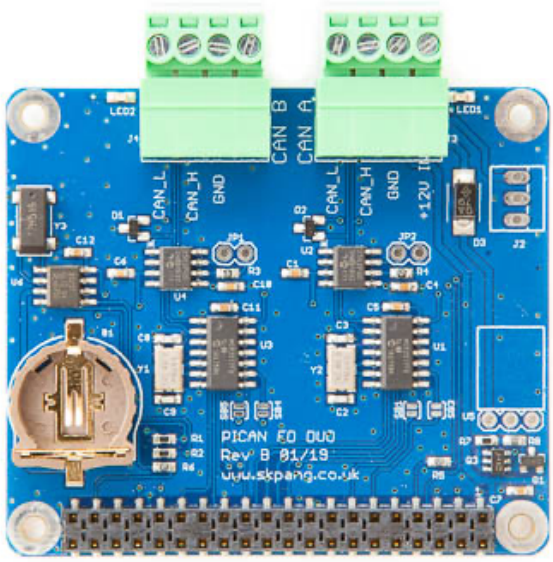

PiCAN FD DUO with RTC

USER GUIDE V2.0

Product name	PICAN FD CAN-Bus Board for Raspberry Pi 4
Model number	RSP-PICAN FD DUO
Manufacturer	SK Pang Electronics Ltd

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1. Introduction

This PiCAN FD Duo board provides two channel CAN-Bus FD capability for the Raspberry Pi. It uses the Microchip MCP2517FD CAN controller with MCP2562FD CAN transceiver. Connection are made via 4 way screw terminal. A real time clock with battery back up (battery not included) is also on the board.

The improved CAN FD extends the length of the data section to up to 64 bytes per frame and a data rate of up to 8 Mbps.

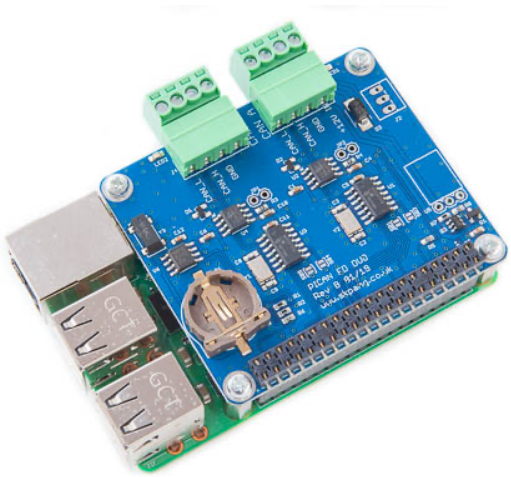
Easy to install SocketCAN driver. Programming can be done in C or Python.

1.1. Features

- Arbitration Bit Rate upto 1Mbps
- Data Bit Rate up to 8Mbps
- CAN FD Controller modes
- Mixed CAN2.0B and CANFD mode
- CAN2.0B mode
- Conforms to ISO11898-1:2015
- High speed SPI Interface
- CAN connection via 4way screw terminal
- 120Ω terminator ready
- Serial LCD ready
- LED indicator
- Four fixing holes, comply with Pi Hat standard
- SocketCAN driver, appears as can0 and can1 to application
- Interrupt RX on GPIO25 and 05
- RTC with battery backup (battery not included)

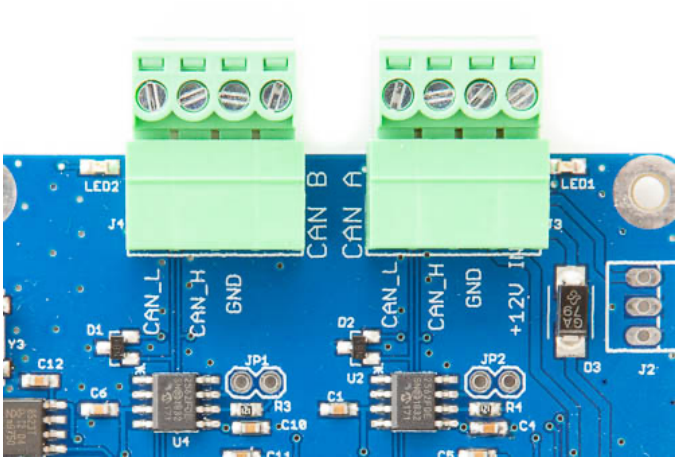
2. Hardware Installation

Before installing the board make sure the Raspberry is switched off. Carefully align the 40way connector on top of the Pi. Use spacer and screw (optional items) to secure the board.



1.2. Screw Terminals

The CAN connections are made via the 4way screw terminals.



J4	Function
1	CAN_L
2	CAN_H
3	GND
4	n/c

J3	Function
1	CAN_L
2	CAN_H
3	GND
4	+12v

Note : The +12v In is only used on the PiCAN2 FD Duo board with SMPS option fitted.

1.3. 120Ω Terminator

There is a 120Ω fitted to the board. To use the terminator solder a 2way header pin to JP1 and JP2 then insert a jumper.

1.4. LED

There is a red LED fitted to each channel. This is connected to GPIO04 and GPIO26.

1.5. Not Fitted Items

J2 can be use to power a serial LCD with data on TXD line from the Pi. There is also 5v supply on J5.

1.6. Switch Mode Power Supply (optional)

This is an optional 5v module that can power the Pi. It has an input voltage range of 6v to 20v.

3. Software Installation

It is best to start with a brand new Raspbian image. Download the latest from:

https://www.raspberrypi.org/downloads/raspbian/

After first time boot up, do an update and upgrade first.

```
sudo apt-get update
sudo apt-get upgrade
sudo reboot
```

Add the overlays by:

```
sudo nano /boot/config.txt
```

Add these lines to the end of file:

```
dtparam=spi=on
dtoverlay=i2c-rtc,pcf8523
dtoverlay=mcp251xfd,spi0-0,interrupt=25
dtoverlay=mcp251xfd,spi0-1,interrupt=05
```

Reboot Pi:

```
sudo reboot
```

1.7. Installing CAN Utils

Install the CAN utils by:

```
sudo apt-get install can-utils
```

1.8. Bring Up the Interface

You can now bring the CAN interface up with CAN 2.0B at 500kbps:

```
sudo /sbin/ip link set can0 up type can bitrate 500000
```

or CAN FD at 500kpbs / 2Mbps. Use copy and paste to a terminal.

```
sudo /sbin/ip link set can0 up type can bitrate 500000 dbitrate 2000000 fd on sample-point .8 dsample-point .8
```

Connect the PiCAN2 to your CAN network via screw terminal or DB9.

To send a CAN 2.0 message use :

```
cansend can0 7DF#0201050000000000
```

This will send a CAN ID of 7DF. Data 02 01 05 – coolant temperature request.

To send a CAN FD message with BRS use :

```
cansend can0 7df##15555555555555555
```

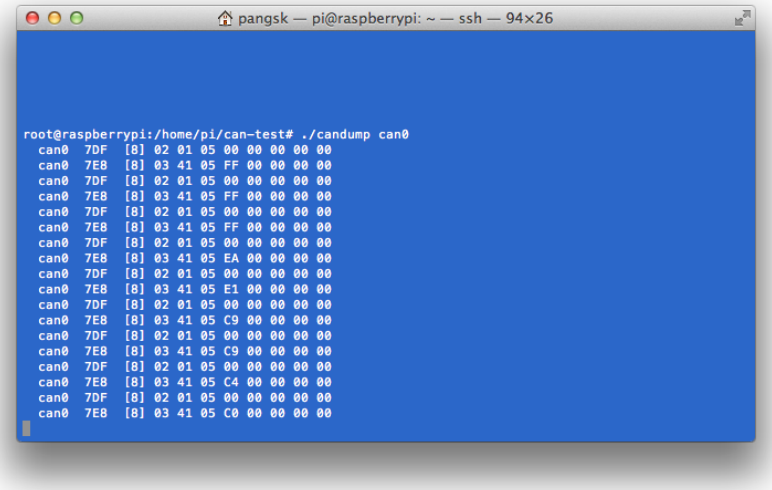
To send a CAN FD message with no BRS use :

```
cansend can0 7df##05555555555555555
```

Connect the PiCAN to a CAN-bus network and monitor traffic by using command:

```
candump can0
```

You should see something like this:



To use the other CAN channel replace can0 with can1.

4. Real Time Clock (RTC) Software Installation

Insert a CR1220 battery (not supplied) into battery holder. Ensure the "+" is facing upward.

Install the i2c-tools by:

```
sudo apt-get install i2c-tools
```

Then check the RTC:

```
sudo i2cdetect -y 1
```

You should see 68 or UU on address 0x68:

```
pi@raspberrypi:~ $ i2cdetect -y 1
     0  1  2  3  4  5  6  7  8  9  a  b  c  d  e  f
00:          -- -- -- -- -- -- -- -- -- -- -- -- --
10: -- -- -- -- -- -- -- -- -- -- -- -- -- -- -- --
20: -- -- -- -- -- -- -- -- -- -- -- -- -- -- -- --
30: -- -- -- -- -- -- -- -- -- -- -- -- -- -- -- --
40: -- -- -- -- -- -- -- -- -- -- -- -- -- -- -- --
50: -- -- -- -- -- -- -- -- -- -- -- -- -- -- -- --
60: -- -- -- -- -- -- -- -- 68 -- -- -- -- -- -- --
70: -- -- -- -- -- -- -- --
pi@raspberrypi:~ $
```

Now you need to disable the "fake hwclock" which interferes with the 'real' hwclock

```
sudo apt-get -y remove fake-hwclock
sudo update-rc.d -f fake-hwclock remove
```

Start the original hw clock script by:

```
sudo nano /lib/udev/hwclock-set
```

and comment out these three lines:

```
#if [ -e /run/systemd/system ] ; then
# exit 0
#fi
```

```
 GNU nano 2.7.4                File: /lib/udev/hwclock-set                Modified

#!/bin/sh
# Reset the System Clock to UTC if the hardware clock from which it
# was copied by the kernel was in localtime.

dev=$1

#if [ -e /run/systemd/system ] ; then
#    exit 0
#fi

if [ -e /run/udev/hwclock-set ]; then
    exit 0
fi

if [ -f /etc/default/rcS ] ; then
    . /etc/default/rcS
fi

# These defaults are user-overridable in /etc/default/hwclock
BADYEAR=no
HWCLOCKACCESS=yes
HWCLOCKPARS=
HCTOSYS_DEVICE=rtc0
if [ -f /etc/default/hwclock ] ; then
    . /etc/default/hwclock
fi

if [ yes = "$BADYEAR" ] ; then
    /sbin/hwclock --rtc=$dev --systz --badyear
```

Reboot the Pi.

Type the following to stop the fake clock services.

```
sudo systemctl stop fake-hwclock.service
sudo systemctl disable fake-hwclock.service
```

Ensure the Ethernet cable or Wifi is on. This will get the time from the network.

Set the clock by:

```
sudo hwclock -w
```

To read the clock:

```
sudo hwclock -r
```

5. Python Installation and Use

Ensure the driver for PiCAN FD is installed and working correctly first.

Clone the pythonCan repository by:

```
git clone https://github.com/hardbyte/python-can
```

```
cd python-can
```

```
sudo python3 setup.py install
```

Check there is no error been displayed.

Bring up the can0 interface:

```
sudo /sbin/ip link set can0 up type can bitrate 500000 dbitrate 2000000 fd on sample-point .8 dsample-point .8
```

Now start python3 and try the transmit with CAN FD and BRS set.

```
python3
```

```
import can
```

```
bus = can.interface.Bus(channel='can0', bustype='socketcan_native',fd =
True)
```

```
msg = can.Message(arbitration_id=0x7de,extended_id=False,is_fd = True,
bitrate_switch = True,data=[0,0,0,0,0,0x1e,0x21,0xfe, 0x80, 0, 0,1,0])
```

```
bus.send(msg)
```

```
pi@raspberrypi:~/python-can $ python3
Python 3.5.3 (default, Jan 19 2017, 14:11:04)
[GCC 6.3.0 20170124] on linux
Type "help", "copyright", "credits" or "license" for more information.
>>> import can
>>> bus = can.interface.Bus(channel='can0', bustype='socketcan_native',fd = True)
>>> msg = can.Message(arbitration_id=0x7de,extended_id=False,is_fd = True, bitrate
_switch = True,data=[0,0,0,0,0,0x1e,0x21,0xfe, 0x80, 0, 0,1,0])
>>> bus.send(msg)
>>>
```

To received messages and display on screen type in:

```
notifier = can.Notifier(bus, [can.Printer()])
```

```
pi@raspberrypi:~/python-can $ python3
Python 3.5.3 (default, Jan 19 2017, 14:11:04)
[GCC 6.3.0 20170124] on linux
Type "help", "copyright", "credits" or "license" for more information.
>>> import can
>>> bus = can.interface.Bus(channel='can0', bustype='socketcan_native',fd = True)
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,0,0,0x1e,0x21,0xfe, 0x80, 0, 0,1,0])
>>> bus.send(msg)
>>> notifier = can.Notifier(bus, [can.Printer()])
>>> Timestamp: 1521407261.782672        ID: 0123    S          DLC: 5    01 22 33 44 04
Timestamp: 1521407262.494297        ID: 0123    S          DLC: 5    01 22 33 44 04
Timestamp: 1521407263.006066        ID: 0123    S          DLC: 5    01 22 33 44 04
Timestamp: 1521407263.406438        ID: 0123    S          DLC: 5    01 22 33 44 04
Timestamp: 1521407265.154456        ID: 07df    S          DLC: 8    23 41 23 41 34 23 04 00
Timestamp: 1521407265.746158        ID: 07df    S          DLC: 8    23 41 23 41 34 23 04 00
Timestamp: 1521407266.226386        ID: 07df    S          DLC: 8    23 41 23 41 34 23 04 00
Timestamp: 1521407307.873616        ID: 0123    S     F    DLC: 12    01 22 33 44 04 00 00 00 00 00 00 00
Timestamp: 1521407308.385764        ID: 0123    S     F    DLC: 12    01 22 33 44 04 00 00 00 00 00 00 00
Timestamp: 1521407308.816160        ID: 0123    S     F    DLC: 12    01 22 33 44 04 00 00 00 00 00 00 00
>>>
```

Documentation for python-can can be found at :

https://python-can.readthedocs.io/en/stable/index.html

More expamles in github:

https://github.com/skpang/PiCAN-FD-Python-examples