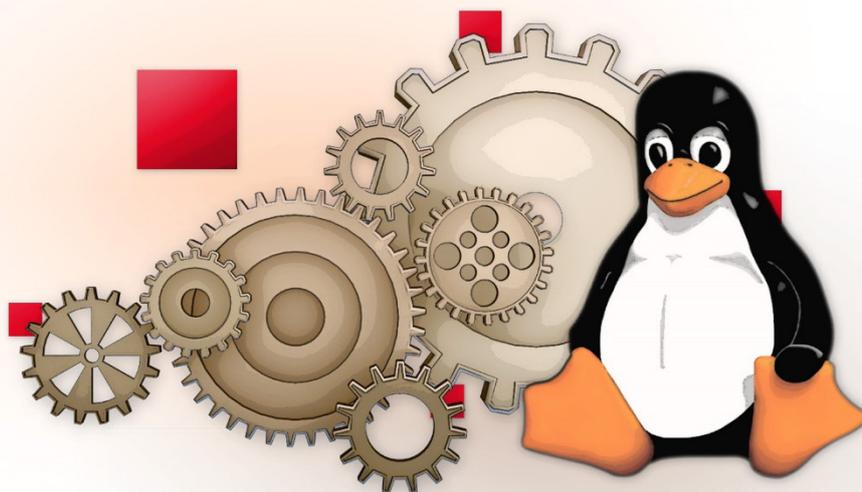


# PCAN Driver for Linux v8

CAN Driver and Library API for Linux

## User Manual



## Relevant Products

Product Name	Version	Part number
PCAN Driver for Linux	8.x.x	not applicable

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# 1 Disclaimer

The provided files are part of the PCAN Driver for Linux package.

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## 2 Introduction

With the PCAN Driver for Linux, you can use CAN 2.0 and, since v8, CAN FD hardware products from PEAK-System under Linux-based systems. Even if the use of Linux 2.4 kernels is declining, the canonical age of the driver ensures compatibility with some versions of this kernel line and with older PEAK-System hardware products.

The driver is also compatible with the latest versions of well-known real-time (RT) extensions like Xenomai<sup>1</sup> and RTAI<sup>2</sup>, by interfacing to the common "Real Time Driver Mode" model.

Historically, the PCAN Driver for Linux provides an application programming interface called *chardev* by implementing the character mode device drivers system calls (*open*, *read*, *write*, *close*, *poll*, *ioctl*). Since version 20070306\_n, the driver also provides a *netdev* interface which, by integrating the Kernel SocketCAN network sub-layer, provides applications with access to the PEAK-System CAN channels via the socket interface of the Linux kernel. The choice of the selected interface is exclusively done when building the driver; the driver cannot run offering both interfaces at the same time.

 **Note:** Since the Linux kernel v3.6, PEAK-System has worked to include the support of their most-used PC CAN interfaces in the mainline Kernel. Thus, if you plan to get access to the CAN bus with a PC CAN interface made by PEAK-System from a socket-based application, there is no need of installing this PCAN Driver for Linux package anymore. The so-called *netdev* interface is however kept for backward compatibility.

Version 8 of the PCAN Driver for Linux is a major evolution since it mainly includes the support of the new CAN FD specification. Because of the new features CAN FD proposes, the historical *chardev* API has had to evolve, too. Time has come for PCAN to propose a more modern and scalable new *chardev* interface, while the "old" good one is obviously always supported.

The package is always evolving, because of the constant support of some new hardware products made by PEAK-System, some new versions of tools and Kernels, or because of some bug fixing. The latest version can be downloaded from the PEAK-System website:

<https://www.peak-system.com/linux/>

### 2.1 Features

- Support of all CAN 2.0 a/b and CAN FD hardware products made by PEAK-System
- Support of all 2.6.x, 3.x, and 4.x Linux Kernels in 32 and 64-bit environments
- DESTDIR and cross-compilation supported
- Udev system support
- Enhanced *sysfs* integration
- Optimized character mode device driver interface (*chardev*) supporting CAN 2.0 as well as CAN FD standard and multiple messages transfers between applications and the driver
- SocketCAN device driver interface (*netdev*) supporting CAN 2.0 as well as CAN FD new features, with enhanced NETLINK integration (*ip link* support)

<sup>1</sup> Website Xenomai: <https://xenomai.org>

<sup>2</sup> Website RTAI: <https://www.rtai.org>

- └ Real-time Linux extensions like Xenomai 3.x and RTAI 4.x and 5.x supported by the driver, as well as by the user space library and the test and examples applications (*chardev* interface only)
- └ Full binary compatibility with existing CAN 2.0 *chardev* applications that run over older versions of the driver (7.x and older)

## 2.2 System Requirements

- └ Linux-based system running a 32 or a 64-bit Kernel
- └ PC CAN interface from PEAK-System
- └ make, gcc
- └ The kernel headers (or Linux headers) package of the running Linux or the sources tree of a cross-compiled Kernel
- └ g++ and libstdc++
- └ libpopt-dev package



**Note:** The g++ compiler as well as the libpopt-dev package are only required for building some user space applications from the `test` directory.

## 2.3 Scope of Supply

- └ PCAN Driver for Linux installation including
  - device driver module sources and Makefile
  - user libraries sources and Makefile
  - test and tools applications sources and Makefile
  - Udev rules
  - Libpcanbasic for Linux library and examples sources and Makefile
- └ Documentation (this user manual) in PDF format

## 3 Installation

The PCAN Driver for Linux is an *out-of-tree* driver module, and because of the GPL, it is provided in a (compressed) *tarball* package including the source files of the driver as well as the user libraries and some test utilities and tools (see 2.3 *Scope of Supply* on page 6).

This chapter covers the setup of the whole driver package under non-RT and RT Linux systems (*root* privileges are required for the installation part). Also, cross-compilation options are explained.

### 3.1 Build Binaries

▶ Do the following to install the package:

1. Untar the compressed tarball file from your `$HOME` (for example) directory:

```
$ tar -xzf peak-linux-driver-X.Y.Z.tar.gz
$ cd peak-linux-driver-X.Y.Z
```

2. Clean the world:

```
$ make clean
```

▶ To build non-real time binaries with default configuration:

```
$ make
```

 **Note:** This behavior is new from v8.x of the driver! In former versions, the global `make` command did build enabling the *netdev* interface rather than the *chardev* one. The main reason of that change is that a great number of PEAK-System CAN hardware products are now natively supported by the mainline kernel as SocketCAN interfaces<sup>3</sup>. Thus, driver users are supposed to prefer using the *chardev* interface instead. But of course, the *netdev* interface can always be selected by rebuilding the driver (only) with:

```
$ make -C driver NET=NETDEV_SUPPORT
```

Or, using the shortcut:

```
$ make netdev
```

▶ To build real-time binaries running in a Xenomai kernel:

```
$ make RT=XENOMAI
```

<sup>3</sup> Kernel code: [https://elixir.bootlin.com/linux/v3.4/source/drivers/net/can/usb/peak\\_usb/pcan\\_usb\\_core.c](https://elixir.bootlin.com/linux/v3.4/source/drivers/net/can/usb/peak_usb/pcan_usb_core.c)

**Note:** Since driver version 8.2, you can also build the Xenomai binaries with:

```
$ make xeno
```

▶ To build real-time binaries running in a RTAI kernel:

```
$ make RT=RTAI
```

**Note:** Since driver version 8.2, you can also build the RTAI binaries with:

```
$ make rtai
```

**Note:** Selecting one of the above real-time compilations also removes the support of some of the non-RT PC CAN interfaces (like the USB adapters, for example).

▶ To cross-compile binaries:

```
$ make KERNEL_LOCATION=/where/are/the/kernel/headers
```

Making something from the package's root directory recursively makes this thing into:

1. the `driver` directory,
2. the `lib` directory, and
3. the `test` directory.
4. The `libpcanbasic` directory.

It is equivalent to the following 3 commands:

```
$ make -C driver
$ make -C lib
$ make -C test
$ make -C libpcanbasic
```

▶ Making the 32-bit version of the library:

Since driver version 8.5, the 32-bit version of the `libpcan` library is automatically built (and installed) when running a 64-bit Kernel if the current C compiler is able to.

**Note:** The `gcc-multilib` package must be installed.

The default configuration of the PCAN Driver for Linux in non-RT configuration is to handle the support of all PC CAN interfaces. However, in order to save memory or to fix some cross-compilation and/or loading issues, it is possible to remove the support of some of these interfaces. The driver's Makefile handles the following set of switches from the `make` command line:

Variable	Value	Description
DNG	DONGLE_SUPPORT	Include the support of the parallel port CAN interfaces from PEAK-System in the driver
	NO_DONGLE_SUPPORT	Remove the support of the parallel port CAN interfaces from the driver (default)

Variable	Value	Description
USB	USB_SUPPORT	Include the support of the USB CAN interfaces from PEAK-System in the driver (default)
	NO_USB_SUPPORT	Remove the support of the USB CAN interfaces from the driver
PCI	PCI_SUPPORT	Include the support of the PCI/PCIe CAN interfaces from PEAK-System in the driver (default)
	NO_PCI_SUPPORT	Remove the support of the PCI/PCIe CAN interfaces from the driver
PCIEC	PCIEC_SUPPORT	Include the support of the ExpressCard CAN interfaces from PEAK-System in the driver (default). Note that loading the driver built with PCIEC_SUPPORT will automatically load the "i2c_algo_bit" module too.
	NO_PCIEC_SUPPORT	Remove the support of the ExpressCard CAN interfaces from the driver
ISA	ISA_SUPPORT	Include the support of the ISA/PC104 CAN interfaces from PEAK-System in the driver (default)
	NO_ISA_SUPPORT	Remove the support of the ISA/PC104 CAN interfaces from the driver
PCC	PCCARD_SUPPORT	Include the support of the PCCard CAN interfaces from PEAK-System in the driver
	NO_PCCARD_SUPPORT	Remove the support of the PCCard CAN interfaces from the driver (default)

Table 1: Supported PC CAN interfaces switches

For example, to build the driver including the support of the PCAN-Dongle and the PCAN-PC Card CAN interfaces:

```
$ make -C driver DNG=DONGLE_SUPPORT PCC=PCCARD_SUPPORT
```

To know which variant of the driver (chardev, netdev or RT) has been built, type in the "driver" directory:

```
$ modinfo pcan.ko | grep -e ^description:
```

## 3.2 Install Package

Once binaries are built, do the following to install the package:

1. Be sure to be in the driver package root directory:

```
$ cd peak-linux-driver-X.Y.Z
```

2. Install everything (root privileges are required):

- a) On Debian-based systems, users can use the `sudo` command:

```
$ sudo make install
```

- b) Otherwise, installation is done with:

```
$ su -c "make install"
```

The above setup will build and install the driver, the user libraries, and the test programs on the running system.

Since v8.14, the driver can also be installed with DKMS support. DKMS is a software system that handles the rebuild of the driver when a new Kernel has been installed in the running Linux based host. To take advantage of DKMS, one have to install the driver with:

```
$ sudo make install_with_dkms
```

Calling the Makefile target "install\_with\_dkms" can be done from the root of `peak-linux-driver-x.y.z` or from the subdirectory "driver". In the first case, the other components (libs and programs) will be installed in the same way as if "make install" had been called.

### 3.3 Configure Software

The PCAN Driver for Linux runs with some default settings. Some of them can be changed by passing parameters to the module when it is loaded:

Parameter	Type	Description								
type	List of characters strings, separated by ",", (comma).	<p>Gives the list of (maximum) 8 PC CAN interfaces that can't be detected by the plug-and-play system. Known types are:</p> <table border="1"> <thead> <tr> <th>type</th> <th>PC CAN interface</th> </tr> </thead> <tbody> <tr> <td>isa</td> <td>ISA and PC/104</td> </tr> <tr> <td>sp</td> <td>Standard parallel port</td> </tr> <tr> <td>epp</td> <td>Enhanced parallel port</td> </tr> </tbody> </table>	type	PC CAN interface	isa	ISA and PC/104	sp	Standard parallel port	epp	Enhanced parallel port
type	PC CAN interface									
isa	ISA and PC/104									
sp	Standard parallel port									
epp	Enhanced parallel port									
io	List of hexadecimal values, separated by ",", (comma).	Gives the list of I/O ports to use to dialog with the corresponding PC CAN interface (see <code>type</code> ).								
irq	List of decimal values, separated by ",", (comma).	Gives the list of IRQ levels to connect to dialog with the corresponding PC CAN interface (see <code>type</code> ).								
btr0btr1	Hexadecimal value.	Change the default (nominal) bitrate value set to every CAN/CAN FD channel when it is opened. The hexadecimal value is interpreted as a BTR0BTR1 value (see SJA1000 specifications). If this parameter is not provided when the module is loaded, the default bitrate value is 0x1c (500 kbit/s).								
bitrate	Numeric value. An ending <code>k</code> is interpreted as factor 1,000, while an ending <code>M</code> is interpreted as factor 1,000,000.	Change the default (nominal) bitrate value set to every CAN/CAN FD channel when it is opened. If this parameter is not provided when the module is loaded, the default bitrate value is 0x1c (500 kbit/s). See also the note below.								
dbitrate	Numeric value. An ending <code>k</code> is interpreted as factor 1,000, while an ending <code>M</code> is interpreted as factor 1,000,000.	<p>Change the default data bitrate value set to every CAN FD channel when it is opened. If this parameter is not provided when the module is loaded, the default data bitrate value is 2,000,000 (2 Mbit/s).</p> <p>Since v8.11, if <code>dbitrate</code> is 0, then the CAN-FD device initializes in CAN 2.0 a/b mode only.</p>								
assign	Characters string	Change the default name assignment between PCAN and SocketCAN layer (see 4.9.1 <i>assign Parameter</i> on page 40). This parameter is only used when the <code>netdev</code> interface is selected.								
usemsi	Numeric value	<p>This parameter controls usage of MSI for the PCIe-based CAN 2.0 cards:</p> <table border="1"> <tbody> <tr> <td>0</td> <td>INTA mode (no MSI)</td> </tr> <tr> <td>1</td> <td>Full MSI mode (one IRQ per channel)</td> </tr> <tr> <td>2</td> <td>Shared MSI (one IRQ per device)</td> </tr> </tbody> </table> <p>0 is the default mode.</p>	0	INTA mode (no MSI)	1	Full MSI mode (one IRQ per channel)	2	Shared MSI (one IRQ per device)		
0	INTA mode (no MSI)									
1	Full MSI mode (one IRQ per channel)									
2	Shared MSI (one IRQ per device)									
irqmaxloop	Numeric value	Set the maximum number of read loops performed by the SJA1000 interrupt handler. Its default value is 6.								
irqmaxrmsg	Numeric value	Set the maximum number of messages read by the SJA1000 interrupt handler per interrupt. Its default value is 8.								

Parameter	Type	Description
fdusemsi	Numeric value	This parameter controls usage of MSI for the PCIe-based CAN FD cards: 0 INTA mode (no MSI) 1 Full MSI mode (one IRQ per channel) 2 Shared MSI (one IRQ per device)  0 is the default mode.
fdirqcl	Numeric value	Define the number of frames received after which the CANFD firmware of the PCIe family cards will generate an interrupt. Its default value is 16.
fdirqtl	Numeric value	Define the delay in 1/10th ms after which the CANFD firmware of the PCIe family cards will generate an interrupt. Its default value is 10.
fast_fwd	Numeric value	Tell the USB CANFD interfaces to transfer the received frames as soon as they arrive rather than waiting a while to agglomerate them and thus minimize the USB traffic. Its default value is 0 (no fast forward).
rxqsize	Numeric value	Define the maximum number of messages that can be saved by the driver into the channel Rx queue. Once the Rx queue is full, next incoming CAN frames are discarded by the driver and the CAN_ERR_OVERRUN (0x0002) flag is set. Default value is 2000.
txqsize	Numeric value	Define the maximum number of messages that can be stored by the application into the channel Tx queue. Once the Tx queue is full, next write will block the application or, if O_NONBLOCK was set, will fail with errno = EAGAIN. Default value is 500.
rxqprealloc	Numeric value	When the value is 1, the driver allocates the channel's message receive queue once and for all when it is loaded and releases it when it is removed from memory, as opposed to the default operation (value 0) where the receive queue is allocated every time the channel is opened and is released when the channel is closed.
txqprealloc	Numeric value	When the value is 1, the driver allocates the channel's message transmit queue once and for all when it is loaded and releases it when it is removed from memory, as opposed to the default operation (value 0) where the transmit queue is allocated every time the channel is opened and is released when the channel is closed.
txqhiwat	Numeric value	Define the maximum level beyond which the driver will no longer wake up the task waiting to write on the Tx queue. Its value varies from 50.00% (5000) to 100.00% (10000). The default value is 10000 (8000 in netdev mode)

Parameter	Type	Description
deftsmode	Numeric value	<p>Control how hardware timestamps are handled by the driver, if the PC CAN interface is able to provide such timestamps:</p> <ul style="list-style-type: none"> <li>0 Timestamps are host (software) timestamps. Timestamp of a received CAN frame corresponds to the time the frame has been saved into the driver Rx queue.</li> <li>1 Timestamps are based on host time + an offset made of hardware timestamps. The host time base is periodically updated by the driver when receiving notifications from the PC CAN interface. The offset corresponds to the hardware time found in the received CAN frames.</li> <li>2 Same as 1 except that the hardware offset is cooked to handle any possible clock drift between the CPU and the PC CAN interface quartz.</li> <li>3 Timestamps are made of hardware timestamps received from the PCAN interface. This means that this timestamp IS NOT a host time, but a count of seconds and <math>\mu</math>s. since the PC CAN interface has been initialized.</li> <li>4 Reserved</li> <li>5 Same as 1, except that the timestamp measurement is triggered on SOF instead of EOF (if device allows it).</li> <li>6 Same as 2, except that the timestamp measurement is triggered on SOF instead of EOF (if device allows it).</li> <li>7 Same as 3, except that the timestamp measurement is triggered on SOF instead of EOF (if device allows it).</li> </ul> <p>Default mode depends on the PC CAN interface:</p> <ul style="list-style-type: none"> <li>0 SJA1000 based internal bus PCAN interfaces default and unique mode.</li> <li>1 PCAN-USB and PCAN-USB Pro default mode.</li> <li>2 CAN FD PCAN interfaces.</li> </ul>
defclk	Characters string	Define the default clocks values for the PCAN channels, when the driver is built in netdev mode (see 4.9.2 <i>defclk Parameter</i> on page 41).
defblperiod	Numeric value	Defines the period in ms. of the message informing the application of the bus load rate, when it has changed. The default value is 500
drvclkref	Numeric value	<p>Define which clock reference the driver is based on, to compute host time timestamps it gives to the applications.</p> <p>Valid values can be:</p> <ul style="list-style-type: none"> <li>0 Real-time clock</li> <li>1 Monotonic clock</li> <li>4 Monotonic raw clock</li> <li>7 Boot time clock</li> </ul> <p>See also "Table 6: clock reference used by the driver for the timestamps" on page 21.</p>

Table 2: Driver module parameters

 **Note:** The `bitrate=` parameter has changed since v8.x of the driver. In previous versions, this parameter allowed to change the default nominal bitrate, but with following the coding format of the BTR0BTR1 SJA1000 register only.

In order to ensure the best backward compatibility with the existing configurations, the `bitrate=` parameter is now parsed as follows:

- If the two first characters of the given value are `0x` or `0X` and if the hexadecimal value is smaller than 65536, then the value is always interpreted as a BTR0BTR1 bitrate specification (as the driver did in previous versions).
- Otherwise, and if the value is obviously a numeric value, then it is used as a bit-per-second (bit/s) bitrate specification.

These parameters and their values can be given on the `insmod` command line or can be written in the `/etc/modprobe.d/pcan.conf` file. The system administrator has to edit this file, then to uncomment the options `pcan` line, and to write his own settings.

### 3.4 Configure Non-PnP-Hardware

**Note:** This paragraph only concerns the users of some non-plug-and-play PC CAN interfaces (like the PCAN-ISA and PC/104 PC CAN interfaces family). The configuration of the driver for the PCI/PCIe and USB PC CAN interfaces families is entirely handled by the system.

When using some non-plug-and-play PC CAN interfaces, the driver has to be informed of the IRQs and I/O ports configured for these boards (see the provided hardware reference and the corresponding jumpers' usage). The installation procedure of the PCAN Driver for Linux has already created a configuration text file which enables to define some optional arguments that are passed to the driver (see 3.3 *Configure Software* on page 10), when it is loaded.

For example, if the Linux host is equipped with a two channels ISA PC CAN interface board, and if IRQ 5 (resp. IRQ 10) and I/O port 0x300 (resp. 0x320) is the configuration selected by the dedicated jumpers on the board, then the `/etc/modprobe.d/pcan.conf` file has to be changed like this:

```
$ sudo vi /etc/modprobe.d/pcan.conf
# PCAN - automatic made entry, begin -----
# if required add options and remove comment
options pcan type=isa,isa irq=10,5 io=0x300,0x320
install pcan /sbin/modprobe --ignore-install pcan
# PCAN - automatic made entry, end -----
```

The standard assignments for ISA and PC/104 PC CAN interfaces are (io/irq): 0x300/10, 0x320/5. The standard assignments for the PCAN-Dongle in SP/EPP mode are (io/irq): 0x378/7, 0x278/5.

## 4 Usage of the Driver

Once installed, and if the Udev system is running on the target system, the driver is automatically loaded by the system at the next boot for internal PC CAN interfaces, like the PCI/PCIe boards, or when the external PC CAN interface (like the USB adapters) is plugged into the system.

### 4.1 Driver Loading

Being a module, the driver, however, can be loaded without rebooting the system by asking the system to probe for the PCAN module (root privileges are required):

```
$ sudo modprobe pcan
```

**Note:** The `modprobe` system command manages to load all the other modules the driver depends on. When using `insmod` instead, you must load all of these modules manually:

```
$ modinfo pcan.ko | grep -e "^depends:"
depends:          pcmcia,parport,i2c-algo-bit

$ sudo modprobe pcmcia parport i2c-algo-bit
$ sudo insmod pcan.ko
```

The driver is reasonably verbose for the kernel: it logs one or several messages in the kernel logs buffer for each PC CAN interface it enumerates. Next, it will save messages only when something wrong has been detected.

Here are the messages it logs when it just has been loaded, for example:

```
$ dmesg | grep pcan
[24612.510888] pcan: Release_YYYYMMDD_n (1e)
[24612.510894] pcan: driver config [mod] [isa] [pci] [pec] [dng] [par] [usb] [pcc]
[24612.511057] pcan: uCAN PCI device sub-system ID 14h (4 channels)
[24612.511125] pcan 0000:01:00.0: irq 48 for MSI/MSI-X
[24612.511140] pcan: uCAN PCB v4h FPGA v1.0.5 (design 3)
[24612.511146] pcan: pci uCAN device minor 0 found
[24612.511148] pcan: pci uCAN device minor 1 found
[24612.511150] pcan: pci uCAN device minor 2 found
[24612.511153] pcan: pci uCAN device minor 3 found
[24612.516206] pcan: pci device minor 4 found
[24612.516230] pcan: pci device minor 5 found
[24612.516258] pcan: pci device minor 6 found
[24612.516280] pcan: pci device minor 7 found
[24612.516335] pcan: isa SJA1000 device minor 8 expected (io=0x0300,irq=10)
[24612.516369] pcan: isa SJA1000 device minor 9 expected (io=0x0320,irq=5)
[24612.516999] pcan: new high speed usb adapter with 2 CAN controller(s) detected
[24612.517237] pcan: PCAN-USB Pro FD (01h PCB01h) fw v2.1.0
[24612.517244] pcan: usb hardware revision = 1
[24612.517605] pcan: PCAN-USB Pro FD channel 1 device number=30
[24612.517729] pcan: usb device minor 0 found
[24612.517732] pcan: usb hardware revision = 1
[24612.518231] pcan: PCAN-USB Pro FD channel 2 device number=31
[24612.518354] pcan: usb device minor 1 found
[24612.522469] pcan: new usb adapter with 1 CAN controller(s) detected
[24612.522491] pcan: usb hardware revision = 28
```

```
[24612.579450] pcan: PCAN-USB channel device number=161
[24612.579453] pcan: usb device minor 2 found
[24612.579487] usbcore: registered new interface driver pcan
[24612.586265] pcan: major 249.
```

The driver enumerates each PC CAN interface according to its type. Up to version 8.5.1, each type had the following range of device minor numbers:

Hardware type	Minor number range
PCI/PCIe	[0 ... 7]
ISA and PC/104	[8 ... 15]
SP mode	[16 ... 23]
EPP mode	[24 ... 31]
USB	[32 ... 39]
PC-CARD	[40 ... 47]

Table 3: Device minor number ranges

The needs of CAN channels increasing, since v8.6.0, the driver enumerates the PC CAN interfaces according to a different scheme:

Hardware type	Minor number range
PCI/PCIe	[0 ... 31]
USB	[32 ... 63]
PC-CARD	[64 ... 71]
ISA and PC/104	[72 ... 79]
SP mode	[80 ... 87]
EPP mode	[88 ... 95]

Table 4: Device minor number ranges

This v8.6.0 new scheme gives more spaces to most used PC CAN interfaces, while always booking slot 32 for the first USB device channel.

## 4.2 Udev Rules

The Udev mechanism loads the non-RT driver when the system recognizes one of the devices it handles, at boot time or when the hardware device is plugged into the system.

 **Note:** No device nodes files are created when running the real-time version of the driver module because it creates real-time (only) devices which are not connected in any way to the Udev system.

The installation of the driver package also adds some default rules to Udev, for helping the system to create the device nodes that implement the CAN channels handled by the driver (see `peak-linux-driver-x.y.z/driver/udev/45-pcan.rules`). By default, Udev creates one (character) device node under the `/dev` directory per CAN/CAN FD channel. The name of this device node is made of:

- └─ pcan prefix
- └─ PC CAN interface bus type (`pci, isa, usb ...`),
- └─ `fd` suffix if the CAN channel is CAN-FD-capable
- └─ unique minor number

For example:

```
$ ls -l /dev/pcan* | grep "^c"
crw-rw-rw- 1 root root 246, 8 févr. 3 14:59 /dev/pcanisa8
crw-rw-rw- 1 root root 246, 9 févr. 3 14:59 /dev/pcanisa9
crw-rw-rw- 1 root root 246, 4 févr. 3 14:59 /dev/pcanpci4
crw-rw-rw- 1 root root 246, 5 févr. 3 14:59 /dev/pcanpci5
crw-rw-rw- 1 root root 246, 0 févr. 3 14:59 /dev/pcanpcifd0
crw-rw-rw- 1 root root 246, 1 févr. 3 14:59 /dev/pcanpcifd1
crw-rw-rw- 1 root root 246, 2 févr. 3 14:59 /dev/pcanpcifd2
crw-rw-rw- 1 root root 246, 3 févr. 3 14:59 /dev/pcanpcifd3
crw-rw-rw- 1 root root 246, 35 févr. 3 15:24 /dev/pcanusb35
crw-rw-rw- 1 root root 246, 36 févr. 3 15:24 /dev/pcanusb36
crw-rw-rw- 1 root root 246, 32 févr. 3 14:59 /dev/pcanusbfd32
crw-rw-rw- 1 root root 246, 33 févr. 3 14:59 /dev/pcanusbfd33
crw-rw-rw- 1 root root 246, 34 févr. 3 14:59 /dev/pcanusbfd34
```

The Udev rules that the driver installs enable to create some symbolic links that give much more information about the CAN channel:

1. Udev rules create one `/dev/pcanX` per CAN channel
2. Udev rules group CAN channels according to their PC CAN interface into the same subdirectory whose name is made of the PC CAN interface product name
3. Udev default rules also create some other symbolic links if the CAN channel exports a `devid` property (different from `-1`) under `/sys` (as USB devices are able to, as well as PCIe devices since v8.10 of the driver).

The example below demonstrates the complete list of `/dev/pcan*` nodes, symbolic links, and subdirectories the Udev rules provided with the driver might create.

```
$ ls -l /dev/pcan*
lrwxrwxrwx 1 root root 10 févr. 3 14:59 /dev/pcan0 -> pcanpcifd0
lrwxrwxrwx 1 root root 10 févr. 3 14:59 /dev/pcan1 -> pcanpcifd1
lrwxrwxrwx 1 root root 10 févr. 3 14:59 /dev/pcan2 -> pcanpcifd2
lrwxrwxrwx 1 root root 10 févr. 3 14:59 /dev/pcan3 -> pcanpcifd3
lrwxrwxrwx 1 root root 11 févr. 3 14:59 /dev/pcan32 -> pcanusbfd32
lrwxrwxrwx 1 root root 11 févr. 3 14:59 /dev/pcan33 -> pcanusbfd33
lrwxrwxrwx 1 root root 11 févr. 3 14:59 /dev/pcan34 -> pcanusbfd34
lrwxrwxrwx 1 root root 9 févr. 3 15:24 /dev/pcan35 -> pcanusb35
lrwxrwxrwx 1 root root 9 févr. 3 15:24 /dev/pcan36 -> pcanusb36
lrwxrwxrwx 1 root root 8 févr. 3 14:59 /dev/pcan4 -> pcanpci4
lrwxrwxrwx 1 root root 8 févr. 3 14:59 /dev/pcan5 -> pcanpci5
lrwxrwxrwx 1 root root 8 févr. 3 14:59 /dev/pcan8 -> pcanisa8
lrwxrwxrwx 1 root root 8 févr. 3 14:59 /dev/pcan9 -> pcanisa9
crw-rw-rw- 1 root root 246, 8 févr. 3 14:59 /dev/pcanisa8
crw-rw-rw- 1 root root 246, 9 févr. 3 14:59 /dev/pcanisa9
crw-rw-rw- 1 root root 246, 4 févr. 3 14:59 /dev/pcanpci4
crw-rw-rw- 1 root root 246, 5 févr. 3 14:59 /dev/pcanpci5
crw-rw-rw- 1 root root 246, 0 févr. 3 14:59 /dev/pcanpcifd0
crw-rw-rw- 1 root root 246, 1 févr. 3 14:59 /dev/pcanpcifd1
crw-rw-rw- 1 root root 246, 2 févr. 3 14:59 /dev/pcanpcifd2
crw-rw-rw- 1 root root 246, 3 févr. 3 14:59 /dev/pcanpcifd3
crw-rw-rw- 1 root root 246, 35 févr. 3 15:24 /dev/pcanusb35
crw-rw-rw- 1 root root 246, 36 févr. 3 15:24 /dev/pcanusb36
crw-rw-rw- 1 root root 246, 32 févr. 3 14:59 /dev/pcanusbfd32
crw-rw-rw- 1 root root 246, 33 févr. 3 14:59 /dev/pcanusbfd33
```

```

crw-rw-rw- 1 root root 246, 34 févr.  3 14:59 /dev/pcanusbfd34
lrwxrwxrwx 1 root root      11 févr.  3 14:59 /dev/pcanusbpfd32 -> pcanusbfd32
lrwxrwxrwx 1 root root      11 févr.  3 14:59 /dev/pcanusbpfd33 -> pcanusbfd33

/dev/pcan-pci:
total 0
drwxr-xr-x 2 root root 80 févr.  3 14:59 0
lrwxrwxrwx 1 root root 11 févr. 13 12:05 'devid=1' -> ../pcanpci4
lrwxrwxrwx 1 root root 11 févr. 13 12:05 'devid=2' -> ../pcanpci5

/dev/pcan-pcie_fd:
total 0
drwxr-xr-x 2 root root 80 févr.  3 14:59 0
drwxr-xr-x 2 root root 80 févr.  3 14:59 1
lrwxrwxrwx 1 root root 13 févr. 13 12:05 'devid=10' -> ../pcanpcifd0
lrwxrwxrwx 1 root root 13 févr. 13 12:05 'devid=11' -> ../pcanpcifd1
lrwxrwxrwx 1 root root 13 févr. 13 12:05 'devid=12' -> ../pcanpcifd2
lrwxrwxrwx 1 root root 13 févr. 13 12:05 'devid=13' -> ../pcanpcifd3

/dev/pcan-usb:
total 0
drwxr-xr-x 2 root root 60 févr.  3 15:24 0
drwxr-xr-x 2 root root 60 févr.  3 15:24 1
lrwxrwxrwx 1 root root 12 févr.  3 15:24 devid=161 -> ../pcanusb35

/dev/pcan-usb_fd:
total 0
drwxr-xr-x 2 root root 60 févr.  3 14:59 0
lrwxrwxrwx 1 root root 14 févr.  3 14:59 devid=12345678 -> ../pcanusbfd34

/dev/pcan-usb_pro_fd:
total 0
drwxr-xr-x 2 root root 80 févr.  3 14:59 0
lrwxrwxrwx 1 root root 14 févr.  3 14:59 devid=2 -> ../pcanusbfd32
lrwxrwxrwx 1 root root 14 févr.  3 14:59 devid=31 -> ../pcanusbfd33

```

Here is the content of the subdirectories created by these Udev rules, one per PC CAN interface. The tree representation provides a better way of showing which CAN channel is connected to which PC CAN interface:

```

$ tree /dev/pcan-pci
1 directory, 4 files
1 directory, 4 files

```

```

$ tree /dev/pcan-pcie_fd
/dev/pcan-pcie_fd
├── 0
│   ├── can0 -> ../../pcanpcifd0
│   ├── can1 -> ../../pcanpcifd1
│   ├── can2 -> ../../pcanpcifd2
│   └── can3 -> ../../pcanpcifd3
└── 1
    ├── can0 -> ../../pcanpcifd6
    ├── can1 -> ../../pcanpcifd7
    ├── devid=10 -> ../pcanpcifd0
    ├── devid=11 -> ../pcanpcifd1
    ├── devid=12 -> ../pcanpcifd2
    └── devid=13 -> ../pcanpcifd3
2 directories, 10 files

```

```

$ tree /dev/pcan-usb
/dev/pcan-usb
├── 0
│   └── can0 -> ../../pcanusb35
└── 1
    ├── can0 -> ../../pcanusb36
    └── devid=161 -> ../pcanusb35
2 directories, 3 files

```

```

$ tree /dev/pcan-usb_fd
/dev/pcan-usb_fd
├── 0
│   ├── can0 -> ../../pcanusbfd34
│   └── devid=12345678 -> ../pcanusbfd34
1 directory, 2 files

```

```

$ tree /dev/pcan-usb_pro_fd
/dev/pcan-usb_pro_fd
├── 0
│   ├── can0 -> ../../pcanusbfd32
│   ├── can1 -> ../../pcanusbfd33
│   ├── devid=2 -> ../pcanusbfd32
│   └── devid=31 -> ../pcanusbfd33
1 directory, 4 files

```

In the above configuration, a user application that wants to access to the CAN bus through the 2<sup>nd</sup> CAN port of the PCAN-USB Pro FD plugged to the host will be able to open indifferently:

- └ /dev/pcanusbfd33
- └ /dev/pcan33
- └ /dev/pcan-usb\_pro\_fd/devid=31
- └ /dev/pcan-usb\_pro\_fd/0/can1

**Note:** With a properly configured and running Udev system, all of these devices files and directories are generated on the fly. If the target non-RT system does not have a running Udev system, you must create the device files manually each time after driver installation. The driver package provides the shell script `driver/pcan_make_devices` for this. For example, to create a maximum of 2 devices of each type:

```
$ cd driver
$ sudo ./pcan_make_devices 2
```

### 4.3 /proc Interface

One of the first tests to do is to check whether the driver module is correctly loaded and runs as expected. To so, read the `/proc/pcan` pseudo file.

Example:

```
$ cat /proc/pcan

*----- PEAK-System CAN interfaces (www.peak-system.com) -----
*----- Release_YYYYMMDD_n (X.Y.Z) MMM DD YYYY HH:MN:SS -----
*----- [mod] [isa] [pci] [pec] [dng] [par] [usb] [pcc] -----
*----- XX interfaces @ major 249 found -----
*n -type- -ndev- --base-- irq --btr- --read-- --write- --irqs-- -errors- status
0  pcifd  -NA- f8c21000 048 0x001c 00000000 00000000 00000000 00000000 0x0000
1  pcifd  -NA- f8c22000 048 0x001c 00000000 00000000 00000000 00000000 0x0000
2  pcifd  -NA- f8c23000 048 0x001c 00000000 00000000 00000000 00000000 0x0000
3  pcifd  -NA- f8c24000 048 0x001c 00000000 00000000 00000000 00000000 0x0000
4   pci   -NA- fdee0000 016 0x001c 00000000 00000000 00000000 00000000 0x0000
5   pci   -NA- fdee0400 016 0x001c 00000000 00000000 00000000 00000000 0x0000
6   pci   -NA- fdee0800 016 0x001c 00000000 00000000 00000000 00000000 0x0000
7   pci   -NA- fdee0c00 016 0x001c 00000000 00000000 00000000 00000000 0x0000
8   isa   -NA-      300 010 0x001c 00000000 00000000 00000000 00000000 0x0000
9   isa   -NA-      320 005 0x001c 00000000 00000000 00000000 00000000 0x0000
32  usbfd  -NA-      3 030 0x001c 00000000 00000000 00000000 00000000 0x0000
33  usbfd  -NA-      3 031 0x001c 00000000 00000000 00000000 00000000 0x0000
34   usb   -NA- ffffffff 161 0x001c 00000000 00000000 00000000 00000000 0x0000
```

The `/proc/pcan` file contains:

- └ the driver version (release date and version numbers) with build date and time
- └ the list of the PC CAN interfaces the driver is able to handle (see Table 1 on page 9)
- └ the count of PC CAN interfaces detected by the driver and the major number the Linux kernel has assigned to the driver
- └ the table of all the CAN devices the driver has detected (one per line)

The columns of the PC CAN interfaces table are properties that are common to each interface:

Column	PC CAN interface property description	
n	decimal value	The minor number the driver has assigned to that PC CAN interface
type	pci	PCI/PCIe/PCC/EC based interface equipped with a physical or FPGA SJA1000 or controller
	isa	ISA based interface equipped with a SJA1000 controller
	sp	Standard Parallel interface equipped with a SJA1000 controller

Column	PC CAN interface property description	
	epp	Enhanced Parallel interface equipped with a SJA1000 controller
	usb	USB interface equipped with a SJA1000 controller (PCAN-USB)
	usbfd	USB interface equipped with a CAN FD FPGA (PCAN-USB FD)
	pcifd	PCI/PCIe based interface equipped with a CAN FD FPGA
ndev	canx	If the <i>netdev</i> interface has been selected when building the driver, this column contains the name of the PC CAN interface for the SocketCAN layer
	not applicable	When the driver has been built to run in <i>chardev</i> mode (default mode), then this column is meaningless
base	hexadecimal value	The I/O port used to access the PC CAN interface hardware, if it is a Parallel or an ISA interface
		The I/O base address to access the PC CAN interface hardware in the other cases
		The serial number of the adapter if the PC CAN interface is an USB interface
irq	decimal value	The IRQ number attached to the PC CAN interface, if any
		The device number <i>devid</i> set to the PC CAN interface, if the PC CAN interface is an USB interface
btr	hexadecimal value	The nominal bitrate set to the PC CAN interface, following the BTR0BTR1 format of the SJA1000 bitrate register
read	hexadecimal value	Number of CAN/CAN FD frames read from the driver by the applications that have opened this interface
write	hexadecimal value	Number of CAN/CAN FD frames written to the driver by the applications that have opened this interface
irqs	hexadecimal value	Number of interrupts counted by the driver for that PC CAN interface (when the driver has connected a handler to an IRQ level)
		Number of packets received by the driver from the USB subsystem, in case of an USB CAN interface
errors	hexadecimal value	Number of errors encountered by the driver for this interface. This counter handles all kind of errors (controller error as well as driver internal errors). Some more information about errors is given in the <i>status</i> column
status	bit mask	The signification of each error bit is defined by the <i>CAN_ERR_xxx</i> constants defined in <i>/usr/include/pcan.h</i> .

Table 5: */proc/pcan* columns

## 4.4 */sysfs* Interface

 **Note:** This feature is new since v8.x of the driver.

For historical reasons, v8.x of the driver always handles the */proc/pcan* file, but it should be considered as deprecated and for CAN 2.0 usage only. Since v8.x, the driver also exports all the */proc/pcan* properties (and some more) to the */sysfs* interface.

- a) The */sys/class/pcan/version* attribute exports the driver version number:

```
$ cat /sys/class/pcan/version
8.0.0
```

- b) Since v8.11.0, the */sys/class/pcan/clk\_ref* attribute exports the clock reference used by the driver:

```
$ cat /sys/class/pcan/clk_ref
0
```

This numeric value corresponds to some `CLOCK_XXX` values defined in `/usr/include/linux/time.h`:

Value	Mnemonic	Description
0	<code>CLOCK_REALTIME</code>	This clock is affected by discontinuous jumps in the system time (e.g., if the system administrator manually changes the clock), and by the incremental adjustments performed by <code>adjtime(3)</code> and NTP.
1	<code>CLOCK_MONOTONIC</code>	This clock is not affected by discontinuous jumps in the system time (e.g., if the system administrator manually changes the clock), but is affected by the incremental adjustments performed by <code>adjtime(3)</code> and NTP.
4	<code>CLOCK_MONOTONIC_RAW</code>	Similar to <code>CLOCK_MONOTONIC</code> , but provides access to a raw hardware-based time that is not subject to NTP adjustments or the incremental adjustments performed by <code>adjtime(3)</code> .
7	<code>CLOCK_BOOTTIME</code>	Identical to <code>CLOCK_MONOTONIC</code> , except it also includes any time that the system is suspended. This allows applications to get a suspend-aware monotonic clock without having to deal with the complications of <code>CLOCK_REALTIME</code> , which may have discontinuities if the time is changed using <code>settimeofday(2)</code> .

Table 6: clock reference used by the driver for the timestamps

c) The `/sys/class/pcan` directory exports the list of all the CAN interfaces it handles:

```
$ tree -a /sys/class/pcan
/sys/class/pcan
├── pcanisa8 -> ../../devices/virtual/pcan/pcanisa8
├── pcanisa9 -> ../../devices/virtual/pcan/pcanisa9
├── pcanpci4 -> ../../devices/virtual/pcan/pcanpci4
├── pcanpci5 -> ../../devices/virtual/pcan/pcanpci5
├── pcanpcifd0 -> ../../devices/virtual/pcan/pcanpcifd0
├── pcanpcifd1 -> ../../devices/virtual/pcan/pcanpcifd1
├── pcanpcifd2 -> ../../devices/virtual/pcan/pcanpcifd2
├── pcanpcifd3 -> ../../devices/virtual/pcan/pcanpcifd3
├── pcanusb35 -> ../../devices/virtual/pcan/pcanusb35
├── pcanusb36 -> ../../devices/virtual/pcan/pcanusb36
├── pcanusbfd32 -> ../../devices/virtual/pcan/pcanusbfd32
├── pcanusbfd33 -> ../../devices/virtual/pcan/pcanusbfd33
├── pcanusbfd34 -> ../../devices/virtual/pcan/pcanusbfd34
└── version
```

d) These entries have been extended to export some PCAN devices private properties, as shown (**bold**) in the example below (**bold-green** lines properties are the same as the columns of `/proc/pcan`):

```
$ ls -l /sys/class/pcan/pcanpci4/
total 0
-r--r--r-- 1 root root 4096 nov. 6 12:34 adapter_name
-r--r--r-- 1 root root 4096 nov. 6 12:34 adapter_number
-r--r--r-- 1 root root 4096 nov. 6 12:34 adapter_partnum
-r--r--r-- 1 root root 4096 nov. 6 12:34 adapter_version
-r--r--r-- 1 root root 4096 nov. 6 12:34 base
-r--r--r-- 1 root root 4096 nov. 6 12:34 btr0btr1
-r--r--r-- 1 root root 4096 nov. 6 12:34 bus_state
-r--r--r-- 1 root root 4096 nov. 6 12:34 clk_drift
-r--r--r-- 1 root root 4096 nov. 6 12:34 clock
-r--r--r-- 1 root root 4096 nov. 6 12:34 ctrlr_number
-r--r--r-- 1 root root 4096 nov. 6 12:34 dev
-rw-r--r-- 1 root root 4096 nov. 6 12:34 devid
-rw-r--r-- 1 root root 4096 nov. 6 12:34 dev_name
```

```

-r--r--r-- 1 root root 4096 nov. 6 12:34 errors
-r--r--r-- 1 root root 4096 nov. 6 12:34 hwtype
-r--r--r-- 1 root root 4096 nov. 6 12:34 init_flags
-r--r--r-- 1 root root 4096 nov. 6 12:34 irq
-r--r--r-- 1 root root 4096 nov. 6 12:34 irqs
-r--r--r-- 1 root root 4096 nov. 6 12:34 minor
-r--r--r-- 1 root root 4096 nov. 6 12:34 ndev
-r--r--r-- 1 root root 4096 nov. 6 12:34 nom_bitrate
-r--r--r-- 1 root root 4096 nov. 6 12:34 nom_brp
-r--r--r-- 1 root root 4096 nov. 6 12:34 nom_sjw
-r--r--r-- 1 root root 4096 nov. 6 12:34 nom_tq
-r--r--r-- 1 root root 4096 nov. 6 12:34 nom_tseg1
-r--r--r-- 1 root root 4096 nov. 6 12:34 nom_tseg2
drwxr-xr-x 2 root root 0 nov. 6 12:34 power
-r--r--r-- 1 root root 4096 nov. 6 12:34 read
-r--r--r-- 1 root root 4096 nov. 6 12:34 rx_error_counter
-r--r--r-- 1 root root 4096 nov. 6 12:34 rx_fifo_ratio
-r--r--r-- 1 root root 4096 nov. 6 12:34 rx_frames_counter
-r--r--r-- 1 root root 4096 nov. 6 12:34 rx_irqs
-r--r--r-- 1 root root 4096 nov. 6 12:34 serialno
-r--r--r-- 1 root root 4096 nov. 6 12:34 status
lrwxrwxrwx 1 root root 0 nov. 6 12:34 subsystem -> ../../../../../../class/pcan
-r--r--r-- 1 root root 4096 nov. 6 12:34 ts_mode
-r--r--r-- 1 root root 4096 nov. 6 12:34 tx_error_counter
-r--r--r-- 1 root root 4096 nov. 6 12:34 tx_fifo_ratio
-r--r--r-- 1 root root 4096 nov. 6 12:34 tx_frames_counter
-r--r--r-- 1 root root 4096 nov. 6 12:34 tx_irqs
-r--r--r-- 1 root root 4096 nov. 6 12:34 type
-rw-r--r-- 1 root root 4096 nov. 6 12:33 uevent
-r--r--r-- 1 root root 4096 nov. 6 12:34 write

```

e) Reading the content of all the above files will display something like that:

```

$ for f in /sys/class/pcan/pcanpci4/*; do [ -f $f ] && echo -n "`basename $f` =
" && cat $f; done
adapter_name = PCAN-PCI Express
adapter_number = 0
adapter_partnum = IPEH-003027
adapter_version = 1.4.0
base = 0xfb400000
btr0btr1 = 0x001c
bus_state = 0
clk_drift = 0
clock = 8000000
ctrlr_number = 0
dev = 510:4
devid = 4294967295
dev_name = /dev/pcan4
errors = 0
hwtype = 10
init_flags = 0x00000000
irq = 77
irqs = 0
minor = 4
nom_bitrate = 500000
nom_brp = 1
nom_sample_point = 8750
nom_sjw = 1
nom_tq = 125
nom_tseg1 = 13
nom_tseg2 = 2
read = 0
rx_error_counter = 0
rx_fifo_ratio = 0.00
rx_frames_counter = 0
rx_irqs = 0
serialno = 4294967295
status = 0x0000
ts_mode = 0
tx_error_counter = 0
tx_fifo_ratio = 0.00
tx_frames_counter = 0
tx_irqs = 0
type = pci
uevent = MAJOR=510
MINOR=4
DEVNAME=pcanpci4
write = 0

```



**Note:** Depending on the CAN hardware and/or the mode the driver has been compiled, the device node might export some more properties. For example, a CAN FD PCIe device will export the following properties (specific properties are **bold**):

```

$ for f in /sys/class/pcan/pcanpcifd1/*; do [ -f $f ] && echo -n "`basename $f`
= " && cat $f; done
adapter_name = PCAN-PCIE FD
adapter_number = 0
adapter_partnum = IPEH-004040
adapter_version = 3.5.1
base = 0x1452000
btr0btr1 = 0x001c
bus_load = 0.00
bus_state = 0
clk_drift = 0
clock = 80000000
ctrlr_number = 1
data_bitrate = 2000000
data_brp = 1
data_sample_point = 7500
data_sjw = 1
data_tq = 12
data_tseg1 = 29
data_tseg2 = 10
dev = 510:1
devid = 4294967295
dev_name = /dev/pcan1
errors = 0
hwtype = 19
init_flags = 0x00000004
irq = 74
irqs = 0
minor = 1
nom_bitrate = 500000
nom_brp = 1
nom_sample_point = 8750
nom_sjw = 1
nom_tq = 12
nom_tseg1 = 139
nom_tseg2 = 20
read = 0
rx_dma_laddr = 0xfffd5000
rx_dma_vaddr = 00000000fc12492a
rx_error_counter = 0
rx_fifo_ratio = 0.00
rx_frames_counter = 0
rx_irqs = 0
serialno = 4294967295
status = 0x0000
ts_mode = 2
tx_dma_laddr = 0xfffd4000
tx_dma_vaddr = 000000005f29e0fb
tx_error_counter = 0
tx_fifo_ratio = 0.00
tx_frames_counter = 0
tx_irqs = 0
type = pcifd
uevent = MAJOR=510
MINOR=1
DEVNAME=pcanpcifd1
write = 0

```

- f) Some of the entries are exposed with Write permission. These entries can be written but with root privileges only:

For example, attaching his own device number to a CAN channel is (also) possible through sysfs:

```
$ cat /sys/class/pcan/pcanusb32/devid
4294967295
$ echo 12 | sudo tee /sys/class/pcan/pcanusb32/devid
[sudo] password for user:
12
$ cat /sys/class/pcan/pcanusb32/devid
12
```

**Note:** Since v8.10, it is also possible to identify a CAN channel through sysfs: by writing a ms. delay to the "led" property, then the channel LED will blink during this delay. For example, to switch the LED of "/dev/pcanusb32" during 3 s:

```
$ echo 3000 | sudo tee /sys/class/pcan/pcanusb32/led
```

## 4.5 lspcan Tool

**Note:** This feature is new since v8.x of the driver.

The `lspcan` tool is a shell script based on the `/sysfs` interface that can be used to get an overview of the PC CAN interfaces and CAN channels of the host.

```
$ ./lspcan --help
lspcan: list PEAK-System CAN/CANFD devices found by driver

Option:
-a | --all           equivalent to: -i -s
-f | --forever       forever loop on devices (^C to stop)
-h | --help          display this help
-i | --info          information about PCAN devices
-s | --stats         statistics about PCAN devices
-t | --title         display a title line over columns
-T | --tree          tree version
--version           display driver version
```

The "-i" option displays static properties of devices nodes:

```

$ ./lspcan -T -t -i
dev name      port      irq      clock    btrs     bus
[PCAN-ISA 0]
|_ pcanisa8   CAN1     10      8MHz     500k     CLOSED
|_ pcanisa9   CAN2     5       8MHz     500k     CLOSED
[PCAN-PCI 0]
|_ pcanpci4   CAN1     19      8MHz     500k     CLOSED
|_ pcanpci5   CAN2     19      8MHz     500k     CLOSED
[PCAN-PCIE FD 0]
|_ pcanpcifd0 CAN1     32      80MHz    500k+2M  CLOSED
|_ pcanpcifd1 CAN2     32      80MHz    500k+2M  CLOSED
[PCAN-PCIE FD 1]
|_ pcanpcifd2 CAN1     33      80MHz    500k+2M  CLOSED
|_ pcanpcifd3 CAN2     33      80MHz    500k+2M  CLOSED
[PCAN-USB 0]
|_ pcanusb32  CAN1     -       8MHz     500k     CLOSED
[PCAN-USB 1]
|_ pcanusb33  CAN1     -       8MHz     500k     CLOSED
[PCAN-USB Pro FD 0]
|_ pcanusbfd34 CAN1     -       80MHz    500k+2M  CLOSED
|_ pcanusbfd35 CAN2     -       80MHz    500k+2M  CLOSED

```

On the other hand, running `lspcan` with `-T -t -s -f` refreshes the screen every second with a detailed view of statistics collected from all the PC CAN interfaces present on the Linux host:

```

PCAN driver version: 8.x.y
dev name      port      irq      clock    btrs     bus      %bus    rx      tx      err
[PCAN-ISA 0]
|_ pcanisa8   CAN1     10      8MHz     500k     CLOSED   -       0       0       0
|_ pcanisa9   CAN2     5       8MHz     500k     CLOSED   -       0       0       0
[PCAN-PCI 0]
|_ pcanpci4   CAN1     19      8MHz     500k     CLOSED   -       0       0       0
|_ pcanpci5   CAN2     19      8MHz     500k     CLOSED   -       0       0       0
[PCAN-PCIE FD 0]
|_ pcanpcifd0 CAN1     30      80MHz    500k+2M  CLOSED   0.00    0       0       0
|_ pcanpcifd1 CAN2     30      80MHz    500k+2M  CLOSED   0.00    0       0       0
[PCAN-PCIE FD 1]
|_ pcanpcifd2 CAN1     31      80MHz    500k+2M  CLOSED   0.00    0       0       0
|_ pcanpcifd3 CAN2     31      80MHz    500k+2M  CLOSED   0.00    0       0       0
[PCAN-USB 0]
|_ pcanusb35  CAN1     -       8MHz     500k     CLOSED   -       0       0       0
[PCAN-USB 1]
|_ pcanusb36  CAN1     -       8MHz     1M       PASSIVE  -       535608  0       585
[PCAN-USB Pro FD 0]
|_ pcanusbfd32 CAN1     -       80MHz    500k+2M  CLOSED   0.00    0       0       0
|_ pcanusbfd33 CAN2     -       80MHz    1M       ACTIVE   10.01   1       535634  0
[PCAN-USB FD 0]
|_ pcanusbfd34 CAN1     -       80MHz    500k+2M  CLOSED   0.00    0       0       0

```



**Note:** The content of the above screen copy may change, depending on the version of the driver.

## 4.6 pcanosdiag.sh Tool

Starting from v8.14, the pcan driver package includes and installs another tool named pcanosdiag.sh. When launched with root rights, this Shell script produces a log file that takes a snapshot of the running Linux host.

```
$ sudo ./pcanosdiag.sh
[sudo] password for xxx:
./pcanosdiag.sh v1.0.5
Done.
Please send /tmp/pcanosdiag-1.0.5-YYMMDD_HHMNSS.log to <support@peak-
system.com>
```

The output log file can be useful to assist in the diagnosis in certain situations.

## 4.7 read/write Interface

As described, when reading `/proc/pcan`, once loaded, the driver is ready to operate on the CAN channels it has detected. For each of them, a default bitrates configuration is defined that enables to read/write from/to the channel. In *chardev* mode, the read/write entries of the driver's *chardev* interface are able to:

- └ initialize a CAN channel
- └ write CAN/CAN FD frames
- └ read CAN/CAN FD frames

This (very) simple interface makes it possible to quickly check if the driver correctly works. This interface uses a syntax made of:

1. a letter that indicates the command
2. a list of parameters for the command

Command and parameters must be separated by blank characters.

Command	Parameter	Description																	
i	XXXX	If XXXX is a number <= 65535, then it is interpreted as a BTR0BTR1 SJA1000 register value. The CAN channel is then initialized with the corresponding bitrate value in CAN 2.0 mode only.																	
	param1=value1[,param2=value2...]	<p>If the parameter is not a number, then it is parsed as a characters string made of a list of param=value couples. Each couple is separated from the next one by a “,” (comma). The parameters list is:</p> <table border="1"> <thead> <tr> <th>Parameter</th> <th>Description</th> </tr> </thead> <tbody> <tr> <td>f_clock</td> <td>The clock to select</td> </tr> <tr> <td>nom_bitrate</td> <td>The nominal bitrate in bit/s.</td> </tr> <tr> <td>nom_brp</td> <td rowspan="4">The bit timing specifications for the nominal bitrate, as defined by ISO 11898.</td> </tr> <tr> <td>nom_tseg1</td> </tr> <tr> <td>nom_tseg2</td> </tr> <tr> <td>nom_sjw</td> </tr> <tr> <td>data_bitrate</td> <td>The data bitrate in bit/s. if the CAN channel is to be initialized in CAN FD mode.</td> </tr> <tr> <td>data_brp</td> <td rowspan="4">The bit timing specifications for the data bitrate, as defined by ISO 11898, when the channel is to be initialized in CAN FD mode.</td> </tr> <tr> <td>data_tseg1</td> </tr> <tr> <td>data_tseg2</td> </tr> <tr> <td>data_sjw</td> </tr> </tbody> </table> <p>Each value is a numeric value. Unit symbol like k or M can be used as shortcut.</p> <p>Example: \$ echo "i nom_bitrate=1M" &gt; /dev/pcanusb0</p> <p>The above command initializes the pcanusb0 CAN channel to connect to a 1 Mbit/s CAN 2.0 channel.</p>	Parameter	Description	f_clock	The clock to select	nom_bitrate	The nominal bitrate in bit/s.	nom_brp	The bit timing specifications for the nominal bitrate, as defined by ISO 11898.	nom_tseg1	nom_tseg2	nom_sjw	data_bitrate	The data bitrate in bit/s. if the CAN channel is to be initialized in CAN FD mode.	data_brp	The bit timing specifications for the data bitrate, as defined by ISO 11898, when the channel is to be initialized in CAN FD mode.	data_tseg1	data_tseg2
Parameter	Description																		
f_clock	The clock to select																		
nom_bitrate	The nominal bitrate in bit/s.																		
nom_brp	The bit timing specifications for the nominal bitrate, as defined by ISO 11898.																		
nom_tseg1																			
nom_tseg2																			
nom_sjw																			
data_bitrate	The data bitrate in bit/s. if the CAN channel is to be initialized in CAN FD mode.																		
data_brp	The bit timing specifications for the data bitrate, as defined by ISO 11898, when the channel is to be initialized in CAN FD mode.																		
data_tseg1																			
data_tseg2																			
data_sjw																			
m	s id len [xx [xx ...]]	<p>Write CAN standard message id (numeric value &lt;= 0x7ff) with len data bytes valued by xx [xx ].</p> <p>Example: \$ echo "m s 0x123 3 01 02 03" &gt; /dev/pcanusb0</p> <p>The above command writes CAN message ID 0x123 with 3 the data bytes “01 02 03” on the CAN bus connected to the 1<sup>st</sup> CAN port of the USB CAN interface.</p>																	
	e id len [xx [xx ...]]	<p>Write CAN extended message id (numeric value &lt;= 0x3fffffff) with len data bytes valued by xx [xx ].</p> <p>Example: \$ echo "m e 0x123 3 01 02 03" &gt; /dev/pcanusb0</p> <p>The above command writes CAN message ID 0x0000123 with 3 the data bytes “01 02 03” on the CAN bus connected to the 1<sup>st</sup> CAN port of the USB CAN interface.</p>																	
r	s id	Write the CAN RTR (Remote Transmission Request) of standard id (numeric value <= 0x7ff).																	
	e id	Write the CAN RTR (Remote Transmission Request) of extended id (numeric value <= 0x7ff).																	
M		Same as m but asking the driver to activate the self-receive feature (if the CAN controller of the given channel can copy an outgoing CAN frame to its own rx queue).																	
R		Same as r but asking the driver to activate the self-receive feature (if the CAN controller of the given channel can copy an outgoing CAN frame to its own rx queue).																	
b		Same as m but asking the driver to activate the BRS feature (if the given channel is equipped with a CAN FD controller).																	
B		Same as b but asking the driver to activate the self-receive feature (if the CAN FD controller of the given channel can copy an outgoing CAN FD frame to its own rx queue).																	

Table 7: read/write interface syntax

If reading from this interface, the user is able to receive any of the above messages, plus status (x) messages:

Message	Parameter	Description	
x	b id len [xx [xx ...]]	Bus status message indicating CAN bus state:	
		<b>id</b>	<b>Bus State</b>
		1	ACTIVE
		2	WARNING
		3	PASSIVE
	4	BUSOFF	
	c id len [xx [xx ...]]	Controller error/status:	
		<b>id</b>	<b>Error</b>
		5	Controller Rx queue empty
		6	Controller Rx queue overflow
		7	Controller Tx queue empty
	8	Controller Tx queue overflow	
i id len [xx [xx ...]]	Internal (driver) error/status.		
	<b>id</b>	<b>Error</b>	
	5	Driver Rx queue empty	
	6	Driver Rx queue overflow	
	7	Driver Tx queue empty	
8	Driver Tx queue overflow		

Table 8: Status (x) message

## 4.8 test Directory

The PCAN Driver for Linux package includes a `test` directory that contains the C/C++ sources and Makefile enabling to quickly build and run some simple test binary applications, in order to check if the entire *chardev* installation (driver and libraries) is fully operational. These test programs also are example programs that demonstrate the usage of the driver library in a non-RT as well as in an RT environment.

The `test` directory applications should be built after the libraries under `lib` directory have been built and installed. Like the driver, these libraries and applications accept non-RT and RT compilation.

The global package installation described in 3.1 *Build Binaries* on page 7 has built and installed those binaries in the system. To (re-)build them (without using any RT system calls):

```
$ cd peak-linux-driver-x.y.z
$ make -C test
```

### ▶ 32-bit version:

Since driver version 8.3, a 64-bit version of the `pcan` driver can operate with any 32-bit application. To build the 32-bit version of the applications stored in this test directory, you need to do:

```
$ cd peak-linux-driver-x.y.z
$ make -C test a1132
```

**Note:** A 32-bit version of `libpcan` must have been built and installed first (see *Making the 32-bit version of the library* on page 8). Moreover, in order to build any 32-bit application while running a 64-bit Kernel, you first need to install the `gcc-multilib` package. Finally, the specific `libpopt 32-bit` package must be installed to:

```
$ sudo apt-get install gcc-multilib
$ sudo apt-get install libpopt-dev:i386
```

#### ▶ Real-time versions:

A user who wants to rebuild the RT version of these binaries will have to:

```
$ cd peak-linux-driver-x.y.z
$ make -C test RT=XENOMAI # Or "make xeno" since pcan 8.2
```

if running a Xenomai RT extended kernel, or

```
$ cd peak-linux-driver-x.y.z
$ make -C test RT=RTAI # Or "make rtai" since pcan 8.2
```

if running a RTAI extended kernel.

**i Note:** Users (as well as developers) of CAN-FD-specific applications can directly have a look at the new `pcanfdtst` application described in 4.8.5 on page 34.

### 4.8.1 receivetest

This application writes all frames it receives from a given CAN 2.0 channel (only!) to `stdout`. This application also demonstrates the usage of the old `lipcan` CAN 2.0 API in both RT and non-RT environments.

Usage:

```
$ receivetest --help

receivetest Version "Release_20150611_n" (www.peak-system.com)
----- Copyright (C) 2004-2009 PEAK System-Technik GmbH -----
receivetest comes with ABSOLUTELY NO WARRANTY. This is free
software and you are welcome to redistribute it under certain
conditions. For details see attached COPYING file.

receivetest - a small test program which receives and prints CAN messages.
usage: receivetest [-b=BTR0BTR1] [-e] [-?]
                {[-f=devicenode] | {[-t=type] [-p=port [-i=irq]]}}

options:
-f=devicenode  path to PCAN device node (default=/dev/pcan0)
-t=type        type of interface (pci, sp, epp, isa, pccard, usb (default=pci)
-p=port        port number if applicable (default=1st port of type)
-i=irq         irq number if applicable (default=irq of 1st port)
-b=BTR0BTR1   bitrate code in hex (default=see /proc/pcan)
-e            accept extended frames (default=standard frames only)
-d=no         donot display received messages (default=yes)
-n=mloop      number of loops to run before exit (default=infinite)
-? or --help  displays this help

receivetest: finished (0): 0 message(s) received
```

**Example:**

Display up to 100 (extended and standard) messages received from the 1<sup>st</sup> CAN port of a USB interface connected to a CAN bus at 1 Mbit/s:

```
$ receivetest -f=/dev/pcanusb32 -b=0x14 -e -n=100
```

**Note:** The bitrate set by this program to this CAN interface is exported by the driver:

```
$ cat /proc/pcan | grep -e "^32"
32 usb      -NA-          3 030 0x0014 00000001 00000000 00000000 00000001 0x0000
$ cat /sys/class/pcan/pcanusb32/nom_bitrate
1000000
$ cat /sys/class/pcan/pcanusb32/btr0btr1
0x0014
```

**Note:** The RT device doesn't appear under "/dev" while running an RT Linux like Xenomai or RTAI, so RT version of CAN\_Open(libpcan) removes the "/dev" prefix from the device name characters string, while pcanfd\_open(lipcanfd) DOES NOT. This workaround ONLY works with "/dev/pcanX" device names.

#### 4.8.2 transmitest

This application writes all the frames it finds in the given text file to the given CAN 2.0 channel (only!). This application also demonstrates the use of the old libpcan CAN 2.0 API in both RT and non-RT environments.

**Usage:**

```
$ transmitest --help

transmitest Version "Release_20150610_n" (www.peak-system.com)
----- Copyright (C) 2004-2009 PEAK System-Technik GmbH -----
transmitest comes with ABSOLUTELY NO WARRANTY. This is free
software and you are welcome to redistribute it under certain
conditions. For details see attached COPYING file.

transmitest - a small test program which transmits CAN messages.
usage: transmitest filename
        [-b=BTR0BTR1] [-e] [-r=msec] [-n=max] [-?]
        {[-f=devicenode] | {[-t=type] [-p=port [-i=irq]]}}
filename      mandatory name of message description file.
options:
-f=devicenode  path to PCAN device node (default=/dev/pcan0)
-t=type        type of interface (pci, sp, epp, isa, pccard, usb (default=pci)
-p=port        port number if applicable (default=1st port of type)
-i=irq         irq number if applicable (default=irq of 1st port)
-b=BTR0BTR1   bitrate code in hex (default=see /proc/pcan)
-e            accept extended frames (default=standard frames only)
-r=msec        max time to sleep before transm. next msg (default=no sleep)
-n=loop        number of loops to run before exit (default=infinite)
-? or --help  displays this help

transmitest: finished (0).
```

The file `transmit.txt` is given as an example in the `test` directory. The syntax of this file is quite simple and follows the syntax of the write interface of the driver. The test loops the transmission of the frames found in the input text file. The number of loops is infinite unless the `-n` option is specified on command line.

Example:

Transmit 100 times all the CAN 2.0 frames described in `transmit.txt` to the 1<sup>st</sup> CAN port of a USB interface connected to a CAN bus at 1 Mbit/s:

```
$ transmitest transmit.txt -f=/dev/pcanusb32 -b=0x14 -e -n=100
```

**Note:** The bitrate set by this program to this CAN interface is exported by the driver:

```
$ cat /proc/pcan | grep -e "^32"
32 usb      -NA-          3 030 0x0014 00000001 00000000 00000000 00000001 0x0000
$ cat /sys/class/pcan/pcanusb32/nom_bitrate
1000000
$ cat /sys/class/pcan/pcanusb32/btr0btr1
0x0014
```

**Note:** The RT device doesn't appear under `/dev` while running an RT Linux like Xenomai or RTAI, so RT version of `CAN_Open(libpcan)` removes the `/dev` prefix from the device name characters string, while `pcanfd_open(lipcanfd)` DOES NOT. This workaround ONLY works with `/dev/pcanX` device names.

### 4.8.3 pcan-settings

This application enables to read/write some specific values from/to the non-volatile memory of some PC CAN interfaces. This feature is useful to the user who wants his hot-pluggable CAN interfaces to always have the same device node name, whatever socket it is plugged on (operating systems devices enumeration rules don't give the same number to the same device, if this device is not plugged to the same socket/bus/port...).

Since driver version 8.8, `pcan-settings` allows any super user to switch specific PC CAN interfaces to "USB Mass Storage Device" mode. This mode is used to easily upgrade these PC CAN interfaces with a new firmware (see also 4.10 *USB Mass Storage Device Mode* on page 44).

Usage:

```
$ pcan-settings --help
Usage: pcan-settings [OPTION...]
  -f, --deviceNode='device file path'  Set path to PCAN device (default:
                                        "/dev/pcan32")
  -s, --SerialNo                        Get serial number
  -d, --DeviceNo[='device number']     Get or set device number
  -v, --verbose                          Make it verbose
  -q, --quiet                            No display at all
  -M, --MSD                             Switch device in Mass Storage Device
                                        mode (root privileges needed)

Help options:
  -?, --help                             Show this help message
  --usage                                Display brief usage message
```

### Example:

- Get the serial number of a USB CAN interface:

```
$ pcan-settings -f=/dev/pcanusb32 -s
0x00000003
```

- Set device numbers 30 and 31 for CAN1 and CAN2 of a USB 2xCAN channels interface:

```
$ pcan-settings -f=/dev/pcanusb32 -d 30
$ pcan-settings -f=/dev/pcanusb33 -d 31
```

- Read the device numbers of CAN1 and CAN2 of a USB 2xCAN channels interface:

```
$ pcan-settings -f=/dev/pcanusb32 -d
30
$ pcan-settings -f=/dev/pcanusb33 -d
31
```

When the driver is reloaded, it reads these numbers and exports them to `/sys`:

```
$ cat /sys/class/pcan/pcanusb32/devid
30
$ cat /sys/class/pcan/pcanusb33/devid
31
```

Thus, Udev is notified and reads the driver's rules. These default rules say that, if `devid` is not `-1`, then it should be used to create a symbolic link to the true device node under a directory which name is the adapter name. In this example, if the USB CAN interface is a PCAN-USB Pro, then two symbolic links are created under `/dev/pcan-usb_pro`:

```
$ ls -l /dev/pcan-usb_pro
total 0
drwxr-xr-x 2 root root  11 nov.  8 11:00 0
lrwxrwxrwx 1 root root  11 nov.  8 11:00 devid=30 -> ../pcanusb32
lrwxrwxrwx 1 root root  11 nov.  8 11:00 devid=31 -> ../pcanusb33
```

-  **Note:** device numbers can also be defined using the `sysfs` interface (see `/sysfs Interface` on page 24).
-  **Note:** since v8.10, a device number can also be set to each CAN channel of the PCAN PCI Express / PCAN-PCIe FD cards.

#### 4.8.4 bitratetest

-  **Note:** This application is kept for historical reasons only but, since bitrate values and clock selection are now proposed by the new API to the user space, it is considered as deprecated.

This application displays the BTR0BTR1 values for some well-known bitrate values. The BTR0BTR1 16-bits codification is 8 MHz SJA1000-controller-specific.

**Usage:**

```

$ bitratetest --help

bitratetest Version "Release_20150617_a" (www.peak-system.com)
----- Copyright (C) 2004-2009 PEAK System-Technik GmbH -----
bitratetest comes with ABSOLUTELY NO WARRANTY. This is free
software and you are welcome to redistribute it under certain
conditions. For details see attached COPYING file.

bitratetest - a small test the calculation of BTR0BTR1 data from PCAN.
usage: bitratetest [-f=device node] [-?]
       -f=device node - path to devicefile, default=/dev/pcan0
       -? or --help - this help

bitratetest: finished (0).

```

**4.8.5 pcanfdtst**

This application enables to test the driver, since it can receive/transmit CAN 2.0/CAN FD messages from/to all of the device nodes handled by the driver. It works in several modes:

- when running in RX mode, the application writes everything received from all the opened device nodes on the screen. It is also able to check the content of the incoming frames
- when running in TX mode, the application transmits CAN 2.0/CAN FD frames on all the opened devices and also displays any event received from them
- when running in record mode, the application records the CAN 2.0/CAN FD frames in a local file instead of transmitting them. Recording frames allows to play the same scenario several times (see `-play` option below)

Moreover, this application demonstrates the usage of the new CAN FD API of the driver in both RT and non-RT Linux. Among all the novelties, the application allows to:

- specify nominal and data bitrates for CAN FD usage
- select the device clock
- select ISO and non-ISO CAN FD modes
- demonstrate the usage of the new entry points of the new API that enable to transmit and receive several messages at once
- demonstrate the new event-based API
- get and set some device specific options value
- play (i.e. transmit) frames from a recorded file

**Usage:**

```

$ pcanfdtst --help
Setup CAN[FD] tests between CAN channels over the pcan driver (>= v8.x)

WARNING
  This application comes with ABSOLUTELY NO WARRANTY. This is free
  software and you are welcome to redistribute it under certain
  conditions. For details, see attached COPYING file.

USAGE

```

```
$ pcanfdtst MODE [OPTIONS] FILE [FILE...]
```

**MODE**

```
tx      generate CAN traffic on the specified CAN interfaces
rx      check CAN traffic received on the specified CAN interfaces
getopt  get a specific option value from the given CAN interface(s)
setopt  set an option value to the given CAN interface(s)
rec     same as 'tx' but frames are recorded into the given file
```

**FILE**

For all modes except 'rec' mode:

```
/dev/pcanx  indicate which CAN interface is used in the test.
             Several CAN interfaces can be specified. In that case,
             each one is opened in non-blocking mode.
```

'rec' mode only:

```
file_name   file path in which frames have to be recorded.
```

**OPTIONS**

```

-l | --one-shot          select one-shot mode
-a | --accept f-t       add message filter [f...t]
-b | --bitrate v        set [nominal] bitrate to "v" bps
  --btr0btrl           bitrates with BTR0BTRL format
-B | --brs              set BRS bit in outgoing CAN FD frames
-c | --clock v          select clock frequency "v" Hz
-D | --debug            (maybe too) lot of display
-d | --dbitrate v       set data bitrate to "v" bps
  --dsample-pt v       define the data bitrate sample point ratio x 10000
-E | --esi              set ESI bit in outgoing CANFD msgs
  --echo               tx frame is echoed by the hw into the rx path
-f | --fd               select CAN-FD ISO mode
  --fd-non-iso         select CAN-FD non-ISO mode
-F | --filler v|r|i|c   select how data are filled:
  --file file          transmit data from/receive data to file
-h | --help             display this help
-i | --id v|r|i         set fixed CAN Id. to "v", randomly or incr.
-is v|r|i               set fixed standard CAN Id "v", randomly or incr.
-ie v|r|i               set fixed extended CAN Id "v", randomly or incr.
-I | --incr v           "v"=nb of data bytes to use for increment counter
-l | --len v|r|i        set fixed CAN dlc "v", randomly or incr.
-m | --mul v            tx/rx "v" msgs at once
-M | --max-duration v  define max duration the test should run in s.
-n v                    send/read "v" CAN msgs then stop
-o | --listen-only      set pcan device in listen-only mode
  --opt-name v          specify the option name (getopt/setopt modes)
  --opt-value v         specify the option value (getopt/setopt modes)
  --opt-size v          specify the option size (getopt/setopt modes)
-p | --pause-us v       "v" us. pause between sys calls (rx/tx def=0/1000)
  --play file           play recorded frames from "file" according to MODE
  --play-forever        file same as --play but loop forever on "file"
-P | --tx-pause-us v   force a pause of "v" us. between each Tx frame
  (if hw supports it)
-q | --quiet            nothing is displayed
-r | --rtr              set the RTR flag to msgs sent
  --no-rtr             clear the RTR flag from msgs sent
-s | --stdmsg-only      don't handle extended msgs
  --sample-pt v        define the bitrate sample point ratio x 10000
-T | --check-ts         check host vs. driver timestatmps, stop if wrong
  --ts-base v          set timestamp base [0..2]
  --ts-mode v          set hw timestamp mode to v (hw dependant)
-u | --bus-load         get bus load notifications from the driver
-v | --verbose          things are (very much) explained
-w | --with-ts          logs are prefixed with time of day (s.us)
+FORMAT                output line format:
                        %t timestamp (s.us format)
                        %d direction (< or >)
                        %n device node name
                        %i CAN Id. (hex format)
                        %f flags
                        %l data length
                        %D data bytes
                        (default format is: "%t %n %d %i %f %l - %D")

```

- `opt-name`, `opt-value` and `opt-size` parameters are only used when in `getopt` or `setopt` mode only. These options enable to get or set devices global or specific options value (see also `int pcanfd_get_option()`)

- └ Bitrates and clock values can be expressed with ending `k` or `M` as shortcuts for factor 1,000 or factor 1,000,000. Note that if the option `--btr0btr1` is used, then `bitrate` and `dbitrate` options value is read as a `BTR0BTR1` format coded value.
- └ The unit of the pause delay between each write or read system call is the microsecond. Here, using an `m` appended to a value (e.g. `5m`) changes to milliseconds and an appended `s` to full seconds (e.g. `7s`).
- └ The unit of the `timeout-ms` parameter is millisecond. Appending an `s` to the value switches to seconds (e.g. `7s`).
- └ If only one PC CAN interface is given on the command line, the application runs in “blocking” mode, that is, the application task blocks into the driver while the receive queue of the driver is empty, or while the transmission queue of the driver is full.
- └ If more than one PC CAN interface is given on the command line, the application does the following:
  - It runs in non-blocking mode and uses the `select()` system call in non-RT environment, to be able to wait for several events at once.
  - It creates as many real-time tasks as given device nodes, to be able to wait for several events at the same time.
- └ The application’s default behavior is to read/write messages from/to the driver one by one. When the `--mul x` option is used (with `x > 1`), then the application reads/writes `x` messages at once.
- └ The `+` option is a character’s string that runs like the Linux Shell command “date”: it enables to specify his own format of the output lines.
- └ `--ts-base` option allows user to set the base of the timestamps of the frames the driver received:

<code>--ts-base</code>	Description
0	Timestamps are based on the host time (default)
1	Timestamps are based on the time when the device has been opened.
2	Timestamps are based on the time the driver has been loaded.

- └ Some options (like `id`, `len`, `incr`, `filler...`) can be used either in `tx` (or `rec`) mode or in `rx` mode:
  - When used in `tx` mode, they control how the transmitted CAN frames are generated
  - When used in `rx` mode, they control how the received CAN frames must be.

#### Examples:

1. Write 10 CAN 2.0 frames (with random ID and data length) each second on a bus with a bitrate of 250 kbit/s using the 2<sup>nd</sup> USB CAN interface:

```

$ pcanfdtst tx -n 10 -b 250k -p 1s /dev/pcanusb33
0.429301518 /dev/pcanusb33 > BUS_STATE=ACTIVE [Rx:0 Tx:0]
0.4293989212 /dev/pcanusb33 < 567 ..... 7 - 00 00 00 00 00 00 00
1.4293989342 /dev/pcanusb33 < 069 ..... 7 - 00 00 00 00 00 00 00
2.4293989614 /dev/pcanusb33 < 451 ..... 7 - 00 00 00 00 00 00 00
3.4293989798 /dev/pcanusb33 < 44a ..... 3 - 00 00 00
4.4293989995 /dev/pcanusb33 < 729 ..... 1 - 00
5.4293990176 /dev/pcanusb33 < 0ba ..... 4 - 00 00 00 00
6.4293990468 /dev/pcanusb33 < 1f2 ..... 7 - 00 00 00 00 00 00 00
7.4293990660 /dev/pcanusb33 < 1e3 ..... 4 - 00 00 00 00
8.4293990845 /dev/pcanusb33 < 07c ..... 0 -
9.4293991023 /dev/pcanusb33 < 054 ..... 1 - 00
/dev/pcanusb33 < [packets=10 calls=10 bytes=41 eagain=0]
sent frames: 10

```

- Write CAN FD (non-ISO) frames with extended ID 0x123 and 24 data bytes at a nominal bitrate of 1 Mbit/s and data bitrate of 2 Mbit/s, using the 60 MHz clock of the 2<sup>nd</sup> USB interface and the 1<sup>st</sup> PCI interface of the host:

```

$ pcanfdtst tx --fd-non-iso -n 10 -ie 0x123 -l 24 -b 1M -d 2M -c 60M /dev/pcanusbfd33
/dev/pcanpcifd0
0.001871 /dev/pcanusbfd33 > BUS_STATE=ACTIVE [Rx:0 Tx:0]
0.022460 /dev/pcanusbfd33 < 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00
0.000000 /dev/pcanpcifd0 > BUS STATE=ACTIVE [Rx:0 Tx:0]
0.023558 /dev/pcanpcifd0 < 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00
0.024662 /dev/pcanusbfd33 < 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00
0.025754 /dev/pcanpcifd0 < 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00
...

```

- Same as above but record (instead of writing) the frames into a file named "test.rec":

```

$ pcanfdtst rec --fd-non-iso -n 10 -ie 0x123 -l 24 test.rec
0.022460 test.rec < 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00
0.023558 test.rec < 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00
0.024662 test.rec < 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00
0.025754 test.rec < 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00
...

```

- Play file "test.rec" writing its frames every 1 s through the 1<sup>st</sup> channel of a PCAN-PCIe FD on a 1Mbps CAN bus:

```

$ pcanfdtst tx --fd-non-iso --play test.rec -b 1M -p 1s /dev/pcanpcifd0
0.022460 /dev/pcanpcifd0 < 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00
1.022460 /dev/pcanpcifd0 < 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00
2.022460 /dev/pcanpcifd0 < 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00
3.022460 /dev/pcanpcifd0 < 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00
...

```

## 5. Read the same bus, but from the 1<sup>st</sup> USB interface:

```
$ pcanfdtst rx --fd-non-iso -b 1M -d 2M -c 60M /dev/pcanusbfd32
0.001848 /dev/pcanusb32 > BUS_STATE=ACTIVE [Rx:0 Tx:0]
14.761845 /dev/pcanusb32 > 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00 00 00
00 00 00 00 00 00 00 00 00 00 00 00 00 00 00 00
14.764041 /dev/pcanusb32 > 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00 00 00
00 00 00 00 00 00 00 00 00 00 00 00 00 00 00 00
14.766249 /dev/pcanusb32 > 00000123 .e... 24 - 00 00 00 00 00 00 00 00 00 00 00 00 00 00 00 00
00 00 00 00 00 00 00 00 00 00 00 00 00 00 00 00
...
```

## 6. Transmit frames but use the new entry point of the multi-messages write API. Here, the application transmits 3 copies of the same frame:

```
$ /pcanfdtst tx --fd-non-iso -n 10 --mul 3 -ie 0x123 -I 4 -b 1M -d 2M -c 60M
/dev/pcanpcifd0
0.000000 /dev/pcanpcifd0 > BUS_STATE=ACTIVE [Rx:0 Tx:0]
0.000283 /dev/pcanpcifd0 < 00000123 .e... 4 - 00 00 00 00
0.001426 /dev/pcanpcifd0 < 00000123 .e... 4 - 01 00 00 00
0.002528 /dev/pcanpcifd0 < 00000123 .e... 4 - 02 00 00 00
0.003675 /dev/pcanpcifd0 < 00000123 .e... 4 - 03 00 00 00
0.005042 /dev/pcanpcifd0 < 00000123 .e... 4 - 04 00 00 00
0.006147 /dev/pcanpcifd0 < 00000123 .e... 4 - 05 00 00 00
0.007252 /dev/pcanpcifd0 < 00000123 .e... 4 - 06 00 00 00
0.008349 /dev/pcanpcifd0 < 00000123 .e... 4 - 07 00 00 00
0.009457 /dev/pcanpcifd0 < 00000123 .e... 4 - 08 00 00 00
0.010564 /dev/pcanpcifd0 < 00000123 .e... 4 - 09 00 00 00
/dev/pcanpcifd0 < [packets=30 calls=10 bytes=120 eagain=0]
sent frames: 30
```

When reading on the same bus, you can see that the driver has written each frame 3 times:

```
$ pcanfdtst rx --fd-non-iso -b 1M -d 2M -c 60M /dev/pcanusbfd32
0.001802 /dev/pcanusbfd32 > BUS STATE=ACTIVE [Rx:0 Tx:0]
8.714190 /dev/pcanusbfd32 > 00000123 .e... 4 - 00 00 00 00
8.714307 /dev/pcanusbfd32 > 00000123 .e... 4 - 00 00 00 00
8.714424 /dev/pcanusbfd32 > 00000123 .e... 4 - 00 00 00 00
8.714540 /dev/pcanusbfd32 > 00000123 .e... 4 - 01 00 00 00
8.714656 /dev/pcanusbfd32 > 00000123 .e... 4 - 01 00 00 00
8.714772 /dev/pcanusbfd32 > 00000123 .e... 4 - 01 00 00 00
8.715402 /dev/pcanusbfd32 > 00000123 .e... 4 - 02 00 00 00
8.715518 /dev/pcanusbfd32 > 00000123 .e... 4 - 02 00 00 00
8.715634 /dev/pcanusbfd32 > 00000123 .e... 4 - 02 00 00 00
8.716552 /dev/pcanusbfd32 > 00000123 .e... 4 - 03 00 00 00
8.716668 /dev/pcanusbfd32 > 00000123 .e... 4 - 03 00 00 00
...
```



**Note:** The RT device doesn't appear under "/dev" while running an RT Linux like Xenomai or RTAI, so the RT version of pcanfdtst MUST use the real name of the CAN device, that is "pcanX". There are neither aliases nor links that Udev can make when a RT device is created.

## 7. Changing the device id. of a PCAN-USB FD device using the getopt/setop modes:

```
$ pcanfdtst getopt --opt-name 1 /dev/pcanusbfd32
/dev/pcanusbfd32 > [option=1 size=4 value=[ff ff ff ff ]
$ pcanfdtst setopt --opt-name 1 --opt-value 0xEFBEADDE --opt-size 4 /dev/pcanusbfd32
/dev/pcanusbfd32 > [option=1 size=4 value=[de ad be ef ]
```

```
$ pcanfdtst getopt --opt-name 1 /dev/pcanusbfd32
/dev/pcanusbfd32 > [option=1 size=4 value=[de ad be ef ]
```

## 8. Getting the version of the firmware running on a PCAN-USB FD adapter:

```
$ pcanfdtst getopt --opt-name 11 /dev/pcanusbfd32
/dev/pcanusbfd32 > [option=11 size=4 value=[00 00 02 03 ]
```

## 4.9 netdev Mode

If the PCAN driver for Linux has been built for SocketCAN<sup>4</sup> usage (a.k.a., in *netdev* mode), it is compatible for running with some network tools as well as the CAN utilities proposed by the SocketCAN community.

 **Note:** Since kernel version 3.6, the *netdev* interface with all of the PEAK-System PC CAN interfaces is natively included in the mainline kernel. So, there is no need to install the PCAN driver for Linux when planning to use the SocketCAN interface in applications.

In this mode, the driver registers a “CAN network interface” for each PC CAN interface it enumerates. Each network interface is given a name made of the prefix `can`, followed by a number starting from 0.

### 4.9.1 assign Parameter

The `assign` parameter of the driver (described in Table 2: Driver module parameters on page 12) allows to break the default ascending number assignment model.

#### **assign=peak**

When loading the driver with the parameter `assign=peak`, the CAN network CAN interface number is fixed to the PCAN device minor number. In this mode, `canX` interface defines the same PC CAN interface as `/dev/pcanX`.

#### **assign=pcanX:canY[,pcanX:canY]**

Loading the driver with the parameter `assign=pcanX:canY` sets the name `canY` to the device which name is `pcanX`. When selecting this mode, the `assign` parameter value can be a list of several assignments, each separated by a “,” (comma).

#### **assign=devid[,peak]**

When loading the driver with the parameter `assign=devid`, then the name of the network CAN interface is made by using the `devid` value of the corresponding PC CAN interface. If the PC CAN interface does not define any `devid`, then the usual (ascending) order enumeration scheme is used (as if `assign=` was not used) unless `assign=devid,peak` is used. In that case, the CAN network number will be the same as the PCAN device number (as if `assign=peak` was used).

<sup>4</sup> Background information: <https://en.wikipedia.org/wiki/SocketCAN>

**Note:** The value of the `devId` property can be changed using `test/pcan-settings` utility (see 4.8.3 *pcan-settings* on page 32).

#### 4.9.2 defclk Parameter

The `defclk` parameter of the driver (described in Table 2: Driver module parameters on page 12) allows to change the default clock value of a CAN interface. Some PEAK-System PC-CAN interfaces can be programmed to switch from one clock to another, in order to get more accurate bit-timing.

##### **defclk=value**

When loading the driver with the parameter `defclk=value`, all the PC-CAN interfaces will try to switch from their default clock value to the given one. `value` is expressed in Hz. Ending letter "M" or "k" can be used as a shortcut to "x1000000" or "x1000". For example:

```
defclk=12M
```

selects the 12 MHz clock of each PC CAN interface that can run with such a clock. If a PC-CAN interface can't select the given clock value, then it silently ignores it. If `value` is 0, the default clock is unchanged.

##### **defclk=pcanX: valueA[, pcanY: valueB]**

Loading the driver with the parameter `defclk=pcanX: valueA[, pcanY: valueB]` defines a specific clock value to each PC CAN interface which name is given in the characters string. For example:

```
defclk=pcan0:12M,pcan1:60M,pcan2:0,pcan3:24M
```

tells the first four PC CAN interfaces to respectively switch to their 12 MHz, 60 MHz, default and 24 MHz clock. If any of these interfaces can't select the given clock, then it silently ignores it.

#### 4.9.3 ifconfig/iproute2

Both utilities configure a `canX` interface. While `ifconfig` is somewhere too old to support all of the CAN/CAN-FD-specific features, the last versions of the `iproute2` package (especially the `ip` tool) includes options to setup a `canX` interface. Since v8, the `canX` interfaces exported by the `pcan` driver can be configured using the `ip link` command.

**Note:** Configuring the `canX` interfaces needs root privileges.

The `ip` tool has been modified to handle protocol-specific features of CAN and CAN FD. This simplifies the bitrate setup of a CAN interface. The help of the tool describes its usage:

```

$ ip link set can0 type can help
Usage: ip link set DEVICE type can
      [ bitrate BITRATE [ sample-point SAMPLE-POINT ] ] |
      [ tq TQ prop-seg PROP_SEG phase-seg1 PHASE-SEG1
        phase-seg2 PHASE-SEG2 [ sjw SJW ] ]

      [ loopback { on | off } ]
      [ listen-only { on | off } ]
      [ triple-sampling { on | off } ]
      [ one-shot { on | off } ]
      [ berr-reporting { on | off } ]

      [ restart-ms TIME-MS ]
      [ restart ]

Where: BITRATE      := { 1..1000000 }
       SAMPLE-POINT := { 0.000..0.999 }
       TQ           := { NUMBER }
       PROP-SEG     := { 1..8 }
       PHASE-SEG1   := { 1..8 }
       PHASE-SEG2   := { 1..8 }
       SJW          := { 1..4 }
       RESTART-MS   := { 0 | NUMBER }

```

Thus, setting the bitrate to a CAN interface is now possible using one of the following options:

- **bitrate bit-timing parameters set** (aka `sample-point`, `tq`, `prop-seg`, `phase-seg1`, `phase-seg2`, `sjw`)
- **bitrate option followed by numeric value** (if the kernel configuration option `CONFIG_CAN_CALC_BITTIMING` was set)

The `restart-ms` option defines a timer in milliseconds. After this period the CAN interface is automatically restarted on BUS-OFF condition. If the given numeric value is 0, then the automatic restart mechanism is disabled, thus user will have to manually do:

```
$ sudo ip link set can0 type can restart
```

The last and complete version of how to use the `ip link` tool with CAN networks is available online at: <https://www.kernel.org/doc/Documentation/networking/can.txt>

Examples:

- Set up a PCAN *netdev* interface with 500 kbit/s:

```
$ ip link set canX up type can bitrate 500000
```

- Set up a PCAN *netdev* CAN FD interface with 1 Mbit/s te and 2 Mbit/s of data bitrate (if supported):

```
$ ip link set canX up type can bitrate 1000000 dbitrate 2000000 fd on
```

- Set up a PCAN *netdev* CAN FD interface with 1 Mbit/s nominal bitrate and 2 Mbit/s data bitrate, running in non-ISO mode (if supported by the device and the kernel):

```
$ ip link set canX up type can bitrate 1000000 dbitrate 2000000 fd-non-iso on
```

**Note:** The latest version of `iproute2` package can be downloaded from:  
<https://www.kernel.org/pub/linux/utils/net/iproute2/>  
 (knowing that `iproute2-ss141224 v3.18` is ok)

You might use `ifconfig` for setting the interface UP or DOWN only:

```
$ ifconfig canX down
# canX can't be used no more
$ ifconfig canX up
# canX can be used by any application
```

**Note:** loopback mode is supported since v8.10 of the driver. The below example shows how to configure `can0` to receive the echo of each frame sent as well as the frame looped back by the controller:

```
$ sudo ip link set can0 up type can loopback on bitrate 500000
```

```
$ candump -x can0
```

```
$ cansend can0 123#0011223344556677
```

```
$ candump -x can0
Can0 TX - - 123 [8] 00 11 22 33 44 55 66 77
Can0 RX - - 123 [8] 00 11 22 33 44 55 66 77
```

#### 4.9.4 can-utils

The `can-utils` package<sup>5</sup> contains some tools and utilities that allow transmitting and receiving CAN as well as CAN FD messages over the PCAN `netdev` interfaces.

**Note:** Transmitting and receiving to/from the CAN bus through the SocketCAN network interfaces needs these interfaces to be configured (see 4.9.3 `ifconfig/iproute2` on page 41).

Examples:

- Dump CAN/CAN FD messages received from the `canX` interface, display timestamps:

<sup>5</sup> Website `can-utils`: <https://github.com/linux-can/can-utils/>

```
$ candump -t a canX
```

- Transmit a CAN message with ID 0x123 on `canX` with 4 data bytes 00 11 22 33:

```
$ cansend canX 123#00112233
```

- Transmit the same message with CAN FD (###) on `canX`, select the data bitrate for the data bytes (BRS flags = 1):

```
$ cansend can1 123##_100112233
```

## 4.10 USB Mass Storage Device Mode

Since driver version 8.8, it is possible to switch specific PC CAN interfaces to Mass Storage Device (MSD) mode. In this mode, the PC CAN interface appears as an external disk drive to the system. The purpose of this mode is to facilitate the upgrade of the firmware of the PC CAN interface. Once turned into that mode, the PC CAN interface must be off to restart in normal mode afterwards.

A PC CAN interface can be switched into MSD mode if its device nodes export the `mass_storage_mode` file under the `/sysfs` tree. In the example below, the PCAN-USB adapter cannot switch into MSD mode, while the PCAN-USB FD is able to:

```
$ cat /sys/class/pcan/pcanusb33/mass_storage_mode
cat: /sys/class/pcan/pcanusb33/mass_storage_mode: No such file or directory
$ cat /sys/class/pcan/pcanusbfd38/mass_storage_mode
0
```

**Note:** Reading the `mass_storage_mode` file (if it exists) always returns the character string "0".

Switching to MSD mode is only useful if the PC CAN interface firmware should be upgraded. In that case, super user should first get a [compatible](#) firmware from the support pages of the PEAK-System website.

The user can switch a device to MSD mode in two ways:

1. With root privileges, writing 1 to the `mass_storage_mode` file of (for example) the directory entry that corresponds to the first device node of the PC CAN interface:

```
# echo 1 > /sys/class/pcan/pcanusbfd38/mass_storage_mode
```

Users of `sudo` will have to enter the command below instead:

```
$ sudo sh -c "echo 1 > /sys/class/pcan/pcanusbfd38/mass_storage_mode"
```

2. With root privileges, running the `pcan-settings` test application:

```
$ sudo pcan-settings -M -f /dev/pcanusbfd38
pcan-settings: Mass Storage mode successfully set
Please wait for the LED(s) of the USB device to flash, then, if not
automatically done by the system, mount a VFAT filesystem on the newly
detected USB Mass Storage Device "/dev/sdX".
```

 **Hint:** the “verbose” mode gives more details that may help for the next steps:

```
$ sudo pcan-settings -v -M -f /dev/pcanusbfd38
pcan-settings: Mass Storage mode successfully set

The device node "/dev/pcanusbfd38" doesn't exist anymore.
Please wait for the LED(s) of the USB device to flash, then, if not
automatically done by the system, mount a VFAT filesystem on the newly
detected USB Mass Storage Device "/dev/sdX".

For example:
# mkdir -p /mnt/pcan-usb
# mount -t vfat /dev/sdX /mnt/pcan-usb
# ls -al /mnt/pcan-usb
```

After a few seconds, the LED(s) of the PC CAN interface should blink, and the Kernel should detect a new USB mass storage device:

```
$ dmesg | tail -15
[27207.291209] usb 2-1.3.1: USB disconnect, device number 42
[27211.354058] usb 2-1.3.1: new high-speed USB device number 45 using ehci-pci
[27211.462592] usb 2-1.3.1: New USB device found, idVendor=0c72, idProduct=0101
[27211.462596] usb 2-1.3.1: New USB device strings: Mfr=0, Product=0, SerialNumber=0
[27211.462977] usb-storage 2-1.3.1:1.0: USB Mass Storage device detected
[27211.463223] scsi host11: usb-storage 2-1.3.1:1.0
[27212.482743] scsi 11:0:0:0: Direct-Access          USB to CAN          1.0 PQ: 0 ANSI: 0 CCS
[27212.483167] sd 11:0:0:0: Attached scsi generic sg4 type 0
[27212.483718] sd 11:0:0:0: [sde] 2048 512-byte logical blocks: (1.05 MB/1.00 MiB)
[27212.484335] sd 11:0:0:0: [sde] Write Protect is off
[27212.484339] sd 11:0:0:0: [sde] Mode Sense: 03 00 00 00
[27212.484944] sd 11:0:0:0: [sde] No Caching mode page found
[27212.484951] sd 11:0:0:0: [sde] Assuming drive cache: write through
[27212.490199]  sde:
[27212.492690] sd 11:0:0:0: [sde] Attached SCSI removable disk
```

In the example above, the Kernel attached the storage device `sde` to the newly detected USB mass storage device with `idVendor 0c72` (that is PEAK-System). If the running Linux system doesn't automatically mount any file system onto that storage device, then super user has to do it manually:

1. Create a mount point (`/mnt/pcan-usb-fd`, for example):

```
$ sudo mkdir -p /mnt/pcan-usb-fd
```

2. Mount the whole storage device on that mount point:

```
$ sudo mount -t vfat /dev/sde /mnt/pcan-usb-fd
```

3. Check the content of the mounted device (for example):

```
$ ls -al /mnt/pcan-usb-fd
total 830
drwxr-xr-x  2 root root   512 janv.  1 1970 .
drwxr-xr-x 10 root root  4096 déc.  13 11:23 ..
-rwxr-xr-x  1 root root 844800 avril  1 2015 firmware.bin
```

#### 4. Remove the existing firmware file:

```
$ sudo rm -f /mnt/pcan-usb-fd/*.bin
```

**Note:** The remove operation is purely virtual but is mandatory to let the system think that the storage device is large enough to store the new firmware file. At that point, if the PC CAN interface is unplugged, then it will normally restart as usual once plugged in again.

#### 5. Copy the new firmware file:

```
$ sudo cp PCAN-New_firmware_file.bin /mnt/pcan-usb-fd
```

#### 6. Unmount all mount points for the storage device:

```
$ sudo umount -A /dev/sdX
```

After a few seconds, the PC CAN interface must be power cycled to run the new firmware. Either unplug it or switch it off, in case the PC CAN interface is powered by another source than the USB cable (like the PCAN-USB X6, for example).

**Note:** The PCAN-USB X6 adapter is equipped with 3 modules, each managing 2 CAN ports. Also, it is necessary to perform the previous manipulation 3 times in total, using each time the first device node of each module (CAN1, CAN3, and CAN5).

For example, if the connected PCAN-USB X6 adapter is exported by the system like that:

```
$ lspcan -t -T -i
dev name      port    irq    clock  btrs    bus
[PCAN-USB X6 0]
|_ pcanusbfd38 CAN1    -      80MHz  500k+2M CLOSED
|_ pcanusbfd39 CAN2    -      80MHz  500k+2M CLOSED
|_ pcanusbfd40 CAN3    -      80MHz  500k+2M CLOSED
|_ pcanusbfd41 CAN4    -      80MHz  500k+2M CLOSED
|_ pcanusbfd42 CAN5    -      80MHz  500k+2M CLOSED
|_ pcanusbfd43 CAN6    -      80MHz  500k+2M CLOSED
```

Then `pcanusbfd38`, `pcanusbfd40`, and `pcanusbfd42` should all be switched to MSD mode.

Once restarted, the PC CAN interface runs the new firmware. The version of the firmware that is embedded into a PC CAN interface (if any) can be read in the `/sysfs` tree. For example:

```
$ cat /sys/class/pcan/pcanusbfd38/adapter_version
3.2.0
```

## 5 Developer Guide

As explained in 3.1 *Build Binaries* on page 7, the PCAN Driver for Linux can be configured to run in two exclusive modes:

1. If built for *chardev* mode, the driver exports a classic open/read/write/ioctl/close character device interface to the user space applications, while
2. if built in *netdev* mode, the driver exports a socket interface.

**Note:** The *netdev* mode is not available when building the driver for real-time environment.

Building and installing the driver as described in 3.1 *Build Binaries* on page 7 and in 0 *To know* which variant of the driver (*chardev*, *netdev* or RT) has been built, type in the "driver" directory:

```
$ modinfo pcan.ko | grep -e ^description:
```

Install Package on page 9 also builds and installs some user API libraries that encapsulate the system calls to the driver:

- `libpcan` is the good and old API which is always offering access to CAN 2.0 channels (see 5.1.1 *CAN 2.0 API* on page 49)
- `libpcanfd` is the new API included in the package since version 8 of the driver. This new API offers access to CAN 2.0 and CAN FD channels, as well as multi-messages services and status events messaging. Since this library also includes all the entry points of `libpcan` described in 5.1.1 *CAN 2.0 API* on page 49, this library can also be linked with CAN 2.0 API applications instead of using `libpcan`.

Both libraries can be built for being used by real-time applications. Two RT environments can be selected when building these libraries, knowing that both make usage of RTDM:

▶ To build real-time libraries for running Xenomai real-time tasks:

```
$ make -C lib RT=XENOMAI # Or "make xeno" since pcan 8.2
```

▶ To build real-time libraries, for running RTAI real-time tasks:

```
$ make -C lib RT=RTAI # Or "make rtai" since pcan 8.2
```

### 5.1 chardev Mode

In this mode, the PCAN Driver for Linux creates one device node per CAN/CAN FD channel it discovers and attaches a minor number to it (unique for the driver). Like every character mode driver, the PCAN Driver for Linux is being attached a major number by the system.

Each device node can be opened, closed, read, and written (see 4.6 *pcanosdiag.sh Tool*)

Starting from v8.14, the pcان driver package includes and installs another tool named pcانosdiag.sh. When launched with root rights, this Shell script produces a log file that takes a snapshot of the running Linux host.

```
$ sudo ./pcانosdiag.sh
[sudo] password for xxx:
./pcانosdiag.sh v1.0.5
Done.
Please send /tmp/pcانosdiag-1.0.5-YYMMDD_HHMNSS.log to <support@peak-
system.com>
```

The output log file can be useful to assist in the diagnosis in certain situations.

read/write Interface on page 27). The main functions are implemented through the `ioctl()` entry point. The architecture of the several software components of the driver package since v8 is summarized in Figure 1 Figure 1.

The chardev mode is especially needed when one wants to take benefits of the PCAN-Basic API PEAK-System has developed, for writing applications that can run on both Windows and Linux systems.

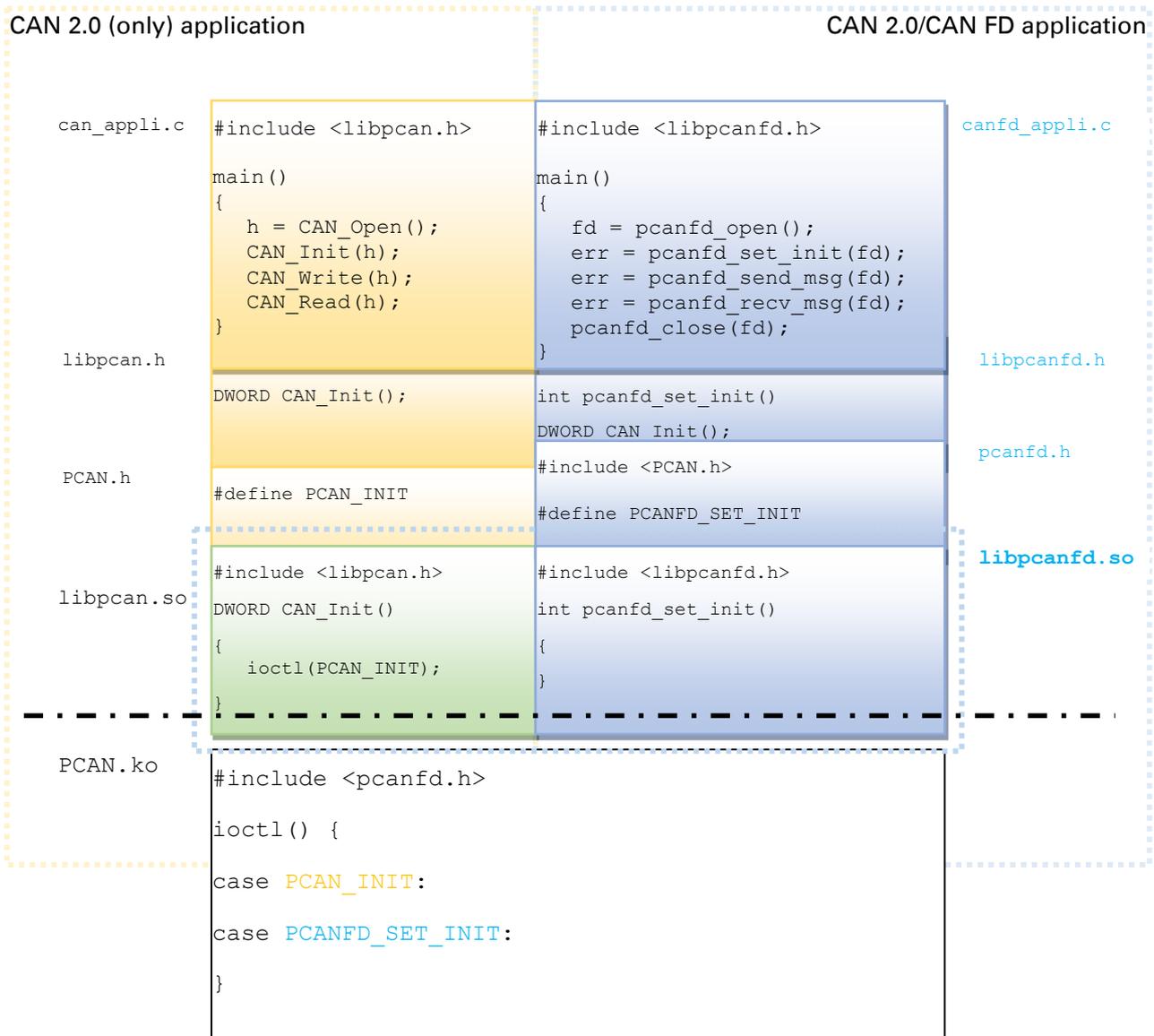


Figure 1: software components architecture

### 5.1.1 CAN 2.0 API

**Note:** This API is kept for backward compatibility reasons, thus these entry points are also proposed by the new libpcanfd library. But, this API is considered as deprecated. Use the new CAN FD API instead.

The (old) CAN 2.0 API ioctl codes are defined by pcan.h:

```
#define PCAN_INIT          _IOWR(PCAN_MAGIC_NUMBER, MYSEQ_START, TPCANInit)
#define PCAN_WRITE_MSG    _IOW (PCAN_MAGIC_NUMBER, MYSEQ_START + 1, TPCANMsg)
#define PCAN_READ_MSG     _IOR (PCAN_MAGIC_NUMBER, MYSEQ_START + 2, TPCANRdMsg)
#define PCAN_GET_STATUS   _IOR (PCAN_MAGIC_NUMBER, MYSEQ_START + 3, TPSTATUS)
#define PCAN_DIAG         _IOR (PCAN_MAGIC_NUMBER, MYSEQ_START + 4, TPDIAG)
#define PCAN_BTROBTR1     _IOWR(PCAN_MAGIC_NUMBER, MYSEQ_START + 5, TPBTROBTR1)
#define PCAN_GET_EXT_STATUS _IOR (PCAN_MAGIC_NUMBER, MYSEQ_START + 6, TPEXTENDEDSTATUS)
#define PCAN_MSG_FILTER    _IOW (PCAN_MAGIC_NUMBER, MYSEQ_START + 7, TPMSGFILTER)
#define PCAN_EXTRA_PARAMS _IOWR(PCAN_MAGIC_NUMBER, MYSEQ_START + 8, TPEXTRAPARAMS)
```

This API enables to read and write CAN 2.0 messages (only) from/through any PC CAN interface of PEAK-System. This API is encapsulated by the `libpcan` library (C/C++ programs like `transmitest`, `receivetest`, `bitratetest`, and `pcan-settings` stored in the `test` directory use this API). Since this API is always supported for CAN 2.0 access, to use this API, the application must link with `-lpcan` or `-lpcanfd`.

The principle of this API is to implement a CAN 2.0 channel with something like an object `HANDLE` used during the whole life of the connection to the CAN bus. This API is greatly inspired of the PCAN-Light version for Windows©.

The library defines the following entry points:

**HANDLE CAN\_Open(WORD wHardwareType, ...);**

This function opens a CAN 2.0 channel according to its type (PCI, USB, ISA ...) and its channel number (or some other arguments depending on the chosen type). See the list of `HW_XXX` symbols defined in `pcan.h` to get the list of supported values for `wHardwareType`.

For example:

```
#include <libpcan.h>

/* open the 2nd CAN 2.0 PCI channel in the system (first is 0) */
HANDLE h = CAN_Open(HW_PCI, 1);
```

**DWORD CAN\_Init(HANDLE hHandle, WORD wBTR0BTR1, int nCANMsgType);**

This function initializes an opened CAN 2.0 channel with a bitrate (expressed in BTR0BTR1 SJA1000 format) and a filter set (or not set) to the extended Id of the CAN messages.

See the list of `CAN_BAUD_XXX` and `CAN_INIT_TYPE_XX` symbols defined in `libpcan.h` to get the list of supported values for `wBTR0BTR1` values and `nCANMsgType`.

For example:

```
#include <libpcan.h>

/* CAN 2.0 channel handle */
HANDLE h;
DWORD status;

...

/* initialize the CAN 2.0 channel with 500 kbps BTR0BTR1, accepting extended ID. */
status = CAN_Init(h, CAN_BAUD_500K, CAN_INIT_TYPE_EX);
```

**DWORD CAN\_write(HANDLE hHandle, TPCANMsg\* pMsgBuff);**

This function writes a CAN 2.0 message to a CAN bus through an opened CAN 2.0 channel.

For example:

```
#include <libpcan.h>

/* CAN 2.0 channel handle */
HANDLE h;
DWORD status;
TPCANMsg msg;

...
msg.ID = 0x123
msg.MSGTYPE = MSGTYPE_STANDARD;
msg.LEN = 3;
msg.DATA[0] = 0x01;
msg.DATA[1] = 0x02;
msg.DATA[2] = 0x03;

/* write standard msg ID = 0x123. with 3 data bytes 0x01 0x02 0x03
 * (the function may block)
 */
status = CAN_Write(h, &msg);
```

**DWORD CAN\_Read(HANDLE hHandle, TPCANMsg\* pMsgBuff);**

This function reads a CAN 2.0 message received from a CAN bus through an opened CAN 2.0 channel. If no message has been received, the calling task is blocked.

For example:

```
#include <libpcan.h>

/* CAN 2.0 channel handle */
HANDLE h;
DWORD status;
TPCANMsg msg;

...
/* wait for a CAN 2.0 msg received from the CAN channel
 * (the function may block)
 */
status = CAN_Read(h, &msg);
```

**DWORD CAN\_Status(HANDLE hHandle);**

This function returns the status of an opened CAN 2.0 channel (corresponding to the last column displayed with `cat /proc/pcan`). The returned value is a bitmask (see the list of `CAN_ERR_XXX` symbols defined in `pcan.h` to get the meaning of each bit).

 **Note:** Reading the status of a channel with this function clears it!

For example:

```
#include <libpcan.h>

/* CAN 2.0 channel handle */
HANDLE h;
DWORD status;

...
/* get the status of a CAN 2.0 channel */
status = CAN_Status(h);
```

**DWORD CAN\_Close(HANDLE hHandle);**

This function closes an opened CAN 2.0 channel. The given handle should not be used next.

For example:

```
#include <libpcan.h>

/* CAN 2.0 channel handle */
HANDLE h;

...
/* wait for a CAN 2.0 msg received from the CAN channel
 * (the function may block)
 */
CAN_Close(h);
```

To get profit from the multi-tasking environment of Linux, the library has been extended with the following `LINUX_XXX()` functions:

**int LINUX\_CAN\_FileHandle(HANDLE hHandle);**

This function returns the file descriptor corresponding to the device node opened by the driver. This is useful when an application has to wait for more than one read/write event.

**HANDLE LINUX\_CAN\_Open(const char \*szDeviceName, int nFlag);**

This function opens a CAN 2.0 channel, but with the Linux system device node name instead.

**DWORD LINUX\_CAN\_Read(HANDLE hHandle, TPCANRdMsg\* pMsgBuff);**

This functions acts like "DWORD CAN\_Read(HANDLE hHandle, TPCANMsg\* pMsgBuff);", but returns extra timestamp information.

**DWORD LINUX\_CAN\_Read\_Timeout(HANDLE hHandle, TPCANRdMsg\* pMsgBuff, int nMicroSeconds);**

This function acts like "DWORD LINUX\_CAN\_Read(HANDLE hHandle, TPCANRdMsg\* pMsgBuff);", but, in case there is no message to read from the CAN, it blocks the calling task for `nMicroSeconds` at maximum.

**DWORD LINUX\_CAN\_Write\_Timeout(HANDLE hHandle, TPCANMsg\* pMsgBuff, int nMicroSeconds);**

This function acts like “DWORD CAN\_Write(HANDLE hHandle, TPCANMsg\* pMsgBuff);”, but in case there is no more room in the transmit queue of the CAN channel, it blocks the calling task for nMicroSeconds at maximum.

**DWORD LINUX\_CAN\_Extended\_Status(HANDLE hHandle, int \*nPendingReads, int \*nPendingWrites);**

This function acts like “DWORD CAN\_Status(HANDLE hHandle);”, but also returns the count of messages waiting to be read from the receive queue of the channel in \*nPendingReads, and the count of messages waiting to be sent from the transmit queue of the channel in \* nPendingWrites.

**DWORD LINUX\_CAN\_Statistics(HANDLE hHandle, TPDIAG \*diag);**

This function gives some statistics about a CAN 2.0 channel but without clearing the status of this channel (like “DWORD CAN\_Status(HANDLE hHandle);” does).

**WORD LINUX\_CAN\_BTR0BTR1(HANDLE hHandle, DWORD dwBitRate);**

This function returns the BTR0BTR1 8 MHz SJA1000 code corresponding to the given bitrate.

### 5.1.2 CAN FD API

This API is new since version 8 of the driver. It always proposes the entry points and data structures defined in the old one (see 5.1.1 *CAN 2.0 API* on page 49), but adds definition of some new data structures and ioctl codes (see `pcanfd.h`). The old entry points always allow connecting to the CAN 2.0 bus as usual, while the new ones enable to connect to CAN 2.0 and/or CAN FD busses. In other words, the new API is a new, modern and universal way of accessing the CAN bus. The old entry points are only kept for ensuring backward compatibility with existing application code.

```
#define PCANFD_SET_INIT          _IOW(PCAN_MAGIC_NUMBER, PCANFD_SEQ_SET_INIT, \
                                     struct pcanfd_init)
#define PCANFD_GET_INIT          _IOR(PCAN_MAGIC_NUMBER, PCANFD_SEQ_GET_INIT, \
                                     struct pcanfd_init)
#define PCANFD_GET_STATE         _IOR(PCAN_MAGIC_NUMBER, PCANFD_SEQ_GET_STATE, \
                                     struct pcanfd state)
#define PCANFD_ADD_FILTERS       _IOW(PCAN_MAGIC_NUMBER, PCANFD_SEQ_ADD_FILTERS, \
                                     struct pcanfd msg_filters)
#define PCANFD_GET_FILTERS       _IOW(PCAN_MAGIC_NUMBER, PCANFD_SEQ_GET_FILTERS, \
                                     struct pcanfd msg_filters)
#define PCANFD_SEND_MSG          _IOW(PCAN_MAGIC_NUMBER, PCANFD_SEQ_SEND_MSG, \
                                     struct pcanfd msg)
#define PCANFD_RECV_MSG          _IOR(PCAN_MAGIC_NUMBER, PCANFD_SEQ_RECV_MSG, \
                                     struct pcanfd msg)
#define PCANFD_SEND_MSGS         _IOWR(PCAN_MAGIC_NUMBER, PCANFD_SEQ_SEND_MSGS, \
                                       struct pcanfd msgs)
#define PCANFD_RECV_MSGS         _IOWR(PCAN_MAGIC_NUMBER, PCANFD_SEQ_RECV_MSGS, \
                                       struct pcanfd msgs)
#define PCANFD_GET_AVAILABLE_CLOCKS _IOWR(PCAN_MAGIC_NUMBER, \
                                           PCANFD_SEQ_GET_AVAILABLE_CLOCKS, \
                                           struct pcanfd_available_clocks)
```

```
#define PCANFD_GET_BITTIMING_RANGES    _IOWR(PCAN_MAGIC_NUMBER, \
                                           PCANFD_SEQ_GET_BITTIMING_RANGES, \
                                           struct pcanfd_bittiming_ranges)
#define PCANFD_GET_OPTION              _IOWR(PCAN_MAGIC_NUMBER, PCANFD_SEQ_GET_OPTION, \
                                           struct pcanfd_option)
#define PCANFD_SET_OPTION              _IOW(PCAN_MAGIC_NUMBER, PCANFD_SEQ_SET_OPTION, \
                                           struct pcanfd_option)
```

These new *ioctl*/codes are also encapsulated by some new entry points of the new `libpcanfd` library. These new entry points are defined in `libpcanfd.h`.

**Note:** The test application `pcanfdtst` uses these new entry points.

This new library does not anymore encapsulate CAN channels into any `HANDLE` objects, but directly deals with file descriptors returned by the `open()` system call, made on the corresponding device node.

**Note:** The old and new APIs are not compatible! Once a CAN channel is opened through one API, it cannot be used with the other one. In other words, opening a CAN channel selects the API that is used for the connection.

The new API offers several levels of usage. While Level 1 encapsulates the above *ioctl*/codes, Level 2 API offers a more friendly way of opening and closing a device node.

Finally, all of the entry points of this new API return an integer value. If it is negative, it must be interpreted as an error code that equals to `-errno`.

**int pcanfd\_set\_init(int fd, struct pcanfd\_init \*pfdi);**

This function initializes an opened device node with some new settings that enable to select CAN 2.0 as well as CAN FD properties (if the corresponding hardware is compatible). These properties are defined by the new `struct pcanfd_init` object (see also `pcanfd.h`):

```
struct pcanfd_init {
    __u32 flags;
    __u32 clock_Hz;
    struct pcan_bittiming    nominal;
    struct pcan_bittiming    data;
};
```

Field	Values	Description
flags	<code>PCANFD_INIT_LISTEN_ONLY</code>	The device is opened in listen-only mode.
	<code>PCANFD_INIT_STD_MSG_ONLY</code>	Only standard CAN message IDs are transmitted and received. If not set, all kinds of messages IDs are used for that device.
	<code>PCANFD_INIT_FD</code>	Open the device for CAN FD ISO access if the device is CAN-FD-capable.
	<code>PCANFD_INIT_FD_NON_ISO</code>	Open the device for CAN FD non-ISO access if the device is CAN-FD-capable.
	<code>PCANFD_INIT_TS_DEV_REL</code>	Timestamps set by the driver to the messages received from the CAN bus are relative to the moment the device is initialized.
	<code>PCANFD_INIT_TS_HOST_REL</code>	Timestamps set by the driver to the messages received from the CAN bus are relative to the moment the host has started.
	<code>PCANFD_INIT_TS_DRV_REL</code>	Timestamps set by the driver to the messages received from the CAN bus will be relative to the moment the driver has started (default).
	<code>PCANFD_INIT_BUS_LOAD_INFO</code>	If the CAN bus load is information the corresponding hardware is able to provide, then the driver will periodically put <code>STATUS</code> messages in the rx fifo queue of this channel to inform the application of the current bus load the channel is connected to.

Field	Values	Description
clock	0	The default clock of the CAN device is selected by the driver (default).
	any other value	The clock frequency (expressed in Hz) to select in the CAN device hardware to select the right bit timing specifications.
nominal	struct pcan_bittiming	Defines the nominal bitrate to use to connect to the CAN bus (default value is defined in Table 2 on page 12).
data	struct pcan_bittiming	Defines the data bitrate to select when the device is a CAN FD one, and the written message flag PCANFD_MSG_BRS is set (default value is defined in Table 2 on page 12).

Table 9: struct pcanfd\_init description

```
int pcanfd_get_init(int fd, struct pcanfd_init *pfdi);
```

This function enables the user application to get the initialization settings that are set to an opened device.

```
int pcanfd_get_state(int fd, struct pcanfd_state *pfd_s);
```

This function gets the current state of an opened device. The state of a CAN channel is summarized in the new struct pcanfd\_state object (see also pcanfd.h):

```
struct pcanfd_state {
    __u16  ver_major, ver_minor, ver_subminor;

    struct timeval  tv_init;          /* time the device was initialized */

    enum pcanfd_status  bus_state;    /* CAN bus state */

    __u32  device_id;                /* device ID, ffffffff is unused */

    __u32  open_counter;             /* open() counter */
    __u32  filters_counter;          /* count of message filters */

    __u16  hw_type;                  /* PCAN device type */
    __u16  channel_number;           /* channel number for the device */

    __u16  can_status;               /* same as wCANStatus but NOT CLEARED */
    __u16  bus_load;                 /* bus load value, ffff if not given */

    __u32  tx_max_msgs;              /* Tx fifo size in count of msgs */
    __u32  tx_pending_msgs;          /* msgs waiting to be sent */
    __u32  rx_max_msgs;              /* Rx fifo size in count of msgs */
    __u32  rx_pending_msgs;          /* msgs waiting to be read */
    __u32  tx_frames_counter;        /* Tx frames written on device */
    __u32  rx_frames_counter;        /* Rx frames read on device */
    __u32  tx_error_counter;         /* CAN Tx errors counter */
    __u32  rx_error_counter;         /* CAN Rx errors counter */

    __u64  host_time_ns;              /* host time in nanoseconds as it was */
    __u64  hw_time_ns;               /* when hw_time_ns has been received */
};
```

```
int pcanfd_add_filter(int fd, struct pcanfd_msg_filter *pf);
```

This function adds a message filter to the device's filters list. When a device is opened, no filters exist for the device, that is, the application receives all message IDs read from the CAN bus. Adding a message filter enables to filter among incoming CAN messages which are to pass to the application and which are

to discard. The message filter is described by the new `struct pcanfd_msg_filter` object (see also `pcanfd.h`):

```

struct pcanfd_msg_filter {
    __u32    id_from;           /* msgs ID in range [id_from..id_to] */
    __u32    id_to;           /* and flags == msg_flags */
    __u32    msg_flags;       /* will be passed to applications */
};

```

**int pcanfd\_add\_filters(int fd, struct pcanfd\_msg\_filters \*pfl);**

This function adds several message filters to the device's filters list at once. The list of messages is saved into the following `struct pcanfd_msg_filters`:

```

struct pcanfd_msg_filters {
    __u32    count
    struct pcanfd_msg_filter list[0];
};

```

**Note:** The `count` field should contain the number of message filters saved in the `list[]` array field.

**int pcanfd\_add\_filters\_list(int fd, int count, struct pcanfd\_msg\_filter \*pf);**

This function adds several message filters to the device's filters list at once. This is a shortcut easier to use than "int pcanfd\_add\_filters(int fd, struct pcanfd\_msg\_filters \*pfl);".

**int pcanfd\_del\_filters(int fd);**

This function deletes all the filters linked to device's filters list. No filters do exist anymore for the device, so the application will receive all message IDs read from the CAN bus. This is the default behavior of a CAN device when it has been opened.

**int pcanfd\_send\_msg(int fd, struct pcanfd\_msg \*pfdm);**

This function writes a message to the CAN bus through an opened device. The message is defined by the new `struct pcanfd_msg` object (see also `pcanfd.h`):

```

struct pcanfd_msg {
    __u16    type;           /* PCANFD_TYPE_XXX */
    __u16    data_len;       /* true length (not the DLC) */
    __u32    id;
    __u32    flags;         /* PCANFD_XXX definitions */
    struct timeval timestamp;
    __u8     ctrlr_data[PCANFD_CTRLR_MAXDATALEN];
    __u8     data[PCANFD_MAXDATALEN] __attribute__((aligned(8)));
};

```

This C structure object is able to carry a CAN 2.0 as well as a CAN FD message. It also can contain some out-of-band message types (like status messages) that can be pushed by the driver to the application.

**Note:** Writing a message to the CAN bus might block the calling task, unless the device node has been opened in non-blocking mode. In that case, `-EWOULDBLOCK` is returned by this function if the task had not enough room to store the outgoing message.

Field	Values	Description
type	PCANFD_TYPE_CAN20_MSG	This message is a CAN 2.0 message (the <code>data_len</code> field cannot be larger than 8).
	PCANFD_TYPE_CANFD_MSG	This message is a CAN FD message. Bits like <code>PCANFD_MSG_BRS</code> are handled by the <code>flags</code> field. The <code>data_len</code> field cannot be larger than 64.
data_len	<= 8	Number of data bytes to copy from the data field to transmit on the CAN bus.
	<= 64	In case of CAN FD message, this value is the true count of bytes to write. The driver is in charge to adapt this to the corresponding DLC code.
flags	PCANFD_MSG_RTR	Remote Transmission Request message.
	PCANFD_MSG_EXT	The message ID is to be coded using 29 bits (the standard message format uses 11 bits only).
	PCANFD_MSG_SLF	If supported, this message is looped back by the hardware to its internal receive queue. Note: Depending on the hardware, this bit may or may not be set in the flags of the looped back frame.
	PCANFD_MSG_SNG	If supported, this message is transmitted in Single-Shot mode, that is, if the CAN frame is not transmitted successfully, no further transmissions are attempted.
	PCANFD_MSG_BRS	In case of CAN FD, this bit enables the alternate data bitrate for the transport of the data bytes, instead of the nominal bitrate.
	PCANFD_MSG_ECHO	If supported, this message is written on the bus and echoed by the hardware to its internal receive queue. Moreover, that bit is set in the echoed frame, as well as <code>ctrlr_data[PCANFD_ECHOID]</code> that contains a copy of <code>ctrlr_data[PCANFD_ECHOID]</code> of the sent message.
id		The ID of the CAN message.
data		The data bytes of the CAN message. Only the count of bytes given by <code>data_len</code> field is copied onto the bus.
ctrlr_data		When <code>PCANFD_MSG_ECHO</code> is set, the 7 low order bit of <code>ctrlr_data[PCANFD_ECHOID]</code> will be copied into <code>ctrlr_data[PCANFD_ECHOID]</code> of the echoed frame.

Table 10: Usage of struct `pcanfd_msg` on the transmit side

```
int pcanfd_send_msgs(int fd, struct pcanfd_msgs *pfdm1);
```

This function writes a list of messages to the CAN bus through an opened device. The message list is defined by the new struct `pcanfd_msgs` object (see also `pcanfd.h`):

```
struct pcanfd_msgs {
    _u32          count;
    struct pcanfd_msg list[0];
};
```

This C structure object is able to carry several CAN 2.0 and CAN FD messages. The number of messages to write is given by the `count` field. This field is also used to indicate how many messages have really been written in the transmit queue of the device.

**Note:** Writing several messages to the CAN bus might block the calling task, unless the device node has been opened in non-blocking mode. In that case, `-EWOULDBLOCK` is returned by this function if the task had not enough room to store the outgoing messages.

If at least one message has been successfully written in the transmit queue, then the function returns 0. Otherwise, it returns a negative error code.

Using this function saves memory copies and constant round trips between kernel and user spaces.

## Example:

```

#include <malloc.h>
#include <libpcanfd.h>

int fill_msg(struct pcanfd_msg *pm);

struct pcanfd_msgs *pml;

/* allocate enough room to store 5 CAN messages */
pml = malloc(sizeof(*pml) + 5 * sizeof(struct pcanfd_msg));
pml->count = 5;

for (pml->count = 0; pml->count < 5; pml->count++) {
    fill_msg(pml->list + pml->count);
}

/* put all of the messages at once in the transmit queue of the device... */
err = pcanfd_send_msgs(fd, pml);
if (err)
    printf("Only %u/5 msgs have been sent because of errno=%d\n",
           pml->count, err);

free(pml);
...

```

```
int pcanfd_send_msgs_list(int fd, int count, struct pcanfd_msg *pfdm);
```

This function writes a list of messages to the CAN bus through an opened device. This is a shortcut easier to use than “int pcanfd\_send\_msgs(int fd, struct pcanfd\_msgs \*pfdml);”.

```
int pcanfd_rcv_msg(int fd, struct pcanfd_msg *pfdm);
```

This function reads any pending message the driver might have pushed in the corresponding device receive queue. This message can be an in band message if it contains a CAN 2.0 or a CAN FD message received from the CAN bus, or an out-of-band message if it contains a status message.

**i Note:** Reading a message from the driver might block the calling task, unless the device node has been opened in non-blocking mode. In that case, `-EWOULDBLOCK` is returned by this function if the task didn't find any message to read.

Field	Values	Description
type	PCANFD_TYPE_CAN20_MSG	This message is a CAN 2.0 message.
	PCANFD_TYPE_CANFD_MSG	This message is a CAN FD message. Bits like <code>PCANFD_MSG_BRS</code> or <code>PCANFD_MSG_ESI</code> can also be set in the flags field.
	PCANFD_TYPE_STATUS	This message is a status message, giving some more information about the state of the CAN device.
	PCANFD_TYPE_ERROR_MSG	This message is an error message read from the CAN bus. This kind of messages ISNOT received by default (see also option <code>PCANFD_ALLOWED_MSG_ERROR</code> in <code>int pcanfd_set_option(int fd, int name, void *value, int size);</code> )
data_len		Number of data bytes in the message received from the CAN device. Note that in case of CAN FD, this value might not be the same as the one given on the transmission side.
id		The ID of the CAN message.

Field	Values	Description
flags	PCANFD_MSG_RTR	Remote Transmission Request message.
	PCANFD_MSG_EXT	The message ID format is an extended one.
	PCANFD_MSG_SLF	This message has been looped-back by the hardware to its internal receive queue.
	PCANFD_MSG_SNG	This message has been transmitted in Single-Shot mode.
	PCANFD_MSG_BRS	In case of CAN FD, this bit indicates that data bitrate has been selected for transmitting the data bytes of the received message.
	PCANFD_MSG_ECHO	This message has been echoed by the hardware to its internal receive queue as well as written on the bus and <code>ctrlr_data[PCANFD_ECHOID]</code> contains a copy of <code>ctrlr_data[PCANFD_ECHOID]</code> of the sent message.
	PCANFD_MSG_ESI	CAN FD error indicator: errors detected on the CAN bus.
	PCANFD_TIMESTAMP	The <code>timestamp</code> field is valued with the timestamp the message has been received.
	PCANFD_HWTIMESTAMP	When <code>PCANFD_TIMESTAMP</code> is set, this flag indicates that the given timestamp is made from the timestamp given by the hardware. If not set, the timestamp has been built by the driver from the host time.
	PCANFD_ERRCNT	<code>ctrlr_data[PCANFD_RXERRCNT]</code> and <code>ctrlr_data[PCANFD_TXERRCNT]</code> contain Rx and Tx error counters read from the CAN controller.
	PCANFD_BUSLOAD	<code>ctrlr_data[PCANFD_BUSLOAD_UNIT]</code> contains the percentage of the bus load computed by the hardware controller, while <code>ctrlr_data[PCANFD_BUSLOAD_DEC]</code> contains the decimal part.
PCANFD_OVRCNT	<code>ctrlr_data[PCANFD_RXERRCNT]</code> contains the number of messages lost because the Rx queue of the driver was full.	
timestamp	struct timeval	If <code>PCANFD_TIMESTAMP</code> is set in the flag field, then this one indicates the moment the message has been received. If <code>PCANFD_HWTIMESTAMP</code> is also set, the given moment is a time made from the hardware clock. If <code>PCANFD_HWTIMESTAMP</code> is not set, this moment is made by the driver, from the host current time (see also option in <code>int pcanfd_set_option(int fd, int name, void *value, int size);</code> ).
ctrlr_data		CAN-controller-specific data (see <code>PCANFD_MSG_ECHO</code> , <code>PCANFD_ERRCNT</code> and <code>PCANFD_BUSLOAD</code> flags above).
data		The data bytes of the CAN message. The count of data bytes received is given by the <code>data_len</code> field.

Table 11: Usage of struct pcanfd\_msg on the receive side

```
int pcanfd_recv_msgs(int fd, struct pcanfd_msgs *pfdm1);
```

This function is able to read a list of messages at once from the driver device receive queue. The messages list is defined by the new `struct pcanfd_msgs` object (see also `pcanfd.h`):

```
struct pcanfd_msgs {
    __u32          count;
    struct pcanfd_msg list[0];
};
```

This C structure object is able to carry several CAN 2.0 and CAN FD messages. The maximum number of messages the list is able to contain must be set in the `count` field. When returning from this function, the `count` field is set by the driver to the real number of copied messages.

**Note:** Reading several messages from the driver might block the calling task, unless the device node has been opened in non-blocking mode. In that case, `-EWOULDBLOCK` is returned by this function if the task didn't find any message to read.

If at least one message has been successfully read, then the function returns 0. Otherwise, it returns a negative error code.

Using this function saves memory copies and constant round trips between kernel and user spaces.

Example:

```
#include <malloc.h>
#include <libpcanfd.h>
#include <errno.h>

int process_msg(struct pcanfd_msg *pm)
{
    switch (pm->type) {
        case PCANFD_TYPE_CAN20_MSG:
            return process_CAN_2_0_msg(pm);
        case PCANFD_TYPE_CANFD_MSG:
            return process_CAN_FD_msg(pm);
        case PCANFD_TYPE_STATUS:
            return process_status_msg(pm);
        case PCANFD_TYPE_ERROR_MSG:
            /* if enabled, see PCANFD_OPT_ALLOWED_MSGS[PCANFD_ALLOWED_MSG_ERROR] */
            return process_error_msg(pm);
    }

    return -EINVAL;
}

struct pcanfd_msgs *pml;
int i, err;

/* allocate enough room to store at least 5 CAN messages */
pml = malloc(sizeof(*pml) + 5 * sizeof(struct pcanfd_msg));
pml->count = 5;

/* waiting for these messages... */
err = pcanfd_recv_msgs(fd, pml);
if (err)
    exit(1);

/* process the received messages... */
for (i = 0; i < pml->count; i++) {
    process_msg(pml->list + i);
}

free(pml);
...
```

```
int pcanfd_recv_msgs_list(int fd, int count, struct pcanfd_msg *pm);
```

This function is able to read a list of messages at once from the driver device receive queue. This is a shortcut easier to use than "int pcanfd\_recv\_msgs(int fd, struct pcanfd\_msgs \*pfdml);".

If the return value is positive, then it indicates the real count of messages read from the device input queue. Otherwise, it's an error code.

```
int pcanfd_get_available_clocks(int fd, struct pcanfd_available_clocks *pac);
```

This function returns the list of all the available clocks the underlying CAN/CAN FD device can run with. The clock is selected at the time the device is initialized (see int pcanfd\_set\_init(int fd, struct pcanfd\_init \*pfdi);).

```

/* Device available clocks value */
struct pcanfd_available_clock {
    __u32    clock_Hz;
    __u32    clock_src;
};

struct pcanfd_available_clocks {
    __u32    count;
    struct pcanfd_available_clock list[0];
};

```

User is responsible to setup the "count" field with the count of items it has allocated in the "list[]" array.

Example:

```

struct pcanfd_available_clocks *pac;
int i, err;

/* allocate enough room to store at least 8 clock values */
pac = malloc(sizeof(*pac) + 6 * sizeof(struct pcanfd_available_clock));
pac->count = 6;

/* reading the available clocks list */
err = pcanfd_get_available_clocks(fd, pac);
if (err)
    exit(1);

/* display all available clocks */
for (i = 0; i < pac->count; i++) {
    printf("clock #%u/%u: %u Hz\n", i, pac->count, pac->list[i]);
}

free(pac);

```

 **Note:** list[0] always contains default clock value. Only CAN FD devices define more than one clock.

**int pcanfd\_get\_bittiming\_ranges(int fd, struct pcanfd\_bittiming\_ranges \*pbtr)**

This function returns the list of all the available bit timing ranges the underlying CAN/CAN FD device can run with. The bit timings are selected at the time the device is initialized (see `int pcanfd_set_init(int fd, struct pcanfd_init *pfdi)`).

```

/* CAN FD bittiming capabilities */
struct pcanfd_bittiming_range {
    __u32   brp_min;
    __u32   brp_max;
    __u32   brp_inc;
    __u32   tseg1_min;
    __u32   tseg1_max;
    __u32   tseg2_min;
    __u32   tseg2_max;
    __u32   sjw_min;
    __u32   sjw_max;
};

struct pcanfd_bittiming_ranges {
    __u32   count;
    struct pcanfd_bittiming_range list[0];
};

```

User is responsible to setup the "count" field with the count of items it has allocated in the "list[]" array.

Version 8.2 of the pcan driver always sets 1 in the "count" field for any CAN 2.0 device, while it sets 2 for any CAN FD device.

Example:

```

struct pcanfd_bittiming_ranges *pbr;
int err;

/* allocate enough room to store 2 ranges */
pbr = malloc(sizeof(*pbr) + 2 * sizeof(struct pcanfd_bittiming_range));
pbr->count = 2;

/* reading the bit timings ranges list */
err = pcanfd_get_bittiming_ranges(fd, pbr);
if (err)
    exit(1);

if (pbr->count == 1)
    printf("CAN 2.0 device\n");
else
    printf("CAN FD device\n");

free(pbr);

```

**int pcanfd\_get\_option(int fd, int name, void \*value, int size);**

This function enables to read the current value of an option attached to a channel device. Each channel handles the same set of options which values are initialized once it is opened. The list of these options is given below and may evolve over time (see also `pcanfd.h`).

Getting the value of an option that doesn't exist returns `-EINVAL`, while getting an unsupported option (for the device) returns `-EOPNOTSUPP`. Reading the value of an option with a too small `value` buffer returns `-ENOSPC`.

Successfully reading the value of an option returns the number of bytes that have been copied into `value`.

Option	Size (bytes)	Description
PCANFD_OPT_CHANNEL_FEATURES	4	<p>The value of this option is a bitmask that gives the features of an opened channel:</p> <p>PCANFD_FEATURE_FD                      Channel is CAN-FD capable  PCANFD_FEATURE_IFRAME_DELAYUS      Delay can be inserted between frames  PCANFD_FEATURE_BUSLOAD              Channel is able to compute bus load  PCANFD_FEATURE_HWTIMESTAMP        timestamp are read from the device  PCANFD_FEATURE_DEVICEID            Channel can be labeled with a user device id.</p>
PCANFD_OPT_DEVICE_ID	4	Get the user id attached to the channel device (if supported by the channel)
PCANFD_OPT_AVAILABLE_CLOCKS		Return the list of clocks available in the channel device. The value returned is of type <code>pcanfd_available_clocks</code> (see <code>pcanfd.h</code> and <code>int pcanfd_get_available_clocks(int fd, struct pcanfd_available_clocks *pac);</code> ). Getting this option is equivalent to calling <code>pcanfd_get_available_clocks()</code> .
PCANFD_OPT_BITTIMING_RANGES		Give the bit timings ranges available for the channel, to specify the nominal bitrate. These ranges depend on which CAN/CAN-FD controller the channel is equipped with (see also <code>int pcanfd_get_bittiming_ranges(int fd, struct pcanfd_bittiming_ranges *pbr)</code> ).
PCANFD_OPT_DBITTIMING_RANGES		Give the bit timings ranges available for the channel, to specify the data bitrate. These ranges depend on which CAN-FD controller the channel is equipped with (see also <code>int pcanfd_get_bittiming_ranges(int fd, struct pcanfd_bittiming_ranges *pbr)</code> ).
PCANFD_OPT_ALLOWED_MSGS	4	<p>The value of this option is a bitmask that describes which kind of message an application is able to receive:</p> <p>PCANFD_ALLOWED_MSG_CAN              CAN/CAN-FD frames  PCANFD_ALLOWED_MSG_RTR              RTR frames  PCANFD_ALLOWED_MSG_EXT              Extended Id.  PCANFD_ALLOWED_MSG_STATUS        STATUS messages  PCANFD_ALLOWED_MSG_ERROR        Error from the CAN bus</p>
PCANFD_OPT_ACC_FILTER_11B	8	Get the current acceptance filter code and mask for the standard messages received on the channel. The high-order 32-bits contain the acceptance code while the low-order ones contain the acceptance mask.
PCANFD_OPT_ACC_FILTER_29B	8	Get the current acceptance filter code and mask for the extended messages received on the channel. The high-order 32-bits contain the acceptance code while the low-order ones contain the acceptance mask.
PCANFD_OPT_IFRAME_DELAYUS	4	Get the value of the delay in $\mu$ s that is currently inserted by the CAN controller between each frame it sends.
PCANFD_OPT_HWTIMESTAMP_MODE	4	<p>Get the current mode the driver currently uses to compute the timestamps saved into each <code>struct pcanfd_msg</code>.</p> <p>PCANFD_OPT_HWTIMESTAMP_OFF        Host time based only (even if hw is capable).  PCANFD_OPT_HWTIMESTAMP_ON        Host time base + raw hw time offset.  PCANFD_OPT_HWTIMESTAMP_COOKED    Host time base + cooked hw time offset.  PCANFD_OPT_HWTIMESTAMP_RAW        Raw hardware timestamps.</p> <p>Same as above but hw timestamp is fired at Start Of Frame instead of End Of Frame.:</p> <p>PCANFD_OPT_HWTIMESTAMP_SOF_ON  PCANFD_OPT_HWTIMESTAMP_SOF_COOKED  PCANFD_OPT_HWTIMESTAMP_SOF_RAW</p> <p>Cooked timestamps handle clocks drift between the different clocks systems (PC, board, USB controller...)</p> <p>Raw hardware timestamps are 64-bits <math>\mu</math>s timestamps given by the controller converted into s. + <math>\mu</math>s. These timestamps ARE NOT host time related.</p>
PCANFD_OPT_DRV_VERSION	4	Get the driver version.
PCANFD_OPT_FW_VERSION	4	Get the device firmware version.

Option	Size (bytes)	Description
PCANFD_IO_DIGITAL_CFG	4	Get/set the configuration of the digital I/O pins of the PCAN-Chip (firmware >= 3.3.0): 1 the I/O pin is setup in output mode 0 the I/O pin is setup in input mode.
PCANFD_IO_DIGITAL_VAL	4	Get/set the digital I/O pins value.
PCANFD_IO_DIGITAL_SET	4	Set the digital I/O pins to high.
PCANFD_IO_DIGITAL_CLR	4	Clear the digital I/O pins to low.
PCANFD_IO_ANALOG_VAL	4	Get the analog I/O value from the PCAN-Chip.
PCANFD_OPT_MASS_STORAGE_MODE	4	The value of this option is always 0 if the device is able to switch in Mass Storage Device mode.  If the device is not able to switch in MSD mode, reading this option fails and errno is set to EOPNOTSUPP.
PCANFD_OPT_DRV_CLK_REF	4	Get the clock reference used by the driver (see Table 6 on page 21 ).
PCANFD_OPT_LINGER	4	Get the maximum waiting time in ms. the driver will wait before closing the device, while there are frames to write pending in the driver device Tx queue.
PCANFD_OPT_SELF_ACK	4	Check whether controller sends ACK by itself to the frames it writes on the bus.
PCANFD_OPT_BRS_IGNORE	4	Check whether the controller ignores received frames with BRS flag set.

Table 12

```
int pcanfd_set_option(int fd, int name, void *value, int size);
```

This function enables to set a value to an option attached to a channel device. Each channel handles the same set of options which values are initialized once it is opened. The list of the options that can be changed is given below and may evolve over time (see also `pcanfd.h`).

Setting the value of an option that does not exist, or setting an invalid value to an existing option returns `-EINVAL`, while setting a value to an unsupported option (for the device) returns `-EOPNOTSUPP`.

Correctly setting a value to an option returns 0.

Option	Size (in bytes)	Description
PCANFD_OPT_DEVICE_ID	4	Set a user numeric value to the channel device (if supported by the channel)
PCANFD_OPT_ALLOWED_MSGS	4	Set what kinds of message the application wants to be notified with. Once opened, each channel is able to receive:  PCANFD_ALLOWED_MSG_CAN           CAN/CAN-FD frames PCANFD_ALLOWED_MSG_RTR         RTR frames PCANFD_ALLOWED_MSG_EXT         Extended Id. PCANFD_ALLOWED_MSG_STATUS      STATUS messages
PCANFD_OPT_ACC_FILTER_11B	8	Set the current acceptance filter code and mask for the standard messages received on the channel. The high-order 32-bits should contain the acceptance code while the low-order ones should contain the acceptance mask.
PCANFD_OPT_ACC_FILTER_29B	8	Set the current acceptance filter code and mask for the extended messages received on the channel. The high-order 32-bits should contain the acceptance code while the low-order ones should contain the acceptance mask.
PCANFD_OPT_IFRAME_DELAYUS	4	Set the value of the delay in $\mu$ s that should be inserted by the CAN controller between each frame it sends, if this controller is able to.

Option	Size (in bytes)	Description
PCANFD_OPT_HWTIMESTAMP_MODE	4	<p>Set the current mode the driver should use to compute the timestamps saved into each <code>struct pcanfd_msg</code>.</p> <p>PCANFD_OPT_HWTIMESTAMP_OFF      Host time based only (even if hw is capable).</p> <p>PCANFD_OPT_HWTIMESTAMP_ON      Host time base + raw hw time offset.</p> <p>PCANFD_OPT_HWTIMESTAMP_COOKED      Host time base + cooked hw time offset.</p> <p>PCANFD_OPT_HWTIMESTAMP_RAW      Raw hardware timestamps.</p> <p>Same as above but hw timestamp is fired at Start Of Frame instead of End Of Frame:.</p> <p>PCANFD_OPT_HWTIMESTAMP_SOF_ON PCANFD_OPT_HWTIMESTAMP_SOF_COOKED PCANFD_OPT_HWTIMESTAMP_SOF_RAW</p> <p>Cooked timestamps handle clocks drift between the different clocks systems (PC, board, USB controller...)</p> <p>Raw hardware timestamps are 64-bits <math>\mu</math>s timestamps given by the controller converted into s. + <math>\mu</math>s. These timestamps ARE NOT host time related.</p>
PCANFD_OPT_MASS_STORAGE_MODE	4	<p>If the device is compatible, setting a value different from 0 to this option switches the PC CAN interface in Mass Storage Device mode.</p> <p>If the device is not able to switch in MSD mode, setting this option fails and <code>errno</code> is set to <code>EOPNOTSUPP</code>.</p> <p>If the user hasn't got root privileges, setting this option fails and <code>errno</code> is set to <code>EPERM</code>.</p>
PCANFD_OPT_FLASH_LED	4	Makes the LED of the device blink to identify it (if it is equipped with one). Value is the number of milliseconds the LED should blink.
PCANFD_OPT_DRV_CLK_REF	4	Set the clock reference used by the driver (see Table 6 on page 21 ).
PCANFD_OPT_LINGER	4	<p>PCANFD_OPT_LINGER_NOWAIT      Task doesn't wait for the Tx queue to be empty before closing the device.</p> <p>PCANFD_OPT_LINGER_AUTO      Driver automatically computes time to wait for the TX queue to be empty before closing the device.</p> <p>Any other positive value defines the maximum waiting time in ms. before closing the device. The default value is 1000.</p>
PCANFD_OPT_SELF_ACK	4	If 1 then requests the controller to send ACK by itself to the frames it writes on the bus. 0 disables this option.
PCANFD_OPT_BRS_IGNORE	4	If 1 then requests the controller to ignore received frames with BRS flag set. 0 disables this option.

Table 13

```
int pcanfd_open(char *dev_pcan, __u32 flags, ...);
```

This function is a shortcut used to open and initialize any PC CAN interface. First parameter is the name of the device node known by the system. Second argument is a bitmask which indicates what the next parameters of the function are, and their sequence order, as well as the `PCANFD_INIT_XXX` flags used to initialize the CAN controller (see also `libpcanfd.h` and `pcanfd.h`).

Table 14 describes the order and how each bit of the `flags` argument is interpreted:

Bit	Description
<code>OFD_BITRATE</code>	<p>The specification of the nominal bitrate starts with the third parameter:</p> <p>If <code>OFD_BTR0BTR1</code> is set too, then the third parameter is interpreted as a 16-bit value respecting the BTR0BTR1 SJA1000 format.</p> <p>If <code>OFD_BRPTSEGSJW</code> is specified, then the 3<sup>rd</sup>, 4<sup>th</sup>, 5<sup>th</sup>, and 6<sup>th</sup> parameters are interpreted as BRP, TSEG1, TSEG2, and SJW values.</p> <p>If none of the above bits is set, then the third argument is interpreted as a bits-per-second value.</p>
<code>OFD_SAMPLEPT</code>	Argument next to the nominal bitrate is the minimal sample point rate requested. If not specified, the driver uses its own default value. If specified, this value must be expressed in 1/10000th (that is, 8750 stands for 87,5 %)
<code>OFD_DBITRATE</code>	<p>The data bitrate is given in the next arguments:</p> <p>If <code>OFD_BTR0BTR1</code> is set too, then the next parameter is interpreted as a 16-bit value respecting the BTR0BTR1 SJA1000 format.</p> <p>If <code>OFD_BRPTSEGSJW</code> is specified, then the 4 next parameters are interpreted as BRP, TSEG1, TSEG2 and SJW values.</p> <p>If none of the above bits is set, then the next argument is interpreted as a bits-per-second value.</p>
<code>OFD_DSAMPLEPT</code>	Argument next to the data bitrate is the minimal sample point rate requested. If not specified, the driver uses its own default value. If specified, this value must be expressed in 1/10000th (that is, 8750 stands for 87,5 %)
<code>OFD_CLOCKHZ</code>	The clock frequency (in Hz) to select in the CAN controller is given in the next argument.
<code>OFD_NONBLOCKING</code>	The device node is opened in non-blocking mode.
<code>PCANFD_INIT_XXX</code>	All of these flags are used to initialize the CAN device, as if it was initialized using <code>"int pcanfd_set_init(int fd, struct pcanfd_init *pfdi);"</code> .

Table 14: Usage of the flags argument of `pcanfd_open()`

Example:

```
#include <libpcanfd.h>

int fd;

/* open the 1st CANFD channel of the PCAN-USB Pro FD and set 1Mbps+2Mbps bitrate */
fd = pcanfd_open("/dev/pcanusbprofd0",
                OFD_BITRATE|OFD_DBITRATE,
                1000000,
                2000000);
...
```

**int pcanfd\_is\_canfd\_capable(int fd);**

This function allows to know if an open device is able to work in CAN-FD or not. It returns 0 if the device is not a CAN-FD device.

**int pcan\_set\_extra\_params(int fd, struct pcan\_extra\_params \*pe);**

This function encapsulates an ioctl code that exists since CAN 2.0 API. It enables to set/get some extra parameters to/from the device through the driver, using the following C structure (see `pcan.h`):

```
#define PCAN_SF_DATA_MAXLEN      64          /* New since 8.14 */

typedef struct pcan_extra_params {
    int    nSubFunction;
    union {
        DWORD    dwSerialNumber;
        BYTE     ucHCDeviceNo;
        BYTE     ucDevData[PCAN_SF_DATA_MAXLEN];    /* New since 8.14 */
    } func;
} TPEXTRAPARAMS;

...
```

CAN 2.0 API defines these two sub functions to set/get specific parameters:

nSubFunction	func	Description
SF_GET_SERIALNUMBER	dwSerialNumber	Get serial number from the device (is possible).
SF_GET_HCDEVICENO	ucHCDeviceNo	Get the user defined device number from the device flash memory.
SF_SET_HCDEVICENO		Set a user defined device number value into the device flash memory.

With pcan v8.14, CAN-FD API has extended this usage by including the "ucDevData" 64 bytes array field to be able to exchange more than simple 32 bit data objects:

nSubFunction	func	Description
SF_GET_FWVERSION	dwSerialNumber	Get firmware version of the device.
SF_GET_ADAPTERNAME	ucDevData	Get the commercial name of the PC CAN interface that control the device. The driver returns a null terminated string.
SF_GET_PARTNUM		Get the PC CAN interface part number. The driver returns a null terminated string.

```
int pcan_init(int fd, const struct pcan_init *pi);
```

```
int pcan_read_msg(int fd, struct pcan_rd_msg *prdm);
```

```
int pcan_write_msg(int fd, const struct pcan_msg *pm);
```

```
int pcan_get_status(int fd, struct pcan_status *ps);
```

```
int pcan_get_ext_status(int fd, struct pcan_ext_status *ps);
```

```
int pcan_get_diag(int fd, struct pcan_diag *pd);
```

```
int pcan_get_btr0btr1(int fd, struct pcan_btr0btr1 *pb);
```

```
int pcan_set_msg_filter(int fd, const struct pcan_msg_filter *pf);
```

These functions are simple clones of the existing functions of the original API (see 5.1.1 CAN 2.0 API).

## 5.2 netdev Mode

The PCAN Driver for Linux is built in *netdev* mode, that is, with:

```
$ make -C driver NET=NETDEV_SUPPORT
```

or:

```
$ make -C driver netdev
```

In this case the user application can neither use the `libpcan` nor the `libpcanfd` library but has to be built over the socket API instead. The programmer can access the online documentation, starting, for example, at these links:

- └─ <https://en.wikipedia.org/wiki/SocketCAN>
- └─ <https://www.kernel.org/doc/Documentation/networking/can.txt>