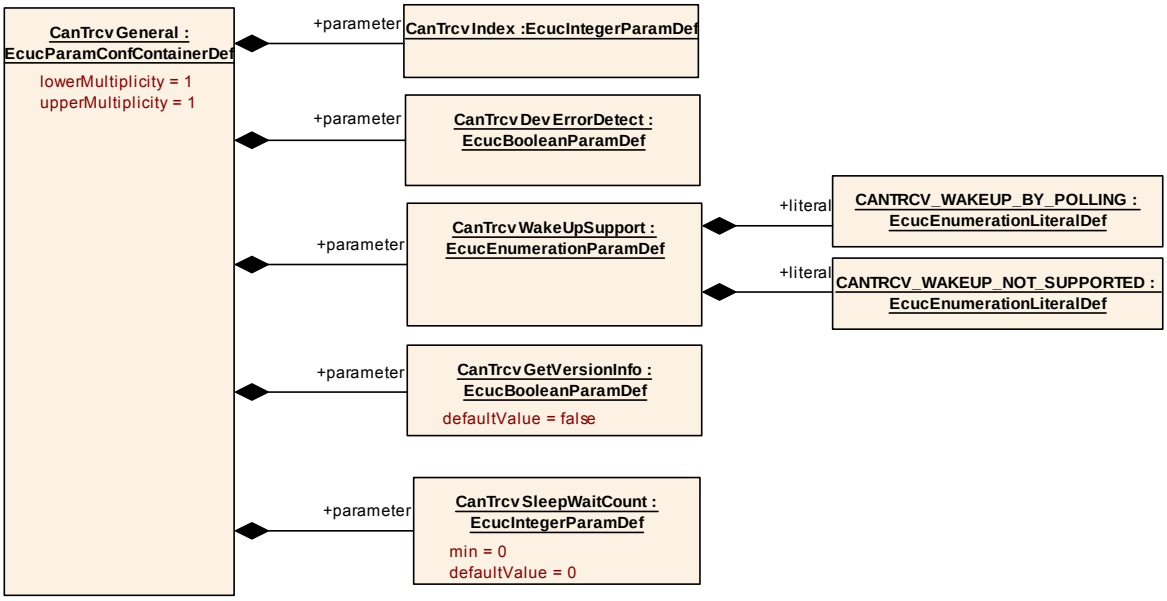
SWS Item	**CanTrcv178_Conf :**
Name	CanTrcvSPICommTimeout
Description	Indicates the maximal time allowed to the Transceiver in order to reply (either positively or negatively) to a SPI command. (value in ms, 0ms means no specific timeout is to be used, communication is executed at the best of the SPI HW capacity)

Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 100		
Default value	0		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Local dependency: This parameter exists only if a SPI Sequence is referenced in CanTrcvSpiSequence.		

SWS Item	**CanTrcv156_Conf :**		
Name	CanTrcvWaitCount		
Description	Indicates the number of wait states to change the transceiver operation mode. Transceiver hardware may need wait states for some transitions.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 4294967295		
Default value	0		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Module		

SWS Item	**CanTrcv154_Conf :**		
Name	CanTrcvWakeUpSupport {CANTRCV_GENERAL_WAKE_UP_SUPPORT}		
Description	Informs whether wake up is supported by polling or not supported. In case no wake up is supported by the hardware, setting has to be NOT_SUPPORTED. Only in the case of wake up supported by polling, function CanTrcv_MainFunction has to be present and to be invoked by the scheduler.		
Multiplicity	1		
Type	EcucEnumerationParamDef		
Range	CANTRCV_WAKEUP_BY_POLLING	Wake up by polling	
	CANTRCV_WAKEUP_NOT_SUPPORTED	Wake up is not supported	
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Module dependency: CanTrcvWakeupByBusUsed		

No Included Containers



10.2.4 CanTrcvChannel

SWS Item	**CanTrcv143_Conf :**
Container Name	CanTrcvChannel{CanTranceiverChannels}
Description	Container gives CAN transceiver driver information about a single CAN transceiver (channel).
Configuration Parameters	

SWS Item	**CanTrcv155_Conf :**		
Name	CanTrcvChannelId {CANTRCV_CHANNEL_ID}		
Description	Unique identifier of the CAN Transceiver Channel.		
Multiplicity	1		
Type	EcucIntegerParamDef (Symbolic Name generated for this parameter)		
Range	0 .. 255		
Default value	--		
ConfigurationClass	*Pre-compile time*	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: ECU		

SWS Item	**CanTrcv096_Conf :**		
Name	CanTrcvChannelUsed {CANTRCV_CHANNEL_USED}		
Description	Shall the related CAN transceiver channel be used?		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	true		
ConfigurationClass	*Pre-compile time*	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Instance		

SWS Item	**CanTrcv097_Conf :**
Name	CanTrcvControlsPowerSupply {CANTRCV_CONTROLS_POWER_SUPPLY}
Description	Is ECU power supply controlled by this transceiver? TRUE = Controlled by transceiver. FALSE = Not controlled by transceiver.
Multiplicity	1

Type	EcucBooleanParamDef		
Default value	false		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Instance		

SWS Item	**CanTrcv160_Conf :**		
Name	CanTrcvHwPnSupport {CANTRCV_HW_PN_SUPPORT}		
Description	Indicates whether the HW supports the selective wake-up function TRUE = Selective wakeup feature is supported by the transceiver FALSE = Selective wakeup functionality is not available in transceiver		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	false		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Local dependency: CanTrcvWakeUpSupport		

SWS Item	**CanTrcv146_Conf :**		
Name	CanTrcvInitState {CANTRCV_INIT_STATE}		
Description	State of CAN transceiver after call to CanTrcv_Init.		
Multiplicity	1		
Type	EcucEnumerationParamDef		
Range	CANTRCV_OP_MODE_NORMAL	Normal operation mode (default)	
	CANTRCV_OP_MODE_SLEEP	Sleep operation mode	
	CANTRCV_OP_MODE_STANDBY	Standby operation mode	
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Instance		

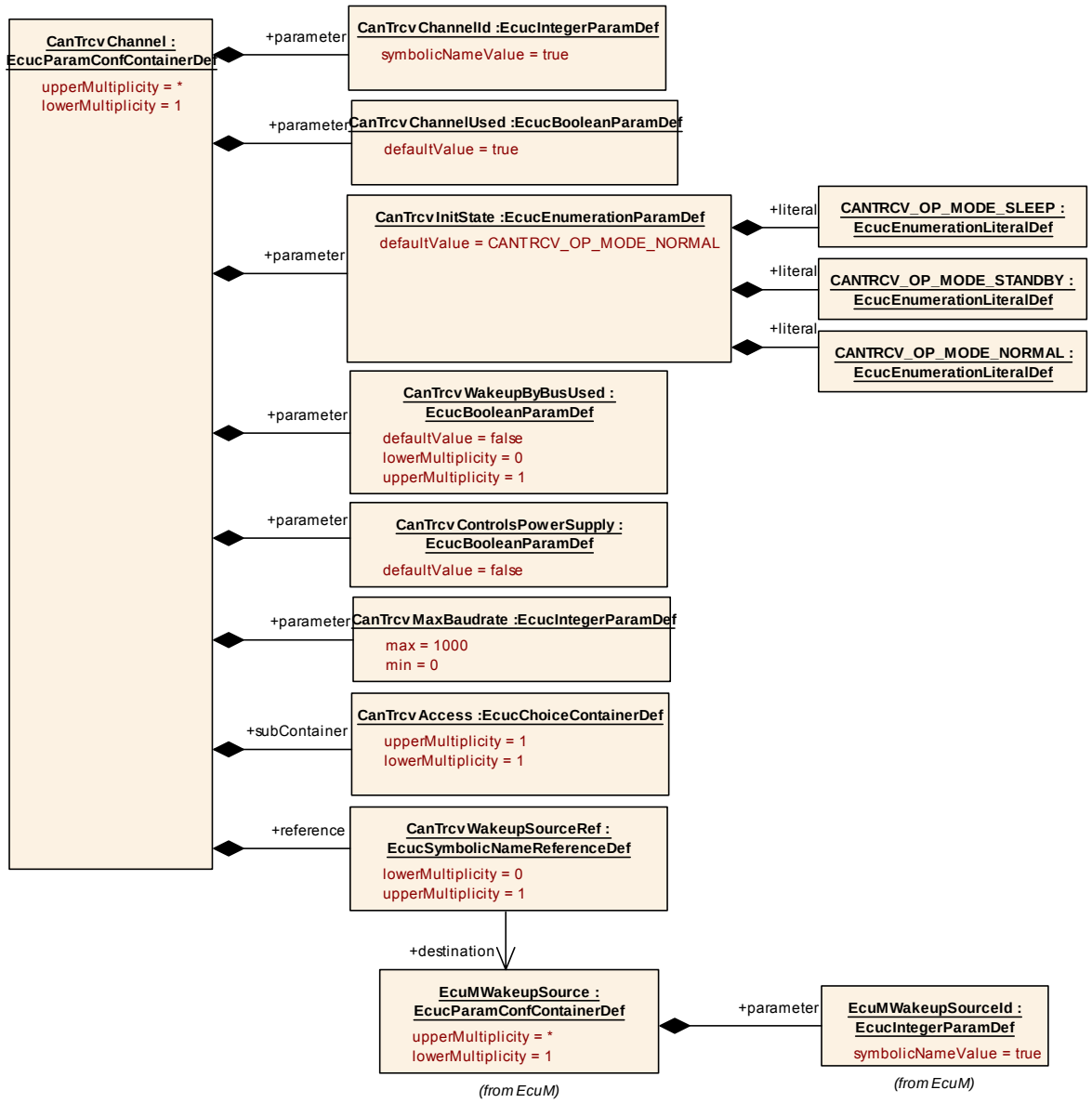
SWS Item	**CanTrcv147_Conf :**		
Name	CanTrcvMaxBaudrate {CANTRCV_MAX_BAUDRATE}		
Description	Max baudrate for transceiver hardware type. Only used for validation purposes. Value shall be configured by configuration tool based on transceiver hardware type.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 1000		
Default value	--		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Instance		

SWS Item	**CanTrcv148_Conf :**
Name	CanTrcvWakeupByBusUsed {CANTRCV_WAKEUP_BY_BUS_USED}
Description	Is wake up by bus supported? If CAN transceiver hardware does not support wake up by bus value is always FALSE. If CAN transceiver hardware supports wake up by bus value is TRUE or FALSE depending whether it is used or not. TRUE = Is used. FALSE = Is not used.
Multiplicity	0..1

Type	EcucBooleanParamDef		
Default value	false		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Instance dependency: CanTrcvWakeUpSupport		

SWS Item	**CanTrcv177_Conf :**		
Name	CanTrcvWakeupSourceRef {CANTRCV_WAKEUP_SOURCE_REF}		
Description	Reference to a wakeup source in the EcuM configuration. This reference is only needed if CanTrcvWakeupByBusUsed is true.		
Multiplicity	0..1		
Type	Reference to [EcuMWakeupSource]		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: ECU dependency: CanTrcvWakeupByBusUsed		

Included Containers		
Container Name	***Multiplicity***	***Scope / Dependency***
CanTrcvAccess	1	Container gives CanTrcv Driver information about access to a single CAN transceiver.
CanTrcvPartialNetwork	0..1	Container gives CAN transceiver driver information about the configuration of Partial Networking functionality.

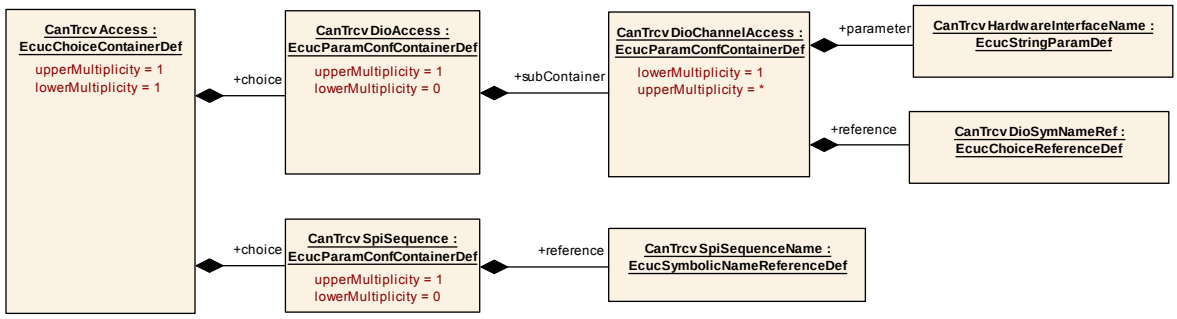


10.2.5 CanTrcvAccess

SWS Item	**CanTrcv101_Conf :**
Choice container Name	CanTrcvAccess
Description	Container gives CanTrcv Driver information about access to a single CAN transceiver.

Container Choices		
Container Name	***Multiplicity***	***Scope / Dependency***
CanTrcvDioAccess	0..1	Container gives CAN transceiver driver information about accessing ports and port pins. In addition relation between CAN transceiver hardware pin names and Dio port access information is given. If a CAN transceiver hardware has no Dio interface, there is no instance of this container.
CanTrcvSpiSequence	0..*	Container gives CAN transceiver driver information about one SPI sequence. One SPI sequence used by CAN transceiver driver is in exclusive use for it. No other driver is allowed to access this sequence. CAN transceiver driver may use one sequence to access n CAN transceiver hardwares chips of the same type or n sequences are used to access one single CAN

		transceiver hardware chip. If a CAN transceiver hardware has no SPI interface, there is no instance of this container.



10.2.6 CanTrcvDioAccess

SWS Item	**CanTrcv145_Conf :**
Container Name	CanTrcvDioAccess{CanTransceiverDioAccess}
Description	Container gives CAN transceiver driver information about accessing ports and port pins. In addition relation between CAN transceiver hardware pin names and Dio port access information is given. If a CAN transceiver hardware has no Dio interface, there is no instance of this container.
Configuration Parameters	

Included Containers		
Container Name	***Multiplicity***	***Scope / Dependency***
CanTrcvDioChannelAccess	1..*	Container gives DIO channel access by single Can transceiver channel.

10.2.7 CanTrcvDioChannelAccess

SWS Item	**CanTrcv157_Conf :**
Container Name	CanTrcvDioChannelAccess{CanTrcvDioChannelAccess}
Description	Container gives DIO channel access by single Can transceiver channel.
Configuration Parameters	

SWS Item	**CanTrcv150_Conf :**		
Name	CanTrcvHardwareInterfaceName {CANTRCV_HARDWARE_INTERFACE_NAME}		
Description	CAN transceiver hardware interface name. It is typically the name of a pin. From a Dio point of view it is either a port, a single channel or a channel group. Depending on this fact either CANTRCV_DIO_PORT_SYMBOLIC_NAME or CANTRCV_DIO_CHANNEL_SYMBOLIC_NAME or CANTRCV_DIO_CHANNEL_GROUP_SYMBOLIC_NAME shall reference a Dio configuration. The CAN transceiver driver implementation description shall list up this name for the appropriate CAN transceiver hardware.		
Multiplicity	1		
Type	EcucStringParamDef		
Default value	--		
maxLength	--		
minLength	--		
regularExpression	--		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	

	Post-build time	--	
Scope / Dependency	scope: Instance		

SWS Item	**CanTrcv149_Conf :**		
Name	CanTrcvDioSymNameRef		
Description	Choice Reference to a DIO Port, DIO Channel or DIO Channel Group. This reference replaces the CANTRCV_DIO_PORT_SYM_NAME, CANTRCV_DIO_CHANNEL_SYM_NAME and CANTRCV_DIO_GROUP_SYM_NAME references in the Can Trcv SWS.		
Multiplicity	1		
Type	Choice reference to [DioChannel , DioChannelGroup , DioPort]		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency			

No Included Containers

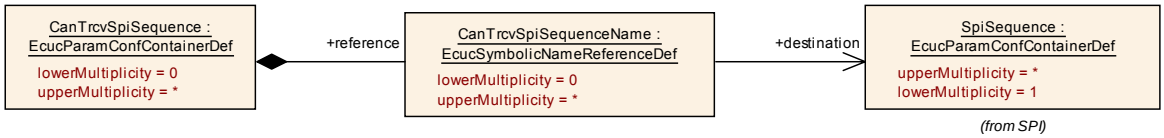
10.2.8 CanTrcvSpiSequence

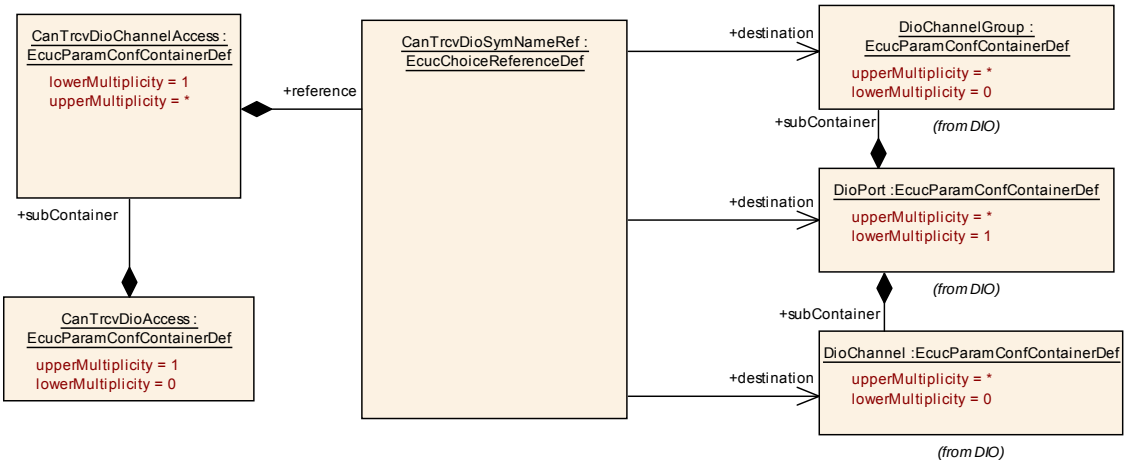
SWS Item	**CanTrcv144_Conf :**
Container Name	CanTrcvSpiSequence{CanTransceiverSPISequences}
Description	Container gives CAN transceiver driver information about one SPI sequence. One SPI sequence used by CAN transceiver driver is in exclusive use for it. No other driver is allowed to access this sequence. CAN transceiver driver may use one sequence to access n CAN transceiver hardwares chips of the same type or n sequences are used to access one single CAN transceiver hardware chip. If a CAN transceiver hardware has no SPI interface, there is no instance of this container.
Configuration Parameters	

SWS Item	**CanTrcv176_Conf :**		
Name	CanTrcvSpiAccessSynchronous {CANTRCV_SPI_ACCESS_SYNCHRONOUS}		
Description	This parameter is used to define whether the access to the Spi sequence is synchronous or asynchronous. true: SPI access is synchronous. false: SPI access is asynchronous.		
Multiplicity	0..1		
Type	EcucBooleanParamDef		
Default value	false		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Module		

SWS Item	**CanTrcv151_Conf :**		
Name	CanTrcvSpiSequenceName {CANTRCV_SPI_SEQUENCE_NAME}		
Description	Reference to a Spi sequence configuration container.		
Multiplicity	0..*		
Type	Reference to [SpiSequence]		
ConfigurationClass	***Pre-compile time***	X	All Variants
	Link time	--	
	Post-build time	--	
Scope / Dependency	scope: Instance dependency: SpiSequence		

No Included Containers





10.2.9 CanTrcvPartialNetwork

SWS Item	**CanTrcv161_Conf :**
Container Name	CanTrcvPartialNetwork
Description	Container gives CAN transceiver driver information about the configuration of Partial Networking functionality.
Configuration Parameters	

SWS Item	**CanTrcv169_Conf :**		
Name	CanTrcvBaudRate {CANTRCV_BAUD_RATE}		
Description	Indicates the CAN Bus communication baud rate in kbps.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 1000		
Default value	--		
ConfigurationClass	*Pre-compile time*	X	VARIANT-PRE-COMPILE
	Link time	--	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: Local dependency: Although WUF with DLC=0 is technically possible, it is explicitly not wanted.		

SWS Item	**CanTrcv171_Conf :**
Name	CanTrcvBusErrFlag {CANTRCV_BUS_ERR_FLAG}
Description	Indicates if the Bus Error (BUSERR) flag is managed by the BSW. This flag is set if a bus failure is detected by the transceiver. TRUE = Supported by transceiver and managed by BSW. FALSE = Not managed by BSW.
Multiplicity	1

Type	EcucBooleanParamDef		
Default value	false		
ConfigurationClass	***Pre-compile time***	X	VARIANT-PRE-COMPILE
	Link time	--	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: Local		

SWS Item	**CanTrcv164_Conf :**		
Name	CanTrcvPnCanIdIsExtended {CANTRCV_PN_CAN_ID_IS_EXTENDED}		
Description	Indicates whether extended or standard ID is used. TRUE = Extended Can identifier is used. FALSE = Standard Can identifier is used		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	false		
ConfigurationClass	***Pre-compile time***	X	VARIANT-PRE-COMPILE
	Link time	--	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: Local		

SWS Item	**CanTrcv172_Conf :**		
Name	CanTrcvPnEnabled {CANTRCV_PN_ENABLED}		
Description	Indicates whether the selective wake-up function is enabled or disabled in HW. TRUE = Selective wakeup feature is enabled in the transceiver hard-ware FALSE = Selective wakeup feature is disabled in the transceiver hardware		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	false		
ConfigurationClass	***Pre-compile time***	X	VARIANT-PRE-COMPILE
	Link time	--	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: Local		

SWS Item	**CanTrcv163_Conf :**		
Name	CanTrcvPnFrameCanId {CANTRCV_PN_FRAME_CAN_ID}		
Description	CAN ID of the Wake-up Frame (WUF).		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 4294967295		
Default value	--		
ConfigurationClass	***Pre-compile time***	X	VARIANT-PRE-COMPILE
	Link time	--	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: Local		

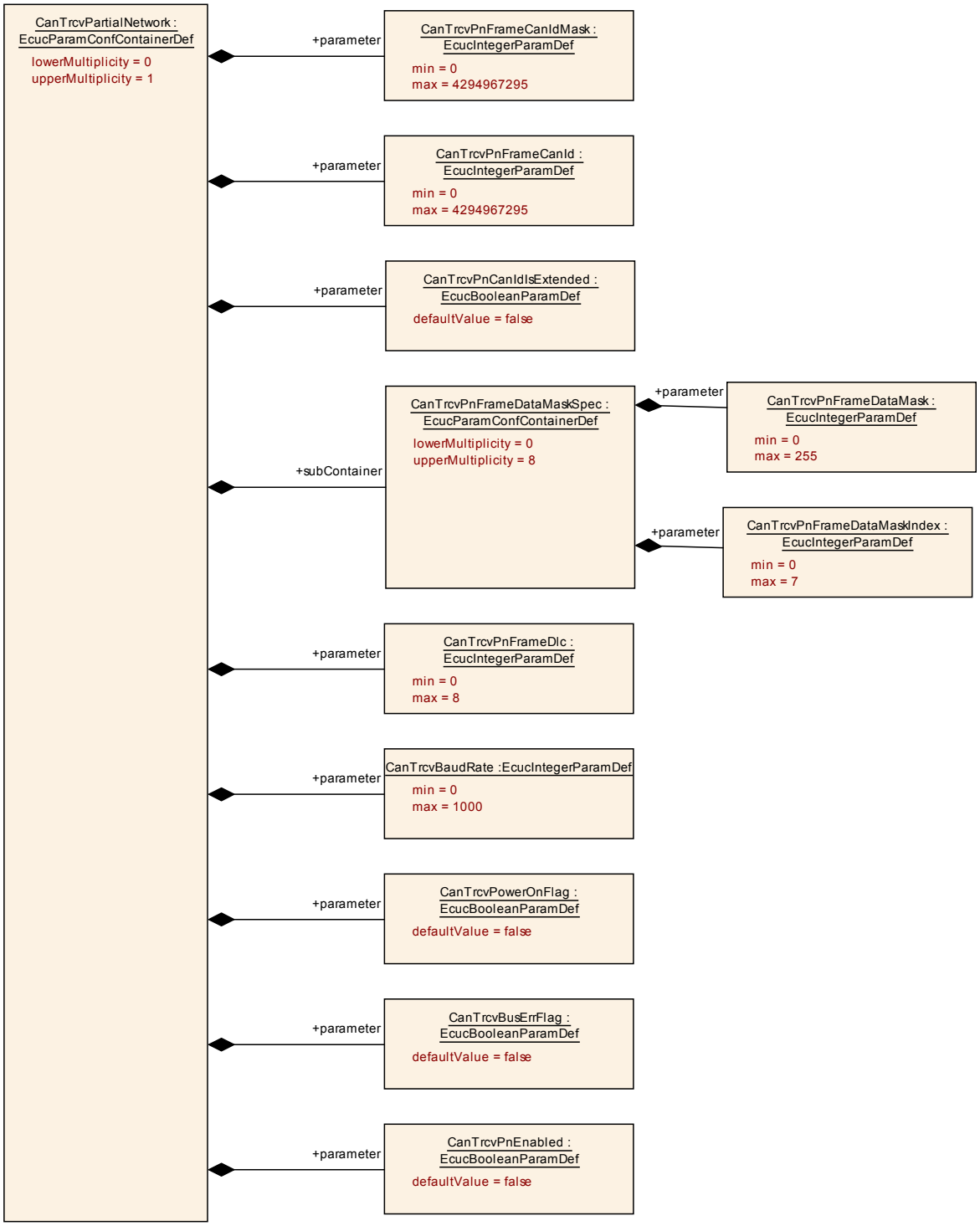
SWS Item	**CanTrcv162_Conf :**		
Name	CanTrcvPnFrameCanIdMask {CANTRCV_PN_FRAME_CAN_ID_MASK}		
Description	ID Mask for the selective activation of the transceiver. It is used to enable-Frame Wake-up (WUF) on a group of IDs.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 4294967295		
Default value	--		
ConfigurationClass	***Pre-compile time***	X	VARIANT-PRE-COMPILE
	Link time	--	
	Post-build time	X	VARIANT-POST-BUILD

Scope / Dependency	scope: Local

SWS Item	**CanTrcv168_Conf :**		
Name	CanTrcvPnFrameDlc {CANTRCV_PN_FRAME_DLC}		
Description	Data Length of the Wake-up Frame (WUF).		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 8		
Default value	--		
ConfigurationClass	***Pre-compile time***	X	VARIANT-PRE-COMPILE
	Link time	--	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: Local		

SWS Item	**CanTrcv170_Conf :**		
Name	CanTrcvPowerOnFlag {CANTRCV_POWER_ON_FLAG}		
Description	Description: Indicates if the Power On Reset (POR) flag is available and is managed by the transceiver. TRUE = Supported by Hardware. FALSE = Not supported by Hardware		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	false		
ConfigurationClass	***Pre-compile time***	X	VARIANT-PRE-COMPILE
	Link time	--	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: Local		

Included Containers		
Container Name	***Multiplicity***	***Scope / Dependency***
CanTrcvPnFrameDataM-askSpec	0..8	Defines data payload mask to be used on the received payload in order to determine if the transceiver must be woken up by the received Wake-up Frame (WUF).



10.2.10 CanTrcvPnFrameDataMaskSpec

SWS Item	**CanTrcv165_Conf :**
Container Name	CanTrcvPnFrameDataMaskSpec{CANTRCV_PN_FRAME_DATA_MASK_SPEC}
Description	Defines data payload mask to be used on the received payload in order to determine if the transceiver must be woken up by the received Wake-up Frame (WUF).
Configuration Parameters	

SWS Item	CanTrcv166_Conf :		
Name	CanTrcvPnFrameDataMask {CANTRCV_PN_FRAME_DATA_MASK}		
Description	Defines the n byte (Byte0 = LSB) of the data payload mask to be used on the received payload in order to determine if the transceiver must be woken up by the received Wake-up Frame (WUF).		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 255		
Default value	--		
ConfigurationClass	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	--	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: Local		

SWS Item	CanTrcv167_Conf :		
Name	CanTrcvPnFrameDataMaskIndex {CANTRCV_PN_FRAME_DATA_MASK_INDEX}		
Description	holds the position n in frame of the mask-part		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 7		
Default value	--		
ConfigurationClass	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	--	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: Local		

No Included Containers

10.3 Published Information

[**CanTrcv169**] ⌈ The standardized common published parameters as required by BSW00402 in the General Requirements on Basic Software Modules (see ch. 3) shall be published within the header file of this module and need to be provided in the BSW Module Description. The according module abbreviation can be found in the List of Basic Software Modules (see ch. 3). ⌋ (BSW00402)

Additional module-specific published parameters are listed below if applicable.

11 Not applicable requirements

[CanTrcv999] ⌈ These requirements are not applicable to this specification. ⌋
(BSW00304, BSW00305, BSW00306, BSW00307, BSW00308, BSW00309, BSW00312, BSW00321, BSW00325, BSW00326, BSW00328, BSW00330, BSW00331, BSW00333, BSW00334, BSW00335, BSW00336, BSW00341, BSW00342, BSW00344, BSW00355, BSW00359, BSW00360, BSW00378, BSW00383, BSW00384, BSW00387, BSW00398, BSW00399, BSW00400, BSW00401, BSW00404, BSW00405, BSW00410, BSW00416, BSW00417, BSW00420, BSW00422, BSW00423, BSW00426, BSW00427, BSW00429, BSW00431, BSW00432, BSW00433, BSW00434, BSW005, BSW006, BSW007, BSW009, BSW010, BSW161, BSW164, BSW168, BSW01107, BSW01138)