

# ACAN2517FD Arduino library

## For the MCP2517FD and MCP2518FD

### CANFD Controllers in CANFD mode

# Version 2.1.5

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## 1 Versions

Version	Date	Comment
2.1.5	January 27, 2021	Fixed retransmission attempts setting bug. Added <code>NoRetransmissionAttemptsDemoTeensy3x.ino</code> sketch.
2.1.4	January 14, 2021	Improved method to read also the <code>BDIAGO_REGISTER</code> diagnostic register (thanks to turmary), see <a href="#">section 21.4 page 55</a> . Fix: <code>mHardwareTxFIFOFull = true</code> will block the transmitter if call <code>begin()</code> multiple times without constructor (thanks to turmary).
2.1.3	October 3, 2020	Add method to read the diagnostic registers (thanks to F101e998), see <a href="#">section 21.4 page 55</a> .
2.1.2	May 31, 2020	Fix retransmission attempts settings (thanks to F101e998)
2.1.1	April 27, 2020	Added <code>dataFloat</code> to <code>CANMessage</code> and <code>CANFDMessage</code> (thanks to Koryphon)
2.1.0	December 31, 2019	For compatibility with <code>ACAN_T4</code> , the <code>DataBitRateFactor</code> enumeration is declared outside of the <code>ACAN2517FDSettings</code> class. Fix commented out line (thank to F101e998).
2.0.1	October 28, 2019	Fix incorrect usage of <code>digitalPinToInterrupt</code> (thank to F101e998).
2.0.0	September 15, 2019	Fixed several bugs. Added <code>ACAN2517FD::currentOperationMode</code> method, see <a href="#">section 21.1 page 54</a> . Added <code>ACAN2517FD::recoverFromRestrictedOperationMode</code> method, see <a href="#">section 21.2 page 54</a> . Added <code>ACAN2517FD::errorCounters</code> method, see <a href="#">section 21.3 page 55</a> . Added description of <code>sendfd-odd</code> and <code>sendfd-even</code> sketches, see <a href="#">section 22 page 55</a> . Added <a href="#">section MCP2517FD or MCP2518FD? page 7</a> .
1.1.6	June 6, 2019	Running <code>pinMode (mINT, INPUT_PULLUP)</code> only if <code>mInt</code> pin is used (thanks to Tyler Lewis).
1.1.5	June 2, 2019	Fixed a race condition on ESP32 (thanks to Nick Kirkby).
1.1.4	March 21, 2019	Fixed dual bit rate bug (thanks to danielhenz). Fixed TxQ enable bug (thanks to danielhenz). Added setting of <i>Enable Edge Filtering during Bus Integration state bit</i> , for reaching the 8 Mbit/s bit data rate. Updated <code>LoopBackIntensiveTestTeensy3x</code> sample code.
1.1.3	February 8, 2019	Compatibility for Arduino Uno. Added demo sketch <code>LoopBackDemoArduinoUno</code> . Renamed <code>ACANBuffer</code> to <code>ACANFDBuffer</code> .
1.1.2	February 3, 2019	Added setting <code>mINTIsOpenDrain</code> ( <a href="#">section 20.11.2 page 52</a> ). Remove useless mutex (ESP32).

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1.1.1	January 31, 2019	First release running on ESP32 ( <a href="#">section 8.4 page 21</a> ). New option: no interrupt pin ( <a href="#">section 8.5 page 22</a> ).
1.0.4	January 14, 2019	Fixed mask and acceptance filters for extended messages. New <code>LoopBackDemoTeensy3xStandardFilterTest.ino</code> sample code for checking base reception filters. New <code>LoopBackDemoTeensy3xExtendedFilterTest.ino</code> sample code for checking extended reception filters.
1.0.3	January 6, 2019	Corrected identifiers for extended messages.
1.0.2	November 2, 2018	added <code>MISO_CRC_ENABLED</code> setting
1.0.1	October 29, 2018	Conformity with Arduino library
1.0.0	October 28, 2018	Initial release

## 2 Features

The `ACAN2517FD` library is a `MCP2517FD` and `MCP2518FD` CANFD (*Controller Area Network with Flexible Data*) Controller driver for any board running Arduino. It handles CANFD frames.

This library is compatible with:

- the ACAN 1.0.6 and above library (<https://github.com/pierremolinaro/acan>), CAN driver for FlexCan module embedded in Teensy 3.1 / 3.2, 3.5, 3.6 microcontrollers;
- the ACAN2515 1.0.1 and above library (<https://github.com/pierremolinaro/acan2515>), CAN driver for `MCP2515` CAN controller;
- the ACAN2517 library (<https://github.com/pierremolinaro/acan2517>), CAN driver for `MCP2517FD` CAN controller, in CAN 2.0B mode.

It has been designed to make it easy to start and to be easily configurable:

- default configuration sends and receives any frame – no default filter to provide;
- ISO CRC enabled by default;
- efficient built-in CAN bit settings computation from arbitration and data bit rates;
- user can fully define its own CAN bit setting values;
- all 32 reception filter registers are easily defined;
- reception filters accept call back functions;
- driver and controller transmit buffer sizes are customisable;
- driver and controller receive buffer size is customisable;

- 
- overflow of the driver receive buffer is detectable;
  - MCP2517FD internal RAM allocation is customizable and the driver checks no overflow occurs;
  - *loop back, self reception, listing only* MCP2517FD controller modes are selectable.

### 3 MCP2517FD or MCP2518FD?

**In short: I recommend using a MCP2518FD. My opinion is that the MCP2517FD has hardware bugs.**

#### 3.1 Reset

An originality of the MCP2517FD is that it has no reset pin. Resetting the MCP2517FD can only be done by software, by sending a `RESET` command through the SPI. But sometimes, for reasons I don't know, the reset is not done correctly. We can see this because the value returned by the `ACAN2517FD::begin` function is not zero (see [section 19.3 page 39](#)). Some possible errors are `0x1` (`kRequestedConfigurationModeTimeout`, the MCP2517FD cannot reach the *configuration* mode), `0x40000` (`kReadBackErrorWithFullSpeedSPIClock`, the MCP2517FD RAM cannot be written and read back). Typically, this can happen when uploading and starting a new version of the firmware into the microcontroller. **So I recommend to always check the value returned by the `ACAN2517FD::begin` function is zero.** In such case, you should power off and the power on.

With a MCP2518FD, uploading and starting a new version of the firmware into the microcontroller always succeeds, but if the previous sketch has provided invalid clock setting, as enabling PLL with a 40MHz clock.

Note you should also add a pullup resistor on the `nCS` pin ([section 8.1 page 18](#)) with a MCP2517FD, I don't think this resistance is necessary with a MCP2518FD.

#### 3.2 Clock

**In short: I recommend using an external clock, as an integrated oscillator. Do not use a crystal oscillator.**

Using a crystal oscillator may be tricky: just take a look to section 3.1.1 page 13 of the DS20005678D document, that gives few guidelines for selecting the correct crystal oscillator or ceramic resonator. This section gives very precise references for crystal oscillator and associated capacitors. Note also an *Optional Feedback Resistor* has been added in the C revision of this document, and the section 3.1.1 has been updated in the C and D revisions.

**4MHz crystal oscillator.** I have tried a 4MHz crystal oscillator (`HC49US-FF3F18-4.0000`), with two 22pF capacitors, so the clock setting is `ACAN2517FDSettings::OSC_4MHz10xPLL`. I noticed that a MCP2517FD worked well for a data bit rate up to 1Mbps; above 1Mbps, the MCP2517FD often enters in *Restricted Operation Mode*, but maybe it's due to internal bugs (see [section 3.3 page 8](#)). A MCP2518FD works perfectly with this oscillator.

**40MHz crystal oscillator.** I have also tried a 40MHz crystal oscillator (`YIC-HC49US`), with the same two 22pF capacitors, and the `ACAN2517FD-Settings::OSC_40MHz` setting. Surprisingly, the observed frequency on

### 3.3 Restricted Operation Mode

---

the OSC2 pin was... 13.3MHz! Exactly one third of 40MHz. Probably the 22pF capacitors are not appropriate. The OSC2 pin signal, observed at the oscilloscope, had a very small amplitude: 300mV.

**Morality: if you choose a crystal oscillator, always observe the frequency obtained with an oscilloscope.**

**4MHz integrated oscillator.** I use a 4MHz integrated oscillator (LFSPX0024978BULK, the supply voltage of my MCP2517FD is 3.3V), connected to OSC1. OSC2 is left unconnected. The clock setting is `ACAN2517FDSettings::OSC_4MHz1`. I have observed with oscilloscope the OSC1 pin signal, it has the correct frequency, and the amplitude I expected: 3.3V.

Same behaviour as with the 4MHz crystal oscillator: buggy with a MCP2517FD above 1Mbps, success with a MCP2518FD.

**40MHz integrated oscillator.** I use a 40MHz integrated oscillator (LFSPX0026068BULK. The clock setting is `ACAN2517FDSettings::OSC_40MHz`. I have also observed with oscilloscope the OSC1 pin signal, it has the correct frequency, and the amplitude I expected: 3.3V.

Same behaviour as with the 4MHz integrated oscillator: buggy with a MCP2517FD above 1Mbps, success with a MCP2518FD.

### 3.3 Restricted Operation Mode

For testing transmission and reception, I use the `sendfd-odd` and `sendfd-even` sketches, that are provided as sample code in the library (see [section 22 page 55](#)). They are designed for a *Teensy 3.5*, but can easily be adapted for other platforms.

For data bit rates higher than 1Mbps with a MCP2517FD, I have noticed the error counters may have not zero values (error counters can be read by the `errorCounters` method, see [section 21.3 page 55](#)), and the MCP2517FD enters sometimes in *Restricted Operation Mode*. The modes operation is described in DS20005678D, figure 2.1 page 9. *Restricted Operation Mode* is reached from *Normal Modes* on *System Error*, as the driver lets the `SERR2LOM` bit equal to 0.

*System Error* is described in section 10.5.6, page 63. The MCP2517FD Data Sheet Errata (DS80000792B) gives an explanation: *The SPI Interface can block the CANFD Controller module from accessing RAM in between SPI bytes and between the last byte and the rising edge of the nCS line during an SPI READ or SPI READ CRC instruction while accessing RAM. If the CANFD Controller module is blocked for more than TSPIMAXDLY, a TX MAB underflow or an RX MAB overflow can occur.* Within the CANFD Control Field, TSPIMAXDLY is  $3 \text{ NBT} + 5 \text{ DBT}$ , that is for an 1Mbps arbitration bit rate and a data bit factor  $\times 8$  (8Mbps):  $3 \cdot 1\mu\text{s} + 5 \cdot 125\text{ns} = 3.625\mu\text{s}$ . The challenge is to write a driver that checks these constraints. This is not easy, as transfers are made through `transfer` and `transfer16` SPI Arduino routines, and their implementation may vary from one platform to another. In the ACAN2517FD code, I have masked interruptions during transfers to minimize the delay between bytes, and to ensure that the `nCS` signal becomes inactive (high) as quickly as possible at the end of the transfer.

You can check current MCP2517FD operation mode by calling the `ACAN2517FD::currentOperationMode` function ([section 21.1 page 54](#)). It returns 7 for the *Restricted Operation Mode*. You can recover from *Restricted Operation Mode* by calling the `ACAN2517FD::recoverFromRestrictedOperationMode` function ([section 21.2 page 54](#)); however, some send or receive data has been lost.

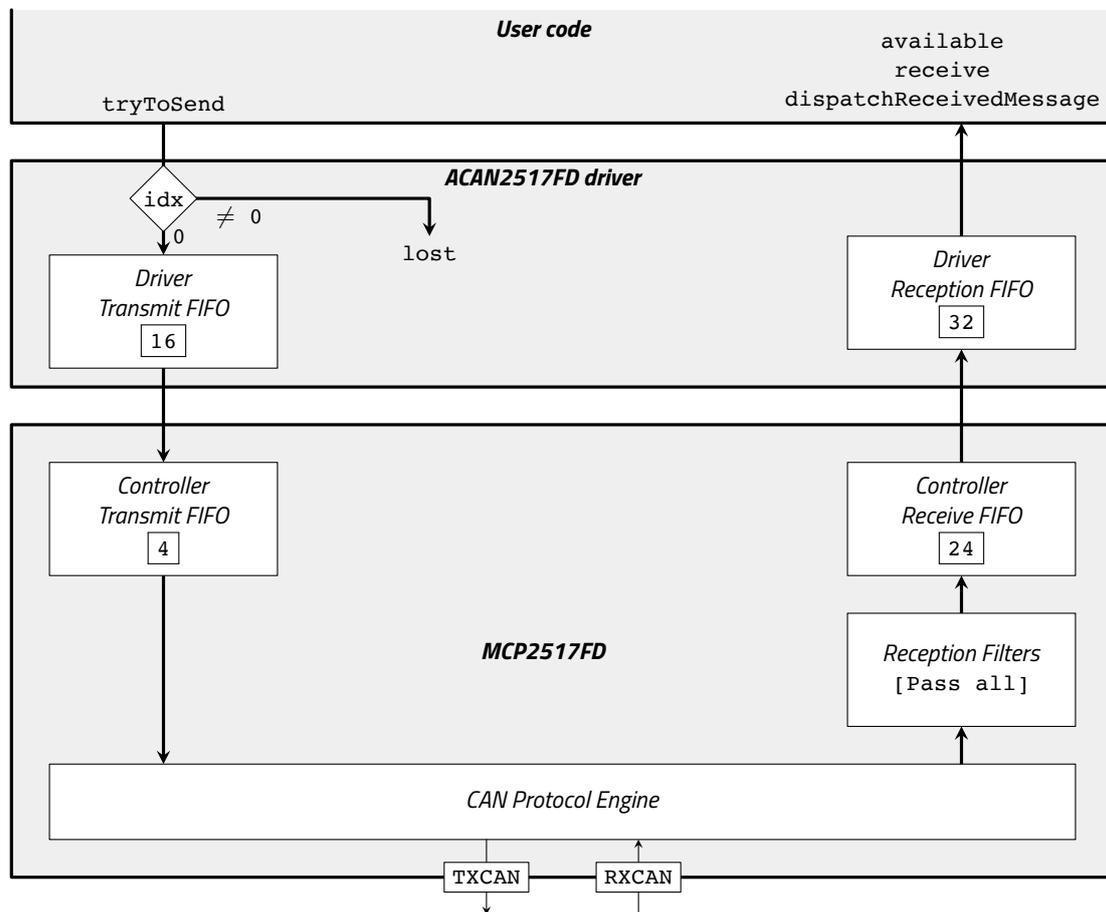
I have never observed that a MCP2518FD enters the Restricted Operation Mode.

## 4 Data flow

Two figures illustrate message flow for sending and receiving CANFD messages: [figure 1](#) is the default configuration, [figure 2](#) is the customized configuration.

### 4.1 Data flow in default configuration

The [figure 1](#) illustrates message flow in the default configuration.



**Figure 1** – Message flow in ACAN2517FD driver and MCP2517FD CAN Controller, default configuration

**Sending messages.** The ACAN2517FD driver defines a *driver transmit FIFO* (default size: 16 messages), and configures the MCP2517FD with a *controller transmit FIFO* with a size of 4 messages. MCP2517FD RAM has a capacity of 2048 bytes, that limits the sizes of the *controller transmit FIFO* and *controller receive FIFO*. See [section 14 page 28](#).

A message is defined by an instance of `CANFDMessage` class. For sending a message, user code calls the `tryToSend` method – see [section 15 page 29](#), and the `idx` property of the sent message should be equal to

## 4.2 Data flow, custom configuration

0 (default value).

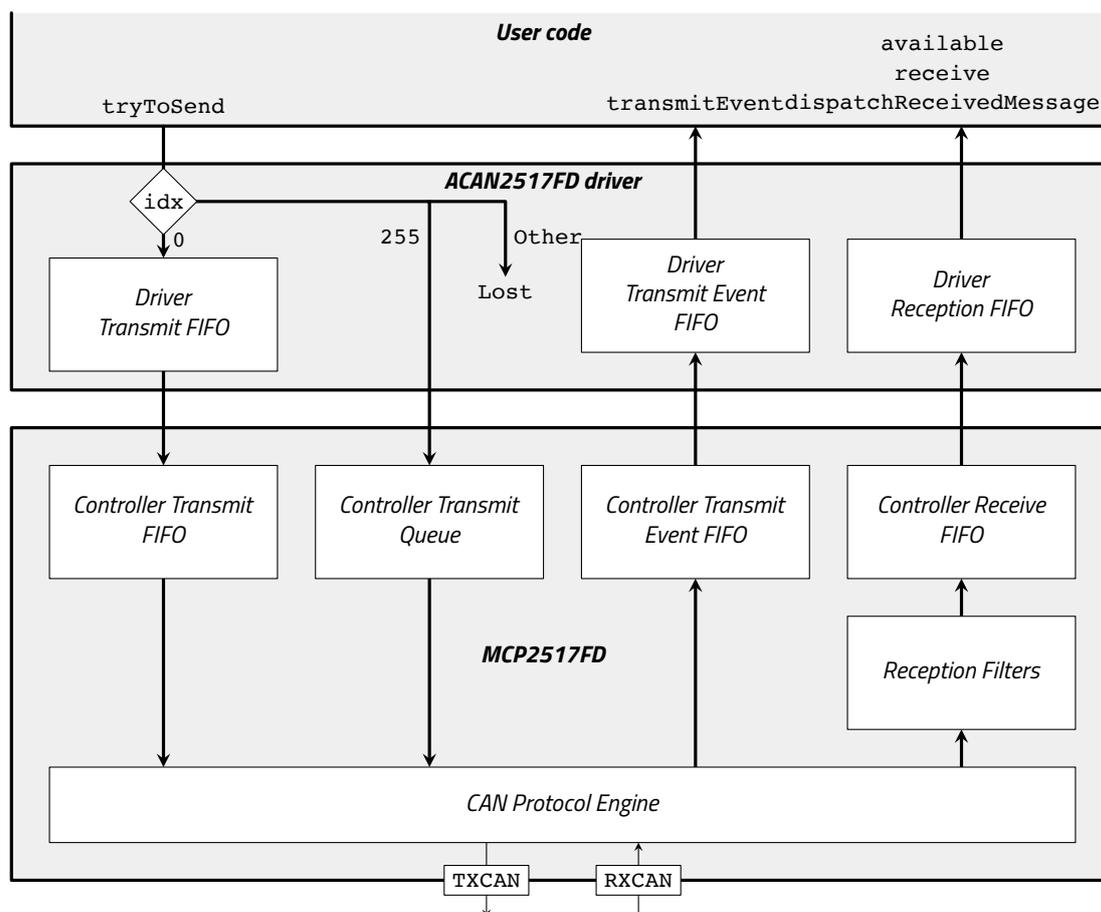
**Receiving messages.** The MCP2517FD *CAN Protocol Engine* transmits all correct frames to the *reception filters*. By default, they are configured as pass-all, see [section 17 page 34](#) for configuring them. Messages that pass the filters are stored in the *Controller Reception FIFO*; its size is 24 message by default. The interrupt service routine transfers the messages from this FIFO to the *Driver Reception FIFO*. The size of the *Driver Receive Buffer* is 32 by default – see [section 16.1 page 33](#) for changing the default value. Three user methods are available:

- the `available` method returns `false` if the *Driver Receive Buffer* is empty, and `true` otherwise;
- the `receive` method retrieves messages from the *Driver Receive Buffer* – see [section 16 page 32](#);
- the `dispatchReceivedMessage` method if you have defined the reception filters that name a call-back function – see [section 18 page 37](#).

## 4.2 Data flow, custom configuration

The [figure 2](#) illustrates message flow in a custom configuration.

**Note.** The *transmit Event FIFO* and the `transmitEvent` function are not currently implemented.



**Figure 2** – Message flow in ACAN2517FD driver and MCP2517FD CAN Controller, custom configuration

---

You can allocate the *Controller transmit Queue*: send order is defined by frame priority (see [section 11 page 26](#)). You can also define up to 32 receive filters (see [section 17 page 34](#)). Sizes of MCP2517FD internal buffer are easily customizable.

## 5 A simple example: LoopBackDemo

The following code is a sample code for introducing the ACAN2517FD library, extracted from the LoopBackDemo sample code included in the library distribution. It runs natively on any Arduino compatible board, and is easily adaptable to any microcontroller supporting SPI. It demonstrates how to configure the driver, to send a CAN message, and to receive a CAN message.

Note: this code runs without any CAN transceiver (the TXCAN and RXCAN pins of the MCP2517FD are left open), the MCP2517FD is configured in the *loop back* mode.

```
#include <ACAN2517FD.h>
```

This line includes the ACAN2517FD library.

```
static const byte MCP2517_CS = 20 ; // CS input of MCP2517FD
static const byte MCP2517_INT = 37 ; // INT output of MCP2517FD
```

Define the pins connected to  $\overline{CS}$  and  $\overline{INT}$  pins (adapt to your design).

```
ACAN2517FD can (MCP2517_CS, SPI, MCP2517_INT) ;
```

Instanciation of the ACAN2517FD library, declaration and initialization of the `can` object that implements the driver. The constructor names: the number of the pin connected to the  $\overline{CS}$  pin, the SPI object (you can use SPI1, SPI2, ...), the number of the pin connected to the  $\overline{INT}$  pin.

```
void setup () {
  //--- Switch on builtin led
  pinMode (LED_BUILTIN, OUTPUT) ;
  digitalWrite (LED_BUILTIN, HIGH) ;
  //--- Start serial
  Serial.begin (38400) ;
  //--- Wait for serial (blink led at 10 Hz during waiting)
  while (!Serial) {
    delay (50) ;
    digitalWrite (LED_BUILTIN, !digitalRead (LED_BUILTIN)) ;
  }
}
```

Builtin led is used for signaling. It blinks led at 10 Hz during until serial monitor is ready.

```
SPI.begin () ;
```

You should call `SPI.begin`. Many platforms define alternate pins for SPI. On Teensy 3.x ([section 8.2 page 18](#)), selecting alternate pins should be done before calling `SPI.begin`, on Adafruit Feather M0 ([section 8.3 page 20](#)), this should be done after. Calling `SPI.begin` explicitly allows you to fully handle alternate pins.

---

```
ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL,  
                             125UL * 1000UL, DataBitRateFactor::DATA_BITRATE_x4) ;
```

Configuration is a four-step operation. This line is the first step. It instantiates the `settings` object of the `ACAN2517FDSettings` class. The constructor has three parameters: the `MCP2517FD` oscillator specification, the desired CAN arbitration bit rate (here, 125 kb/s), and the data bit rate, given by a multiplicative factor of the arbitration bit rate; here, the data bit rate is 125 kb/s \* 4 = 500 kbit/s. It returns a `settings` object fully initialized with CAN bit settings for the desired arbitration and data bit rates, and default values for other configuration properties.

**Note.** For releases before 2.1.0, the data bit rate enumerated type was declared within the `ACAN2517FDSettings` class, so the declaration was `ACAN2517FDSettings::DATA_BITRATE_x4`. In release 2.1.0 and above, the `DataBitRateFactor` enumerated type is declared outside any class, enabling its compatibility with other CANFD libraries, as `ACAN_T4`.

```
settings.mRequestedMode = ACAN2517FDSettings::InternalLoopBack ;
```

This is the second step. You can override the values of the properties of `settings` object. Here, the `mRequestedMode` property is set to `InternalLoopBack` – its value is `NormalFD` by default. Setting this property enables *loop back*, that is you can run this demo sketch even if you have no connection to a physical CAN network. The [section 20.11 page 51](#) lists all properties you can override.

```
const uint32_t errorCode = can.begin (settings, [] { can.isr () ; }) ;
```

This is the third step, configuration of the `can` driver with `settings` values. The driver is configured for being able to send any (base / extended, data / remote, CAN / CANFD) frame, and to receive all (base / extended, data / remote, CAN / CANFD) frames. If you want to define reception filters, see [section 17 page 34](#). The second argument is the *interrupt service routine*, and is defined by a C++ lambda expression<sup>1</sup>. See [section 19.2 page 38](#) for using a function instead.

```
if (errorCode != 0) {  
    Serial.print ("Configuration error 0x") ;  
    Serial.println (errorCode, HEX) ;  
}  
}
```

Last step: the configuration of the `can` driver returns an error code, stored in the `errorCode` constant. It has the value 0 if all is ok – see [section 19.3 page 39](#).

```
static uint32_t gBlinkLedDate = 0 ;  
static uint32_t gReceivedFrameCount = 0 ;  
static uint32_t gSentFrameCount = 0 ;
```

The `gSendDate` global variable is used for sending a CAN message every 2 s. The `gSentCount` global variable counts the number of sent messages. The `gReceivedCount` global variable counts the number of received messages.

```
void loop() {  
    CANFDMessage frame ;
```

---

<sup>1</sup><https://en.cppreference.com/w/cpp/language/lambda>

---

The message object is fully initialized by the default constructor, it represents a base data frame, with an identifier equal to 0, and without any data – see [section 6 page 13](#).

```
if (gBlinkLedDate < millis ()) {
    gBlinkLedDate += 2000 ;
    digitalWrite (LED_BUILTIN, !digitalRead (LED_BUILTIN)) ;
    const bool ok = can.tryToSend (frame) ;
    if (ok) {
        gSentFrameCount += 1 ;
        Serial.print ("Sent: ") ;
        Serial.println (gSentFrameCount) ;
    }else{
        Serial.println ("Send failure") ;
    }
}
```

We try to send the data message. Actually, we try to transfer it into the *Driver transmit buffer*. The transfer succeeds if the buffer is not full. The `tryToSend` method returns `false` if the buffer is full, and `true` otherwise. Note the returned value only tells if the transfer into the *Driver transmit buffer* is successful or not: we have no way to know if the frame is actually sent on the the CAN network. Then, we act the successful transfer by setting `gSendDate` to the next send date and incrementing the `gSentCount` variable. Note if the transfer did fail, the send date is not changed, so the `tryToSend` method will be called on the execution of the `loop` function.

```
if (can.available ()) {
    can.receive (frame) ;
    gReceivedFrameCount ++ ;
    Serial.print ("Received: ") ;
    Serial.println (gReceivedFrameCount) ;
}
}
```

As the MCP2517FD controller is configured in *loop back* mode, all sent messages are received. The `receive` method returns `false` if no message is available from the *driver reception buffer*. It returns `true` if a message has been successfully removed from the *driver reception buffer*. This message is assigned to the message object. If a message has been received, the `gReceivedCount` is incremented and displayed.

## 6 The CANFDMessage class

**Note.** The `CANFDMessage` class did change in release 2.0.0: the `rtx` property has been removed, the `type` property has been added.

**Note.** The `CANFDMessage` class is declared in the `CANFDMessage.h` header file. The class declaration is protected by an include guard that causes the macro `GENERIC_CANFD_MESSAGE_DEFINED` to be defined. This allows an other library to freely include this file without any declaration conflict.

A CANFD message is an object that contains all CANFD frame user informations.

## 6.1 Properties

---

**Example:** The message object describes an extended frame, with identifier equal to 0x123, that contains 12 bytes of data:

```
CANFDMessage message ; // message is fully initialized with default values
message.id = 0x123 ; // Set the message identifier (it is 0 by default)
message.ext = true ; // message is an extended one (it is a base one by default)
message.len = 12 ; // message contains 12 bytes (0 by default)
message.data [0] = 0x12 ; // First data byte is 0x12
...
message.data [11] = 0xCD ; // 11th data byte is 0xCD
```

## 6.1 Properties

```
class CANFDMessage {
    ...
    public : uint32_t id; // Frame identifier
    public : bool ext ; // false -> base frame, true -> extended frame
    public : Type type ;
    public : uint8_t idx ; // Used by the driver
    public : uint8_t len ; // Length of data (0 ... 64)
    public : union {
        uint64_t data64 [ 8] ; // Caution: subject to endianness
        uint32_t data32 [16] ; // Caution: subject to endianness
        uint16_t data16 [32] ; // Caution: subject to endianness
        float dataFloat [16] ; // Caution: subject to endianness
        uint8_t data [64] ;
    } ;
    ...
} ;
```

Note the message datas are defined by an **union**. So message datas can be seen as 64 bytes, 32 x 16-bit unsigned integers, 16 x 32-bit, 8 x 64-bit or 16 x 32-bit floats. Be aware that multi-byte integers are subject to endianness (Cortex M4 processors of Teensy 3.x are little-endian).

## 6.2 The default constructor

All properties are initialized by default, and represent a base data frame, with an identifier equal to 0, and without any data ([table 2](#)).

## 6.3 Constructor from CANMessage

```
class CANFDMessage {
    ...
    CANFDMessage (const CANMessage & inCANMessage) ;
    ...
}
```

## 6.4 The type property

Property	Initial value	Comment
id	0	
ext	false	Base frame
type	CANFD_WITH_BIT_RATE_SWITCH	CANFD frame, with bit rate switch
idx	0	
len	0	No data
data	-	<i>unitialized</i>

**Table 2** – CANFDMessage default constructor initialization

```
} ;
```

All properties are initialized from the `inCANMessage` (table 3). Note that only `data64[0]` is initialized from `inCANMessage.data64`.

Property	Initial value
id	<code>inCANMessage.id</code>
ext	<code>inCANMessage.ext</code>
type	<code>inCANMessage.rtr ? CAN_REMOTE : CAN_DATA</code>
idx	<code>inCANMessage.idx</code>
len	<code>inCANMessage.len</code>
data64[0]	<code>inCANMessage.data64</code>

**Table 3** – CANFDMessage constructor CANMessage

## 6.4 The type property

The type property has been added in release 2.0.0. Its value is an instance of an enumerated type:

```
class CANFDMessage {
  ...
  public: typedef enum : uint8_t {
    CAN_REMOTE,
    CAN_DATA,
    CANFD_NO_BIT_RATE_SWITCH,
    CANFD_WITH_BIT_RATE_SWITCH
  } Type ;
  ...
} ;
```

The type property specifies the frame format, as indicated in the table 4.

## 6.5 The len property

Note that `len` property contains the actual length, not its encoding in CANFD frames. So valid values are: 0, 1, ..., 8, 12, 16, 20, 24, 32, 48, 64. Having other values is an error that prevents frame to be sent by the

## 6.6 The idx property

---

type property	Meaning	Constraint on len
CAN_REMOTE	CAN 2.0B remote frame	0 ... 8
CAN_DATA	CAN 2.0B data frame	0 ... 8
CANFD_NO_BIT_RATE_SWITCH	CANFD frame, no bit rate switch	0 ... 8, 12, 16, 20, 24, 32, 48, 64
CANFD_WITH_BIT_RATE_SWITCH	CANFD frame, bit rate switch	0 ... 8, 12, 16, 20, 24, 32, 48, 64

**Table 4** – CANFDMessage type property

ACAN2517FD::tryToSend method. You can use the pad method (see [section 6.7 page 16](#)) for padding with 0x00 bytes to the next valid length.

## 6.6 The idx property

The idx property is not used in CANFD frames, but:

- for a received message, it contains the acceptance filter index (see [section 18 page 37](#));
- on sending messages, it is used for selecting the transmit buffer (see [section 15 page 29](#)).

## 6.7 The pad method

```
void CANFDMessage::pad (void) ;
```

The CANFDMessage::pad method appends zero bytes to datas for reaching the next valid length. Valid lengths are: 0, 1, ..., 8, 12, 16, 20, 24, 32, 48, 64. If the length is already valid, no padding is performed. For example:

```
CANFDMessage frame ;  
frame.length = 21 ; // Not a valid value for sending  
frame.pad ( ) ;  
// frame.length is 24, frame.data [21] is 0, frame.data [22] is 0, frame.data [23] is 0
```

## 6.8 The isValid method

```
bool CANFDMessage::isValid (void) const ;
```

Not all settings of CANFDMessage instances represent a valid frame. For example, there is no CANFD remote frame, so a remote frame should have its length lower than or equal to 8. There is no constraint on extended / base identifier (ext property).

The isValid returns true if the constraints on the len property are checked, as indicated the [table 4 page 16](#), and false otherwise.

---

## 7 The CANMessage class

**Note.** The `CANMessage` class is declared in the `CANMessage.h` header file. The class declaration is protected by an include guard that causes the macro `GENERIC_CAN_MESSAGE_DEFINED` to be defined. The `ACAN`<sup>2</sup> (version 1.0.3 and above) driver, the `ACAN2515`<sup>3</sup> driver and the `ACAN2517`<sup>4</sup> driver contain an identical `CANMessage.h` file header, enabling using `ACAN` driver, `ACAN2515` driver, `ACAN2517` driver and `ACAN2517FD` driver in a same sketch.

A *CAN message* is an object that contains all CAN 2.0B frame user informations. All properties are initialized by default, and represent a base data frame, with an identifier equal to 0, and without any data. In the `ACAN2517FD` library, the `CANMessage` class is only used by a `CANFDMessage` constructor (section 6.3 page 14).

```
class CANMessage {
    public : uint32_t id = 0 ; // Frame identifier
    public : bool ext = false ; // false -> standard frame, true -> extended frame
    public : bool rtr = false ; // false -> data frame, true -> remote frame
    public : uint8_t idx = 0 ; // Used by the ACAN driver
    public : uint8_t len = 0 ; // Length of data (0 ... 8)
    public : union {
        uint64_t data64 ; // Caution: subject to endianness
        uint32_t data32 [2] ; // Caution: subject to endianness
        uint16_t data16 [4] ; // Caution: subject to endianness
        float dataFloat [2] ; // Caution: subject to endianness
        uint8_t data [8] = {0, 0, 0, 0, 0, 0, 0, 0} ;
    } ;
};
```

Note the message datas are defined by an **union**. So message datas can be seen as height bytes, four 16-bit unsigned integers, two 32-bit, one 64-bit or two 32-bit floats. Be aware that multi-byte integers and floats are subject to endianness (Cortex M4 processors of Teensy 3.x are little-endian).

The `idx` property is not used in CAN frames, but:

- for a received message, it contains the acceptance filter index (see section 18 page 37);
- on sending messages, it is used for selecting the transmit buffer (see section 15 page 29).

## 8 Connecting a MCP2517FD to your microcontroller

Connecting a `MCP2517FD` requires 5 pins (figure 3):

---

<sup>2</sup>The `ACAN` driver is a CAN driver for FlexCAN modules integrated in the Teensy 3.x microcontrollers, <https://github.com/pierremolinaro/acan>.

<sup>3</sup>The `ACAN2515` driver is a CAN driver for the `MCP2515` CAN controller, <https://github.com/pierremolinaro/acan2515>.

<sup>4</sup>The `ACAN2517` driver is a CAN driver for the `MCP2517FD` CAN controller in CAN 2.0B mode, <https://github.com/pierremolinaro/acan2517>.

## 8.1 Pullup resistor on nCS pin

- hardware SPI requires you use dedicated pins of your microcontroller. You can use alternate pins (see below), and if your microcontroller supports several hardware SPIs, you can select any of them;
- connecting the  $\overline{\text{CS}}$  signal requires one digital pin, that the driver configures as an `OUTPUT` ;
- connecting the  $\overline{\text{INT}}$  signal requires one other digital pin, that the driver configures as an external interrupt input; so this pin should have interrupt capability (checked by the `begin` method of the driver object);
- the  $\overline{\text{INT0}}$  and  $\overline{\text{INT1}}$  signals are not used by driver and are left not connected.

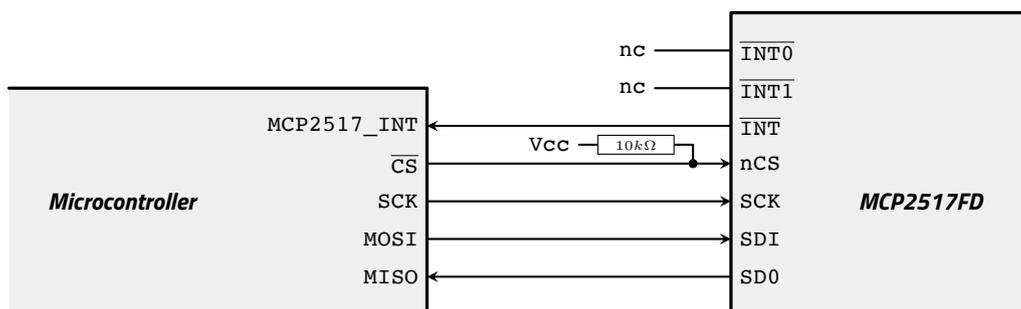


Figure 3 – MCP2517FD connection to a microcontroller

## 8.1 Pullup resistor on nCS pin

Note the  $10\text{ k}\Omega$  resistor between `nCS` and `VCC`. I have experienced that this resistor is useful in the following case: a sketch using the `MCP2517FD` is running, and I upload a new sketch. During this process, the microcontroller is reset, leaving its  $\overline{\text{CS}}$  pin floating. Without the  $10\text{ k}\Omega$  resistor, the `nCS` level is unpredictable, and if it becomes low, initiates transactions. I think this can crash the `MCP2517FD` firmware, and the following reset command sent by the driver not handled. With the resistor, the `nCS` level remains high until the driver sets the `nCS` as output.

However, I noticed that the `MCP2518FD` reset properly even without any pullup resistor.

## 8.2 Using alternate pins on Teensy 3.x

**Demo sketch:** `LoopBackDemoTeensy3x`.

On Teensy 3.x, "the main SPI pins are enabled by default. SPI pins can be moved to their alternate position with `SPI.setMOSI(pin)`, `SPI.setMISO(pin)`, and `SPI.setSCK(pin)`. You can move all of them, or just the ones that conflict, as you prefer."<sup>5</sup>

For example, the `LoopBackDemoTeensy3x` sketch uses `SPI1` on a Teensy 3.5 with these alternate pins<sup>6</sup>:

You call the `SPI1.setMOSI`, `SPI1.setMISO`, and `SPI1.setSCK` functions **before** calling the `begin` function of your `ACAN2517FD` instance:

<sup>5</sup>See [https://www.pjrc.com/teensy/td\\_libs\\_SPI.html](https://www.pjrc.com/teensy/td_libs_SPI.html)

<sup>6</sup>See <https://www.pjrc.com/teensy/pinout.html>

## 8.2 Using alternate pins on Teensy 3.x

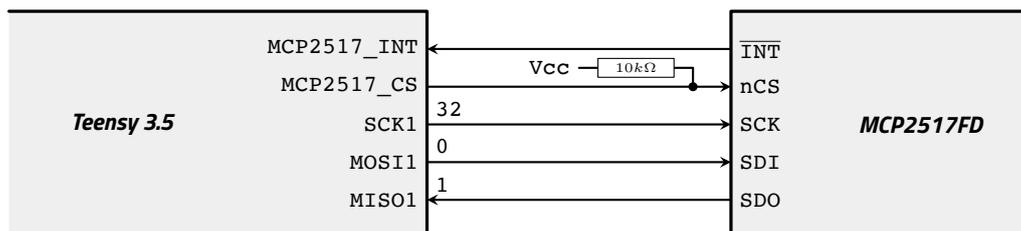


Figure 4 – Using SPI alternate pins on a Teensy 3.5

```

ACAN2517FD can (MCP2517_CS, SPI1, MCP2517_INT) ;
...
static const byte MCP2517_SCK = 32 ; // SCK input of MCP2517
static const byte MCP2517_SDI = 0 ; // SDI input of MCP2517
static const byte MCP2517_SDO = 1 ; // SDO output of MCP2517
...
void setup () {
    ...
    SPI1.setMOSI (MCP2517_SDI) ;
    SPI1.setMISO (MCP2517_SDO) ;
    SPI1.setSCK (MCP2517_SCK) ;
    SPI1.begin () ;
    ...
    const uint32_t errorCode = can.begin (settings, [] { can.isr () ; }) ;
    ...
}

```

Note you can use the `SPI1.pinIsMOSI`, `SPI1.pinIsMISO`, and `SPI1.pinIsSCK` functions to check if the alternate pins you select are valid:

```

void setup () {
    ...
    Serial.print ("Using pin #") ;
    Serial.print (MCP2517_SDI) ;
    Serial.print (" for MOSI: ") ;
    Serial.println (SPI1.pinIsMOSI (MCP2517_SDI) ? "yes" : "NO!!!") ;
    Serial.print ("Using pin #") ;
    Serial.print (MCP2517_SDO) ;
    Serial.print (" for MISO: ") ;
    Serial.println (SPI1.pinIsMISO (MCP2517_SDO) ? "yes" : "NO!!!") ;
    Serial.print ("Using pin #") ;
    Serial.print (MCP2517_SCK) ;
    Serial.print (" for SCK: ") ;
    Serial.println (SPI1.pinIsSCK (MCP2517_SCK) ? "yes" : "NO!!!") ;
    SPI1.setMOSI (MCP2517_SDI) ;
    SPI1.setMISO (MCP2517_SDO) ;
    SPI1.setSCK (MCP2517_SCK) ;
    SPI1.begin () ;
    ...
    const uint32_t errorCode = can.begin (settings, [] { can.isr () ; }) ;
}

```

...

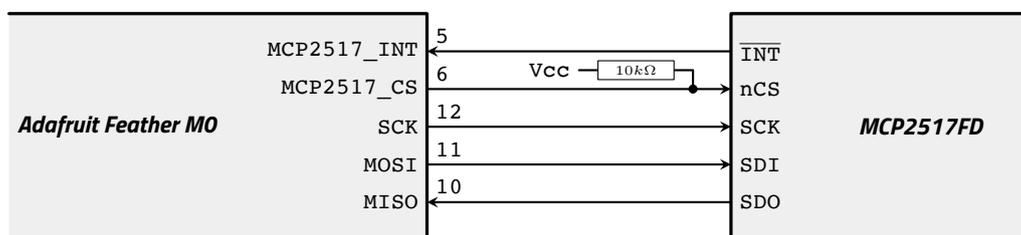
### 8.3 Using alternate pins on an Adafruit Feather M0

**Demo sketch:** LoopBackDemoAdafruitFeatherM0.

**Link:** <https://learn.adafruit.com/using-at-samd21-sercom-to-add-more-spi-i2c-serial-ports/overview>

This document explains in details how configure and set alternate SPI pins on Adafruit Feather M0.

For example, the LoopBackDemoAdafruitFeatherM0 sketch uses SERCOM1 on an Adafruit Feather M0 as illustrated in [figure 5](#).



**Figure 5** – Using SPI alternate pins on an Adafruit Feather M0

The configuration code is the following. Note you should call the `pinPeripheral` function **after** calling the `mySPI.begin` function.

```
#include <wiring_private.h>
...
static const byte MCP2517_SCK = 12 ; // SCK pin, SCK input of MCP2517FD
static const byte MCP2517_SDI = 11 ; // MOSI pin, SDI input of MCP2517FD
static const byte MCP2517_SDO = 10 ; // MISO pin, SDO output of MCP2517FD

SPIClass mySPI (&sercom1,
               MCP2517_SDO, MCP2517_SDI, MCP2517_SCK,
               SPI_PAD_0_SCK_3, SERCOM_RX_PAD_2);

static const byte MCP2517_CS = 6 ; // CS input of MCP2517FD
static const byte MCP2517_INT = 5 ; // INT output of MCP2517FD
...
ACAN2517FD can (MCP2517_CS, mySPI, MCP2517_INT) ;
...
void setup () {
  ...
  mySPI.begin () ;
  pinPeripheral (MCP2517_SDI, PIO_SERCOM);
  pinPeripheral (MCP2517_SCK, PIO_SERCOM);
  pinPeripheral (MCP2517_SDO, PIO_SERCOM);
  ...
}
```

## 8.4 Connecting to an ESP32

```
const uint32_t errorCode = can.begin (settings, [] { can.isr () ; }) ;  
...
```

### 8.4 Connecting to an ESP32

**Demo sketches:** LoopBackDemoESP32 and LoopBackESP32-intensive. See also the ESP32 demo sketch SPI\_Multiple\_Busses.

**Link:** <https://randomnerdtutorials.com/esp32-pinout-reference-gpios/>

Two ESP32 SPI busses are available in Arduino, `HSPI` and `VSPI`. By default, Arduino SPI is `VSPI`. The ESP32 default pins are given in [table 5](#).

Port	SCK	MOSI	MISO
VSPI	IO18	IO23	IO19
HSPI	IO14	IO13	IO12

**Table 5** – ESP32 SPI default pins

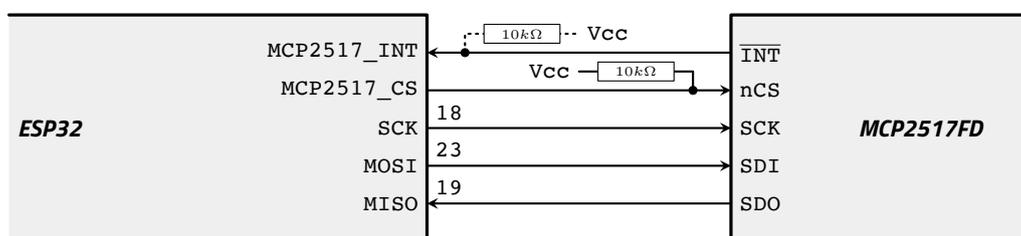
#### 8.4.1 Connecting MCP2517\_CS and MCP2517\_INT

For `MCP2517_CS`, you can use any port that can be configured as digital output. `ACAN2517FD` does not support hardware chip select. For `MCP2517_INT`, you can use any port that can be configured as digital input, as ESP32 provides interrupt capability on any input pin.

**Note.** `IO34` to `IO39` are input only pins, without internal pullup or pulldown. So you cannot use these pins for `MCP2517_CS`. If you use one of these pins for `MCP2517_INT`, you should add an external pullup resistor if you configure the `INT` pin as Open Drain ([section 20.11.2 page 52](#)).

#### 8.4.2 Using SPI

Default SPI (i.e. `VSPI`) pins are: `SCK=18`, `MISO=19`, `MOSI=23` ([figure 6](#)).



**Figure 6** – Using VSPI default pins on an ESP32

You can change the default pins with additional arguments (up to three) for `SPI.begin` :

```
SPI.begin (SCK_PIN) ; // Uses MISO and MOSI default pins
```

or

## 8.5 Connection with no interrupt pin

---

```
SPI.begin (SCK_PIN, MISO_PIN) ; // Uses MOSI default pin
```

or

```
SPI.begin (SCK_PIN, MISO_PIN, MOSI_PIN) ;
```

Note that `SPI.begin` accepts a fourth argument, for CS pin. Do not use this feature with `ACAN2517FD`.

### 8.4.3 Using HSPI

The ESP32 demo sketch `SPI_Multiple_Busses` shows how to use both `HSPI` and `VSPI`. However for `ACAN2517FD`, we proceed in a slightly different way:

```
#include <SPI.h>
....
SPIClass hspi (HSPI) ;
ACAN2517FD can (MCP2517_CS, hspi, MCP2517_INT) ;
....
void setup () {
  ....
  hspi.begin () ; // You can also add parameters for not using default pins
  ....
}
```

You declare the `hspi` object before declaring the `can` object. You can change the `hspi` name, the important point is the `HSPI` argument that specifies the HSPI bus. Then, instead of using the `SPI` name, you use the `hspi` name in:

- `can` object declaration;
- in `begin` SPI instruction.

See the `LoopBackESP32-intensive` sketch for an example with `VSPI`.

## 8.5 Connection with no interrupt pin

See the `LoopBackDemoTeensy3xNoInt` and `LoopBackDemoESP32NoInt` sketches.

**Note that not using an interruption is only valid if the message throughput is not too high. Received messages are recovered by polling, so the risk of MCP2517FD internal buffers overflowing is greater.**

For not using the interrupt signal, you should adapt your sketch as following:

1. the last argument of `can` constructor should be 255, meaning no interrupt pin;
2. the second argument of `can.begin` should be `NULL` (no interrupt service routine);
3. in the `loop` function, you should call `can.poll` as often as possible.

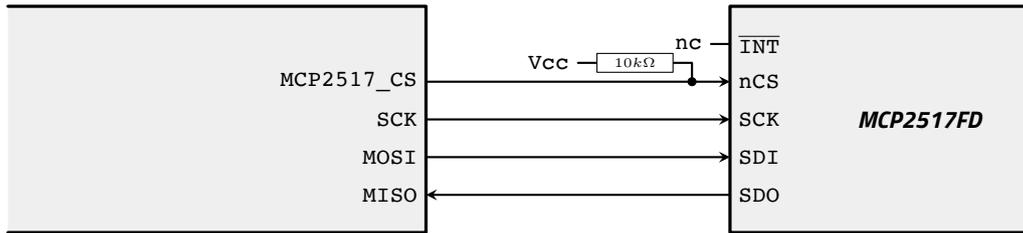


Figure 7 – Connection with no interrupt pin

```

ACAN2517FD can (MCP2517_CS, SPI, 255) ; // Last argument is 255 -> no interrupt pin

void setup () {
  ...
  const uint32_t errorCode = can.begin (settings, NULL) ; // ISR is null
  ...
}

void loop () {
  can.poll () ;
  ...
}

```

## 9 Clock configuration

The MCP251xFD Oscillator Block Diagram is given in figure 8. Microchip recommends using a 4, 40 or 20 MHz CLKIN, Crystal or Ceramic Resonator. A PLL can be enabled to multiply a 4 MHz clock by 10 by setting the PLLEN bit. Setting the SCLKDIV bit divides the SYSCLK by 2.<sup>7</sup> My opinion is that it is better to use an external clock (see section 3.2 page 7).

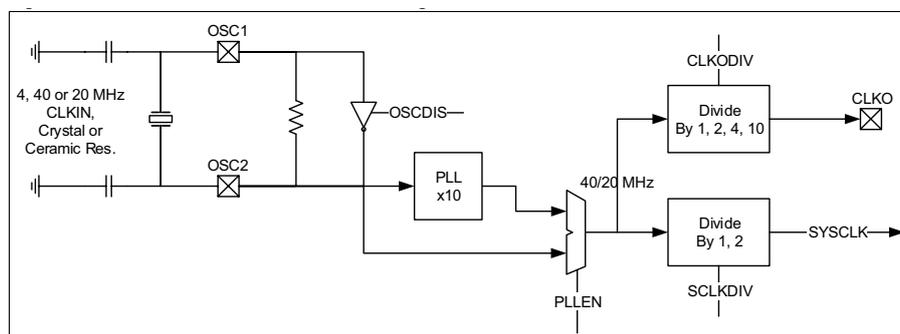


Figure 8 – MCP251xFD Oscillator Block Diagram (DS20005678B, figure 3.1 page 13)

The ACAN2517FDSettings class defines an enumerated type for specifying your settings:

```

class ACAN2517FDSettings {

```

<sup>7</sup>DS20005678B, page 13.

```

public: typedef enum {
    OSC_4MHz,
    OSC_4MHz_DIVIDED_BY_2,
    OSC_4MHz10xPLL,
    OSC_4MHz10xPLL_DIVIDED_BY_2,
    OSC_20MHz,
    OSC_20MHz_DIVIDED_BY_2,
    OSC_40MHz,
    OSC_40MHz_DIVIDED_BY_2
} Oscillator ;

...
} ;

```

The first argument of the `ACAN2517FDSettings` constructor specifies the oscillator. For example, with a 4 MHz clock, the `ACAN2517FDSettings::OSC_4MHz10xPLL` setting leads to a 40 MHz `SYSCLK`.

The eight clock settings are given in the [table 6](#). Note Microchip recommends a 40 MHz or 20 MHz `SYSCLK`. The `ACAN2517FDSettings` class has two accessors that return current settings: `oscillator()` and `sysClock()`.

Oscillator Frequency	Oscillator parameter	SYSCLK
4 MHz	<code>OSC_4MHz</code>	4 MHz
4 MHz	<code>OSC_4MHz_DIVIDE_BY_2</code>	2 MHz
4 MHz	<code>OSC_4MHz10xPLL</code>	40 MHz
4 MHz	<code>OSC_4MHz10xPLL_DIVIDE_BY_2</code>	20 MHz
20 MHz	<code>OSC_20MHz</code>	20 MHz
20 MHz	<code>OSC_20MHz_DIVIDE_BY_2</code>	10 MHz
40 MHz	<code>OSC_40MHz</code>	40 MHz
40 MHz	<code>OSC_40MHz_DIVIDE_BY_2</code>	20 MHz

**Table 6** – The `ACAN2517FD` oscillator selection

The `begin` function of `ACAN2517FD` library first configures the selected SPI with a frequency of 1 Mbit/s, for resetting the `MCP2517FD` and programming the `PLEN` and `SCLKDIV` bits. Then SPI clock is set to a frequency equal to `SYSCLK / 2`, the maximum allowed frequency. More precisely, the SPI library of your microcontroller may adopt a lower frequency; for example, the maximum frequency of the Arduino Uno SPI is 8 Mbit/s.

Note that an incorrect setting may crash the `MCP2517FD` firmware (for example, enabling the PLL with a 20 MHz or 40 MHz oscillator). In such case, no SPI communication can then be established, and in particular, the `MCP2517FD` cannot be reset by software. As the `MCP2517FD` has no `RESET` pin, the only way is to power off and power on the `MCP2517FD`.

## 10 Transmit FIFO

The transmit FIFO (see [figure 1 page 9](#)) is composed by:

- the *driver transmit FIFO*, whose size is positive or zero (default 16); you can change the default size by setting the `mDriverTransmitFIFOSize` property of your settings object;

## 10.1 The `driverTransmitBufferSize` method

---

- the *controller transmit FIFO*, whose size is between 1 and 32 (default 32); you can change the default size by setting the `mControllerTransmitFIFOSize` property of your `settings` object.

Having a *driver transmit FIFO* of zero size is valid; in this case, the FIFO must be considered both empty and full.

For sending a message through the *Transmit FIFO*, call the `tryToSend` method with a message whose `idx` property is zero:

- if the *controller transmit FIFO* is not full, the message is appended to it, and `tryToSend` returns `true`;
- otherwise, if the *driver transmit FIFO* is not full, the message is appended to it, and `tryToSend` returns `true`; the interrupt service routine will transfer messages from *driver transmit FIFO* to the *controller transmit FIFO* when it becomes not full;
- otherwise, both FIFOs are full, the message is not stored and `tryToSend` returns `false`.

The transmit FIFO ensures sequentiality of emissions.

There are three other parameters you can override:

- `settings.mControllerTransmitFIFOretransmissionAttempts` is the number of retransmission attempts; by default, it is set to `UnlimitedNumber`; other values are `Disabled` and `ThreeAttempts`;
- `settings.mControllerTransmitFIFOPriority` is the priority of the transmit FIFO: between 0 (lowest priority) and 31 (highest priority); default value is 0;
- `settings.mControllerTransmitFIFOPayload` is the controller transmit FIFO object payload size; default value is `PAYLOAD_64`, enabled sending any CANFD frame; see [section 13 page 27](#).

The *controller transmit FIFO* is located in the MCP2517FD RAM. It requires 16 bytes for each message (see [section 14 page 28](#)).

## 10.1 The `driverTransmitBufferSize` method

The `driverTransmitBufferSize` method returns the allocated size of this driver transmit buffer, that is the value of `settings.mDriverTransmitBufferSize` when the `begin` method is called.

```
const uint32_t s = can.driverTransmitBufferSize ();
```

## 10.2 The `driverTransmitBufferCount` method

The `driverTransmitBufferCount` method returns the current number of messages in the driver transmit buffer.

```
const uint32_t n = can.driverTransmitBufferCount ();
```

### 10.3 The driverTransmitBufferPeakCount method

The `driverTransmitBufferPeakCount` method returns the peak value of message count in the driver transmit buffer

```
const uint32_t max = can.driverTransmitBufferPeakCount ( ) ;
```

If the transmit buffer is full when `tryToSend` is called, the return value of this call is `false`. In such case, the following calls of `driverTransmitBufferPeakCount ( )` will return `driverTransmitBufferSize ( )+1`.

So, when `driverTransmitBufferPeakCount ( )` returns a value lower or equal to `transmitBufferSize ( )`, it means that calls to `tryToSend` have always returned `true`, and no overflow occurs on driver transmit buffer.

## 11 Transmit Queue (TXQ)

The *Transmit Queue* is handled by the `MCP2517FD`, its contents is located in its RAM. **It is not a FIFO.** Messages inside the TXQ will be transmitted based on their ID. The message with the highest priority ID, lowest ID value will be transmitted first<sup>8</sup>.

By default, the *transmit queue* is disabled (its default size is 0); you can change the default size by setting the `mControllerTXQSize` property of your `settings` object. The maximum valid size is 32.

For sending a message through the *transmit queue*, call the `tryToSend` method with a message whose `idx` property is 255:

- if the *transmit queue* size is not zero and if it is not full, the message is appended to it, and `tryToSend` returns `true`;
- otherwise, the message is not stored and `tryToSend` returns `false`.

There are three other parameters you can override:

- `inSettings.mControllerTXQBufferRetransmissionAttempts` is the number of retransmission attempts; by default, it is set to `UnlimitedNumber`; other values are `Disabled` and `ThreeAttempts`;
- `inSettings.mControllerTXQBufferPriority` is the priority of the TXQ buffer: between 0 (lowest priority) and 31 (highest priority); default value is 31;
- `inSettings.mControllerTXQBufferPayload` is the controller TXQ buffer object payload size; default value is `PAYLOAD_64`, enabled sending any CANFD frame; see [section 13 page 27](#).

The *transmit queue* is located in the `MCP2517FD` RAM. It requires 16 bytes for each message (see [section 14 page 28](#)).

---

<sup>8</sup>DS20005678B, section 4.5, page 28.

---

## 12 Receive FIFO

The receive FIFO (see [figure 1 page 9](#)) is composed by:

- the *driver receive FIFO*, whose size is positive (default 32); you can change the default size by setting the `mDriverReceiveFIFOSize` property of your settings object;
- the *controller receive FIFO*, whose size is between 1 and 32 (default 32); you can change the default size by setting the `mControllerReceiveFIFOSize` property of your settings object.

You can override the `mControllerReceiveFIFOPayload` value, which represents the controller receive FIFO object payload size; default value is `PAYLOAD_64`, enabled receiving any CANFD frame. See [section 13 page 27](#).

When an incoming message is accepted by a receive filter:

- if the *controller receive FIFO* is full, the message is lost;
- otherwise, it is stored in the *controller receive FIFO*.

Then, if the *driver receive FIFO* is not full, the message is transferred by the *interrupt service routine* from *controller receive FIFO* to the *driver receive FIFO*. So the *driver receive FIFO* never overflows, but *controller receive FIFO* may.

The `ACAN2517FD::available`, `ACAN2517FD::receive` and `ACAN2517FD::dispatchReceivedMessage` methods work only with the *driver receive FIFO*. As soon as it becomes not full, messages from *controller receive FIFO* are transferred by the *interrupt service routine*.

The receive FIFO ensures sequentiality of reception.

The *controller receive FIFO* is located in the `MCP2517FD` RAM. It requires 16 bytes for each message (see next section).

## 13 Payload size

Controller transmit FIFO, controller TXQ buffer and controller receive FIFO objects are stored in the internal `MCP2517FD` RAM. The size of each object depends on the setting applied to the corresponding FIFO or buffer.

By default, all FIFOs and buffer accept objects up to 64 data bytes. The size of each object is 72 bytes. As the internal `MCP2517FD` RAM has a capacity of 2048 bytes, only 28 objects are available, and they are allocated as follows:

- controller transmit FIFO (`mControllerTransmitFIFOSize` property): 4 objects;
- controller TXQ buffer (`mControllerTXQSize` property): no object;
- controller receive FIFO (`mControllerReceiveFIFOSize` property): 24 objects.

The details of RAM usage computation are presented in [section 14 page 28](#).

### 13.1 The `ACAN2517FDSettings::objectSizeForPayload` static method

Note the `ACAN2517` library<sup>9</sup> handles an `MCP2517FD` in CAN 2.0B mode. As CAN 2.0B frames contains at most 8 bytes, the size of each object is 16 bytes, allowing using up to 128 objects.

With the `mControllerTransmitFIFOPayload`, the `mControllerTXQBufferPayload` and the `mControllerReceiveFIFOPayload` properties, you can adjust the object size following your application requirements. The [table 7](#) shows the possible values of these properties and the corresponding payload and object size.

By example, suppose your application always send data frames with no more than 24 bytes. You can set the `mControllerTransmitFIFOPayload` and `mControllerReceiveFIFOPayload` properties to `ACAN2517FDSettings::PAYLOAD_24` leading to an object size equal to 32 bytes. If your application also receives data frames with no more than 24 bytes, you can also set the `mControllerReceiveFIFOPayload` property to `ACAN2517FDSettings::PAYLOAD_24`. All your objects require 32 bytes, allowing 64 objects in the `MCP2517FD` RAM. The benefit is you can now increase controller buffer sizes, for example:

- controller transmit FIFO (`mControllerTransmitFIFOSize` property): 16 objects;
- controller TXQ buffer (`mControllerTXQSize` property): 16 objects;
- controller receive FIFO (`mControllerReceiveFIFOSize` property): 32 objects.

Object Size specification	Payload	Object Size
<code>ACAN2517FDSettings::PAYLOAD_8</code>	Up to 8 bytes	16 bytes
<code>ACAN2517FDSettings::PAYLOAD_12</code>	Up to 12 bytes	20 bytes
<code>ACAN2517FDSettings::PAYLOAD_16</code>	Up to 16 bytes	24 bytes
<code>ACAN2517FDSettings::PAYLOAD_20</code>	Up to 20 bytes	28 bytes
<code>ACAN2517FDSettings::PAYLOAD_24</code>	Up to 24 bytes	32 bytes
<code>ACAN2517FDSettings::PAYLOAD_32</code>	Up to 32 bytes	40 bytes
<code>ACAN2517FDSettings::PAYLOAD_48</code>	Up to 48 bytes	56 bytes
<code>ACAN2517FDSettings::PAYLOAD_64</code>	Up to 64 bytes	72 bytes

**Table 7** – `ACAN2517FD` object size from payload size specification

### 13.1 The `ACAN2517FDSettings::objectSizeForPayload` static method

```
uint32_t ACAN2517FDSettings::objectSizeForPayload (const PayloadSize inPayload) ;
```

This static method returns the object size for a given payload specification, following [table 7](#).

## 14 RAM usage

The `MCP2517FD` contains a 2048 bytes RAM that is used to store message objects<sup>10</sup>. There are three different kinds of message objects:

- Transmit Message Objects used by the TXQ buffer;

<sup>9</sup><https://github.com/pierremolinaro/acan2517>

<sup>10</sup>DS20005688B, section 3.3, page 63.

- Transmit Message Objects used by the transmit FIFO;
- Receive Message Objects used by the receive FIFO.

There are six parameters that affect the required memory amount:

- the `mControllerTransmitFIFOSize` property sets the controller transmit FIFO object count;
- the `mControllerTransmitFIFOPayload` property defines the controller transmit FIFO object size;
- the `mControllerTXQSize` property sets the controller TXQ buffer object count;
- the `mControllerTXQBufferPayload` property defines the controller TXQ buffer object size;
- the `mControllerReceiveFIFOSize` property sets the controller receive FIFO object count;
- the `mControllerReceiveFIFOPayload` property defines the controller receive FIFO object size.

The `ACAN2517FDSettings::ramUsage` method computes the required memory amount as follows:

```
uint32_t ACAN2517FDSettings::ramUsage (void) const {
    uint32_t r = 0 ;
    //--- TXQ
    r += objectSizeForPayload(mControllerTXQBufferPayload) * mControllerTXQSize;
    //--- Receive FIFO (FIFO #1)
    r += objectSizeForPayload(mControllerReceiveFIFOPayload) * mControllerReceiveFIFOSize;
    //--- Send FIFO (FIFO #2)
    r += objectSizeForPayload(mControllerTransmitFIFOPayload) * mControllerTransmitFIFOSize;
    //---
    return r ;
}
```

The `ACAN2517FD::begin` method checks the required memory amount is lower or equal than 2048 bytes. Otherwise, it raises the error code `kControllerRamUsageGreaterThan2048`.

You can also use the *MCP2517FD RAM Usage Calculations* Excel sheet from Microchip<sup>11</sup>.

## 15 Sending frames: the `tryToSend` method

The `ACAN2517FD::tryToSend` method sends CAN 2.0B and CANFD frames:

```
bool ACAN2517FD::tryToSend (const CANFDMessage & inMessage) ;
```

You call the `tryToSend` method for sending a message in the CAN network. Note this function returns before the message is actually sent; this function only appends the message to a transmit buffer.

The `idx` property of the message specifies the transmit buffer:

<sup>11</sup><http://ww1.microchip.com/downloads/en/DeviceDoc/MCP2517FD%20RAM%20Usage%20Calculations%20-%20UG.xlsx>

## 15.1 Calling `tryToSend` with an `CANMessage` argument

---

- 0 for the transmit FIFO ([section 10 page 24](#));
- 255 for the transmit Queue ([section 11 page 26](#)).

The `type` property of `inMessage` specifies how the frame is sent:

- `CAN_REMOTE`, the frame is sent in the CAN 2.0B remote frame format;
- `CAN_DATA`, the frame is sent in the CAN 2.0B data frame format;
- `CANFD_NO_BIT_RATE_SWITCH`, the frame is sent in CANFD format at arbitration bit rate, regardless of the `ACAN2517FDSettings::DATA_BITRATE_xn` setting;
- `CANFD_WITH_BIT_RATE_SWITCH`, with the `ACAN2517FDSettings::DATA_BITRATE_x1` setting, the frame is sent in CANFD format at arbitration bit rate, and otherwise in CANFD format with bit rate switch.

```
...
CANFDMessage message ;
// Setup message
const bool ok = can.tryToSend (message) ;
...
```

The `tryToSend` method returns:

- `false` if the message responds `false` to the `isValid` method (see [section 6.8 page 16](#)), or if its `len` property has a value greater than the corresponding buffer payload; an invalid message is never submitted to a transmit buffer;
- otherwise, if the message responds `true` to the `isValid` method:
  - `true` if the message has been successfully transmitted to the transmit buffer; note that does not mean that the CAN frame has been actually sent;
  - `false` if the message has not been successfully transmitted to the transmit buffer, it was full.

So it is wise to systematically test the returned value.

### 15.1 Calling `tryToSend` with an `CANMessage` argument

The `CANFDMessage` class provides a constructor from a `CANMessage` object, so it is valid to call the `tryToSend` method with an `CANMessage` argument.

```
...
CANMessage message ;
// Setup message
const bool ok = can.tryToSend (message) ;
...
```

So, if the `message.rtr` is:

## 15.2 Usage example

---

- `true`, the frame is sent in the CAN 2.0B remote frame format;
- `false`, the frame is sent in the CAN 2.0B data frame format.

### 15.2 Usage example

A way is to use a global variable to note if the message has been successfully transmitted to driver transmit buffer. For example, for sending a message every 2 seconds:

```
static uint32_t gSendDate = 0 ;

void loop () {
  if (gSendDate < millis ()) {
    CANFDMessage message ;
    // Initialize message properties
    const bool ok = can.tryToSend (message) ;
    if (ok) {
      gSendDate += 2000 ;
    }
  }
}
```

An other hint to use a global boolean variable as a flag that remains `true` while the message has not been sent.

```
static bool gSendMessage = false ;

void loop () {
  ...
  if (frame_should_be_sent) {
    gSendMessage = true ;
  }
  ...
  if (gSendMessage) {
    CANMessage message ;
    // Initialize message properties
    const bool ok = can.tryToSend (message) ;
    if (ok) {
      gSendMessage = false ;
    }
  }
  ...
}
```

---

## 16 Retrieving received messages using the receive method

There are two ways for retrieving received messages :

- using the `receive` method, as explained in this section;
- using the `dispatchReceivedMessage` method (see [section 18 page 37](#)).

This is a basic example:

```
void loop () {
    CANFDMessage message ;
    if (can.receive (message)) {
        // Handle received message
    }
    ...
}
```

The `receive` method:

- returns `false` if the driver receive buffer is empty, `message` argument is not modified;
- returns `true` if a message has been removed from the driver receive buffer, and the `message` argument is assigned.

The `type` property contains the received frame format:

- `CAN_REMOTE`, the received frame is a CAN 2.0B remote frame;
- `CAN_DATA`, the received frame is a CAN 2.0B data frame;
- `CANFD_NO_BIT_RATE_SWITCH`, the frame received frame is a CANFD frame, received at at arbitration bit rate;
- `CANFD_WITH_BIT_RATE_SWITCH`, the frame received frame is a CANFD frame, received with bit rate switch.

You need to manually dispatch the received messages. If you did not provide any receive filter, you should check the `type` property (remote or data frame?), the `ext` bit (base or extended frame), and the `id` (identifier value). The following snippet dispatches three messages:

```
void loop () {
    CANFDMessage message ;
    if (can.receive (message)) {
        if (!message.rtr && message.ext && (message.id == 0x123456)) {
            handle_myMessage_0 (message) ; // Extended data frame, id is 0x123456
        }else if (!message.rtr && !message.ext && (message.id == 0x234)) {
            handle_myMessage_1 (message) ; // Base data frame, id is 0x234
        }else if (message.rtr && !message.ext && (message.id == 0x542)) {

```

## 16.1 Driver receive buffer size

---

```
    handle_myMessage_2 (message) ; // Base remote frame, id is 0x542
  }
}
...
}
```

The `handle_myMessage_0` function has the following header:

```
void handle_myMessage_0 (const CANFDMessage & inMessage) {
  ...
}
```

So are the header of the `handle_myMessage_1` and the `handle_myMessage_2` functions.

### 16.1 Driver receive buffer size

By default, the driver receive buffer size is 24. You can change it by setting the `mReceiveBufferSize` property of `settings` variable before calling the `begin` method:

```
ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL,
                             125 * 1000, DataBitRateFactor::DATA_BITRATE_x4) ;
settings.mReceiveBufferSize = 100 ;
const uint32_t errorCode = can.begin (settings, [] { can.isr () ; }) ;
...
```

As the size of `CANFDMessage` class is 72 bytes, the actual size of the driver receive buffer is the value of `settings.mReceiveBufferSize * 72`.

### 16.2 The `receiveBufferSize` method

The `receiveBufferSize` method returns the size of the driver receive buffer, that is the value of the `mReceiveBufferSize` property of `settings` variable when the `begin` method is called.

```
const uint32_t s = can.receiveBufferSize () ;
```

### 16.3 The `receiveBufferCount` method

The `receiveBufferCount` method returns the current number of messages in the driver receive buffer.

```
const uint32_t n = can.receiveBufferCount () ;
```

### 16.4 The `receiveBufferPeakCount` method

The `receiveBufferPeakCount` method returns the peak value of message count in the driver receive buffer.

---

```
const uint32_t max = can.receiveBufferPeakCount () ;
```

Note the driver receive buffer can overflow, if messages are not retrieved (by calling the `receive` or the `dispatchReceivedMessage` methods). If an overflow occurs, further calls of `can.receiveBufferPeakCount ()` return `can.receiveBufferSize ()+1`.

## 17 Acceptance filters

**Note.** The acceptance filters implemented in the `ACAN2517` library, that handles a `MCP2517FD` CAN Controller in the CAN 2.0B mode<sup>12</sup>, are almost identical, they differ only from the prototype of the callback routine.

If you invoke the `ACAN2517FD.begin` method with two arguments, it configures the `MCP2517FD` for receiving all messages.

```
const uint32_t errorCode = can.begin (settings, [] { can.isr () ; } ) ;
```

If you want to define receive filters, you have to set up an `MCP2517FDFilters` instance object, and pass it as third argument of the `ACAN2517FD.begin` method:

```
MCP2517FDFilters filters ;  
... // Append filters  
const uint32_t errorCode = can.begin (settings, [] { can.isr () ; }, filters) ;  
...
```

### 17.1 An example

**Sample sketch:** the `LoopBackDemoTeensy3xWithFilters` sketch is an example of filter definition.

```
MCP2517FDFilters filters ;
```

First, you instantiate an `MCP2517FDFilters` object. It represents an empty list of filters. So, if you do not append any filter, `can.begin (settings, [] { can.isr () ; }, filters)` configures the controller in such a way that no messages can be received.

```
// Filter #0: receive base frame with identifier 0x123  
filters.appendFrameFilter (kStandard, 0x123, receiveFromFilter0) ;  
// Filter #1: receive extended frame with identifier 0x12345678  
filters.appendFrameFilter (kExtended, 0x12345678, receiveFromFilter1) ;
```

You define the filters sequentially, with the four methods: `appendPassAllFilter`, `appendFormatFilter`, `appendFrameFilter`, `appendFilter`. These methods have as last argument an optional callback routine, that is called by the `dispatchReceivedMessage` method (see [section 18 page 37](#)).

The `appendFrameFilter` defines a filter that matches for an extended or base identifier of a given value.

You can define up to 32 filters. Filter definition registers are outside the `MCP2517FD` RAM, so defining filter does not restrict the receive and transmit buffer sizes. Note that `MCP2517FD` filter does not allow to establish a filter based on the data / remote information.

<sup>12</sup><https://github.com/pierremolinaro/acan2517>

## 17.2 The appendPassAllFilter method

---

```
// Filter #2: receive base frame with identifier 0x3n4 (0 <= n <= 15)
filters.appendFilter (kStandard, 0x70F, 0x304, receiveFromFilter2) ;
```

The `appendFilter` defines a filter that matches for an identifier that matches the condition:

$$\text{identifier} \& 0x70F == 0x304$$

The `kStandard` argument constraints to accept only base frames. So the accepted base identifiers are `0x304`, `0x314`, `0x324`, ..., `0x3E4`, `0x3F4`.

```
//----- Filters ok ?
if (filters.filterStatus () != MCP2517FDFilters::kFiltersOk) {
    Serial.print ("Error filter ") ;
    Serial.print (filters.filterErrorIndex ()) ;
    Serial.print (": ") ;
    Serial.println (filters.filterStatus ()) ;
}
```

Filter definitions can have error(s), you can check error kind with the `filterStatus` method. If it returns a value different than `MCP2517FDFilters::kFiltersOk`, there is at least one error: only the last one is reported, and the `filterErrorIndex` returns the corresponding filter index. Note this does not check the number of filters is lower or equal than 32.

```
const uint32_t errorCode = can.begin (settings, [] { can.isr () ; }, filters) ;
```

The `begin` method checks the filter definition:

- it raises the `kMoreThan32Filters` error if more than 32 filters are defined;
- it raises the `kFilterDefinitionError` error if one or more filter definitions are erroneous (that is if `filterStatus` returns a value different than `MCP2517FDFilters::kFiltersOk`).

## 17.2 The appendPassAllFilter method

```
void MCP2517FDFilters::appendPassAllFilter (const ACANFDCallbackRoutine inCallbackRoutine) ;
```

This defines a filter that accepts all (base / extended, remote / data) frames.

If used, this filter must be the last one: as the `MCP2517FD` tests the filters sequentially, the following filters will never match.

## 17.3 The appendFormatFilter method

```
void MCP2517FDFilters::appendFormatFilter (const tFrameFormat inFormat,
                                           const ACANFDCallbackRoutine inCallbackRoutine) ;
```

This defines a filter that accepts:

## 17.4 The `appendFrameFilter` method

---

- if `inFormat` is equal to `kStandard`, all base remote frames and all base data frames;
- if `inFormat` is equal to `kExtended`, all extended remote frames and all extended data frames.

### 17.4 The `appendFrameFilter` method

```
void MCP2517FDFilters::appendFrameFilter (const tFrameFormat inFormat,  
                                           const uint32_t inIdentifier,  
                                           const ACANFDCallbackRoutine inCallbackRoutine) ;
```

This defines a filter that accepts:

- if `inFormat` is equal to `kStandard`, all base remote frames and all base data frames with a given identifier;
- if `inFormat` is equal to `kExtended`, all extended remote frames and all extended data frames with a given identifier.

If `inFormat` is equal to `kStandard`, the `inIdentifier` should be lower or equal to `0x7FF`. Otherwise, `settings.filterStatus ()` returns the `kStandardIdentifierTooLarge` error.

If `inFormat` is equal to `kExtended`, the `inIdentifier` should be lower or equal to `0x1FFFFFFF`. Otherwise, `settings.filterStatus ()` returns the `kExtendedIdentifierTooLarge` error.

### 17.5 The `appendFilter` method

```
void MCP2517FDFilters::appendFilter (const tFrameFormat inFormat,  
                                      const uint32_t inMask,  
                                      const uint32_t inAcceptance,  
                                      const ACANFDCallbackRoutine inCallbackRoutine) ;
```

The `inMask` and `inAcceptance` arguments defines a filter that accepts frame whose identifier verifies:

$$\text{identifier} \& \text{inMask} == \text{inAcceptance}$$

The `inFormat` filters base (if `inFormat` is equal to `kStandard`) frames, or extended ones (if `inFormat` is equal to `kExtended`).

Note that `inMask` and `inAcceptance` arguments should verify:

$$\text{inAcceptance} \& \text{inMask} == \text{inAcceptance}$$

Otherwise, `settings.filterStatus ()` returns the `kInconsistencyBetweenMaskAndAcceptance` error.

If `inFormat` is equal to `kStandard`:

- 
- the `inAcceptance` should be lower or equal to `0x7FF`; Otherwise, `settings.filterStatus ()` returns the `kStandardAcceptanceTooLarge` error;
  - the `inMask` should be lower or equal to `0x7FF`; Otherwise, `settings.filterStatus ()` returns the `kStandardMaskTooLarge` error.

If `inFormat` is equal to `kExtended`:

- the `inAcceptance` should be lower or equal to `0x1FFFFFFF`; Otherwise, `settings.filterStatus ()` returns the `kExtendedAcceptanceTooLarge` error;
- the `inMask` should be lower or equal to `0x1FFFFFFF`; Otherwise, `settings.filterStatus ()` returns the `kExtendedMaskTooLarge` error.

## 18 The `dispatchReceivedMessage` method

**Sample sketch:** the `LoopBackDemoTeensy3xWithFilters` shows how using the `dispatchReceivedMessage` method.

Instead of calling the `receive` method, call the `dispatchReceivedMessage` method in your `loop` function. It calls the call back function associated with the matching filter.

If you have not defined any filter, do not use this function, call the `receive` method.

```
void loop () {
  can.dispatchReceivedMessage () ; // Do not use can.receive any more
  ...
}
```

The `dispatchReceivedMessage` method handles one message at a time. More precisely:

- if it returns `false`, the driver receive buffer was empty;
- if it returns `true`, the driver receive buffer was not empty, one message has been removed and dispatched.

So, the return value can be used for emptying and dispatching all received messages:

```
void loop () {
  while (can.dispatchReceivedMessage ()) {
  }
  ...
}
```

If a filter definition does not name a call back function, the corresponding messages are lost.

The `dispatchReceivedMessage` method has an optional argument – `NULL` by default: a function name. This function is called for every message that passes the receive filters, with an argument equal to the matching filter index:

```

void filterMatchFunction (const uint32_t inFilterIndex) {
    ...
}

void loop () {
    can.dispatchReceivedMessage (filterMatchFunction) ;
    ...
}

```

You can use this function for maintaining statistics about receiver filter matches.

## 19 The ACAN2517FD::begin method reference

### 19.1 The prototypes

```

uint32_t ACAN2517FD::begin (const ACAN2517FDSettings & inSettings,
                            void (* inInterruptServiceRoutine) (void)) ;

```

This prototype has two arguments, a `ACAN2517FDSettings` instance that defines the settings, and the interrupt service routine, that can be specified by a lambda expression or a function (see [section 19.2 page 38](#)). It configures the controller in such a way that all messages are received (*pass-all* filter).

```

uint32_t ACAN2517FD::begin (const ACAN2517FDSettings & inSettings,
                            void (* inInterruptServiceRoutine) (void),
                            const MCP2517FDFilters & inFilters) ;

```

The second prototype has a third argument, an instance of `MCP2517FDFilters` class that defines the receive filters.

### 19.2 Defining explicitly the interrupt service routine

In this document, the *interrupt service routine* is defined by a lambda expression:

```

const uint32_t errorCode = can.begin (settings, [] { can.isr () ; }) ;

```

Instead of a lambda expression, you are free to define the *interrupt service routine* as a function:

```

void canISR () {
    can.isr () ;
}

```

And you pass `canISR` as argument to the `begin` method:

```

const uint32_t errorCode = can.begin (settings, canISR) ;

```

## 19.3 The error code

The `ACAN2517FD::begin` method returns an error code. The value 0 denotes no error. Otherwise, you consider every bit as an error flag, as described in [table 8](#). An error code could report several errors. The `ACAN2517FD` class defines static constants for naming errors.

Bit	Code	Static constant Name	Link
0	0x1	<code>kRequestedConfigurationModeTimeout</code>	<a href="#">section 19.3.1 page 39</a>
1	0x2	<code>kReadBackErrorWith1MHzSPIClock</code>	<a href="#">section 19.3.2 page 39</a>
2	0x4	<code>kTooFarFromDesiredBitRate</code>	<a href="#">section 19.3.3 page 40</a>
3	0x8	<code>kInconsistentBitRateSettings</code>	<a href="#">section 19.3.4 page 40</a>
4	0x10	<code>kINTPinIsNotAnInterrupt</code>	<a href="#">section 19.3.5 page 40</a>
5	0x20	<code>kISRIsNull</code>	<a href="#">section 19.3.6 page 40</a>
6	0x40	<code>kFilterDefinitionError</code>	<a href="#">section 19.3.7 page 40</a>
7	0x80	<code>kMoreThan32Filters</code>	<a href="#">section 19.3.8 page 40</a>
8	0x100	<code>kControllerReceiveFIFOSizeIsZero</code>	<a href="#">section 19.3.9 page 40</a>
9	0x200	<code>kControllerReceiveFIFOSizeGreaterThan32</code>	<a href="#">section 19.3.10 page 41</a>
10	0x400	<code>kControllerTransmitFIFOSizeIsZero</code>	<a href="#">section 19.3.11 page 41</a>
11	0x800	<code>kControllerTransmitFIFOSizeGreaterThan32</code>	<a href="#">section 19.3.12 page 41</a>
12	0x1000	<code>kControllerRamUsageGreaterThan2048</code>	<a href="#">section 19.3.13 page 41</a>
13	0x2000	<code>kControllerTXQPriorityGreaterThan31</code>	<a href="#">section 19.3.14 page 41</a>
14	0x4000	<code>kControllerTransmitFIFOPriorityGreaterThan31</code>	<a href="#">section 19.3.15 page 41</a>
15	0x8000	<code>kControllerTXQSizeGreaterThan32</code>	<a href="#">section 19.3.16 page 41</a>
16	0x1_0000	<code>kRequestedModeTimeout</code>	<a href="#">section 19.3.17 page 41</a>
17	0x2_0000	<code>kX10PLLNotReadyWithin1MS</code>	<a href="#">section 19.3.18 page 42</a>
18	0x4_0000	<code>kReadBackErrorWithFullSpeedSPIClock</code>	<a href="#">section 19.3.19 page 42</a>
19	0x8_0000	<code>kISRNotNullAndNoIntPin</code>	<a href="#">section 19.3.20 page 42</a>
20	0x10_0000	<code>kInvalidTDCO</code>	<a href="#">section 19.3.21 page 42</a>

**Table 8** – The `ACAN2517FD::begin` method error code bits

### 19.3.1 `kRequestedConfigurationModeTimeout`

The `ACAN2517FD::begin` method first configures SPI with a 1 Mbit/s clock, and then requests the configuration mode. This error is raised when the `LCP2517FD` does not reach the configuration mode with 2ms. It means that the `MCP2517FD` cannot be accessed via SPI.

### 19.3.2 `kReadBackErrorWith1MHzSPIClock`

Then, the `ACAN2517FD::begin` method checks accessibility by writing and reading back 32-bit values at the first `MCP2517FD` RAM address (0x400). The values are  $1 \ll n$ , with  $0 \leq n \leq 31$ . This error is raised when the read value is different from the written one. It means that the `MCP2517FD` cannot be accessed via SPI.

### 19.3.3 `kTooFarFromDesiredBitRate`

This error occurs when the `mArbitrationBitRateClosedToDesiredRate` property of the `settings` object is `false`. This means that the `ACAN2517FDSettings` constructor cannot compute a CAN bit configuration close enough to the desired bit rate. For example:

```
void setup () {
  ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL,
                               1, DataBitRateFactor::DATA_BITRATE_x1) ; // 1 bit/s !!!
  // Here, settings.mArbitrationBitRateClosedToDesiredRate is false
  const uint32_t errorCode = can.begin (settings, [] { can.isr () ; }) ;
  // Here, errorCode contains ACAN2517FD::kCANBitConfigurationTooFarFromDesiredBitRate
}
```

### 19.3.4 `kInconsistentBitRateSettings`

The `ACAN2517FDSettings` constructor always returns consistent bit rate settings – even if the settings provide a bit rate too far away the desired bit rate. So this error occurs only when you have changed the CAN bit properties (`mBitRatePrescaler`, `mPropagationSegment`, `mArbitrationPhaseSegment1`, `mArbitrationPhaseSegment2`, `mArbitrationSjw`), and one or more resulting values are inconsistent. See [section 20.2 page 49](#).

### 19.3.5 `kINTPinIsNotAnInterrupt`

The pin you provide for handling the `MCP2517FD` interrupt has no interrupt capability.

### 19.3.6 `kISRIsNull`

The interrupt service routine argument is `NULL`, you should provide a valid function.

### 19.3.7 `kFilterDefinitionError`

`settings.filterStatus()` returns a value different than `MCP2517FDFilters::kFiltersOk`, meaning that one or more filters are erroneous. See [section 17.1 page 34](#).

### 19.3.8 `kMoreThan32Filters`

You have defined more than 32 filters. `MCP2517FD` cannot handle more than 32 filters.

### 19.3.9 `kControllerReceiveFIFOSizeIsZero`

You have assigned 0 to `settings.mControllerReceiveFIFOSize`. The *controller receive FIFO size* should be greater than 0.

### 19.3.10 `kControllerReceiveFIFOSizeGreaterThan32`

You have assigned a value greater than 32 to `settings.mControllerReceiveFIFOSize`. The *controller receive FIFO size* should be lower or equal than 32.

### 19.3.11 `kControllerTransmitFIFOSizeIsZero`

You have assigned 0 to `settings.mControllerTransmitFIFOSize`. The *controller transmit FIFO size* should be greater than 0.

### 19.3.12 `kControllerTransmitFIFOSizeGreaterThan32`

You have assigned a value greater than 32 to `settings.mControllerTransmitFIFOSize`. The *controller transmit FIFO size* should be lower or equal than 32.

### 19.3.13 `kControllerRamUsageGreaterThan2048`

The configuration you have defined requires more than 2048 bytes of MCP2517FD internal RAM. See [section 14 page 28](#).

### 19.3.14 `kControllerTXQPriorityGreaterThan31`

You have assigned a value greater than 31 to `settings.mControllerTXQBufferPriority`. The *controller transmit FIFO size* should be lower or equal than 31.

### 19.3.15 `kControllerTransmitFIFOPriorityGreaterThan31`

You have assigned a value greater than 31 to `settings.mControllerTransmitFIFOPriority`. The *controller transmit FIFO size* should be lower or equal than 31.

### 19.3.16 `kControllerTXQSizeGreaterThan32`

You have assigned a value greater than 32 to `settings.mControllerTXQSize`. The *controller transmit FIFO size* should be lower than 32.

### 19.3.17 `kRequestedModeTimeOut`

During configuration by the `ACAN2517FD::begin` method, the MCP2517FD is in the *configuration* mode. At this end of this process, the mode specified by the `inSettings.mRequestedMode` value is requested. The switch to this mode is not immediate, a register is repetitively read for checking the switch is done. This error is raised if the switch is not completed within a delay between 1 ms and 2 ms.

### 19.3.18 kX10PLLNotReadyWithin1MS

You have requested the `OSC_4MHz10xPLL` oscillator mode, enabling the 10x PLL. The `ACAN2517FD::begin` method waits during 2ms the PLL to be locked. This error is raised when the PLL is not locked within 2 ms.

### 19.3.19 kReadBackErrorWithFullSpeedSPIClock

After the oscillator configuration has been established, the `ACAN2517FD::begin` method configures the SPI at its full speed (`SYSCLK/2`), and checks accessibility by writing and reading back 32 32-bit values at the first `MCP2517FD` RAM address (`0x400`). The 32 used values are  $1 \ll n$ , with  $0 \leq n \leq 31$ . This error is raised when the read value is different from the written one.

### 19.3.20 kISRNotNullAndNoIntPin

This error occurs when you have no `INT` pin, and a not-null interrupt service routine:

```
ACAN2517 can (MCP2517_CS, SPI, 255) ; // Last argument is 255 -> no interrupt pin

void setup () {
  ...
  const uint32_t errorCode = can.begin (settings, [] { can.isr () ; }) ; // ISR is not null
  ...
}
```

Interrupt service routine should be `NULL` if no `INT` pin is defined:

```
ACAN2517 can (MCP2517_CS, SPI, 255) ; // Last argument is 255 -> no interrupt pin

void setup () {
  ...
  const uint32_t errorCode = can.begin (settings, NULL) ; // Ok, ISR is null
  ...
}
```

See the `LoopBackDemoTeensy3xNoInt` and `LoopBackDemoESP32NoInt` sketches.

### 19.3.21 kInvalidTDCO

`TDCO` should be a 7-bit signed integer (i.e.  $-64 \leq \text{TDCO} \leq 63$ ). `ACAN2517FDSettings` constructor ensures this constraint, and provides a valid value in `mTDCO` property.

This error occurs when you have manually change the `mTDCO` property, for example:

```
ACAN2517FDSettings settings (... arguments ...) ;
settings.mTDCO = 100 ; // Invalid value
const uint32_t errorCode = can.begin (settings, [] { can.isr () ; }) ;
```

---

## 20 ACAN2517FDSettings class reference

**Note.** The `ACAN2517FDSettings` class is not Arduino specific. You can compile it on your desktop computer with your favorite C++ compiler. In the <https://github.com/pierremolinaro/acan2517FD-dev> GitHub repository, a command line tool is defined for exploring all CAN arbitration bit rates from 1 bit/s to 1 Mbit/s. It also checks that computed CAN bit decompositions are all consistent, even if they are too far from the desired baud rate.

### 20.1 The `ACAN2517FDSettings` constructor: computation of the CAN bit settings

The constructor of the `ACAN2517FDSettings` has three mandatory arguments: the oscillator frequency, the desired arbitration bit rate, and the data bit rate factor. It tries to compute the CAN bit settings for these bit rates. If it succeeds, the constructed object has its `mArbitrationBitRateClosedToDesiredRate` property set to `true`, otherwise it is set to `false`. For example, for an 1 Mbit/s arbitration bit rate and an 8 Mbit/s data bit rate:

```
void setup () {
  // Arbitration bit rate: 1 Mbit/s, data bit rate: 8 Mbit/s
  ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL,
                               1000 * 1000, DataBitRateFactor::DATA_BITRATE_x8) ;
  // Here, settings.mArbitrationBitRateClosedToDesiredRate is true
  ...
}
```

Note the data bit rate is not defined by its frequency, but by its multiplicative factor from arbitration bit rate. If you want a single bit rate, use `ACAN2517FDSettings::DATA_BITRATE_x1` as data bit rate factor.

Of course, with a 40 MHz or 20 MHz `SYSCLOCK`, CAN bit computation always succeeds for classical arbitration bit rates: 1 Mbit/s, 500 kbit/s, 250 kbit/s, 125 kbit/s. With a 40 MHz `SYSCLOCK`, there are 184 exact arbitration / data bit rate combinations (table 9 page 44), and 178 with a 20 MHz `SYSCLOCK` (table 10 page 45). Note a 8 MHz data bit rate cannot be performed with a 20 MHz `SYSCLOCK`. By "exact", we mean that arbitration bit rate and data bit rate are both exactly integer values. There is no such combination for data bit rate factors 3x, 6x, 7x.

But this does not mean there is no possibility to get such data bit rates factors. For example, we can have a data bit rate of 4 Mbit/s, and an arbitration bit rate of  $4/7$  Mbit/s = 571 428 kbit/s:

```
void setup () {
  ...
  ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL,
                               571428, DataBitRateFactor::DATA_BITRATE_x7) ;
  Serial.print ("mArbitrationBitRateClosedToDesiredRate: ") ;
  Serial.println (settings.mArbitrationBitRateClosedToDesiredRate) ; // 1 (--> is true)
  Serial.print ("Actual Arbitration Bit Rate: ") ;
  Serial.println (settings.actualArbitrationBitRate ()) ; // 571428 bit/s
  Serial.print ("distance: ") ;
  Serial.println (settings.ppmFromDesiredArbitrationBitRate ()) ; // 1 ppm= 0,0001 %
  Serial.print ("Actual Data Bit Rate: ") ;
```

Arbitration Bit Rate	Valid Data Rate factors
500 bit/s	1x 8x
625 bit/s	1x 8x
640 bit/s	1x
800 bit/s	1x 5x 8x
1 kbit/s	1x 4x 5x 8x
1250 bit/s	1x 4x 5x 8x
1280 bit/s	1x 5x
1600 bit/s	1x 4x 5x 8x
2 kbit/s	1x 2x 4x 5x 8x
2500 bit/s	1x 2x 4x 5x 8x
2560 bit/s	1x 5x
3125 bit/s	1x 2x 4x 5x 8x
3200 bit/s	1x 2x 4x 5x
4 kbit/s	1x 2x 4x 5x 8x
5 kbit/s	1x 2x 4x 5x 8x
6250 bit/s	1x 2x 4x 5x 8x
6400 bit/s	1x 2x 5x
8 kbit/s	1x 2x 4x 5x 8x
10 kbit/s	1x 2x 4x 5x 8x
12500 bit/s	1x 2x 4x 5x 8x
12800 bit/s	1x 5x
15625 bit/s	1x 2x 4x 5x 8x
16 kbit/s	1x 2x 4x 5x
20 kbit/s	1x 2x 4x 5x 8x
25 kbit/s	1x 2x 4x 5x 8x
31250 bit/s	1x 2x 4x 5x 8x
32 kbit/s	1x 2x 5x
40 kbit/s	1x 2x 4x 5x 8x
50 kbit/s	1x 2x 4x 5x 8x
62500 bit/s	1x 2x 4x 5x 8x
64 kbit/s	1x 5x
78125 bit/s	1x 2x 4x 8x
80 kbit/s	1x 2x 4x 5x
100 kbit/s	1x 2x 4x 5x 8x
125 kbit/s	1x 2x 4x 5x 8x
156250 bit/s	1x 2x 4x 8x
160 kbit/s	1x 2x 5x
200 kbit/s	1x 2x 4x 5x 8x
250 kbit/s	1x 2x 4x 5x 8x
312500 bit/s	1x 2x 4x 8x
320 kbit/s	1x 5x
400 kbit/s	1x 2x 4x 5x
500 kbit/s	1x 2x 4x 5x 8x
625 kbit/s	1x 2x 4x 8x
800 kbit/s	1x 2x 5x
1000 kbit/s	1x 2x 4x 5x 8x

**Table 9** – 40 MHz SYSCLK: the 184 exact bit rates

```
Serial.println (settings.actualDataBitRate ()); // 4 Mbit/s
...
}
```

Due to integer computations, and the distance from desired arbitration bit rate is 1 ppm. "ppm" stands for "part-per-million", and 1 ppm = 10<sup>-6</sup>. In other words, 10,000 ppm = 1%.

Arbitration Bit Rate	Valid Data Rate factors
250 bit/s	1x 8x
320 bit/s	1x
400 bit/s	1x 5x 8x
500 bit/s	1x 4x 5x 8x
625 bit/s	1x 4x 5x 8x
640 bit/s	1x 5x
800 bit/s	1x 4x 5x 8x
1 kbit/s	1x 2x 4x 5x 8x
1250 bit/s	1x 2x 4x 5x 8x
1280 bit/s	1x 5x
1600 bit/s	1x 2x 4x 5x
2 kbit/s	1x 2x 4x 5x 8x
2500 bit/s	1x 2x 4x 5x 8x
3125 bit/s	1x 2x 4x 5x 8x
3200 bit/s	1x 2x 5x
4 kbit/s	1x 2x 4x 5x 8x
5 kbit/s	1x 2x 4x 5x 8x
6250 bit/s	1x 2x 4x 5x 8x
6400 bit/s	1x 5x
8 kbit/s	1x 2x 4x 5x
10 kbit/s	1x 2x 4x 5x 8x
12500 bit/s	1x 2x 4x 5x 8x
15625 bit/s	1x 2x 4x 5x 8x
16 kbit/s	1x 2x 5x
20 kbit/s	1x 2x 4x 5x 8x
25 kbit/s	1x 2x 4x 5x 8x
31250 bit/s	1x 2x 4x 5x 8x
32 kbit/s	1x 5x
40 kbit/s	1x 2x 4x 5x
50 kbit/s	1x 2x 4x 5x 8x
62500 bit/s	1x 2x 4x 5x 8x
78125 bit/s	1x 2x 4x 8x
80 kbit/s	1x 2x 5x
100 kbit/s	1x 2x 4x 5x 8x
125 kbit/s	1x 2x 4x 5x 8x
156250 bit/s	1x 2x 4x 8x
160 kbit/s	1x 5x
200 kbit/s	1x 2x 4x 5x
250 kbit/s	1x 2x 4x 5x 8x
312500 bit/s	1x 2x 4x 8x
400 kbit/s	1x 2x 5x
500 kbit/s	1x 2x 4x 5x 8x
625 kbit/s	1x 2x 4x 8x
800 kbit/s	1x 5x
1000 kbit/s	1x 2x 4x 5x

**Table 10** – 20 MHz SYSCLK: the 178 exact bit rates

By default, a desired bit rate is accepted if the distance from the computed actual bit rate is lower or equal to 1,000 ppm = 0.1 %. You can change this default value by adding your own value as fourth argument of ACAN2517FDSettings constructor. For example, with an arbitration bit rate equal to 727 kbit/s:

```
void setup () {
    ...
    ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL,
                                727 * 1000, DataBitRateFactor::DATA_BITRATE_x1,
```

## 20.1 The ACAN2517FDSettings constructor: computation of the CAN bit settings

```
        100) ; // 100 ppm
Serial.print ("mArbitrationBitRateClosedToDesiredRate: ") ;
Serial.println (settings.mArbitrationBitRateClosedToDesiredRate) ; // 0 (--> is false)
Serial.print ("actual arbitration bit rate: ") ;
Serial.println (settings.actualArbitrationBitRate ()) ; // 727272 bit/s
Serial.print ("distance: ") ;
Serial.println (settings.ppmFromDesiredArbitrationBitRate ()) ; // 375 ppm
...
}
```

The fourth argument does not change the CAN bit computation, it only changes the acceptance test for setting the `mArbitrationBitRateClosedToDesiredRate` property. For example, you can specify that you want the computed actual bit to be exactly the desired bit rate:

```
void setup () {
...
ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL,
                             500 * 1000, DataBitRateFactor::DATA_BITRATE_x1,
                             0) ; // Max distance is 0 ppm
Serial.print ("mArbitrationBitRateClosedToDesiredRate: ") ;
Serial.println (settings.mArbitrationBitRateClosedToDesiredRate) ; // 1 (--> is true)
Serial.print ("actual arbitration bit rate: ") ;
Serial.println (settings.actualArbitrationBitRate ()) ; // 500,000 bit/s
Serial.print ("distance: ") ;
Serial.println (settings.ppmFromDesiredArbitrationBitRate ()) ; // 0 ppm
...
}
```

In any way, the bit rate computation always gives a consistent result, resulting an actual arbitration / data bit rates closest from the desired bit rate. For example, we query a 423 kbit/s arbitration bit rate, and a  $423 \text{ kbit/s} * 3 = 1\,269 \text{ kbit/s}$  data bit rate:

```
void setup () {
...
ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL,
                             423 * 1000, DataBitRateFactor::DATA_BITRATE_x3) ;
Serial.print ("mArbitrationBitRateClosedToDesiredRate: ") ;
Serial.println (settings.mArbitrationBitRateClosedToDesiredRate) ; // 0 (--> is false)
Serial.print ("Actual Arbitration Bit Rate: ") ;
Serial.println (settings.actualArbitrationBitRate ()) ; // 416 666 bit/s
Serial.print ("Actual Data Bit Rate: ") ;
Serial.println (settings.actualDataBitRate ()) ; // 1 250 kbit/s
Serial.print ("distance: ") ;
Serial.println (settings.ppmFromDesiredArbitrationBitRate ()) ; // 14972 ppm
...
}
```

The resulting bit rates settings are far from the desired values, the CAN bit decomposition is consistent. You can get its details:

```

void setup () {
  ...
  ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL,
                               423 * 1000, DataBitRateFactor::DATA_BITRATE_x6) ;
  Serial.print ("mArbitrationBitRateClosedToDesiredRate: ") ;
  Serial.println (settings.mArbitrationBitRateClosedToDesiredRate) ; // 0 (--> is false)
  Serial.print ("Actual Arbitration Bit Rate: ") ;
  Serial.println (settings.actualArbitrationBitRate ()) ; // 416 666 bit/s
  Serial.print ("Actual Data Bit Rate: ") ;
  Serial.println (settings.actualDataBitRate ()) ; // 1 250 kbit/s
  Serial.print ("distance: ") ;
  Serial.println (settings.ppmFromDesiredArbitrationBitRate ()) ; // 14972 ppm
  Serial.print ("Bit rate prescaler: ") ;
  Serial.println (settings.mBitRatePrescaler) ; // BRP = 2
  Serial.print ("Arbitration Phase segment 1: ") ;
  Serial.println (settings.mArbitrationPhaseSegment1) ; // PS1 = 38
  Serial.print ("Arbitration Phase segment 2: ") ;
  Serial.println (settings.mArbitrationPhaseSegment2) ; // PS2 = 9
  Serial.print ("Arbitration Resynchronization Jump Width: ") ;
  Serial.println (settings.mArbitrationSJW) ; // SJW = 9
  Serial.print ("Arbitration Sample Point: ") ;
  Serial.println (settings.arbitrationSamplePointFromBitStart ()) ; // 81, meaning 81%
  Serial.print ("Data Phase segment 1: ") ;
  Serial.println (settings.mDataPhaseSegment1) ; // PS1 = 12
  Serial.print ("Data Phase segment 2: ") ;
  Serial.println (settings.mDataPhaseSegment2) ; // PS2 = 3
  Serial.print ("Data Resynchronization Jump Width: ") ;
  Serial.println (settings.mDataSJW) ; // SJW = 3
  Serial.print ("Data Sample Point: ") ;
  Serial.println (settings.dataSamplePointFromBitStart ()) ; // 81, meaning 81%
  Serial.print ("Consistency: ") ;
  Serial.println (settings.CANBitSettingConsistency ()) ; // 0, meaning Ok
  ...
}

```

The `samplePointFromBitStart` method returns sample point, expressed in per-cent of the bit duration from the beginning of the bit.

Note the computation may calculate a bit decomposition too far from the desired bit rate, but it is always consistent. You can check this by calling the `CANBitSettingConsistency` method.

You can change the property values for adapting to the particularities of your CAN network propagation time. By example, you can increment the `mArbitrationPhaseSegment1` property value, and decrement the `mArbitrationPhaseSegment2` property value in order to sample the CAN Rx pin later.

```

void setup () {
  ...
  ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL,
                               500 * 1000, DataBitRateFactor::DATA_BITRATE_x1) ;

```

## 20.1 The ACAN2517FDSettings constructor: computation of the CAN bit settings

```
Serial.print ("mArbitrationBitRateClosedToDesiredRate: ") ;
Serial.println (settings.mArbitrationBitRateClosedToDesiredRate) ; // 1 (--> is true)
settings.mArbitrationPhaseSegment1 -= 8 ; // 63 -> 55: safe, 1 <= PS1 <= 256
settings.mArbitrationPhaseSegment2 += 8 ; // 16 -> 24: safe, 1 <= PS2 <= 128
settings.mArbitrationSJW += 8           ; // 16 -> 24: safe, 1 <= SJW <= PS2
Serial.print ("Sample Point: ") ;
Serial.println (settings.samplePointFromBitStart ()) ; // 68, meaning 68%
Serial.print ("actual arbitration bit rate: ") ;
Serial.println (settings.actualArbitrationBitRate ()) ; // 500000: ok, no change
Serial.print ("Consistency: ") ;
Serial.println (settings.CANBitSettingConsistency ()) ; // 0, meaning Ok
...
}
```

Be aware to always respect CAN bit timing consistency! The MCP2517FD constraints are:

$$\begin{aligned}1 &\leq \text{mBitRatePrescaler} \leq 256 \\2 &\leq \text{mArbitrationPhaseSegment1} \leq 256 \\1 &\leq \text{mArbitrationPhaseSegment2} \leq 128 \\1 &\leq \text{mArbitrationSJW} \leq \text{mArbitrationPhaseSegment2} \\2 &\leq \text{mDataPhaseSegment1} \leq 32 \\1 &\leq \text{mDataPhaseSegment2} \leq 16 \\1 &\leq \text{mDataSJW} \leq \text{mDataPhaseSegment2}\end{aligned}$$

Miicrochips recommends using the same bit rate prescaler for arbitration and data bit rates.

Resulting actual bit rates are given by:

$$\begin{aligned}\text{Actual Arbitration Bit Rate} &= \frac{\text{SYSCLK}}{\text{mBitRatePrescaler} \cdot (1 + \text{mArbitrationPhaseSegment1} + \text{mArbitrationPhaseSegment2})} \\ \text{Actual Data Bit Rate} &= \frac{\text{SYSCLK}}{\text{mBitRatePrescaler} \cdot (1 + \text{mDataPhaseSegment1} + \text{mDataPhaseSegment2})}\end{aligned}$$

And the sampling point (in per-cent unit) are given by:

$$\begin{aligned}\text{Arbitration Sampling Point} &= 100 \cdot \frac{1 + \text{mArbitrationPhaseSegment1}}{1 + \text{mArbitrationPhaseSegment1} + \text{mArbitrationPhaseSegment2}} \\ \text{Data Sampling Point} &= 100 \cdot \frac{1 + \text{mDataPhaseSegment1}}{1 + \text{mDataPhaseSegment1} + \text{mDataPhaseSegment2}}\end{aligned}$$

## 20.2 The CANBitSettingConsistency method

This method checks the CAN bit decomposition (given by `mBitRatePrescaler`, `mArbitrationPhaseSegment1`, `mArbitrationPhaseSegment2`, `mArbitrationSJW`, `mDataPhaseSegment1`, `mDataPhaseSegment2`, `mDataSJW` property values) is consistent.

```
void setup () {
  ...
  ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL,
                               500 * 1000, DataBitRateFactor::DATA_BITRATE_x2) ;
  Serial.print ("mArbitrationBitRateClosedToDesiredRate: ") ;
  Serial.println (settings.mArbitrationBitRateClosedToDesiredRate) ; // 1 (--> is true)
  settings.mDataPhaseSegment1 = 0 ; // Error, mDataPhaseSegment1 should be >= 1 (and <= 32)
  Serial.print ("Consistency: 0x") ;
  Serial.println (settings.CANBitSettingConsistency (), HEX) ; // != 0, meaning error
  ...
}
```

The `CANBitSettingConsistency` method returns 0 if CAN bit decomposition is consistent. Otherwise, the returned value is a bit field that can report several errors – see [table 11](#).

The `ACAN2517FDSettings` class defines static constant properties that can be used as mask error. For example:

```
public: static const uint32_t kBitRatePrescalerIsZero = 1 << 0 ;
```

Bit	Error Name	Error
0	<code>kBitRatePrescalerIsZero</code>	<code>mBitRatePrescaler == 0</code>
1	<code>kBitRatePrescalerIsGreaterThan256</code>	<code>mBitRatePrescaler &gt; 256</code>
2	<code>kArbitrationPhaseSegment1IsLowerThan2</code>	<code>mArbitrationPhaseSegment1 &lt; 2</code>
3	<code>kArbitrationPhaseSegment1IsGreaterThan256</code>	<code>mArbitrationPhaseSegment1 &gt; 256</code>
4	<code>kArbitrationPhaseSegment2IsZero</code>	<code>mArbitrationPhaseSegment2 == 0</code>
5	<code>kArbitrationPhaseSegment2IsGreaterThan128</code>	<code>mArbitrationPhaseSegment2 &gt; 128</code>
6	<code>kArbitrationSJWIsZero</code>	<code>mArbitrationSJW == 0</code>
7	<code>kArbitrationSJWIsGreaterThan128</code>	<code>mArbitrationSJW &gt; 128</code>
8	<code>kArbitrationSJWIsGreaterThanPhaseSegment1</code>	<code>mArbitrationSJW &gt; mArbitrationPhaseSegment1</code>
9	<code>kArbitrationSJWIsGreaterThanPhaseSegment2</code>	<code>mArbitrationSJW &gt; mArbitrationPhaseSegment2</code>
10	<code>kArbitrationTQCountNotDivisibleByDataBitRateFactor</code>	See <a href="#">section 20.3 page 50</a>
11	<code>kDataPhaseSegment1IsLowerThan2</code>	<code>mDataPhaseSegment1 &lt; 2</code>
12	<code>kDataPhaseSegment1IsGreaterThan32</code>	<code>mDataPhaseSegment1 &gt; 32</code>
13	<code>kDataPhaseSegment2IsZero</code>	<code>mDataPhaseSegment2 == 0</code>
14	<code>kDataPhaseSegment2IsGreaterThan16</code>	<code>mDataPhaseSegment2 &gt; 16</code>
15	<code>kDataSJWIsZero</code>	<code>mDataSJW == 0</code>
16	<code>kDataSJWIsGreaterThan16</code>	<code>mDataSJW &gt; 16</code>
17	<code>kDataSJWIsGreaterThanPhaseSegment1</code>	<code>mDataSJW &gt; mDataPhaseSegment1</code>
18	<code>kDataSJWIsGreaterThanPhaseSegment2</code>	<code>mDataSJW &gt; mDataPhaseSegment2</code>

**Table 11** – The `ACAN2517FDSettings::CANBitSettingConsistency` method error codes

### 20.3 The `kArbitrationTQCountNotDivisibleByDataBitRateFactor` error

This error occurs when you have changed the properties relative to arbitration and / or data bit rates, and the resulting values provide a data bit rate that is not an integer multiple of arbitration bit rate, that is the `ACAN2517FDSettings::dataBitRateIsAMultipleOfArbitrationBitRate` method returns `false`.

### 20.4 The `actualArbitrationBitRate` method

The `actualArbitrationBitRate` method returns the actual bit computed from `mBitRatePrescaler`, `mPropagationSegment`, `mArbitrationPhaseSegment1`, `mArbitrationPhaseSegment2`, `mArbitrationSjw` property values.

```
void setup () {
  ...
  ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL,
                               440 * 1000, DataBitRateFactor::DATA_BITRATE_x1) ;
  Serial.print ("mArbitrationBitRateClosedToDesiredRate: ") ;
  Serial.println (settings.mArbitrationBitRateClosedToDesiredRate) ; // 0 (--> is false)
  Serial.print ("actual arbitration bit rate: ") ;
  Serial.println (settings.actualArbitrationBitRate ()) ; // 444,444 bit/s
  ...
}
```

**Note.** If CAN bit settings are not consistent (see [section 20.2 page 49](#)), the returned value is irrelevant.

### 20.5 The `exactArbitrationBitRate` method

```
bool ACAN2517FDSettings::exactArbitrationBitRate (void) const ;
```

The `exactArbitrationBitRate` method returns `true` if the actual arbitration bit rate is equal to the desired arbitration bit rate, and `false` otherwise.

**Note.** If CAN bit settings are not consistent (see [section 20.2 page 49](#)), the returned value is irrelevant.

### 20.6 The `exactDataBitRate` method

```
bool ACAN2517FDSettings::exactDataBitRate (void) const ;
```

The `exactDataBitRate` method returns `true` if the actual data bit rate is equal to the desired data bit rate, and `false` otherwise.

**Note.** If CAN bit settings are not consistent (see [section 20.2 page 49](#)), the returned value is irrelevant.

### 20.7 The `ppmFromDesiredArbitrationBitRate` method

## 20.8 The ppmFromDesiredDataBitRate method

---

```
uint32_t ACAN2517FDSettings::ppmFromDesiredArbitrationBitRate (void) const ;
```

The `ppmFromDesiredArbitrationBitRate` method returns the distance from the actual arbitration bit rate to the desired arbitration bit rate, expressed in part-per-million (ppm):  $1 \text{ ppm} = 10^{-6}$ . In other words,  $10,000 \text{ ppm} = 1\%$ .

**Note.** If CAN bit settings are not consistent (see [section 20.2 page 49](#)), the returned value is irrelevant.

## 20.8 The ppmFromDesiredDataBitRate method

```
uint32_t ACAN2517FDSettings::ppmFromDesiredDataBitRate (void) const ;
```

The `ppmFromDesiredDataBitRate` method returns the distance from the actual data bit rate to the desired data bit rate, expressed in part-per-million (ppm):  $1 \text{ ppm} = 10^{-6}$ . In other words,  $10,000 \text{ ppm} = 1\%$ .

**Note.** If CAN bit settings are not consistent (see [section 20.2 page 49](#)), the returned value is irrelevant.

## 20.9 The arbitrationSamplePointFromBitStart method

```
uint32_t ACAN2517FDSettings::arbitrationSamplePointFromBitStart (void) const ;
```

The `arbitrationSamplePointFromBitStart` method returns the distance of sample point from the start of the arbitration CAN bit, expressed in part-per-cent (ppc):  $1 \text{ ppc} = 1\% = 10^{-2}$ . It is a good practice to get sample point from 65% to 80%. The bit rate calculator tries to set the sample point at 80%.

**Note.** If CAN bit settings are not consistent (see [section 20.2 page 49](#)), the returned value is irrelevant.

## 20.10 The dataSamplePointFromBitStart method

```
uint32_t ACAN2517FDSettings::dataSamplePointFromBitStart (void) const ;
```

The `dataSamplePointFromBitStart` method returns the distance of sample point from the start of the data CAN bit, expressed in part-per-cent (ppc):  $1 \text{ ppc} = 1\% = 10^{-2}$ . It is a good practice to get sample point from 65% to 80%. The bit rate calculator tries to set the sample point at 80%.

**Note.** If CAN bit settings are not consistent (see [section 20.2 page 49](#)), the returned value is irrelevant.

## 20.11 Properties of the ACAN2517FDSettings class

All properties of the `ACAN2517FDSettings` class are declared `public` and are initialized ([table 12](#)).

### 20.11.1 The `mTXCANIsOpenDrain` property

This property defines the output mode of the MCP2517FD `TXCAN` pin:

## 20.11 Properties of the ACAN2517FDSettings class

Property	Type	Initial value	Comment
mOscillator	Oscillator	Constructor argument	
mSysClock	uint32_t	Constructor argument	
mDesiredBitRate	uint32_t	Constructor argument	
mBitRatePrescaler	uint16_t	0	See <a href="#">section 20.1 page 43</a>
mArbitrationPhaseSegment1	uint16_t	0	See <a href="#">section 20.1 page 43</a>
mArbitrationPhaseSegment2	uint8_t	0	See <a href="#">section 20.1 page 43</a>
mArbitrationSJW	uint8_t	0	See <a href="#">section 20.1 page 43</a>
mArbitrationBitRateClosedToDesiredRate	bool	false	See <a href="#">section 20.1 page 43</a>
mDataPhaseSegment1	uint16_t	0	See <a href="#">section 20.1 page 43</a>
mDataPhaseSegment2	uint8_t	0	See <a href="#">section 20.1 page 43</a>
mDataSJW	uint8_t	0	See <a href="#">section 20.1 page 43</a>
mDataBitRateClosedToDesiredRate	bool	false	See <a href="#">section 20.1 page 43</a>
mTXCANIsOpenDrain	bool	false	See <a href="#">section 20.11.1 page 51</a>
mINTIsOpenDrain	bool	false	See <a href="#">section 20.11.2 page 52</a>
mCLKOPin	CLKOPin	CLKO_DIVIDED_BY_10	See <a href="#">section 20.11.3 page 53</a>
mISOCRCEnabled	bool	true	See <a href="#">section 20.11.5 page 53</a>
mRequestedMode	RequestedMode	NormalFD	See <a href="#">section 20.11.4 page 53</a>
mDriverTransmitFIFOSize	uint16_t	16	See <a href="#">section 10 page 24</a>
mControllerTransmitFIFOSize	uint8_t	1	See <a href="#">section 10 page 24</a>
mControllerTransmitFIFOPayload	PayloadSize	PAYLOAD_64	See <a href="#">section 10 page 24</a>
mControllerTransmitFIFOPriority	uint8_t	0	See <a href="#">section 10 page 24</a>
mControllerTransmitFIFORetransmissionAttempts	RetransmissionAttempts	UnlimitedNumber	See <a href="#">section 10 page 24</a>
mControllerTXQSize	uint8_t	0	See <a href="#">section 11 page 26</a>
mControllerTXQBufferPayload	PayloadSize	PAYLOAD_64	See <a href="#">section 11 page 26</a>
mControllerTXQBufferPriority	uint8_t	31	See <a href="#">section 11 page 26</a>
mControllerTXQBufferRetransmissionAttempts	RetransmissionAttempts	UnlimitedNumber	See <a href="#">section 11 page 26</a>
mDriverReceiveFIFOSize	uint16_t	32	See <a href="#">section 12 page 27</a>
mControllerReceiveFIFOPayload	PayloadSize	PAYLOAD_64	See <a href="#">section 12 page 27</a>
mControllerReceiveFIFOSize	uint8_t	27	See <a href="#">section 12 page 27</a>
mTDCO	int8_t	0	See <a href="#">section 20.11.6 page 54</a>

**Table 12** – Properties of the ACAN2517FDSettings class

- if `false` (default value), the TXCAN pin is a push/pull output;
- if `true`, the TXCAN pin is an open drain output.

### 20.11.2 The mINTIsOpenDrain property

This property defines the output mode of the MCP2517FD INT pin:

- if `false` (default value), the INT pin is a push/pull output;
- if `true`, the INT pin is an open drain output.

### 20.11.3 The CLKO/SOF pin

The CLKO/SOF pin of the MCP2517FD controller is an output pin has five functions<sup>13</sup>:

- output *internally generated clock*;
- output *internally generated clock* divided by 2;
- output *internally generated clock* divided by 4;
- output *internally generated clock* divided by 10;
- output SOF ("Start Of Frame").

By default, after power on, CLKO/SOF pin outputs *internally generated clock* divided by 10.

The ACAN2517FDSettings class defines an enumerated type for specifying these settings:

```
class ACAN2517FDSettings {
public: typedef enum {CLKO_DIVIDED_BY_1, CLKO_DIVIDED_BY_2,
                    CLKO_DIVIDED_BY_4, CLKO_DIVIDED_BY_10,
                    SOF} CLKOPin ;

    ...
};
```

The mCLKOPin property lets you select the CLKO/SOF pin function; by default, this property value is CLKO\_DIVIDED\_BY\_10, that corresponds to MCP2517FD power on setting. For example:

```
ACAN2517FDSettings settings (ACAN2517FDSettings::OSC_4MHz10xPLL, CAN_BIT_RATE) ;
...
settings.mCLKOPin = ACAN2517FDSettings::SOF ;
...
const uint32_t errorCode = can.begin (settings, [] { can.isr () ; } ) ;
```

### 20.11.4 The mRequestedMode property

This property defines the mode requested at this end of the configuration: NormalFD (default value), InternalLoopBack, ExternalLoopBack, ListenOnly.

### 20.11.5 The mISOCRCEnabled property

This property enables ISO CRC in CANFD Frames bit:

- true (default): include Stuff Bit Count in CRC Field and use Non-Zero CRC Initialization Vector according to ISO 11898-1:2015;
- false: do NOT include Stuff Bit Count in CRC Field and use CRC Initialization Vector with all zeros.

This setting correspondonds to the ISOCRCEN bit of the CiCON register.

<sup>13</sup> *Internally generated clock* is not SYSCLK, see [figure 8 page 23](#).

---

### 20.11.6 The `mTDCO` property

*Transmitter Delay Compensation* is required when data phase bit time that is shorter than the transceiver loop delay. The `mTDCO` property is by default set to `mBitRatePrescaler * mDataPhaseSegment1` by the `ACAN2517FDSettings` constructor.

For more details, see DS20005678D, sections 3.4.3 to 3.4.8, pages 18 to 20.

## 21 Other `ACAN2517FD` methods

### 21.1 The `currentOperationMode` method

```
ACAN2517FD::OperationMode ACAN2517FD::currentOperationMode (void) ;
```

This function returns the `MCP2517FD` current operation mode, as a value of the `ACAN2517FD::currentOperationMode` enumerated type. This type is defined in the `ACAN2517FD.h` header file.

```
class ACAN2517FD {
    ...
public: typedef enum : uint8_t {
    NormalFD = 0,
    Sleep = 1,
    InternalLoopBack = 2,
    ListenOnly = 3,
    Configuration = 4,
    ExternalLoopBack = 5,
    Normal20B = 6,
    RestrictedOperation = 7
} OperationMode ;
    ...
} ;
```

### 21.2 The `recoverFromRestrictedOperationMode` method

```
bool ACAN2517FD::recoverFromRestrictedOperationMode (void) ;
```

If the `MCP2517FD` is in *Restricted Operation Mode*, this method requests the operation mode defined by the `mRequestedMode` property of the `ACAN2517FDSettings` class instance. This method has no effect if the current mode is not the *Restricted Operation Mode*.

This method returns `true` if both conditions are met:

- the `MCP2517FD` is in *Restricted Operation Mode*;
- the operation mode has been successfully recovered.

It returns `false` otherwise.

## 21.3 The errorCounters method

```
uint32_t ACAN2517FD::errorCounters (void) ;
```

This method returns the transmit / receive error count register value, as described in DS20005688B, REGISTER 3-19 page 41. The CiTREC value is zero when there is no error.

## 21.4 The diagInfos method

```
uint32_t ACAN2517FD::diagInfos (const int inIndex = 1) ;
```

**Thanks to Flole998 and turmary.** This method returns:

- if `inIndex` is equal to 0, the C1BDIAG0 register value, as described in DS20005688B, REGISTER 3-20 page 42;
- if `inIndex` is not equal to 0, the C1BDIAG1 register value, as described in DS20005688B, REGISTER 3-21 page 43.

## 22 The sendfd-odd and sendfd-even sketches

I use these two sketches for testing transmission and reception of CANFD frames. They try to send the frames as quickly as possible, repeatedly calling the `tryToSend` function.

They are designed for Teensy 3.5, with the MCP2517FD connected to SPI1. It is easy to adapt them to any other platform, although it can be tricky for an Arduino Uno which has little RAM and small computation power.

Make a small CANFD network with two boards, one running the `sendfd-odd` sketch, the other running the `sendfd-even` sketch. Both display results in the Arduino Serial Monitor, you need two desktop computers.

The `sendfd-odd` sketch sends 50,000 CANFD base frames with an odd identifier, and waits for receiving 50,000 frames. Identifier is computed randomly, by `((micros () & 0x7FE) | 1)`.

The `sendfd-even` sketch sends 50,000 CANFD base frames with an even identifier, and waits for receiving 50,000 frames. Identifier is computed randomly, by `(micros () & 0x7FE)`.

In a CANFD network, as in a CAN network, two stations must not transmit frames with the same identifier: the arbitration does not operate, and a collision occurs when the DLC field or data is transmitted. As an odd identifier is always different from an even identifier, it is safe to run the two sketches in the same network.

You should adopt the same settings for the two sketches: same arbitration bit rate, same data bit rate factor.

Start the `sendfd-odd` sketch first: after initialization, it displays `Ready` in the Arduino Serial Monitor, meaning it is waiting for receiving frames.

Then, start the `sendfd-even` sketch: it sends frames immediately; when the `sendfd-odd` sketch receives the first frame, it begins to send frames. Both sides send 50,000 frames. When the `sendfd-odd` sketch has sent and received 50,000 frames, it displays the duration from the reception of the first frame.

---

Every second, each sketch displays on its Arduino Serial Monitor:

- the sent frame count;
- the received frame count;
- the MCP2517FD error counter (0 if no error);
- the MCP2517FD operation mode (0 in normal mode, 7 if it reaches the *Restricted Operation Mode*);
- the driver receive buffer peak count;
- the MCP2517FD receive buffer overflow count.

It is safe to observe that one side is stopping temporarily, while the other sends continuously. For example, consider the case where the `sendfd-odd` sketch tries to send a frame with the `0x7FF` identifier; any frame with an even identifier has higher priority, so the `sendfd-even` sketch sends all remaining frames before the `sendfd-odd` sketch resumes sending.