

Application Note

Application of the P8xC592 microcontroller with CAN-interface

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Summary:

The integrated circuit P8xC592 from Philips is a single-chip high performance microcontroller designed for use in automotive and general industrial applications. It is a high-end derivative of the 80C51 family CMOS microcontrollers.

In addition to the 80C51 standard features the P8xC592 provides a number of dedicated hardware features for sophisticated control applications. It includes timers, A/D converter, PWM output, UART and a CAN protocol controller (CAN = Controller Area Network) for serial communication.

The P8xC592 covers the complete CAN specification, offering important features such as multi-master serial communication capability with a high number of participating network nodes, programmable data transmission rate up to 1 Mbit/s and powerful error handling.

This technical publication puts special emphasis on CAN applications of the P8xC592. The application note provides a simple circuit example for a CAN module built with a P8xC592. Furthermore flowcharts are discussed to let the reader become familiar with the software aspects of CAN communication. A practical example shows that there is very little CPU load for the control of CAN communication.

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1. Introduction

CAN (Controller Area Network) is an advanced serial communication protocol, which efficiently supports distributed real-time control with a very high safety level. CAN allows the flexible configuration of networks with different types of microprocessors and microcontrollers. Typical applications of CAN-based networks can be found in automotive and industrial environment:

- o Automotive Systems:
 - multiplex wiring (< 125kbit/s)
 - engine control, ABS etc. (up to 1 Mbit/s)
- o Industrial Systems:
 - field bus applications
 - robotics, numeric machine control

Fig.1 shows a schematic network using the P8xC592 for distributed control applications. The kernel of each module is a Module Controller (CPU) that communicates via the Bus Controller (i.e. CAN controller) with the other modules. CPU and CAN controller can also be implemented on the very same chip, as it is in the P8xC592.

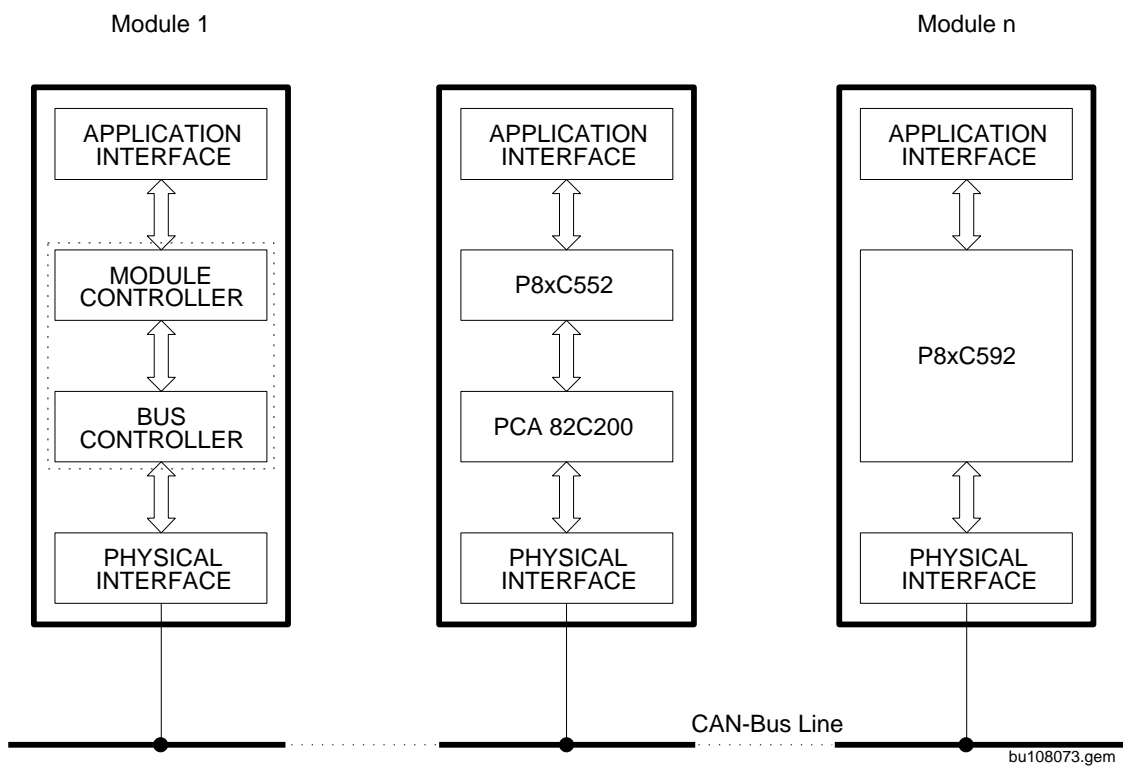


Fig. 1 Example of a "Controller Area Network"

The P8xC592 is a stand-alone high performance microcontroller designed for use in automotive and general industrial applications. In addition to the 80C51 standard features this device provides a number of dedicated hardware functions for these applications. It basically combines the functions of the well-known P8xC552 microcontroller [9] (without I²C hardware) and the PCA 82C200 (Philips Stand-alone CAN-controller [3]), with some enhanced features.

The CAN-part of the P8xC592 fulfills the complete CAN specification, to provide the following important features:

- o multi-master operation in a serial communication network with an unlimited number of active network nodes,
- o programmable data transmission rate, up to 1 Mbit/s,
- o very low probability of undetected errors, due to powerful error handling,
- o 40 m maximum distance between two bus nodes at a data transmission rate of 1 Mbit/s, lower transmission rates allow even longer distances,
- o guaranteed latency time supporting real-time applications.

This Application Note covers the CAN related items of P8xC592 applications. It describes a simple circuit example for a module in a CAN network. To apply and understand the application examples given in this document, the reader should be familiar with the Philips P8xC592 data sheet [2].

2. P8xC592 Features

Fig.2 shows the block diagram of the P83C592 (ROM) or the P87C592 (EPROM) versions. There is also a ROM-less version labeled P80C592 without on-chip program memory. Except the three blocks "CAN controller", "DMA" and "256 Bytes Aux. RAM", the blocks shown are not different from those which are present in other 80C51 derivatives like in the well-known Philips **P8xC552**. The use of the CPU, the memory access modes, the timers, A/D converter and PWM outputs have already been described in detail in the User Manual for the P8xC552 [9], which shall not be repeated in this application note again. Please refer to that document for information about these topics.

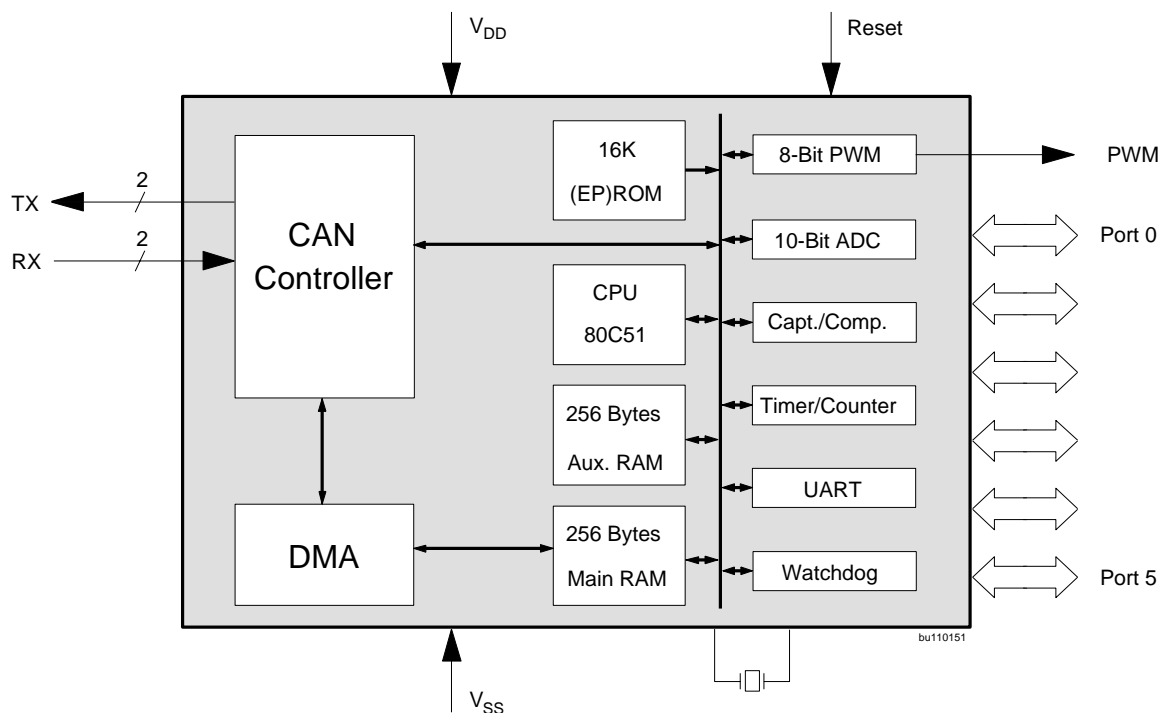


Fig. 2 Block diagram of the P8xC592

The **CAN controller** on the P8xC592 is mainly an on-chip implementation of the Philips Stand-alone CAN-controller **PCA 82C200** [3]. The access to the internal CAN registers now is given via 4 Special Function Registers (**SFR**). The transfer of the messages between the CAN controller and the P8xC592's main RAM can be done in extremely short time by using Direct Memory Access (**DMA**). More information about this feature is given in chapter 4.2.3 .

The P8xC592 has a 256 bytes **on-chip auxiliary RAM**, which is indirectly addressable in the same way as external data memory. This doubling of internal RAM capacity satisfies the rising demand for parameter storage in distributed control applications.

Summarizing the P8xC592 is a single-chip 8-bit microcontroller featuring:

- o 80C51 CPU
- o CAN controller with DMA
- o 16K bytes ROM / EPROM
- o 2 * 256 bytes RAM
- o 10-bit A/D converter, 8 channels
- o 3 * 16 bit timer/counters
 - 4 capture registers
 - 3 comparators controlling 8 outputs
- o 6 * 8-bit I/O ports
- o 2 * PWM outputs
- o full-duplex UART
- o interrupt controller (15 sources)
- o watchdog timer

3. Hardware Aspects

This section covers hardware considerations of a CAN-based module in a network. The first part describes the minimum circuitry required for the P83C592 / P87C592. The second part gives suggestions for the connection of the controller to the CAN bus wires.

3.1 Main Circuitry

The P8xC592 is designed to work with a minimum of external components. Fig.3 shows the circuitry of a CAN node using the ROM- or EPROM- version P83C592 or P87C592. The only additional components that are required are a crystal (Q1) plus two small capacitors (C1, C2) to drive the on-chip oscillator, a reset circuit to provide the power-on RESET and a transceiver circuit (see section 3.2) for the connection to the bus wires.

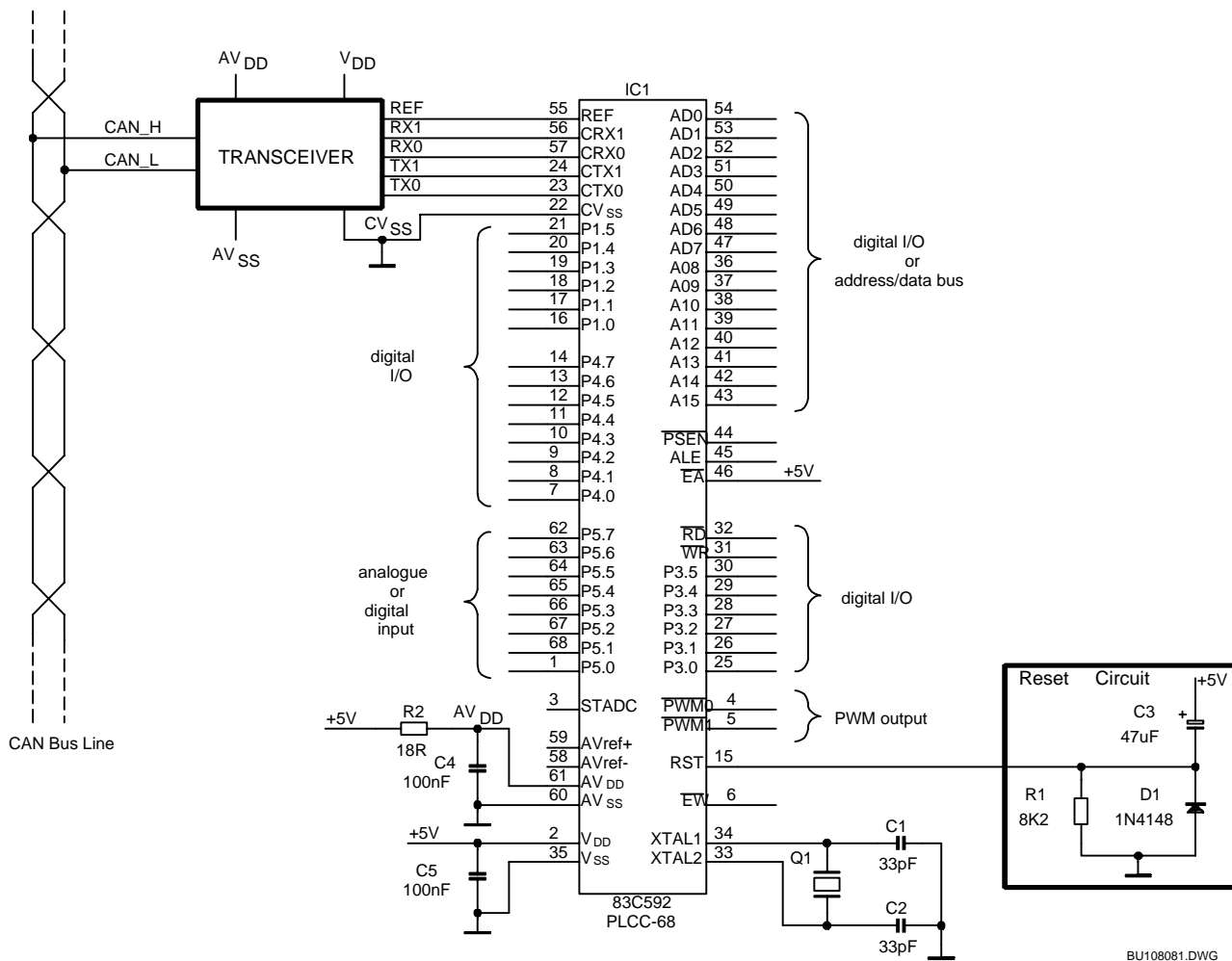


Fig. 3 P87C592 / P83C592 circuitry for a CAN application

Power Supply

The 5V power supply is split on the different power input pins of the μC . The main supply for the (digital part of the) CPU is fed to the $\text{V}_{\text{DD}} / \text{V}_{\text{SS}}$ pins, buffered by capacitor C5.

It is recommended that the supply $\text{AV}_{\text{DD}} / \text{AV}_{\text{SS}}$ for the analogue parts is derived from the main supply by the filter R2 / C4. The $\text{AV}_{\text{DD}} / \text{AV}_{\text{SS}}$ supply is used to drive the on-chip A/D converter and the receiver section of the CAN controller; it shall also be used for optional biasing of the RX0 / RX1 pins in the off-chip transceiver.

The pin CV_{SS} is the ground pin belonging to the CAN on-chip transmitter output stages (cf. chapter 3.2.1), which shall also be used for optional ground potential of the off-chip transceiver.

Program Fetch

The schematics of fig.3 present the circuitry for microcontrollers with on-chip program memory (ROM or EPROM). Therefore the pin $\overline{\text{EA}}$ is connected to +5V for program being fetched from internal memory. Note that the EA-pin is only read by the CPU during RESET, that means, switching it during program execution is not possible. This can give an additional protection against unauthorized copying of the on-chip program.

Reset Circuit

The schematics of fig.3 present a proposal for a discrete circuit that provides the necessary RESET signal to the CPU during power-up. The Reset Circuit can be replaced by a connection of the RST-pin to the power-on/power-fail reset output of the power supply, if available. Note that internal RESET conditions of the CPU (e.g. watchdog or recover from power-down) may cause the output of a short pulse on the RST pin, which the Reset Circuit has to tolerate.

3.2 Transceiver: Physical Interface to the Transmission Medium

The transceiver circuit performs the following functions:

- o it converts signals TX0, TX1 into the voltage levels for the bus wires,
- o it converts the voltage levels on the bus wires to be compatible with the CRX0, CRX1 inputs of the P8xC592.

How this connection actually is implemented, is application-specific. Depending on the requirements for the bus signals, the transceiver can be realized with more or less effort, the cheapest solution consists only of a couple of resistors, more expensive ones need some more discrete components or an extra IC. In principle the very same transceiver circuits can be used as for the stand-alone CAN controller PCA 82C200 [3]. Three examples for cheap discrete transceivers have been described in the Application Note [4] for the PCA 82C200, for instance.

In order to get to an international standard for CAN communication (including the transceiver), the International Standardization Organization (ISO) has prepared two standards, one for lower bit rates (up to 125 kbit/s) [6], one for higher ones [7]. They also define the electrical parameters for the transceiver. Application hints for implementation of an ISO-compatible transceiver circuit are given in [10].

3.2.1 On-chip Transceiver Components

The off-chip transceiver circuit connects the bus wires to the on-chip transceiver components. The on-chip transceiver provides the transmitter output stage and the receiver input comparator, see fig.4.

Transmitter

The transmitter provides two output lines (CTX0, CTX1); their characteristics can be programmed individually with the OUTPUT CONTROL register. Each line can work as open-drain or open-source or push-pull output, with positive or negative polarity. Thus the transmitter is well prepared to drive any kind of differential bus lines.

The connections of the transmitter outputs to the bus wires have to be done in such a way, that the resulting level on the bus is:

- o recessive level, when all nodes transmit a logical 1 or do not transmit,
- o dominant level, when one or more nodes transmit a logical 0.

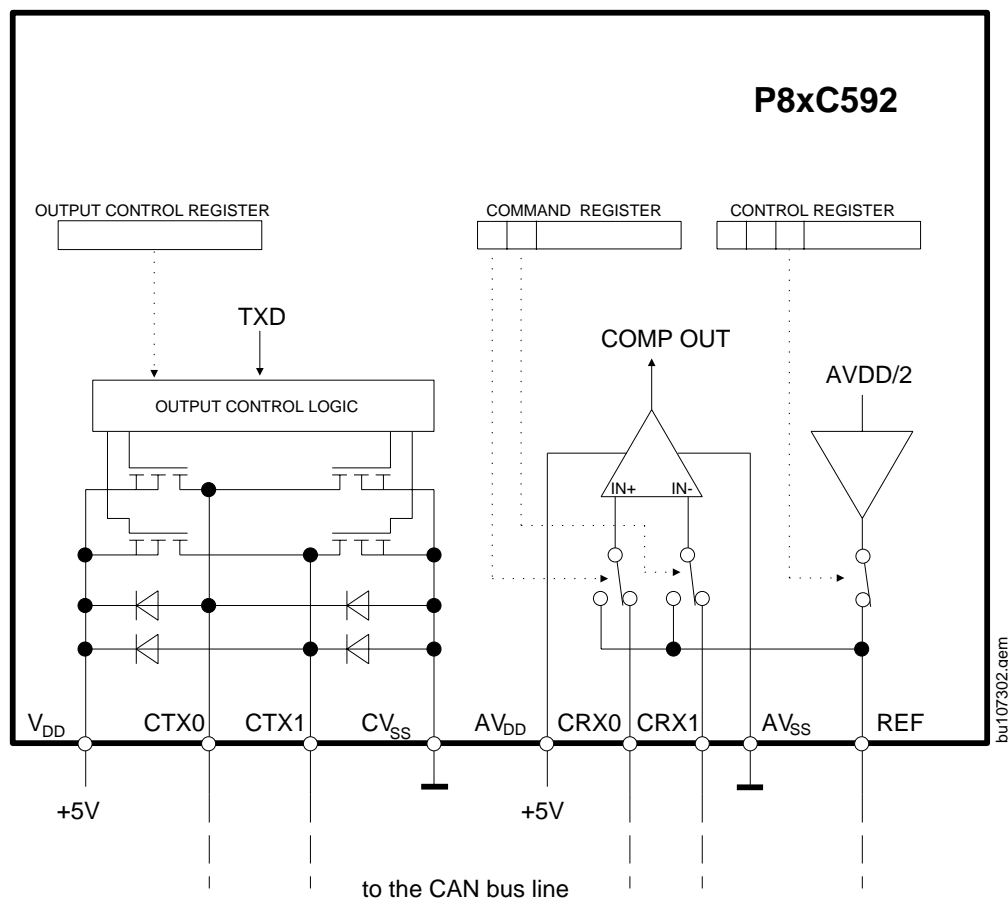


Fig. 4 Structure of the on-chip CAN transceiver

Receiver

The on-chip receiver is a differential input comparator with the input lines CRX0 and CRX1. It decodes

- o the recessive level to a logical 1, when the voltage at the CRX0-pin is higher than at the CRX1-pin,
- o the dominant level to a logical 0, when the voltage at the CRX0-pin is lower than at the CRX1-pin.

Instead of decoding the **differential** bus signal, the comparator inputs can also be switched by software to decode the signal of only one of the two bus lines, comparing it to the reference voltage at the REF pin. The reference voltage can either be provided by the internal on-chip voltage generator (= default), or, if desired, it is fed to the REF pin by an external source, with the internal source being switched off by software. The use of **single wire** decoding is beneficial to continue communication, when one of the two bus lines has a wiring failure (open or short circuit), please refer to [8].

4. Software Aspects

4.1 CAN Registers

The P8xC592's on-chip CAN controller is a full implementation of the CAN protocol. It contains all necessary features required for a high performance communication protocol.

The CAN controller appears to the CPU as a memory-mapped I/O device which is arranged as Control Segment, Transmit (Tx) Buffer and Receive (Rx) Buffer (see fig.5).

Exchange of status, control and command signals between the CPU and the CAN controller is done by the control segment which contains 10 bytes. It is programmed during initialization for configuration of the communication parameters. Additionally the CPU controls the CAN communication via this segment.

Data to be transmitted are loaded into the Transmit Buffer by the CPU. The buffer contains the descriptor (Identifier, RTR-bit and DLC) and up to eight data bytes.

After a successful reception messages are read from the Receive Buffer. It consists of two 10 byte memories which are alternatively used to store messages. The CPU can process one message while another is being received.

4.2 On-chip Interface Between CPU and CAN Controller

To access the described CAN controller registers, four special function registers CANADR, CANDAT, CANCON and CANSTA are implemented. All CAN registers of the Control Segment which are used during communication now appear as being directly addressable as they are represented by these four special function registers. The Status Register represented by CANSTA now is even bit-addressable. With the help of these registers and the DMA logic, data transfer between Transmit/Receive Buffers and internal main RAM is also done very effectively (see fig. 6).

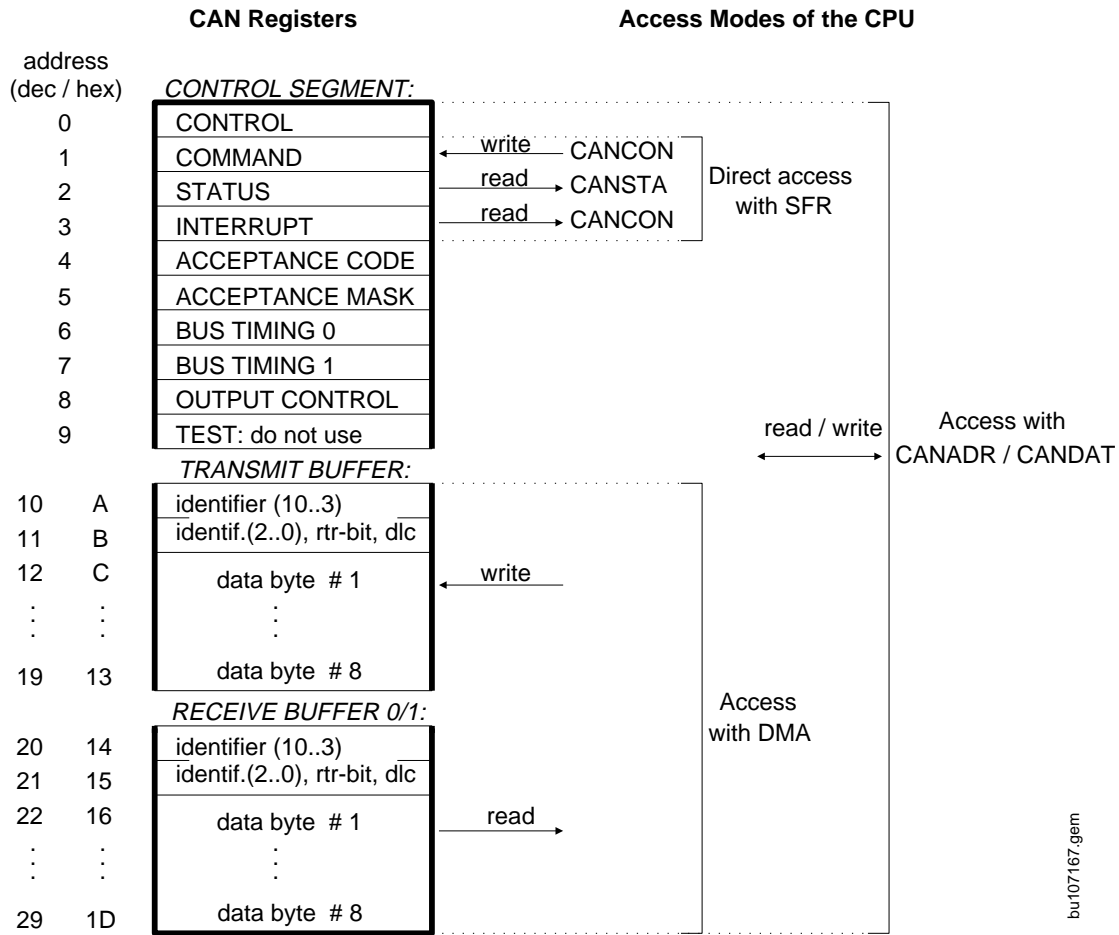


Fig. 5 CAN register mapping

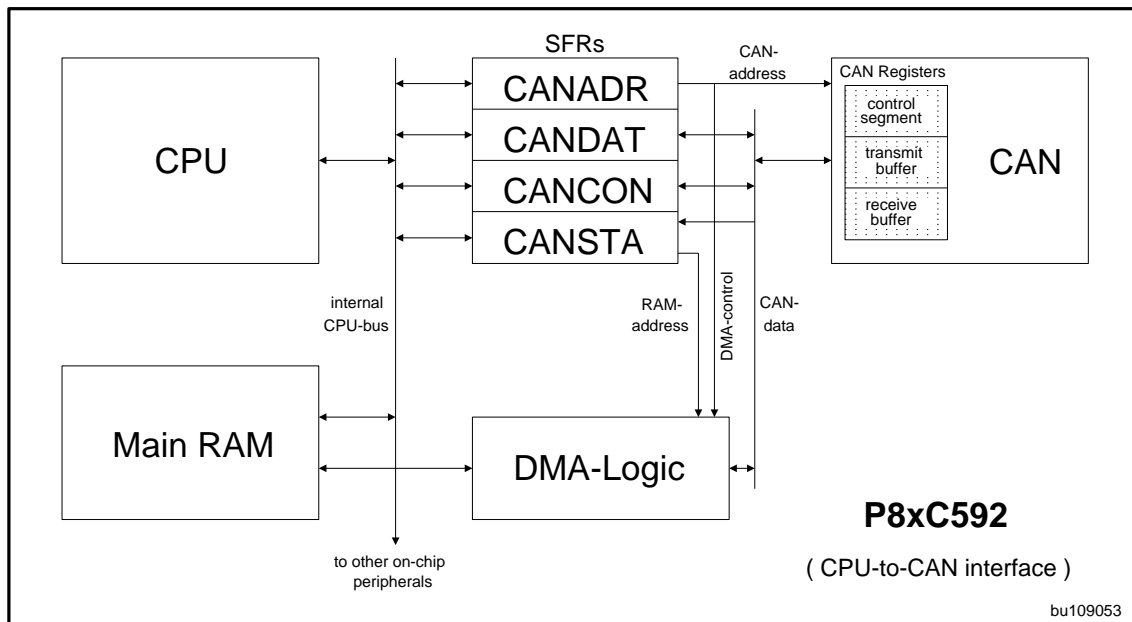


Fig. 6 Block diagram of the CPU - to - CAN interface

4.2.1 CAN Related Special Function Registers

Table 1 shows the special function register arrangement. Note that CANCON and CANSTA have different meanings for a read and write access.

SFR	ADR	ACS	MSB 7	6	5	4	3	2	1	LSB 0
CANADR	D8H	R/W	DMA	reserved	AutInc	CANA4	CANA3	CANA2	CANA1	CANA0
CANDAT	DAH	R/W	CAND7	CAND6	CAND5	CAND4	CAND3	CAND2	CAND1	CAND0
CANCON	D9H	R	reserved	reserved	reserved	Wake up Int	Overrun Int	Error Int	Transmit Int	Receive Int
		W	RX0 active	RX1 active	Wake up Mode	Sleep	Clear Overrun	Release Rx Buffer	Abort Transm.	Transmit Request
CANSTA	D8H	R	Bus Status	Error Status	Transmit Status	Receive Status	TX compl. Status	Tx Buffer Access	Data Overrun	Rx Buffer Status
		W	RAMA7	RAMA6	RAMA5	RAM4	RAMA3	RAMA2	RAMA2	RAMA1

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Table 1: CAN Special Function Registers

CANADR

With the least significant bits CANA4...CANA0 each of the CAN controller internal registers can be addressed by a write access to CANADR. Reading or modification of the particular CAN register then is done by reading or writing to CANDAT. CANADR is implemented as a read/write register which also contains control bits to select auto increment addressing and to start a DMA transfer.

CANDAT

When reading or writing CANDAT, access to the CAN registers addressed by CANADR is possible. The way of accessing CAN registers via CANADR/CANDAT normally is only necessary for the registers Acceptance Code, Acceptance Mask, Bus Timing 0, Bus Timing 1, Output Control, which the CPU has to access during initialization only.

CANCON

CANCON is a register with different meaning for write and read operation. Writing to CANCON is a direct access to the command register and reading from it is a direct access to the interrupt register.

CANSTA

The bit addressable register allows a direct read access to the Status Register of the CAN Controller. Writing to CANSTA sets the address of the on-chip main RAM for a subsequent DMA transfer.

4.2.2 Auto Address Increment

Fast reading and writing of consecutive CAN Controller internal registers is possible by setting the AutoInc bit of CANADR and the concerning register address simultaneously. A first access to CANDAT refers to the register specified in CANADR. After any read or write access to CANDAT the contents of CANADR are incremented automatically in this mode.

Incrementing CANADR beyond XX111111B resets the AutoInc bit automatically to XX000000B.

4.2.3 High Speed DMA

The DMA logic provides a very fast transfer of complete messages between receive/transmit buffers and internal data memory (Main RAM) within 2 instruction cycles. The transfer process operates in the background and therefore the CPU can continue with the next instruction. However, an access to the Main RAM or to the CAN special function registers is not allowed during this time.

A DMA transfer action is achieved by first writing the RAM address into CANSTA and then writing the Tx- or Rx-Buffer address and the DMA bit simultaneously into CANADR.

The DMA automatically recognizes the transfer direction (see table 2). For the Rx Buffer DMA there is the option to copy a whole message or only a part of it.

CANADR	subject to transfer	transfer direction
8AH	whole message	RAM -> Tx Buffer
94H	whole message	Rx Buffer -> RAM
95H	whole message without first byte	
96H	data bytes only *)	
97H	last data bytes *)	
.	.	
9DH	only the last data byte *)	

*) data bytes are copied as far as they are available (DLC!)

Table 2: DMA Modes

Setting the DMA bit causes an automatic evaluation of the data length and subsequent transfer. For a Tx Buffer DMA transfer the data length is always expected at "RAM address + 1".

After the DMA transfer has been finished, the DMA bit and the AutoInc bit are reset.

4.3 Basic Functions for CAN Communication

4.3.1 Initialization

During Initialization the P8xC592's CAN Controller is configured according to the required communication parameters. Before setting the registers in the Control Segment (see fig.5) first the Reset Request bit in the Control Register has to be set to "present" (high). An initialization procedure should include definitions of the following items:

- o Acceptance Filter
- o Bus Timing
- o Output Mode
- o Interrupts
- o Reference Voltage Mode

A flow chart of the initialization procedure is shown in table 4.

When the configuration of the P8xC592 is finished the Reset Request bit has to be set to "absent" to allow receive- or transmit operations.

4.3.2 Transmission

The CPU may write a message into the transmit buffer whenever the transmit buffer access bit (Status Register) is set. After writing the message to the transmit buffer and setting the transmission request bit high (Command Register), the CAN Controller begins with the transmission process.

If the CPU cannot access the transmit buffer because a previously requested message is still waiting for transmission, it is possible to abort the current process. A transmission already in progress is not stopped.

```
+-----+
|if (status bit TRANSMIT BUFFER ACCESS = "released") |
+-----then-----+-----else-----+
| write message into |if (<high priority message to be transmitted>)|
| TRANSMIT BUFFER   +-----then-----+-----else---+
+-----+ set command bit |
|set command bit TRANSMISSION | ABORT TRANSMISSION:= "present" |
|REQUEST := "present" |
| |
| | (* the next transmission is delayed until |
| | TRANSMIT BUFFER ACCESS = "released" is |
| | signalled by a TRANSMIT INTERRUPT or by |
| | polling the STATUS REGISTER *) |
+-----+-----+
```

Table 3: Flow chart of a transmission procedure

```

+-----+
| (* start initialization; write CONTROL REGISTER *)
|
|     - set RESET_REQUEST := "present"
|     - set TEST_MODE     := "disabled"
|
+-----+
| (* write acceptance filter *)
|
|     - write ACCEPTANCE CODE REGISTER
|     - write ACCEPTANCE MASK REGISTER
|
| (* example: contents of ACCEPTANCE CODE REGISTER = 01110010B
|              contents of ACCEPTANCE MASK REGISTER = 00111000B
|              allows for messages with following IDs: 01xxx010xxxB
| *)
|
+-----+
| (* define bus timing (baud rate on the CAN Bus) *)
|
|     - write BUS TIMING 0 REGISTER
|     - write BUS TIMING 1 REGISTER
|
| (* example: contents of BUS TIMING 0 REGISTER = 10001001B
|              contents of BUS TIMING 1 REGISTER = 11101011B
|              results in:
|              tSCL      = (9 + 1) * 2 * tOSC   (with fOSC = 16 MHz: 1.25 us)
|              tSJW      = (2 + 1) * tSCL      (3.75 us)
|              SAM       = 1                    (three samples / bit taken)
|              tSYNC     = 1 * tSCL            (1.25 us)
|              tTSEG2    = (6 + 1) * tSCL     (8.75 us)
|              tTSEG1    = (11 + 1) * tSCL    (15.00 us)
|              tBIT      = tSYNCSEG + tTSEG1 + tTSEG2 = 20 * tSCL (25.00 us)
|              variation of bit time due to resynchronization:
|              tBITmin   = tBIT - tSJW = 17 tSCL (21.25 us)
|              tBITmax   = tBIT + tSJW = 23 tSCL (28.75 us)
| *)
|
+-----+
| (* define bus driver characteristics *)
|
|     - write OUTPUT CONTROL REGISTER
|
| (* example: contents of OUTPUT CONTROL REGISTER = 10101010B
|              results in:
|              output mode: normal 1 (bit sequence on TX0 and TX1 pins)
|              TX0 configuration: bit-state 0 (1) -> output-state low (float)
|              TX1 configuration: bit-state 0 (1) -> output-state high (float)
| *)
|
+-----+
| (* end initialization; write to CONTROL REGISTER *)
|
|     - enable interrupt sources          (* bits 4 .. 1 *)
|     - define mode of reference voltage (* bit 5 *)
|     - define the resynchronization mode (* SYNCH; bit 6 *)
|     - set RESET REQUEST := "absent"    (* bit 0 *)
|
+-----+
| (* = start of comment          *) = end of comment

```

Table 4: Flow chart of an initialization procedure

4.3.3 Reception

Whenever the status bit 'Receive Buffer Status' is set, a new message is available in the Rx Buffer. Polling the Status Register enables the information of new message data in the Rx Buffer to be coordinated and controlled by the CPU.

When the Receive Interrupt is enabled the according bit in the interrupt register is set simultaneously with the Receive Buffer Status bit and the interrupt service can start with reading of message data from the Rx Buffer.

After Reading the buffer contents the CPU has to release this buffer by setting the Release Receive Buffer command bit. This may result in another message becoming immediately available.

```
+-----+
|read message from RECEIVE BUFFER                               |
+-----+
|set command bit RELEASE RECEIVE BUFFER := "released"         |
+-----+
```

Table 5: Flow chart of a reception procedure

4.3.4 Sleep Mode

If the Sleep Bit of the Command Register is set high the CAN controller enters the Sleep Mode, requiring that there is no bus activity and no interrupt is pending. A network enters the 'Sleep Mode' when all its nodes enter the Sleep Mode.

The CAN Controller wakes up after setting the Sleep bit of the Command Register low or when there is any bus activity. Upon wake up a wake up interrupt is generated. It is not necessary to enable the wake up interrupt.

After the CAN Controller entered Sleep Mode the CPU may be set into the 'Power Down Mode' (oscillator stopped). Upon wake up, the oscillator is started again. The wake up interrupt will wake up a CPU from 'Power Down Mode' by generating a Reset pulse, if the SIO1 (CAN) interrupt source was enabled. A CAN Controller that wakes up because of bus activity is not able to receive this message until it detects a bus free signal.

Reading of the Sleep bit reflects the status of the CAN Controller.

```
+-----+
|Set command bit SLEEP := "sleep"                             |
+-----+
```

Table 6: Flow chart of a "go to sleep" procedure

4.3.5 Comparator Switches

Data communication between the nodes of a network is disturbed or stopped when the bus wires are short-circuited (global failures) or interrupted (local failures). With the P8xC592 precautions have been taken to continue data communication despite of a bus failure.

With the help of the comparator switches, implemented in the CAN Controller, it is possible to tolerate the following single wiring failures:

- o one of the bus lines is short-circuited with VBAT or GND
- o one bus line is short-circuited against the other
- o interruption of one of the bus lines

The structure of the on-chip CAN Transceiver in fig.4 shows that in case of a short circuit it is possible to disconnect a blocked bus wire from the CAN receivers of all network nodes and replace this faulty bus line potential by a local reference level at one of the comparator inputs. In some cases it might be necessary to disconnect the bias voltage of one bus wire from the power supply terminal, additionally, to continue with communication.

Bus line interruptions are solved similar to the short circuit failures by replacing the potential of one bus line with a local reference potential.

The positions of the switches are defined via the Command Register bits RX0A and RX1A (see table 7). Reading of RX0A/RX1A reflects the status of the switches.

RX0A	RX1A	Result
0	0	unchanged
0	1	IN+ = REF, IN- = CRX1
1	0	IN+ = CRX0, IN- = REF
1	1	IN+ = CRX0, IN- = CRX1

Table 7: Results of setting RX0A/RX1A

With the help of the described comparator switches three configurations can be selected:

- o two wire communication (differential signal)
- o single wire communication using CAN_H
- o single wire communication using CAN_L

Thereby a test of the bus wires can be implemented easily by software: if single wire communication is possible in the network with each of the bus lines as well as differential communication, then there is no wiring failure. Otherwise the faulty wire is detected (**diagnosis**) and the network may continue to communicate on the other wire till the faulty wire is repaired.

For more details on CAN Bus failure management please refer to [8].

4.4 Control of CAN Communication

Information about the reception of messages, the completion of a transmission, data overrun, error status etc. can be signalled to the CPU either with interrupt processing, described in chapter 4.4.1 or with polling, described in chapter 4.4.2. It can be of advantage to mix both, polling and interrupt control. Note, that the wake up event can only be processed by interrupt.

4.4.1 Interrupts

The P8xC592 controls five different CAN related interrupt sources. These are the Receive-, Transmit-, Overrun-, Error- and the Wake up Interrupt. All interrupts can be enabled/disabled via the Control Register except of the Wake up Interrupt which is always enabled. Setting of the interrupt sources is usually done during initialization (see also table 4). Do not forget to enable the CPU's SIO1 interrupt (by ES1 bit) and the global interrupt (by EA bit).

Upon the occurrence of one or more (enabled) interrupts the according bits are set in the **Interrupt Register** and a CAN interrupt (SIO1) for the CPU is performed. After reading this register, that appears to the CPU as a read only memory, all bits are reset by the CAN Controller. Therefore, the Interrupt Register should be stored in a bitaddressable part of the CPU memory for later interrupt evaluation.

Table 8 shows the procedure for an Interrupt Register data evaluation. In this example it is assumed that all interrupt sources are enabled to present a complete description.

The following summary gives a short overview of the CAN related interrupts and their occurrences.

Receive Interrupt:	If a new message is available in the Receive Buffer, the Receive Interrupt is given.
Transmit Interrupt:	A Transmit Interrupt is signalled, when a transmission has been completed or aborted.
Error Interrupt:	If the Bus Status or the Error Status changes, an Error Interrupt is given.
Overrun Interrupt:	When both Receive Buffers contain a message and the first byte of the next message should be stored, the Overrun Interrupt is signalled.
Wake up Interrupt:	Whenever the Sleep Mode is left, a Wake up Interrupt is signalled.

When CAN communication is controlled partly in the interrupt service routine and partly in the main program, care has to be taken about the use of CANADR/CANDAT (indirect addressing of the CAN Registers) or CANADR/CANSTA (use of DMA), respectively. If they are used as well in main program level as in interrupt level, it might be necessary to save the address of CANADR (push/pop) during interrupt processing, or disable the CAN interrupt during DMA transfer at main level, respectively. For the latter, if required, the interrupt has to be disabled right before the RAM address is written into CANSTA, and can be re-enabled just after the start of the DMA transfer.



Table 8: Flow chart of Interrupt Register data evaluation

4.4.2 Polling

Analysing the contents of the Status Register, as shown in table 9, is very similar to analysing the contents of the Interrupt Register. With the following overview the concerning Status bits are described:

- Receive Buffer Status: This bit is set when a new message is available.
- Transmit Buffer Access: The CPU may write a message to the Tx Buffer when this bit is set.
- Error Status: The Error Status bit is set when at least one of the Error Counters has reached the warning limit.
- Data Overrun: When both Receive Buffers are full and the first byte of a new message should be stored, this bit is set.

```

+-----+
|if (TRANSMIT BUFFER ACCESS = "released")
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|a next message may be written into the TRANSMIT BUFFER
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|if (<using the ABORT TRANSMISSION command>)
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|if (TRANSMISSION COMPLETE STATUS = "complete") |(* last requested
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|(* last requested |(* last requested | transmission has
| transmission has | transmission has not | been completed
| been completed, | been completed due to |
| no ABORT TRANS- | an ABORT TRANSMISSION |
| MISSION command | command |
| has been exec. *)|*)
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|if (RECEIVE BUFFER STATUS = "full")
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|read RECEIVE BUFFER into CPU memory
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|set command bit RELEASE RECEIVE BUFFER := "released"
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|if (DATA OVERRUN = "overrun")
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|an application may use this information to change its
|behaviour (e.g. faster reaction on a RECEIVE INTERRUPT)
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|set command bit CLEAR OVERRUN := "clear"
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|if (BUS STATUS = "on-bus")
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|(* P8xC592 takes part in bus |(* P8xC592 does not take part in bus
| activities | activities
| *) | *)
|if (ERROR STATUS = "ok") |if (<restart CAN hardware required>)
+-----+-----+-----+-----+-----+-----+-----+-----+-----+
|(* the CAN-bus is |(* the CAN-bus is |set control bit RESET |perform
| presently | presently |REQUEST := "absent" |application-
| not severely | severely |(* now the P8xC592 |specific
| disturbed | disturbed | waits for 128 * 11 |default-mode
| *) | *) | consecutive |operation
| | | recessive bits |
| | | before going |
| | | "on-bus" again |
| | | *)
+-----+-----+-----+-----+-----+-----+-----+-----+-----+

```

Table 9: Flow chart of Status Register data evaluation (polling)

4.5 CPU Load for CAN - a Real Example

In a CAN system data transfer can be done with a very high level of safety with the CAN controller part of the P8xC592. The CPU has only the task of post-processing the received data and pre-processing the data to be transmitted. Communication between CPU and CAN controller is easily done via the Special Function Registers described in chapter 4.2.1. Using the DMA transfer facility, data exchange between CPU and Rx/Tx buffer is very effective.

That means that the resulting CPU load for CAN communication is very low, as the analysis of the following communication example proves. Simulations with "NetSim" (a simulator for CAN communication, see chapter 5.4) have been done with a real communication example of 7 nodes. At a data rate of 500kbit/s, 12 different messages M are transferred on the bus. Fig.7 shows the structure of the network. M3_2 means: 2nd type of message that is transmitted by node number 3, for instance.

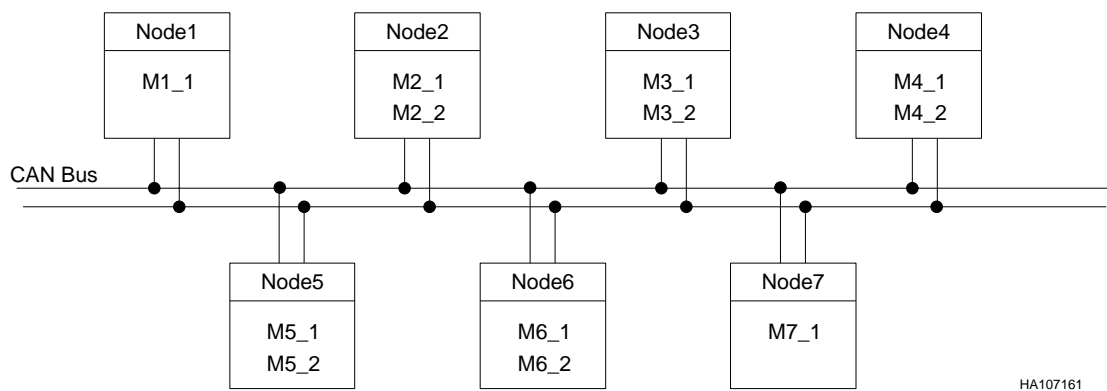


Fig. 7 Network example

The communication matrix and information about message length, repetition time and node numbers are given in table 10, whereby the described communication of the example with the according messages results in a total bus load of about 23%.

The CPU load for CAN communication is defined as the percentage of time the CPU is serving the CAN communication; its calculation is described in detail in chapter 4.6.

The diagram of figure 8 shows the CPU load of nodes 1...7, split up in receive and transmit actions of the CPU. Receive actions are executed for all messages that pass the acceptance filter. These messages are **copied** into the CPU RAM except they are not of interest for the CPU, the latter means they are **rejected**. The result of this simulation is that the CPU spends only 3.4% of the time for CAN related procedures. In this example 96.6% of the time is free for other CPU activities.

Transmitting node / message		DLC	ID	Repetition Time [ms]	receiving node						
					1	2	3	4	5	6	7
1	M1_1	4	10	2	-	x	x	x	-	-	x
2	M2_1	7	11	2	x	-	x	x	x	x	x
2	M2_2	2	30	100	-	-	-	-	-	-	x
3	M3_1	5	15	20	x	x	-	-	x	-	x
3	M3_2	3	31	100	-	-	-	-	-	-	x
4	M4_1	5	32	20	-	x	-	-	-	x	x
4	M4_2	3	33	100	-	-	-	-	-	-	x
5	M5_1	8	20	100	x	x	x	-	-	x	x
5	M5_2	8	34	100	-	-	-	-	-	-	x
6	M6_1	8	21	100	-	x	-	x	x	-	x
6	M6_2	8	35	100	-	-	-	-	-	-	x
7	M71	8	36	100	-	-	-	-	x	x	-

Table 10: Communication Matrix of the network example. (ID = Identifier, DLC = data length code)

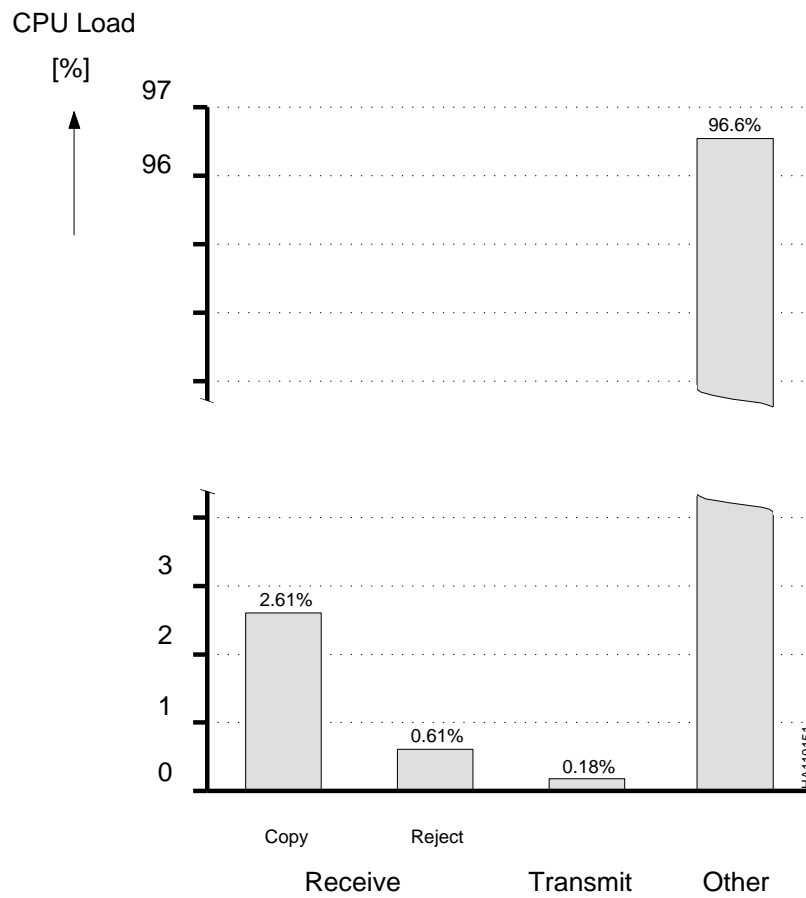


Fig. 8 CPU load (Average of nodes 1 . . . 7)

4.6 Calculation of the CPU Load for CAN Communication

In chapter 4.5 a practical example was presented for which the CPU load for CAN communication had been investigated. The figures were obtained for a real set-up using 7 nodes. In this chapter the details of such a CPU load calculation are presented.

The following calculations and diagrams give hints and ideas to the user of the P8xC592 about the receive interrupt service execution time and CPU load when serving the CAN controller. To get results as reliable as possible all figures are calculated for worst case. As shown in fig.8 both reception of messages and transmission of messages result in CPU load, but the partial CPU load for transmission obviously is almost negligible. Therefore the considerations in the next sections have been focussed on the reception of messages. Reception of messages is normally initiated by interrupt. The according interrupt service routine copies the Rx buffer contents to an internal CPU RAM location. Its execution time should be as short as possible in order to achieve a low CPU load.

The **CPU load** for CAN communication is defined as the percentage of time the CPU is serving the CAN communication, measured in a time interval of interest.

In case the time interval is shorter than the duration of a message transfer on the bus, the **Spare Time** should be considered instead of the CPU load. The **Spare Time** is defined as the amount of coherent CPU time the CPU may reserve for non-CAN activities between the reception of consecutive messages.

The next section presents the software which meets the requirements for a fast execution of the receive interrupt service.

Receive Interrupt Service Routine

Base of all the following calculations is a simple receive interrupt service routine for the P8xC592 (table 11, see also Appendix A.1). The calculations of CPU load have been investigated by using a reference software (fig.9, Appendix A.1) that uses the receive interrupt service routine. It also checks the data overrun condition in order to evaluate the Spare Time. The described software and the results are an example and transformation to user specific requirements is very easy.

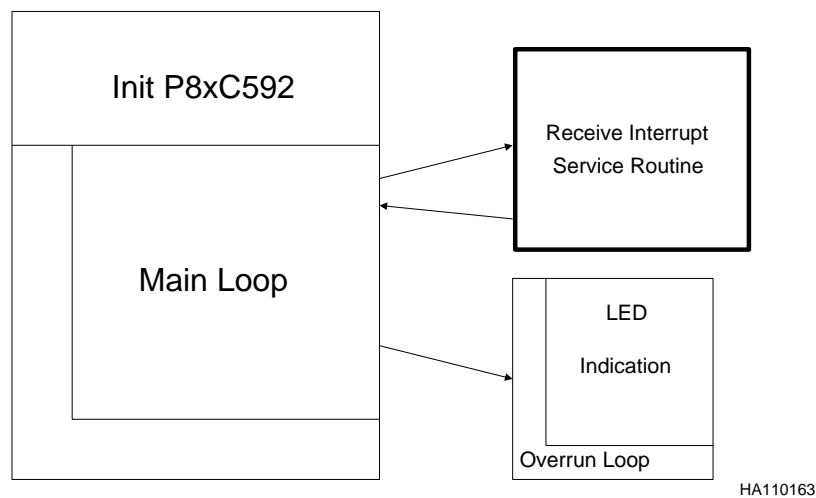


Fig. 9 Reference software with Receive Interrupt Service Routine

First of all the arrangement of the reference software is given in a short summary:

Identifier:	ID10, ID9, ID8, ID7 are fixed by acceptance filter, e.g. ID = 0101 XXXX XXX
Interrupts:	Receive Interrupt enabled
Data Copy:	data bytes according data length code and a part of the identifier (as an indication for a new message) are copied into the internal μ C Main RAM
Remote Frames:	in case of remote frame reception the data length code is deleted and only a part of the identifier is copied as an indication of its reception.
Overrun:	the overrun status bit is checked in the main loop. Whenever an overrun condition would be detected, indication would be done via LED. The program remains in the overrun loop until reset.
Reject:	Messages which pass the acceptance filter, but are useless for the μ C, are rejected by the software automatically.

CAN_INTERRUPT:

context switch save Accu & PSW select register bank
clear interrupt bits (read Interrupt Register)
calculate table address fetch target address from table
if target address \neq 0, then copy Rx Buffer to int. μ C RAM starting at target address
release Receive Buffer (Acknowledge)
restore context

Table 11: Flowchart of the Receive Interrupt Service Routine

Receive Interrupt Execution Time

Table 12 shows the interrupt execution time for the used receive interrupt service routine. The routine is split up into different macros, for each of them the according processing time has been calculated.

The receive interrupt execution time is shorter, when a message has to be rejected. Therefore two columns are shown, the particular processing time for the copy and the reject case. Another column shows the time passing until the Receive Buffer is released, for evaluation of the CPU Spare Time (see chapter 4.6.2).

Times are given in units of machine cycles and one cycle consists of 12 oscillator periods. The used oscillator frequency of the P8xC592 is 16 MHz resulting in a cycle time of 0.75 μ s.

Fig. 10 shows the receive interrupt execution time ("copy" and "reject") as a function of the message data length code (DLC). For purpose of comparison also the message transfer time on the bus is given for the data rates: 250kbit/s, 500kbit/s and 1Mbit/s.

Macro Name	Machine Cycles	Copy	Reject	Rx Buff Release
Max. Interrupt Response Time	5	x	x	x
Long Jump to Interrupt Service Routine	2	x	x	x
Context Switch	6	x	x	x
Clear Int. Bits	1	x	x	x
Calculate Target Address	15	x	x	x
Copy rx buffer	8	x	-	x
Acknowledge	2	x	x	x
Restore Context	6	x	x	-
Sum of cycles		45	37	39

Table 12: Summary of receive interrupt execution times (machine cycles)

Fig. 10 shows that due to the DMA function of the P8xC592 the receive interrupt execution time is always independent of the length of the received message. It is very important that the receive interrupt execution time is much shorter than the time the message itself spends on the bus. This clearly shows that a data overrun caused by a burst of messages can be excluded.

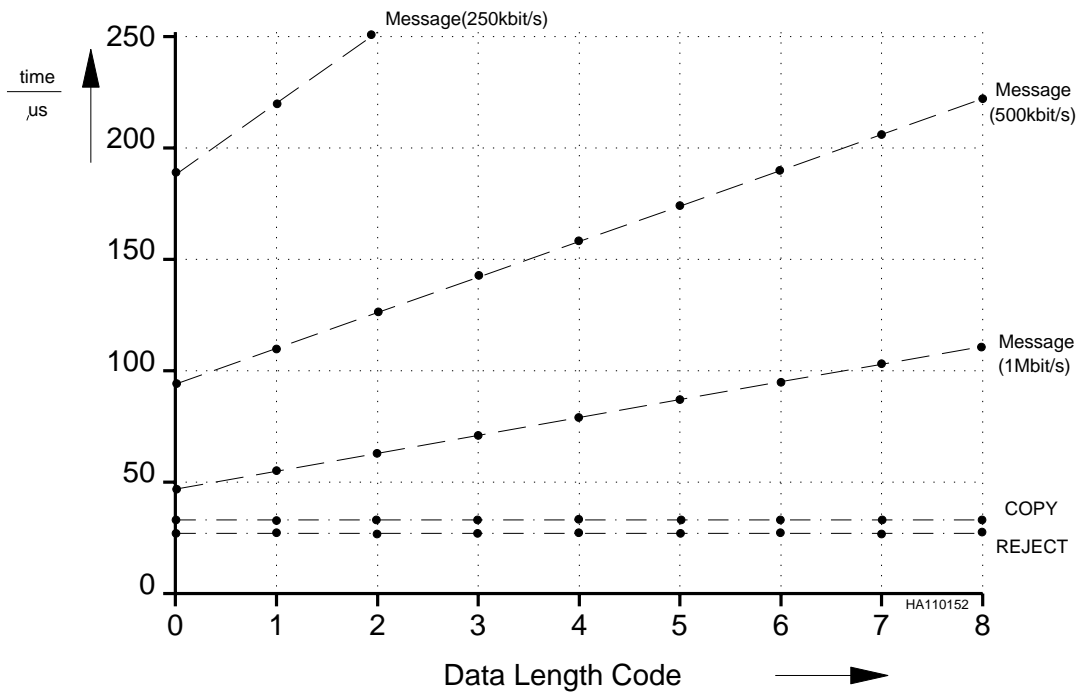


Fig.10 Receive interrupt execution time ("copy" and "reject") and message transfer time ("Message") for 16MHz CPU as a function of Data Length Code

4.6.1 CPU Load

Three parameters are important for the calculation of the CPU load while receiving messages: The used receive interrupt execution time (see tables 11/12), the bit rate and the bus load.

The **bus load** is the percentage of time the bus is occupied (active) by transferring messages. Therefore it has to be calculated how many messages are transferred in a time interval, and how long a message transfer is on the bus. The latter is the message length (=number of bits) multiplied by the time of one bit. The message length depends on the data length code. For the following calculations a data length code estimation has to be made.

$$\text{bus load} = \frac{\text{bus active time}}{\text{time interval}} = \frac{\text{number of messages} \cdot \text{message length} \cdot \text{bit time}}{\text{time interval}}$$

In order to get a direct relation between CPU Load, bit rate and bus load, from the formula for the bus load the formula for the number of messages is derived, which can be inserted into the definition of the CPU load:

$$\text{number of messages} = \frac{\text{bus load} \cdot \text{time interval}}{\text{message length} \cdot \text{bit time}}$$

$$\text{CPU load} = \frac{\text{number of messages} \cdot \text{receive interrupt execution time}}{\text{time interval}}$$

$$\text{CPU Load} = \frac{\text{bus load} \cdot \text{time interval} \cdot \text{receive interrupt execution time}}{\text{message length} \cdot \text{bit time} \cdot \text{time interval}}$$

With the definition of $\text{bit rate} = 1 / \text{bit time}$ we get

$$\text{CPU load} = \text{bus load} \cdot \text{bit rate} \cdot \frac{\text{receive interrupt execution time}}{\text{message length}} = \text{bus load} \cdot \text{bit rate} \cdot \tau$$

The result is, that the CPU load is proportional to the bus load and bit rate. The term $\tau := \text{receive interrupt execution time} / \text{message length}$ only depends on the data length code, as it is shown in fig. 11.

Using this formula the CPU load can be calculated for any bit rate at any bus load: for example, a bus load of 10% at 400kbit/s with only one-byte messages (copy all of them) means $10\% \cdot 0.4 \text{ Mbit/s} \cdot 0.6 \mu\text{s/bit} = 2.4\%$ of CPU load. For the example of 4-byte messages (DLC=4) the CPU load has been calculated for different bit rates and different bus loads, the result is shown in table 13.

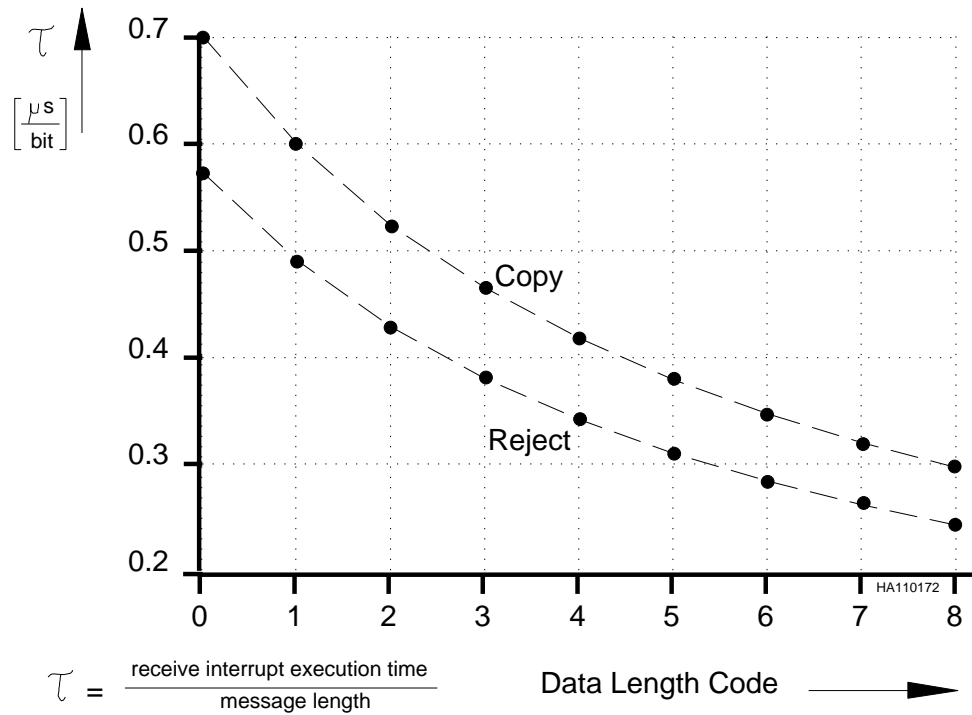


Fig. 11 Diagram for calculation of the CPU load while receiving messages

bit rate	10 % bus load	20 % bus load	50 % bus load
100 kbit/s	0.4 %	0.8 %	2.1 %
250 kbit/s	1.0 %	2.1 %	5.2 %
500 kbit/s	2.1 %	4.2 %	10 %
1 Mbit/s	4.2 %	8.4 %	21 %

Table 13: CPU load when 4-byte messages (DLC=4) are used, for worst case (copy all of them)

4.6.2 Spare Time

But, what happens when the CAN interrupt is delayed or interrupted (e.g. by other interrupt service routines with same or higher priority) ? The first statement is, that the CAN receive interrupt can be delayed for at least that amount of time that is the difference between message transfer time and the receive interrupt execution time.

The actual time that a CAN receive interrupt service may be delayed without risk of losing a message ("data overrun") is even longer: In fig.12 the execution of the receive interrupt service routine has been delayed so that the routine is not yet finished when the next message comes in, but the 'Release Receive Buffer' command comes just in time before the first byte of the next message is to be stored in the Receive Buffer. No message is lost, but of course that long delay must be compensated by faster response for subsequent reception.

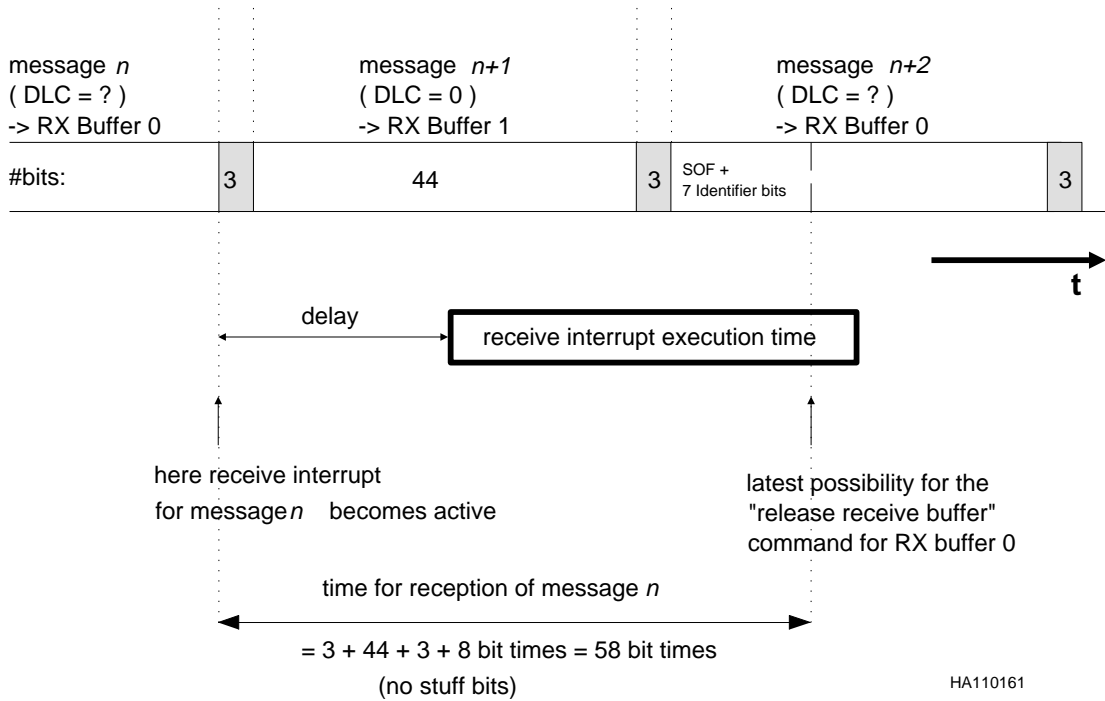


Fig. 12 Delay of receive interrupt service. The worst case is, when a message is followed by a 0-byte message plus another message of any DLC.

The resulting allowed spare time (worst case) is shown in fig.13 for different bit rates. It has been calculated by relating the Receive Buffer Release time of table 12 (39 cycles) to the transmission time of a 0-byte message plus the first byte of a next message (58 bits).

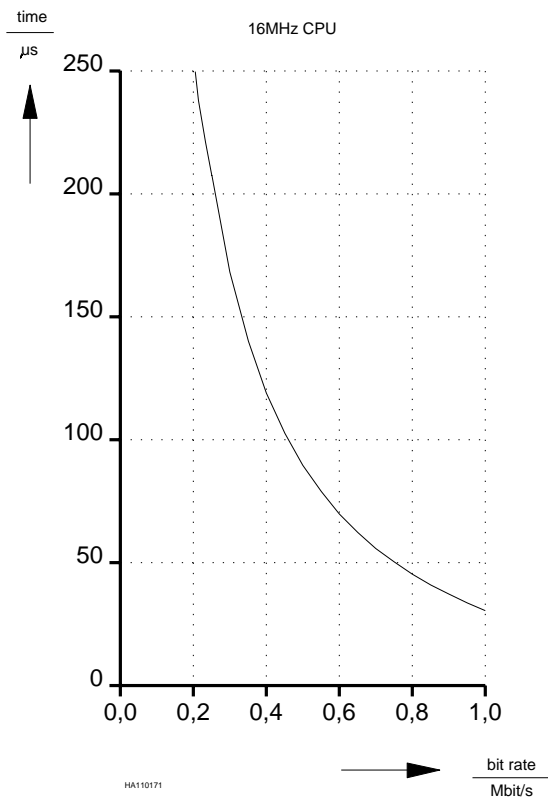


Fig. 13 Worst case spare time

5. Development Tools

For the P8xC592 several powerful support tools can be supplied to assist during the design and test phase. These tools are:

- o the P8xC592 Evaluation Board
- o P8xC592 In-Circuit Emulators
- o P87C592 EPROM programmers
- o debug tools for CAN communication
NetSim NetAna NetEmu

5.1 Philips P8xC592 Evaluation Board

The P8xC592 evaluation board (OM4239) is a most versatile aid consisting of a ready-to-use hardware and software module very similar to a real CAN bus node. The P8xC592 evaluation board can be used in a car since it has its own 5V supply. An RS232 interface allows the P8xC592 evaluation board to be connected to a terminal or to a PC with terminal emulating software.

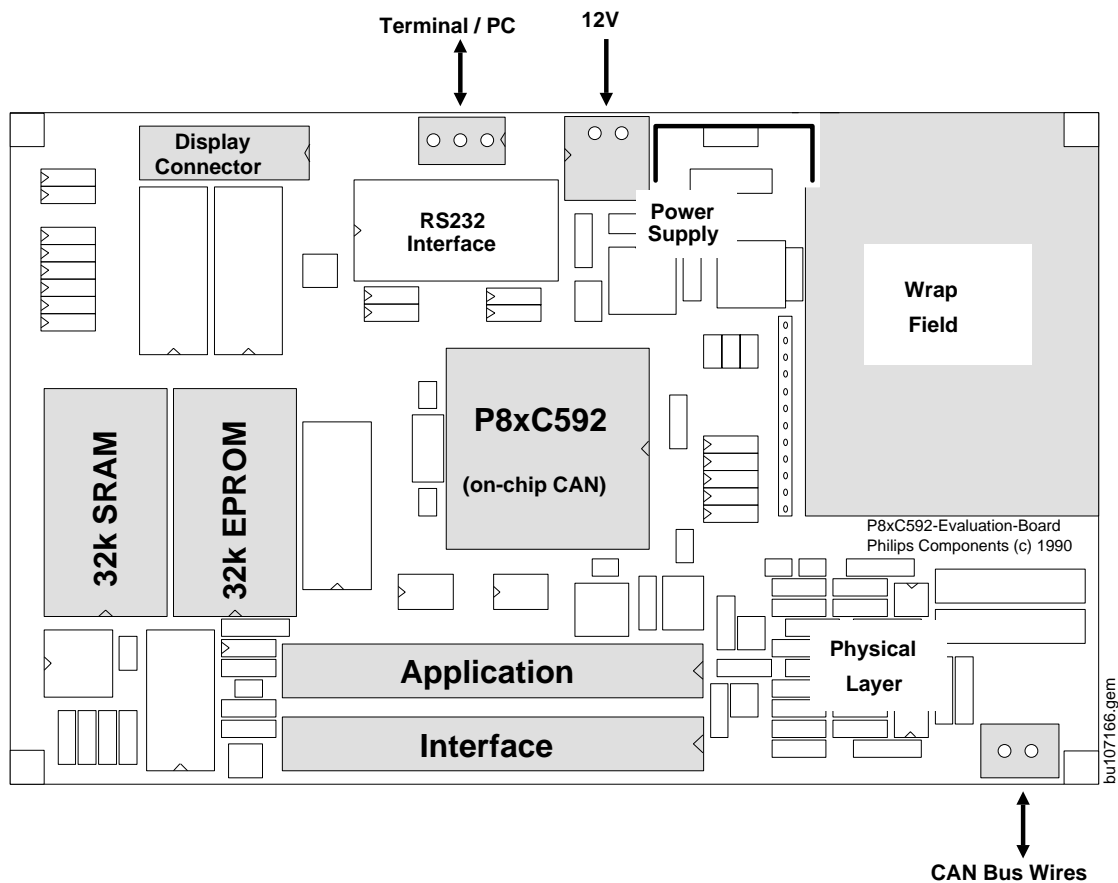


Fig. 14 P8xC592 Evaluation Board

5.1.1 P8xC592 Evaluation Board Hardware

The P8xC592 evaluation board hardware (single EURO format size) is shown in figure 14. It consists of:

- o P87C592 microcontroller with an external memory capacity of 32 KBytes for RAM and 32 KBytes for ROM storage. Together with the on-chip EPROM there are 48 KBytes of continuous program memory
- o 5V power supply with protection against car battery voltage fluctuations
- o off-chip transceiver circuit, designed to meet ISO/TC 22/SC 3 N608E, with two selectable options:
 - very low standby power consumption
 - support of single wire communication to recover from wiring failures.
- o RS232 interface
- o removable LED unit for demonstration purposes
- o wrap field for the user's specific circuitry

5.1.2 P8xC592 Evaluation Board Software

The software for the P8xC592 evaluation board is stored in the on-board EPROM. The software is designed to assist users with different experience in CAN-based networks:

- o A user with little experience is able to activate the demonstration software. A menu-driven software monitor allows the contents of the P87C592's CAN-registers to be altered and thereby enables the user to gain experience. For the latter an RS232-terminal (e.g. VT100) is required.
- o A user with more experience will use the "download" facility; this allows the user to load new software on to the P8xC592 evaluation board. Download requires a PC with terminal emulating software.

The P8xC592 evaluation board is also ready to be used as a bus monitor, receiving messages from the bus for display on a terminal.

5.2 In-Circuit-Emulators

For the software development on the P8xC592 several in-circuit-emulators (ICE) are available.

5.2.1 Philips Stand-alone Debug System (SDS)

Philips' well known and well accepted stand-alone debug station (SDS) for the real-time development of 8-bit μ Cs is already prepared for future probes > 16MHz. Three configurations are possible:

- o stand-alone operation together with a terminal
- o connected to a terminal plus a host computer (download/upload)
- o connected to a PC/AT (IBM or compatible) with terminal emulation software.

Features of the SDS:

- o fully transparent real-time emulation
- o allows optimal emulation according to the exact specification of the target controller
- o emulation memory: 64 KBytes with no wait states
- o interfaces to external equipment
- o full assembly-level debugging
- o HLL debugging possible
- o single step and breakpoint setting
- o trace and triggering with hardware qualifiers
- o trace memory 2048 lines
- o new improved handbook
- o probes for
 - optimal connection to the target system
 - optimal emulation of the target μ C.

For emulation of the P8xC592 the user needs the following parts:

- o SDS80C51 stand-alone debug system (OM4120S)
- o probe base (OM4110)
- o emulation head "592" (OM4112)

Software for development support with the SDS (assembler, PL/M-compiler, C-compiler, HLL debugger) is offered and supported by

Tasking B.V.
Plotterweg 31
3821 BB Amersfoort, Netherlands

their products can also be ordered via Philips.

5.2.2 ICE from Other Vendors

Philips supports all major third-party ICE suppliers with emulating chips for the P8xC592. Most of them already announced to support the P8xC592.

5.3 Programming Support for P87C592 (EPROM)

Philips offers a low-cost programmer for microcontrollers inclusively the P87C592:

- o LCPX5X40 programmer (OM4232)
 - 87C592-PLCC68 adaptor (OM4235)

5.4 Debug Tools for CAN Communication

In addition to the P8xC592 evaluation board three other sophisticated development and debug tools for CAN communication can be supplied. These are offered and supported by

Gesellschaft für Informatik und Mikro-Elektronik
Prof. Dr.-Ing. W.Lawrenz mbH
Ferdinandstr. 15 A
3340 Wolfenbüttel
Germany

NetSim

NetSim (Network Simulator) is a software simulator for use with a Personal Computer. The CAN network is described using NetSim on the PC by:

- o number of network nodes
- o data transmission rate
- o message identifiers / message length / message transmission repetition rate
- o noise

The simulation is then started. NetSim provides information for various parameters, such as:

- o message delays
- o bus load

NetSim assists during the design phase to investigate these parameters.

NetAna

NetAna (Network Analyzer) is a combined hardware / software tool, operating in conjunction with a PC.

NetAna has two basic functions:

- o to monitor the bus traffic and store the data on the hard disk in the PC for subsequent analysis
- o an event is triggered (identifier, bus error, etc.) and the messages around the trigger point are recorded.

NetAna assists to trace communication failures in an existing CAN network

NetEmu

NetEmu (Network Emulator) enables the user to transmit defined messages into an operational CAN network. The resultant network response can then be analyzed by NetAna.

6. References

- [1] CAN Specification Version 1.2, Philips Components 1990
- [2] P8xC592 target device specification, Version 2.2, Philips Export B.V. 1991
- [3] Data sheet PCA 82C200 Stand-alone CAN-controller, Philips Export B.V. 1990, 12NC: 9397 285 30011
- [4] Application of the PCA 82C200 CAN Controller (PSCC), Philips Export B.V. 1990, 12NC: 9398 373 50011
- [5] Bit Timing Parameters for CAN Networks, Application Note KIE07/91ME, Philips Components PCALH 1991
- [6] Road vehicles - Serial data communication for automotive application. Part 1: Controller Area Network (CAN). ISO/DIS 11519 part 1, International Organization for Standardization 1992
- [7] Road vehicles - Interchange of digital information - Controller Area Network (CAN) for high speed communication. ISO/DIS 11898, International Organization for Standardization 1992
- [8] CAN bus failure management using the P8xC592 microcontroller, Application Note HKI/AN 91 020, Philips Semiconductors PCALH 1991
- [9] Single-chip 8-bit microcontrollers: PCB83C552 - User Manual, Philips Export B.V. 1988, 12NC: 9398 637 90011
- [10] CAN Physical Layer Concepts for the P8xC592 Microcontroller, Application Note HKI/AN 91 027, Philips Semiconductors PCALH 1991

Appendix

A. Reference software for investigation of the CPU load

A.1 Receiver part

This module is a program including a very fast, versatile receive interrupt service routine which is able to handle up to 128 identifiers. It runs on the P8xC592 Evaluation Board (OM4239), for instance. With only little modifications it can be adapted to other applications.

The receive interrupt execution time is less than 34µs and every software reject is done within 28µs.

The acceptance filter of the CAN part is set to 0101 XXXX XXX. Upon reception of a message which passes the acceptance filter, the data bytes (plus the second byte of the Rx buffer for signalling the reception of new data to the main program) are copied into the internal RAM of the P8xC592, according to a table. In this table for each message the corresponding RAM address can be found or a "0", telling that the message is not of interest and shall be rejected.

In case of an overrun condition, indication is done via LED.

```
CONTROL          EQU      0H
COMMAND          EQU      1H
STATUS           EQU      2H
INTERRUPT        EQU      3H
ACCEPTANCE_CODE EQU      4H
ACCEPTANCE_MASK EQU      5H
BUS_TIMING_0     EQU      6H
BUS_TIMING_1     EQU      7H
OUTPUT_CONTROL   EQU      8H

CANADR           EQU      0DBH
CANDAT           EQU      0DAH
CANCON           EQU      0D9H
CANSTA           EQU      0D8H

AUTO_RX_BUFFER   EQU      34H
RX_BUFFER        EQU      14H
DMA_RX_BUFFER    EQU      94H

INT_MASK         EQU      0000010B      ; Rx Interrupt enabled

ES1              BIT      0ADH

DSEG AT 30H
  ARRAY_LONG: DS      9      ; space for Rx of an 8-byte message
  ARRAY_SHORT: DS     1      ; space for Rx of a 0-byte message

BIT_VAR SEGMENT DATA BITADDRESSABLE
RSEG BIT_VAR
  INT_SAVE: DS      1
  RX_INT BIT INT_SAVE.0

CSEG AT RESET
  LJMP          MAIN_PROG

CSEG AT 2BH
  LJMP          CAN_INTERRUPT
```

MAIN SEGMENT CODE
RSEG MAIN

MAIN_PROG:

```
----- Initialization -----  
  
    MOV     SP,#7FH           ; set stackpointer  
  
    CLR     EA                ; disable all interrupts  
    SETB   ES1              ; CAN Controller interrupt enabled  
  
    MOV     DPTR,#4000H  
    MOV     A,#0FFH  
    MOVX   @DPTR,A          ; LEDs - dark  
  
    MOV     ARRAY_LONG,#0     ; delete RAM position  
    MOV     ARRAY_LONG+1,#0  
  
    MOV     INT_SAVE,#0      ; delete interrupt save register  
  
INIT_CAN:  
    MOV     CANADR,#CONTROL   ; reset request  
    MOV     CANDAT,#0000001B  
  
    MOV     A,CANDAT  
    JNB    ACC.0,INIT_CAN    ; repeat reset, if reset request is  
                                ; absent  
  
    MOV     CANADR,#ACCEPTANCE_MASK  
    MOV     CANDAT,#0FH  
  
    MOV     CANADR,#ACCEPTANCE_CODE ; ID = 0101 XXXX XXX  
    MOV     CANDAT,#05FH  
  
    MOV     CANADR,#BUS_TIMING_0  
    MOV     CANDAT,#80H  
  
    MOV     CANADR,#BUS_TIMING_1  
    MOV     CANDAT,#23H  
  
    MOV     CANADR,#OUTPUT_CONTROL  
    MOV     CANDAT,#0FAH  
  
    MOV     CANADR,#CONTROL  
    MOV     A,CANDAT  
  
    ORL     A,#INT_MASK      ; enable receive interrupt  
    ANL     A,#11111110B    ; reset request bit = 0  
    MOV     CANDAT,A  
  
    SETB   EA                ; enable all interrupts  
  
LOOP:  
    JB     CANSTA.1,OVERRUN  
    SJMP   LOOP  
  
OVERRUN:  
    MOV     A,ARRAY_LONG  
    MOV     DPTR,#4100H  
    MOVX   @DPTR,A          ; first byte of message to green LED  
  
    MOV     A,ARRAY_LONG+1  
    MOV     DPTR,#4200H  
    MOVX   @DPTR,A          ; second byte of message to red LED  
  
    SJMP   $
```

```

----- Receive Interrupt Service Routine -----
CAN_INTERRUPT:

----- CONTEXT_SWITCH ----- 6 cycles -

    PUSH        ACC
    PUSH        PSW
USING 1
    SETB        RS0
    CLR         RS1

----- CLEAR_INTERRUPT ----- 1 cycle -

CLR_INT:
    MOV         A,CANCON          ; clear interrupt bits

----- RX_INT_TARGET_ADDR ----- 15 cycles -

BEGIN_RX:
    MOV         CANADR,#AUTO_RX_BUFFER ; set auto incr. and CANA = 20dec
    MOV         A,CANDAT          ; fetch RX buffer
    ANL        A,#0FH            ; upper 4 bits masked per
                                ; acceptance filter

    MOV         R1,A
    MOV         A,CANDAT          ; fetch RX buffer+1
    MOV         R5,A            ; temp. save of RX buffer+1
    ANL        A,#0E0H          ; ID2,ID1,ID0,0,0,0,0,0
    RR         A                ; 0,ID2,ID1,ID0,0,0,0,0
    ORL        A,R1            ; 0,ID2,ID1,ID0,ID6,ID5,ID4,ID3
    ADD        A,#TABLE-TABLE_BASE
    MOVC       A,@A+PC          ; accu contains the target address
TABLE_BASE:
    JZ         RELEASE_BUF      ; software reject - no data copying

----- RX_INT_COPY_DATA_LOOP_DMA ----- 8 cycles -

    MOV         CANSTA,A          ; target address for DMA
    MOV         A,R5            ; get RX Buffer+1
    JNB        ACC.4,DMA_START   ; test of RTR bit
    MOV         CANADR,#RX_BUFFER+1 ; in case of a Remote Frame:
    ANL        CANDAT,#0F0H     ; delete data length code,
                                ; only the descriptor byte is copied

DMA_START:
    MOV         CANADR,#DMA_RX_BUFFER+1
    NOP
    NOP                                ; wait for data transfer

----- RX_INT_ACKN ----- 2 cycles -

RELEASE_BUF:
    MOV         CANCON,#4        ; release receive buffer

----- RESTORE_CONTEXT ----- (6) cycles -

END_RX:
    POP        PSW
    POP        ACC
    RETI

----- RX_INT_TARGET_ADDRESS_TABLE -----

TABLE:
    ; copy data of message 01010101000 to ARRAY_LONG (8+1 bytes)
    ; copy data of message 01010101010 to ARRAY_SHORT (0+1 byte)
    DB         0,0,0,0,0,ARRAY_LONG,0,0,0,0,0,0,0,0,0,0 ; ID2=0,ID1=0,ID0=0
    DB         0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0        ; ID2=0,ID1=0,ID0=1
    DB         0,0,0,0,0,ARRAY_SHORT,0,0,0,0,0,0,0,0,0,0 ; ID2=0,ID1=1,ID0=0
    DB         0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0        ; ID2=0,ID1=1,ID0=1
    DB         0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0        ; ID2=1,ID1=0,ID0=0
    DB         0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0        ; ID2=1,ID1=0,ID0=1
    DB         0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0        ; ID2=1,ID1=1,ID0=0
    DB         0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0        ; ID2=1,ID1=1,ID0=1
END

```

A.2 Transmitter part

----- Tx Procedure -----

This module is a program including a transmit procedure using a loop that copies data from the internal μ C RAM to the Tx buffer of the P8xC592. It runs on the P8xC592 Evaluation Board, for instance. Whenever the controller gets bus access, the contents of the buffer is transmitted on the CAN bus. Therefore it generates a very high bus load. The Identifier of the message has been chosen such, that it will be received by the reference software (see Appendix A.1).

```
CONTROL      EQU      0H
COMMAND      EQU      1H
STATUS       EQU      2H
INTERRUPT    EQU      3H
ACCEPTANCE_CODE EQU    4H
ACCEPTANCE_MASK EQU    5H
BUS_TIMING_0 EQU      6H
BUS_TIMING_1 EQU      7H
OUTPUT_CONTROL EQU    8H

CANADR       EQU      0DBH
CANDAT       EQU      0DAH
CANCON       EQU      0D9H
CANSTA       EQU      0D8H

DMA_TX_BUFFER EQU    8AH

DSEG AT 30H
  ARRAY:     DS      10

CSEG AT RESET
  LJMP      MAIN_PROG

MAIN SEGMENT CODE
RSEG      MAIN

MAIN_PROG:
```

----- Initialization -----

```
MOV      SP,#7FH          ; set stackpointer

CLR      EA              ; disable all interrupts

MOV      DPTR,#4000H
MOV      A,#0FFH
MOVX    @DPTR,A          ; LEDs - dark

MOV      ARRAY+0,#01010101B ; ID10, ID9, ID8, ID7, ID6, ID5, ID4, ID3
MOV      ARRAY+1,#00001000B ; ID2, ID1, ID0, RTR, DLC3, DLC2,
                           ; DLC1, DLC0

MOV      ARRAY+2,#011H    ; 1st data byte
MOV      ARRAY+3,#022H    ; 2nd data byte
MOV      ARRAY+4,#033H    ;
MOV      ARRAY+5,#044H    ;
MOV      ARRAY+6,#055H    ;
MOV      ARRAY+7,#066H    ;
MOV      ARRAY+8,#077H    ;
MOV      ARRAY+9,#088H    ; last data byte
```

```
INIT_CAN:
  MOV     CANADR,#CONTROL      ; reset request
  MOV     CANDAT,#0000001B
  MOV     A,CANDAT
  JNB    ACC.0,INIT_CAN      ; repeat reset, if reset request is
                             ; absent

  MOV     CANADR,#ACCEPTANCE_MASK ; acceptance filter not used for Tx
  MOV     CANDAT,#0FFH

  MOV     CANADR,#BUS_TIMING_0
  MOV     CANDAT,#80H

  MOV     CANADR,#BUS_TIMING_1
  MOV     CANDAT,#23H

  MOV     CANADR,#OUTPUT_CONTROL
  MOV     CANDAT,#0FAH

  MOV     CANADR,#CONTROL
  MOV     A,CANDAT
  ANL    A,#11111110B      ; reset request bit = 0
  MOV     CANDAT,A

----- Tx Loop -----

BEGIN_TX:
  MOV     CANSTA,#ARRAY      ; target RAM address

WAIT:
  JNB    CANSTA.2,WAIT      ; wait until Transmit Buffer access

  MOV     CANADR,#DMA_TX_BUFFER ; Transmit Buffer = 10H
  NOP    ; set DMA bit
  NOP

  MOV     CANCON,#0000001B   ; transmission request

  SJMP   BEGIN_TX

END
```

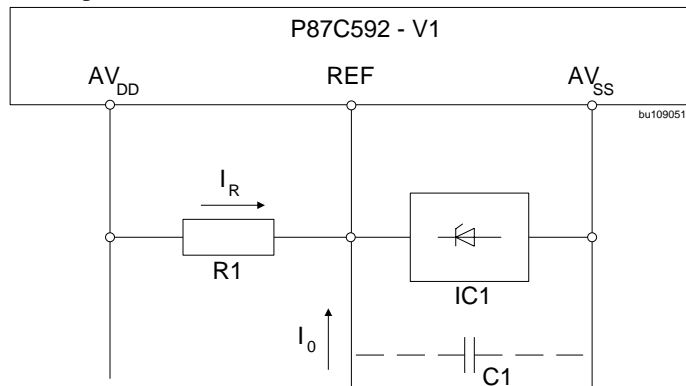
Specification Differences for the P87C592 - V1

Control Register / REF pin:

The bit "Reference Active" (bit 5 of the Control Register) is not provided in the P87C592-V1. This means it is not necessary to set the input function of pin REF (see Initialization procedure, chapter 4.3.1).

In the case that the REF pin (pin 55) shall be used in the application for tolerating physical bus errors - opens and shorts of the bus wires - a simple external circuit has to be connected to it.

Application example for a 2.5V reference voltage:



Components:

IC1: LM285Z-2.5 (-40°C ... +85°C; 1.5%)
 LM385BZ-2.5 (0°C ... +70°C; 1.5%)
 LM385Z-2.5 (0°C ... +70°C; 3%)

R1: High-Speed Transceiver: 1kΩ (IR = 2.5 mA typ.)
 Low-Speed Transceiver: 16kΩ (IR = 160 μA typ.)

C1: High-Speed Transceiver: 0
 Low-Speed Transceiver: 1nF

Characteristics:

- Precise voltage regulation: $\pm 3.4\%$ LM285Z } over temperature
 $\pm 2.6\%$ LM385BZ }
- Low current consumption: (2.5 mA resp. 160 μA)
- Supply voltage range: 4.5 V to 5.5 V
- Load capacity:

I _O	High-speed-circuit	Low-speed-circuit
source	-1.9 mA	-70 μA
sink	5 mA	5 mA

