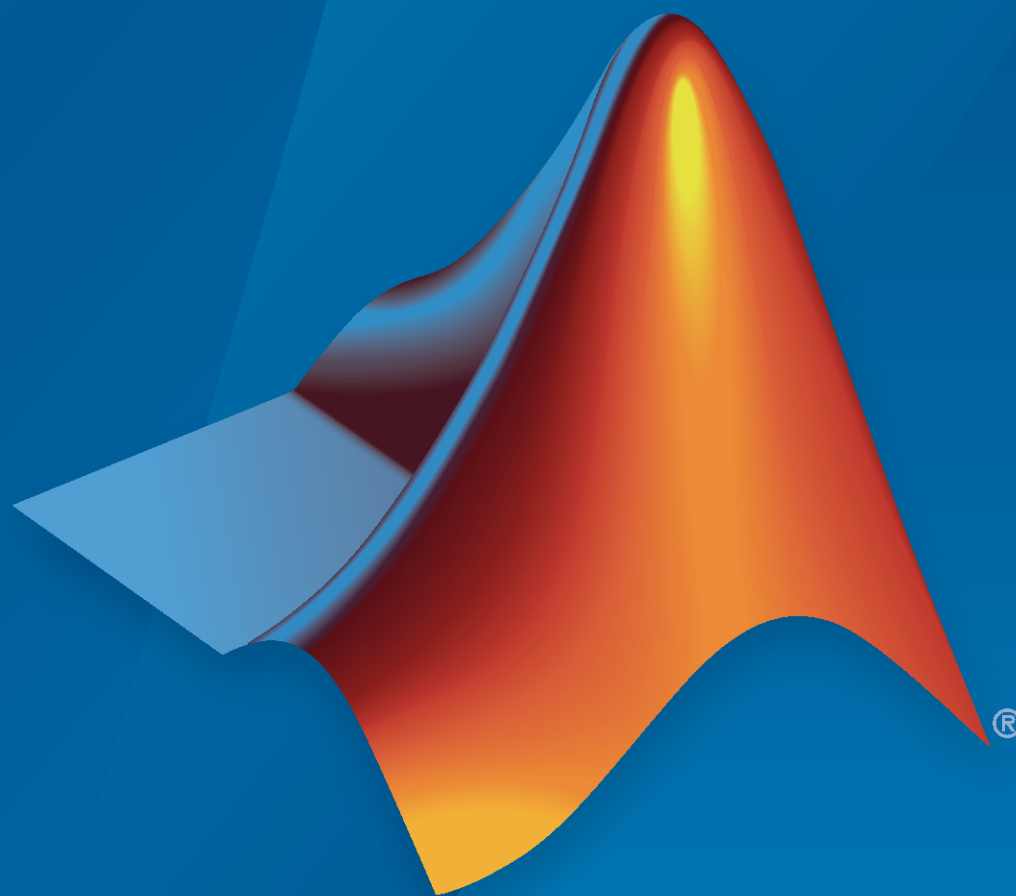


Vehicle Network Toolbox™

User's Guide



MATLAB® & SIMULINK®

R2020b



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The MathWorks, Inc.
1 Apple Hill Drive
Natick, MA 01760-2098

Vehicle Network Toolbox™ User's Guide

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Getting Started

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- “Toolbox Characteristics and Capabilities” on page 1-3
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- “Vehicle Network Communication in MATLAB” on page 1-8
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Vehicle Network Toolbox Product Description

Communicate with in-vehicle networks using CAN, J1939, and XCP protocols

Vehicle Network Toolbox provides MATLAB® functions and Simulink® blocks to send, receive, encode, and decode CAN, CAN FD, J1939, and XCP messages. The toolbox lets you identify and parse specific signals using industry-standard CAN database files and then visualize the decoded signals using the CAN Bus Monitor app. Using A2L description files, you can connect to an ECU via XCP on CAN or Ethernet. You can access messages and measurement data stored in MDF files.

The toolbox simplifies communication with in-vehicle networks and lets you monitor, filter, and analyze live CAN bus data, or log and record messages for later analysis and replay. You can simulate message traffic on a virtual CAN bus or connect to a live network or ECU. Vehicle Network Toolbox supports CAN interface devices from Vector, Kvaser, PEAK-System, and National Instruments™.

Key Features

- MATLAB functions for transmitting and receiving CAN, CAN FD, J1939, and XCP messages
- Simulink blocks for communicating over CAN, CAN FD, J1939 or XCP protocols
- XCP support for interacting with ECUs over Ethernet or CAN
- Vector CAN database (.dbc) file, A2L description file, and MDF file support
- Vehicle CAN Bus Monitor app to configure devices and visualize live CAN network traffic
- Signal packing and unpacking for simplified encoding and decoding of CAN messages, CAN FD messages, and J1939 parameter groups
- Support for Vector, Kvaser, PEAK-System, and National Instruments CAN interface devices and for virtual channels

Toolbox Characteristics and Capabilities

In this section...

“Vehicle Network Toolbox Characteristics” on page 1-3

“Interaction Between the Toolbox and Its Components” on page 1-4

“Prerequisite Knowledge” on page 1-5

Vehicle Network Toolbox Characteristics

The toolbox is a collection of functions built on the MATLAB technical computing environment.

You can use the toolbox to:

- “Connect to CAN Devices” on page 1-3
- “Use Supported CAN Devices and Drivers” on page 1-3
- “Communicate Between MATLAB and CAN Bus” on page 1-3
- “Simulate CAN Communication” on page 1-3
- “Visualize CAN Communication” on page 1-3

Connect to CAN Devices

Vehicle Network Toolbox provides host-side CAN connectivity using defined CAN devices. CAN is the predominant protocol in automotive electronics by which many distributed control systems in a vehicle function.

For example, in a common design when you press a button to lock the doors in your car, a control unit in the door reads that input and transmits lock commands to control units in the other doors. These commands exist as data in CAN messages, which the control units in the other doors receive and act on by triggering their individual locks in response.

Use Supported CAN Devices and Drivers

You can use Vehicle Network Toolbox to communicate over the CAN bus using supported Vector, Kvaser, PEAK-System, or National Instruments devices and drivers.

See “Vehicle Network Toolbox Supported Hardware” for more information.

Communicate Between MATLAB and CAN Bus

Using a set of well-defined functions, you can transfer messages between the MATLAB workspace and a CAN bus using a CAN device. You can run test applications that can log and record CAN messages for you to process and analyze. You can also replay recorded sequences of messages.

Simulate CAN Communication

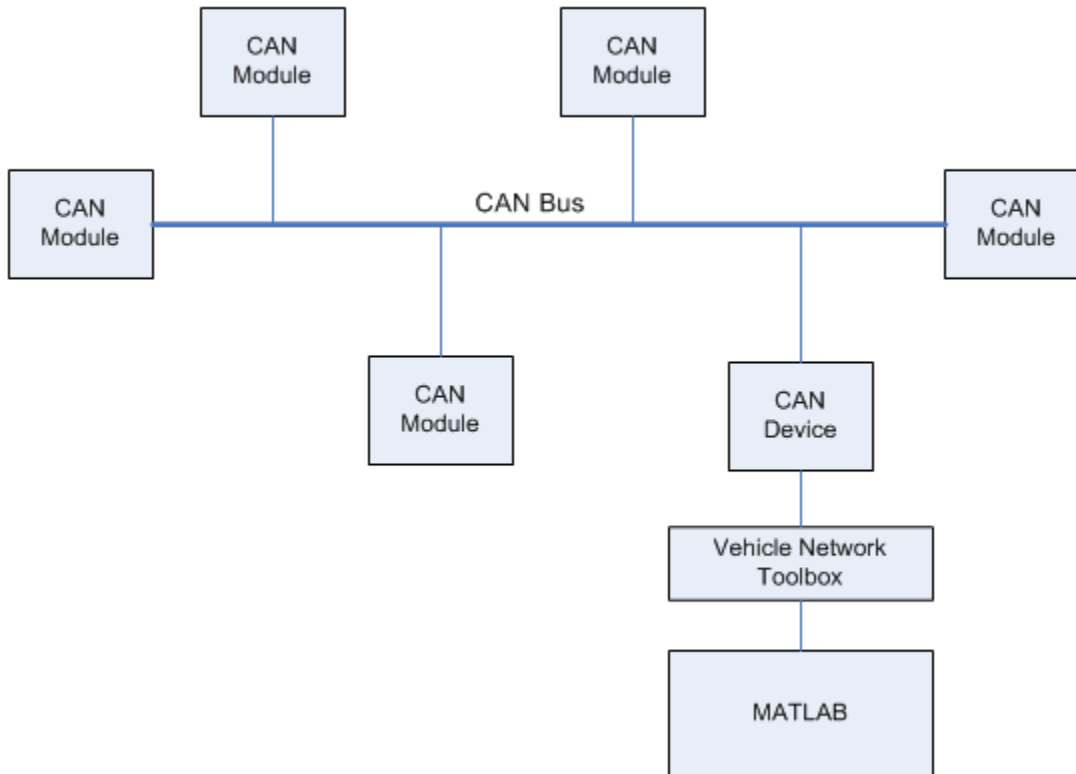
With Vehicle Network Toolbox block library and other blocks from the Simulink library, you can create sophisticated models to connect to a live network and to simulate message traffic on a CAN bus.

Visualize CAN Communication

Using Vehicle CAN Bus Monitor, a simple graphical user interface, you can monitor message traffic on a selected device and channel. You can then analyze these messages.

Interaction Between the Toolbox and Its Components

Vehicle Network Toolbox is a conduit between MATLAB and the CAN bus.



In this illustration:

- Six CAN modules are attached to a CAN bus.
- One module, which is a CAN device, is attached to the Vehicle Network Toolbox, built on the MATLAB technical computing environment.

Using Vehicle Network Toolbox from MATLAB, you can configure a channel on the CAN device to:

- Transmit messages to the CAN bus.
- Receive messages from the CAN bus.
- Trigger a callback function to run when the channel receives a message.
- Attach the database to the configured CAN channel to interpret received CAN messages.
- Use the CAN database to construct messages to transmit.
- Log and record messages and analyze them in MATLAB.
- Replay live recorded sequence of messages in MATLAB.
- Build Simulink models to connect to a CAN bus and to simulate message traffic.
- Monitor CAN traffic with the “Vehicle CAN Bus Monitor” on page 5-2.

Vehicle Network Toolbox is a comprehensive solution for CAN connectivity in MATLAB and Simulink. Refer to the Functions and Simulink Blocks for more information.

Prerequisite Knowledge

The Vehicle Network Toolbox document set assumes that you are familiar with these products:

- MATLAB — To write scripts and functions, and to use functions with the command-line interface.
- Simulink — To create simple models to connect to a CAN bus or to simulate those models.
- Vector CANdb — To understand CAN databases, along with message and signal definitions.

MathWorks Virtual Channels

Description

To facilitate code prototyping and model simulation without hardware, Vehicle Network Toolbox provides a MathWorks® virtual CAN device with two channels. These channels are identified with the vendor "MathWorks" and the device "Virtual 1", and are accessible in both MATLAB and Simulink.

These virtual channels support CAN, CAN FD, and J1939 communication on Windows®, and support CAN and CAN FD on Linux®. Many examples throughout the documentation show how to use these virtual channels, so that you can run them on your own system.

The two virtual channels belong to a common device, so you could send a message on channel 1 and have that message received on channel 1 and channel 2. But because the virtual device is an application-level representation of a CAN/CAN FD bus without an actual bus, the following limitations apply:

- The virtual interface does not perform low level protocol activity like arbitration, error frames, acknowledgment, and so on.
- Although you can connect multiple channels of the same virtual device in the same MATLAB session or in Simulink models running in that MATLAB session, you cannot use virtual channels to communicate between different MATLAB sessions.

Examples

You can view the device and channels in MATLAB with the `canChannelList` function.

```
canChannelList
```

```
ans =
```

```
2x6 table
```

Vendor	Device	Channel	DeviceModel	ProtocolMode	SerialNumber
"MathWorks"	"Virtual 1"	1	"Virtual"	"CAN, CAN FD"	"0"
"MathWorks"	"Virtual 1"	2	"Virtual"	"CAN, CAN FD"	"0"

Create a virtual CAN channel.

```
canch = canChannel("MathWorks","Virtual 1",1);
```

Create a virtual CAN FD channel.

```
canfdch = canFDChannel("MathWorks","Virtual 1",2);
```

Create a virtual J1939 channel.

```
db = canDatabase([matlabroot] '/examples/vnt/data/J1939.dbc');
jch = j1939Channel(db,"MathWorks","Virtual 1",1);
```

See Also

Functions

`canChannel` | `canChannelList` | `j1939Channel`

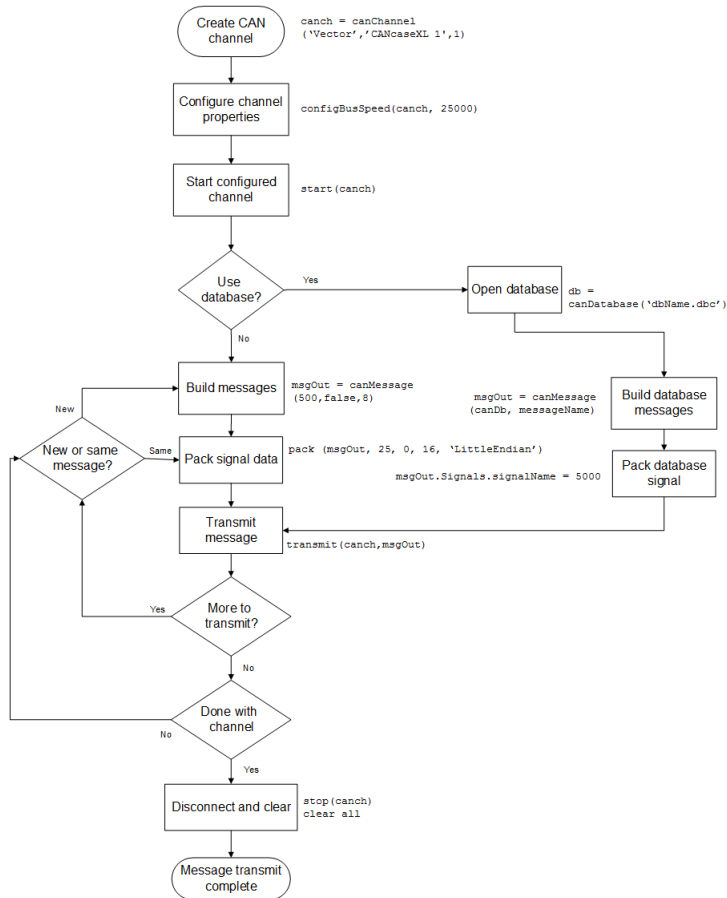
More About

- “Transmit and Receive CAN Messages” on page 1-10

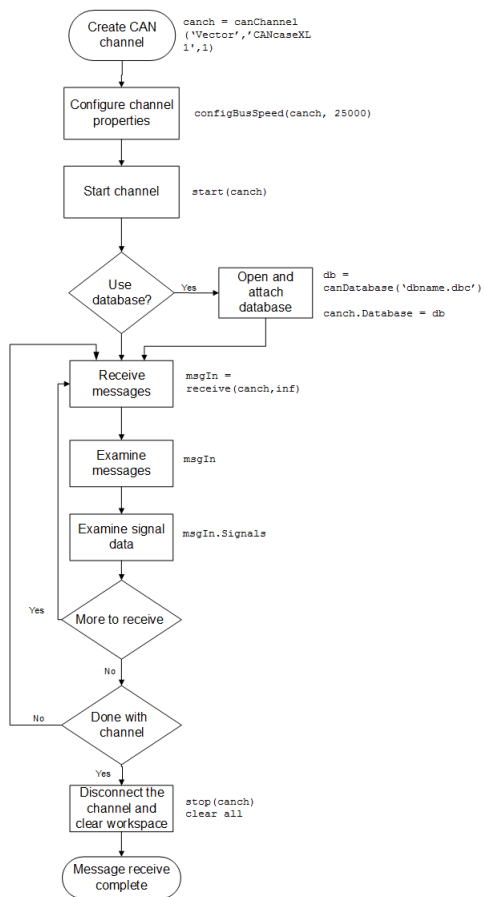
Vehicle Network Communication in MATLAB

Workflows in this section are sequential and will help you understand how the communication works.

Transmit Workflow



Receive Workflow



See Also

More About

- “Transmit and Receive CAN Messages” on page 1-10

Transmit and Receive CAN Messages

In this section...

"Discover Installed Hardware" on page 1-10
 "Create CAN Channels" on page 1-10
 "Configure Channel Properties" on page 1-12
 "Start the Channels" on page 1-13
 "Create a Message" on page 1-14
 "Pack a Message" on page 1-15
 "Transmit a Message" on page 1-15
 "Receive a Message" on page 1-16
 "Unpack a Message" on page 1-19
 "Save and Load CAN Channels" on page 1-19
 "Disconnect Channels and Clean Up" on page 1-19

Discover Installed Hardware

In the example, you discover your system CAN devices with `canChannelList`, then create two CAN channels using `canChannel`. Later, you edit the properties of the first channel and create a message using `canMessage`, then transmit the message from the first channel using `transmit`, and receive it on the other channel using `receive`.

- 1 Get information about the CAN hardware devices on your system.

```
info = canChannelList
```

```
info =
```

```
14x6 table
```

Vendor	Device	Channel	DeviceModel	ProtocolMode	SerialNumber
"MathWorks"	"Virtual 1"	1	"Virtual"	"CAN, CAN FD"	"0"
"MathWorks"	"Virtual 1"	2	"Virtual"	"CAN, CAN FD"	"0"
"Vector"	"VN1610 1"	1	"VN1610"	"CAN, CAN FD"	"18959"
"Vector"	"VN1610 1"	2	"VN1610"	"CAN, CAN FD"	"18959"
"Vector"	"Virtual 1"	1	"Virtual"	"CAN, CAN FD"	"0"
"Vector"	"Virtual 1"	2	"Virtual"	"CAN, CAN FD"	"0"
"PEAK-System"	"PCAN-USB Pro"	1	"PCAN-USB Pro"	"CAN, CAN FD"	"0"
"PEAK-System"	"PCAN-USB Pro"	2	"PCAN-USB Pro"	"CAN, CAN FD"	"0"
"Kvaser"	"USBcan Professional 1"	1	"USBcan Professional"	"CAN"	"10680"
"Kvaser"	"USBcan Professional 1"	1	"USBcan Professional"	"CAN"	"10680"
"Kvaser"	"Virtual 1"	1	"Virtual"	"CAN, CAN FD"	"0"
"Kvaser"	"Virtual 1"	2	"Virtual"	"CAN, CAN FD"	"0"
"NI"	"9862 CAN/HS (CAN1)"	1	"9862"	"CAN, CAN FD"	"17F5094"
"NI"	"9862 CAN/HS (CAN2)"	1	"9862"	"CAN, CAN FD"	"17F50B2"

Note To modify this example for a hardware CAN device, make a loopback connection between the two channels.

Create CAN Channels

Create two MathWorks virtual CAN channels.

```
canch1 = canChannel('MathWorks','Virtual 1',1)
canch2 = canChannel('MathWorks','Virtual 1',2)
```

```
canch1 =
```

```
Channel with properties:
```

```
Device Information
```

```
    DeviceVendor: 'MathWorks'
        Device: 'Virtual 1'
    DeviceChannelIndex: 1
    DeviceSerialNumber: 0
        ProtocolMode: 'CAN'
```

```
Status Information
```

```
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 0
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: [0x0 datetime]
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'
```

```
Channel Information
```

```
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    BusSpeed: 500000
        SJW: []
        TSEG1: []
        TSEG2: []
    NumOfSamples: []
```

```
Other Information
```

```
    Database: []
    UserData: []
```

```
canch2 =
```

```
Channel with properties:
```

```
Device Information
```

```
    DeviceVendor: 'MathWorks'
        Device: 'Virtual 1'
    DeviceChannelIndex: 2
    DeviceSerialNumber: 0
        ProtocolMode: 'CAN'
```

```
Status Information
```

```
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 0
    MessagesTransmitted: 0
```

```
InitializationAccess: 1
  InitialTimestamp: [0x0 datetime]
  FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

Channel Information
  BusStatus: 'N/A'
  SilentMode: 0
  TransceiverName: 'N/A'
  TransceiverState: 'N/A'
  ReceiveErrorCount: 0
  TransmitErrorCount: 0
  BusSpeed: 500000
  SJW: []
  TSEG1: []
  TSEG2: []
  NumOfSamples: []

Other Information
  Database: []
  UserData: []
```

For each channel, notice that its initial Running value is 0 (stopped), and its bus speed is 500000.

Note You cannot use the same variable to create multiple channels sequentially. Clear any channel before using the same variable to construct a new CAN channel.

You cannot create arrays of CAN channel objects. Each object you create must be assigned to its own scalar variable.

Configure Channel Properties

You can set the behavior of your CAN channel by configuring its property values. For this exercise, change the bus speed of channel 1 to 250000 using the `configBusSpeed` function.

Tip Configure property values before you start the channel.

- 1 Change the bus speed of both channels to 250000, then view the channel `BusSpeed` property to verify the setting.

```
configBusSpeed(canch1,250000)
canch1.BusSpeed
```

```
ans =
    250000
```

- 2 You can also see the updated bus speed in the channel display.

```
canch1

canch1 =
```

Channel with properties:

```

Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 1
    DeviceSerialNumber: 0
    ProtocolMode: 'CAN'

Status Information
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 0
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: [0x0 datetime]
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

Channel Information
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    BusSpeed: 250000
    SJW: []
    TSEG1: []
    TSEG2: []
    NumOfSamples: []

Other Information
    Database: []
    UserData: []

```

- 3 In a similar way, change the bus speed of the second channel.

```
configBusSpeed(canch2,250000)
```

Start the Channels

After you configure their properties, start both channels. Then view the updated status information of the first channel.

```
start(canch1)
start(canch2)
canch1
```

```
canch1 =
```

```
Channel with properties:
```

```

Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'

```

```
DeviceChannelIndex: 1
DeviceSerialNumber: 0
  ProtocolMode: 'CAN'

Status Information
  Running: 1
  MessagesAvailable: 0
  MessagesReceived: 0
  MessagesTransmitted: 0
  InitializationAccess: 1
  InitialTimestamp: 23-May-2019 15:43:40
  FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

Channel Information
  BusStatus: 'N/A'
  SilentMode: 0
  TransceiverName: 'N/A'
  TransceiverState: 'N/A'
  ReceiveErrorCount: 0
  TransmitErrorCount: 0
  BusSpeed: 250000
  SJW: []
  TSEG1: []
  TSEG2: []
  NumOfSamples: []

Other Information
  Database: []
  UserData: []
```

Notice that the channel Running property value is now 1 (true).

Create a Message

After you set all the property values as desired and your channels are running, you are ready to transmit and receive messages on the CAN bus. For this exercise, transmit a message using `canch1` and receive it using `canch2`. To transmit a message, create a message object and pack the message with the required data.

Build a CAN message with a standard ID of 500, and a data length of 8 bytes.

```
messageout = canMessage(500,false,8)
```

```
messageout =
```

```
Message with properties:
```

```
Message Identification
  ProtocolMode: 'CAN'
  ID: 500
  Extended: 0
  Name: ''
```

```
Data Details
  Timestamp: 0
```



```

    Data: [0 0 0 0 0 0 0 0]
    Signals: []
    Length: 8

    Protocol Flags
      Error: 0
      Remote: 0

    Other Information
      Database: []
      UserData: []

```

Some of the properties of the message indicate:

- **Error** — A logical 0 (false) because the message is not an error.
- **Remote** — A logical 0 (false) because the message is not a remote frame.
- **ID** — The ID you specified.
- **Extended** — A logical 0 (false) because you did not specify an extended ID.
- **Data** — A uint8 array of 0s, with size specified by the data length.

Refer to the `canMessage` function to understand more about its input arguments.

Pack a Message

After you create the message, pack it with the required data.

- 1 Use the `pack` function to pack your message with these input parameters: a `Data` value of 25, start bit of 0, signal size of 16, and byte order using little-endian format. View the message `Data` property to verify the settings.

```

pack(messageout,25,0,16,'LittleEndian')
messageout.Data

ans =

    1×8 uint8 row vector

    25     0     0     0     0     0     0     0

```

The only message property that changes from packing is `Data`. Refer to the `pack` function to understand more about its input arguments.

Transmit a Message

Now you can transmit the packed message. Use the `transmit` function, supplying the channel `canch1` and the message as input arguments.

```

transmit(canch1,messageout)
canch1

```

```

canch1 =

```

Channel with properties:

```
Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 1
    DeviceSerialNumber: 0
    ProtocolMode: 'CAN'

Status Information
    Running: 1
    MessagesAvailable: 1
    MessagesReceived: 0
    MessagesTransmitted: 1
    InitializationAccess: 1
    InitialTimestamp: 23-May-2019 15:43:40
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

Channel Information
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    BusSpeed: 250000
    SJW: []
    TSEG1: []
    TSEG2: []
    NumOfSamples: []

Other Information
    Database: []
    UserData: []
```

MATLAB displays the updated channel. In the Status Information section, the `MessagesTransmitted` value increments by 1 each time you transmit a message. The message to be received is available to all devices on the bus, so it shows up in the `MessagesAvailable` property even for the transmitting channel.

Refer to the `transmit` function to understand more about its input arguments.

Receive a Message

Use the `receive` function to receive the available message on `canch2`.

- 1 To see messages available to be received on this channel, type:

```
canch2
```

```
canch2 =
```

```
Channel with properties:
```

```

Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 2
    DeviceSerialNumber: 0
    ProtocolMode: 'CAN'

Status Information
    Running: 1
    MessagesAvailable: 1
    MessagesReceived: 0
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: 23-May-2019 15:43:40
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

Channel Information
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    BusSpeed: 250000
    SJW: []
    TSEG1: []
    TSEG2: []
    NumOfSamples: []

Other Information
    Database: []
    UserData: []

```

The channel status information indicates 1 for MessagesAvailable.

- 2 Receive one message on canch2 and assign it to messagein.

```
messagein = receive(canch2,1)
```

```
messagein =
```

```
Message with properties:
```

```
Message Identification
```

```
    ProtocolMode: 'CAN'
    ID: 500
    Extended: 0
    Name: ''
```

```
Data Details
```

```
    Timestamp: 0.0312
    Data: [25 0 0 0 0 0 0 0]
    Signals: []
    Length: 8
```

```
Protocol Flags
```

```
    Error: 0
```

```
Remote: 0
```

```
Other Information  
Database: []  
UserData: []
```

Note the received message `Data` property. This matches the data transmitted from `canch1`.

Refer to the `receive` function to understand more about its input arguments.

- 3 To check if the channel received the message, view the channel display.

```
canch2
```

```
canch2 =
```

```
Channel with properties:
```

```
Device Information
```

```
DeviceVendor: 'MathWorks'  
Device: 'Virtual 1'  
DeviceChannelIndex: 2  
DeviceSerialNumber: 0  
ProtocolMode: 'CAN'
```

```
Status Information
```

```
Running: 1  
MessagesAvailable: 0  
MessagesReceived: 1  
MessagesTransmitted: 0  
InitializationAccess: 1  
InitialTimestamp: 23-May-2019 15:43:40  
FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'
```

```
Channel Information
```

```
BusStatus: 'N/A'  
SilentMode: 0  
TransceiverName: 'N/A'  
TransceiverState: 'N/A'  
ReceiveErrorCount: 0  
TransmitErrorCount: 0  
BusSpeed: 250000  
SJW: []  
TSEG1: []  
TSEG2: []  
NumOfSamples: []
```

```
Other Information
```

```
Database: []  
UserData: []
```

The channel status information indicates 1 for `MessagesReceived`, and 0 for `MessagesAvailable`.

Unpack a Message

After your channel receives a message, specify how to unpack the message and interpret the data in the message. Use `unpack` to specify the parameters for unpacking a message; these should correspond to the parameters used for packing.

```
value = unpack(messagein,0,16,'LittleEndian','int16')
```

```
value =
    int16
     25
```

Refer to the `unpack` function to understand more about its input arguments.

Save and Load CAN Channels

You can save a CAN channel object to a file using the `save` function anytime during the CAN communication session.

To save `canch1` to the MATLAB file `mycanch.mat`, type:

```
save mycanch.mat canch1
```

If you have saved a CAN channel in a MATLAB file, you can load the channel into MATLAB using the `load` function. For example, to reload the channel from `mycanch.mat` which was created earlier, type:

```
load mycanch.mat
```

The loaded CAN channel object reconnects to the specified hardware and reconfigures itself to the specifications when the channel was saved.

Disconnect Channels and Clean Up

- “Disconnect the Configured Channels” on page 1-19
- “Clean Up the MATLAB Workspace” on page 1-20

Disconnect the Configured Channels

When you no longer need to communicate with your CAN bus, use the `stop` function to disconnect the CAN channels that you configured.

- 1 Stop the first channel.

```
stop(canch1)
```

- 2 Check the channel status.

```
canch1
```

```
:
:
```

```
.
  Status Information
      Running: 0
  MessagesAvailable: 1
  MessagesReceived: 0
  MessagesTransmitted: 1
```

- 3 Stop the second channel.

```
stop(canch2)
```

- 4 Check the channel status.

```
canch2
```

```
.
.
.
  Status Information
      Running: 0
  MessagesAvailable: 0
  MessagesReceived: 1
  MessagesTransmitted: 0
```

Clean Up the MATLAB Workspace

When you no longer need these objects and variables, remove them from the MATLAB workspace with the `clear` command.

- 1 Clear each channel.

```
clear canch1
clear canch2
```

- 2 Clear the CAN messages.

```
clear messageout
clear messagein
```

- 3 Clear the unpacked value.

```
clear value
```

See Also

Related Examples

- “Filter Messages” on page 1-21
- “Multiplex Signals” on page 1-22
- “Configure Silent Mode” on page 1-25

More About

- “MathWorks Virtual Channels” on page 1-6

Filter Messages

You can set up filters on your channel to accept messages based on the filtering parameters you specify. Set up your filters before putting your channel online. For more information on message filtering, see these functions:

- `filterAllowAll`
- `filterBlockAll`
- `filterAllowOnly`

To specify message names you want to filter, create a CAN channel and attach a database to the channel.

```
canch1 = canChannel('Vector', 'CANcaseXL 1', 1);  
canch1.Database = canDatabase('demoVNT_CANdbFiles.dbc');
```

Set a filter on the channel to allow only the message `EngineMsg`, and display the channel `FilterHistory` property.

```
filterAllowOnly(canch1, 'EngineMsg');  
canch1.FilterHistory
```

Standard ID Filter: Allow Only | Extended ID Filter: Allow All

When you start the channel and receive messages, only those marked `EngineMsg` pass through the filter.

For more information about using a message database, see “Message Database”.

See Also

Related Examples

- “Transmit and Receive CAN Messages” on page 1-10

Multiplex Signals

Use multiplexing to represent multiple signals in one signal's location in a CAN message's data. A multiplexed message can have three types of signals:

- **Standard signal** — This signal is always active. You can create one or more standard signals.
- **Multiplexor signal** — Also called the mode signal, it is always active and its value determines which multiplexed signal is currently active in the message data. You can create only one multiplexor signal per message.
- **Multiplexed signal** — This signal is active when its multiplex value matches the value of the multiplexor signal. You can create one or more multiplexed signals in a message.

Multiplexing works only with a CAN database with message definitions that already contain multiplex signal information. This example shows you how to access the different multiplex signals using a database constructed specifically for this purpose. This database has one message with these signals:

- SigA — A multiplexed signal with a multiplex value of 0.
- SigB — Another multiplexed signal with a multiplex value of 1.
- MuxSig — A multiplexor signal, whose value determines which of the two multiplexed signals are active in the message.

For example,

- 1 Create a CAN database.

```
d = canDatabase('Mux.dbc')
```

Note This is an example database constructed for creating multiplex messages. To try this example, use your own database.

- 2 Create a CAN message.

```
m = canMessage(d, 'Msg')
```

```
m =
```

```
can.Message handle
Package: can

Properties:
    ID: 250
    Extended: 0
    Name: 'Msg'
    Database: [1x1 can.Database]
    Error: 0
    Remote: 0
    Timestamp: 0
    Data: [0 0 0 0 0 0 0 0]
    Signals: [1x1 struct]
```

```
Methods, Events, Superclasses
```

- 3 To display the signals, type:

```
m.Signals
```



```
ans =
    SigB: 0
    SigA: 0
    MuxSig: 0
```

MuxSig is the multiplexor signal, whose value determines which of the two multiplexed signals are active in the message. **SigA** and **SigB** are the multiplexed signals that are active in the message if their multiplex values match **MuxSig**. In the example shown, **SigA** is active because its current multiplex value of 0 matches the value of **MuxSig** (which is 0).

- 4 If you want to make **SigB** active, change the value of the **MuxSig** to 1.

```
m.Signals.MuxSig = 1
```

To display the signals, type:

```
m.Signals
ans =
    SigB: 0
    SigA: 0
    MuxSig: 1
```

SigB is now active because its multiplex value of 1 matches the current value of **MuxSig** (which is 1).

- 5 Change the value of **MuxSig** to 2.

```
m.Signals.MuxSig = 2
```

Here, neither of the multiplexed signals are active because the current value of **MuxSig** does not match the multiplex value of either **SigA** or **SigB**.

```
m.Signals
ans =
    SigB: 0
    SigA: 0
    MuxSig: 2
```

Always check the value of the multiplexor signal before using a multiplexed signal value.

```
if (m.Signals.MuxSig == 0)
% Feel free to use the value of SigA however is required.
end
```

This ensures that you are not using an invalid value, because the toolbox does not prevent or protect reading or writing inactive multiplexed signals.

Note You can access both active and inactive multiplexed signals, regardless of the value of the multiplexor signal.

Refer to the `canMessage` function to learn more about creating messages.

See Also

Related Examples

- “Transmit and Receive CAN Messages” on page 1-10

Configure Silent Mode

The `SilentMode` property of a CAN channel specifies that the channel can only receive messages and not transmit them. Use this property to observe all message activity on the network and perform analysis without affecting the network state or behavior.

- 1 Change the `SilentMode` property of the first CAN channel, `canch1` to `true`.

```
canch.SilentMode = true
```

- 2 To see the changed property value, type:

```
canch1.SilentMode
```

```
ans =
```

```
1
```

See Also

Functions

`canChannel`

Properties

`can.Channel` Properties

Related Examples

- “Transmit and Receive CAN Messages” on page 1-10

Hardware Support Package Installation

Install Hardware Support Package for Device Driver

In this section...

“Install Support Packages” on page 2-2
--

“Update or Uninstall Support Packages” on page 2-2
--

To communicate with a CAN device, you must install the required driver on your system.

The drivers are available in the support packages for the following vendors:

- National Instruments (NI-XNET CAN)
- Kvaser
- Vector
- PEAK-System

Note For deployed applications, the target machine also needs the appropriate drivers installed. If the target machine does not have MATLAB on it, you must install the vendor drivers manually.

Install Support Packages

To install the support package for the required driver:

- 1 On the MATLAB **Home** tab, in the **Environment** section, click **Add-Ons > Get Hardware Support Packages**.
- 2 In the left pane of the Add-On Explorer, scroll to **Filter by Type** and check **Hardware Support Packages**.
- 3 Under **Filter by Hardware Type** check **CAN Devices**. The Add-On Explorer displays all the support packages for the supported vendors of CAN devices. Click the support package for your device vendor.
- 4 Click **Install > Install**. Sign in to your MathWorks account if necessary, and proceed.

Update or Uninstall Support Packages

To uninstall support packages:

On the MATLAB **Home** tab, in the **Environment** section, click **Add-Ons > Manage Add-Ons**.

To update existing support packages:

On the MATLAB **Home** tab, in the **Environment** section, click **Add-Ons > Check for Updates > Hardware Support Packages**.

See Also

More About

- “Get and Manage Add-Ons”

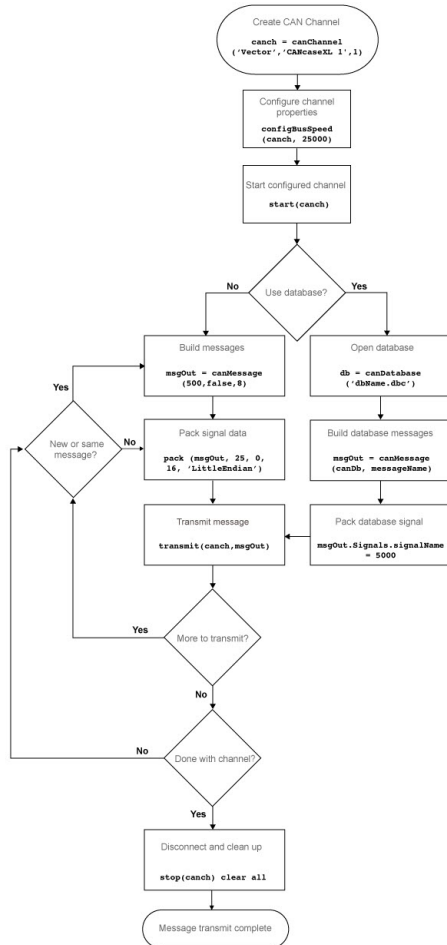
- “Vendor Limitations”

CAN Communication Workflows

- “CAN Transmit Workflow” on page 3-2
- “CAN Receive Workflow” on page 3-3

CAN Transmit Workflow

This workflow helps you create a CAN channel and transmit messages.



See Also

Functions

canChannel | canDatabase | canMessage | canMessageImport | configBusSpeed | pack | start | stop | transmit | transmitConfiguration | transmitEvent | transmitPeriodic

Properties

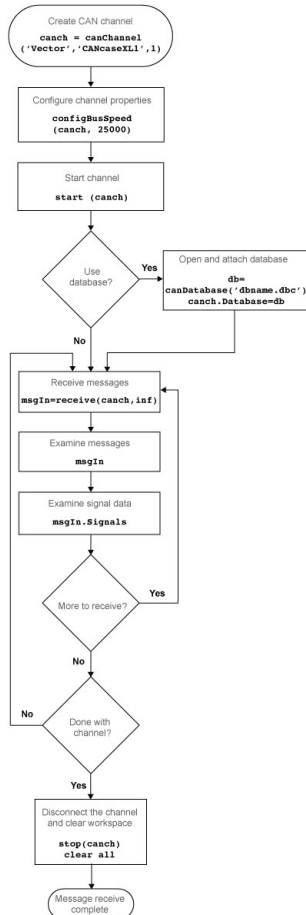
can.Channel Properties | can.Message Properties

Blocks

CAN Pack | CAN Replay | CAN Transmit

CAN Receive Workflow

Use this workflow to receive and unpack CAN messages.



See Also

Functions

attachDatabase | canDatabase | configBusspeed | extractAll | extractRecent | extractTime | receive | stop | unpack

Properties

can.Channel Properties | can.Message Properties

Blocks

CAN Log | CAN Receive | CAN Unpack

Using a CAN Database

- “Load .dbc Files and Create Messages” on page 4-2
- “View Message Information in a CAN Database” on page 4-5
- “View Signal Information in a CAN Message” on page 4-7
- “Attach a CAN Database to Existing Messages” on page 4-8

Load .dbc Files and Create Messages

In this section...

“Vector CAN Database Support” on page 4-2

“Load the CAN Database” on page 4-2

“Create a CAN Message” on page 4-2

“Access Signals in the Constructed CAN Message” on page 4-3

“Add a Database to a CAN Channel” on page 4-3

“Update Database Information” on page 4-3

Vector CAN Database Support

Vehicle Network Toolbox allows you to use a Vector CAN database. The database .dbc file contains definitions of CAN messages and signals. Using the information defined in the database file, you can look up message and signal information, and build messages. You can also represent message and signal information in engineering units so that you do not need to manipulate raw data bytes.

Load the CAN Database

To use a CAN database file, load the database into your MATLAB session. At the MATLAB command prompt, type:

```
db = canDatabase('filename.dbc')
```

Here *db* is a variable you chose for your database handle and *filename.dbc* is the actual file name of your CAN database. If your CAN database is not in the current working directory, type the path to the database:

```
db = canDatabase('path\filename.dbc')
```

Tip CAN database file names containing non-alphanumeric characters such as equal signs, ampersands, and so forth are incompatible with Vehicle Network Toolbox. You can use periods in your database name. Rename any CAN database files with non-alphanumeric characters before you use them.

This command returns a database object that you can use to create and interpret CAN messages using information stored in the database. Refer to the `canDatabase` function for more information.

Create a CAN Message

This example shows you how to create a message using a database constructed specifically for this example. You can access this database in the **Toolbox > VNT > VNTDemos** subfolder in your MATLAB installation folder. This database has a message, `EngineMsg`. To try this example, create messages and signals using definitions in your own database.

- 1 Create the CAN database object.

```
cd ([matlabroot '\examples\vnt'])  
d = canDatabase('demoVNT_CANdbFiles.dbc');
```

- 2 Create a CAN message using the message name in the database.

```
message = canMessage(d, 'EngineMsg');
```

Access Signals in the Constructed CAN Message

You can access the two signals defined for the message you created in the example database, `message`. You can also change the values for some signals.

- 1 To display signals in your message, type:

```
sig = message.Signals
sig =
    struct with fields:
        VehicleSpeed: 0
        EngineRPM: 250
```

- 2 Change the value of the EngineRPM signal:

```
message.Signals.EngineRPM = 300;
```

- 3 Reassign the signals and display them again to see the change.

```
sig = message.Signals
sig =
    struct with fields:
        VehicleSpeed: 0
        EngineRPM: 300
```

Add a Database to a CAN Channel

To add a database to the CAN channel `canch`, type:

```
canch.Database = canDatabase('Mux.dbc')
```

Update Database Information

When you make changes to a database file:

- 1 Reload the database file into your MATLAB session using the `canDatabase` function.
- 2 Reattach the database to messages using the `attachDatabase` function.

See Also

Functions

`canDatabase`

Properties

`can.Database` Properties

Related Examples

- “Create and Process Messages Using Database Definitions” on page 16-23

More About

- “View Message Information in a CAN Database” on page 4-5
- “View Signal Information in a CAN Message” on page 4-7
- “Attach a CAN Database to Existing Messages” on page 4-8

View Message Information in a CAN Database

You can look up information on message definitions by a single message by name, or a single message by ID. You can also look up information on all message definitions in the database by typing:

```
msgInfo = messageInfo(database name)
```

This returns the message structure of information about messages in the database. For example:

```
msgInfo = messageInfo(db)
```

```
msgInfo =
```

```
5x1 struct array with fields:
```

```
    Name
    Comment
    ID
    Extended
    Length
    Signals
```

To get information on a single message by message name, type:

```
msgInfo = messageInfo(database name, 'message name')
```

This returns information about the message as defined in the database. For example:

```
msgInfo = messageInfo(db, 'EngineMsg')
```

```
msgInfo =
```

```
    Name: 'EngineMsg'
    Comment: ''
    ID: 100
    Extended: 0
    Length: 8
    Signals: {2x1 cell}
```

Here the function returns information about message with name `EngineMsg` in the database `db`. You can also use the message ID to get information about a message. For example, to view the example message given here by inputting the message ID, type:

```
msgInfo = messageInfo(db, 100, false)
```

This command provides the database name, the message ID, and a Boolean value for the extended value of the ID.

See Also

Functions

`messageInfo`

More About

- “Load .dbc Files and Create Messages” on page 4-2

- “View Signal Information in a CAN Message” on page 4-7
- “Attach a CAN Database to Existing Messages” on page 4-8

View Signal Information in a CAN Message

You can get signal definition information on a specific signal or all signals in a CAN message with database definitions attached. Provide the message name or the ID as a parameter in the command:

```
sigInfo = signalInfo(db, 'EngineMsg')
```

You can also get information about a specific signal by providing the signal name:

```
sigInfo = signalInfo(db, 'EngineMsg', 'EngineRPM')
```

To learn how to use this property and work with the database, see the `signalInfo` function.

You can also access the `Signals` property of the message to view physical signal information. When you create physical signals using database information, you can directly write to and read from these signals to pack or unpack data from the message. When you write directly to the signal name, the value is translated, scaled, and packed into the message data.

See Also

Functions

`signalInfo`

More About

- “Load .dbc Files and Create Messages” on page 4-2
- “View Message Information in a CAN Database” on page 4-5
- “Attach a CAN Database to Existing Messages” on page 4-8

Attach a CAN Database to Existing Messages

You can attach a .dbc file to messages and apply the message definition defined in the database. Attaching a database allows you to view the messages in their physical form and use a signal-based interaction with the message data.

To attach a database to a message, type:

```
attachDatabase(message name, database name)
```

Note If your message is an array, all messages in the array are associated with the database that you attach.

You can also dissociate a message from a database so that you can view the message in its raw form. To clear the attached database from a message, type:

```
attachDatabase(message name, [])
```

Note The database gets attached even if the database does not find the specified message. Even though the database is still attached to the message, the message is displayed in its raw mode.

See Also

Functions

attachDatabase

More About

- “Load .dbc Files and Create Messages” on page 4-2
- “View Message Information in a CAN Database” on page 4-5
- “View Signal Information in a CAN Message” on page 4-7

Monitoring Vehicle CAN Bus

- “Vehicle CAN Bus Monitor” on page 5-2
- “Using the Vehicle CAN Bus Monitor” on page 5-7

Vehicle CAN Bus Monitor

In this section...
“About the Vehicle CAN Bus Monitor” on page 5-2
“Opening the Vehicle CAN Bus Monitor” on page 5-2
“Vehicle CAN Bus Monitor Fields” on page 5-2

About the Vehicle CAN Bus Monitor

Vehicle Network Toolbox provides a graphical user interface that monitors CAN bus traffic on selected channels. Using the CAN Bus Monitor you can:

- View live CAN message data.
- Configure connection to the CAN bus.
- View unique messages.
- Attach a database to view signal information.
- Save the messages to a log file.

You cannot programmatically configure the Vehicle CAN Bus Monitor. However, you can use it to independently visualize bus traffic generated on CAN channels by MATLAB or Simulink CAN blocks.

Opening the Vehicle CAN Bus Monitor

To open the Vehicle CAN Bus Monitor, type `canTool` in the MATLAB Command Window.

Vehicle CAN Bus Monitor Fields

The Vehicle CAN Bus Monitor has the following menus, buttons and table.

The screenshot shows the Vehicle CAN Bus Monitor application window. The window title is "File Configure Run View Help". Below the title bar is a toolbar with icons for play, pause, stop, refresh, and help. The main area contains a table with the following columns: Timestamp, ID, Name, Length, and Data. The table lists 30 captured messages, with the first message selected (highlighted in blue). The messages alternate between ID 4B1 and 201, all with a length of 8 bytes. The data field shows hexadecimal values for each message.

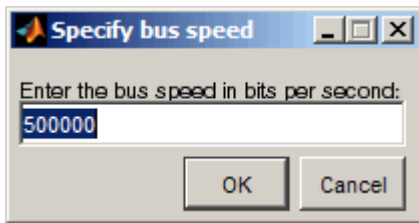
Timestamp	ID	Name	Length	Data
49.271169	4B1		8	4C 08 4B 0E 4D 02 ...
49.266196	201		8	17 A7 00 00 00 00 8...
49.171186	4B1		8	4C 08 4B 0E 4D 02 ...
49.166148	201		8	17 A7 00 00 00 00 8...
49.071145	4B1		8	69 00 67 13 6A ED 6...
49.066181	201		8	43 7E 00 00 00 00 A...
48.971186	4B1		8	4C 08 4B 0E 4D 02 ...
48.966132	201		8	49 5B 00 00 00 00 1...
48.871334	4B1		8	45 E7 44 18 47 B6 4...
48.866132	201		8	43 9D 00 00 00 00 1...
48.771129	4B1		8	4C 08 4B 0E 4D 02 ...
48.766140	201		8	4C 24 00 00 00 00 9...
48.671171	4B1		8	4C 08 4B 0E 4D 02 ...
48.666116	201		8	55 D0 00 00 00 00 9...
48.571138	4B1		8	4C 08 4B 0E 4D 02 ...
48.566133	201		8	55 D0 00 00 00 00 5...
48.471114	4B1		8	4C 08 4B 0E 4D 02 ...
48.466117	201		8	21 F0 00 00 00 00 A...
48.371122	4B1		8	03 0B 01 75 04 A1 F...
48.366133	201		8	25 D3 00 00 00 00 6...
48.271106	4B1		8	0B 05 09 68 0C A2 ...
48.266109	201		8	59 69 00 00 00 00 3...
48.171172	4B1		8	0B 05 09 68 0C A2 ...
48.166109	201		8	59 69 00 00 00 00 3...
48.071148	4B1		8	2F 22 2D 66 30 DD ...
48.066101	201		8	30 F7 00 00 00 00 5...
47.971115	4B1		8	0B 8C 09 EF 0D 2A ...

File Menu

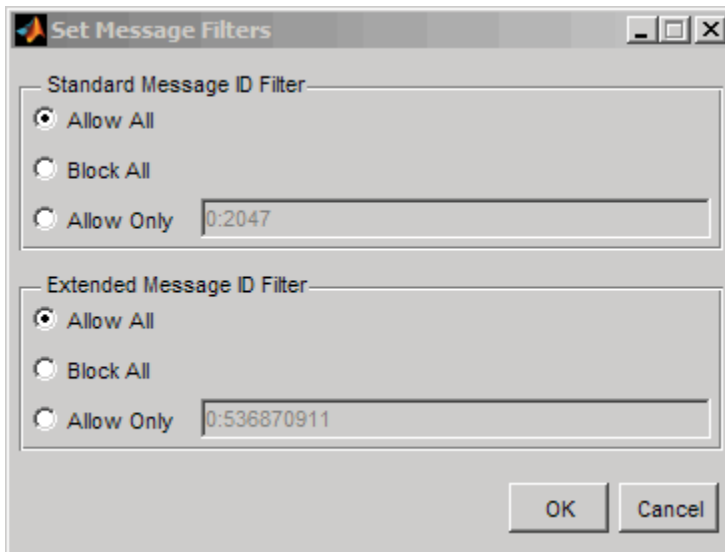
- **Save Messages** — Saves messages to a log file.
- **Clear Messages** — Clears messages in the Vehicle CAN Bus Monitor window.
- **Exit** — Click to exit the Vehicle CAN Bus Monitor.

Configure Menu

- **Channel** — Displays all available CAN devices and channels on your system. Select the CAN channel to monitor.
- **Bus Speed** — Opens the Specified bus speed dialog box. To change the bus speed of the selected channel, type the new value in bits per second in the box.



- **Message Filters** — Opens the Set Message Filters dialog box. Select an option in the dialog box to configure hardware filters to block or allow messages.



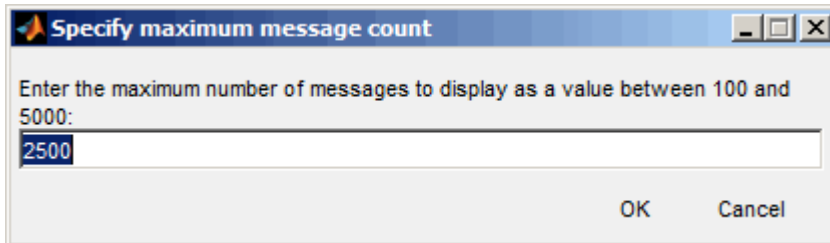
- Standard Message ID Filter
 - Allow All — Select to allow all standard ID messages.
 - Block All — Select to block all standard ID messages.
 - Allow only — Select to set up custom filtering of messages. Type the standard message IDs that you want to allow.
- Extended Message ID Filter
 - Allow All — Select to allow all extended ID messages.
 - Block All — Select to block all extended ID messages.
 - Allow only — Select to set up custom filtering of messages. Type the extended message IDs that you want to allow.
- **Database** — Selects the database to attach to the CAN messages on the selected channel.

Run Menu

- **Start** — Click to view message activity on the selected channel.
- **Pause** — Click to pause the display of message activity on the selected channel.
- **Stop** — Click to stop the display of message activity on the selected channel.

View Menu

- **Maximum message count** — Opens the Specify maximum message count dialog box. To change the maximum number of messages displayed at a time in the Vehicle CAN Bus Monitor, type the new value in the box.



- **Number Format** — Select the number format to display message identifier data. Choose **Hexadecimal** or **Decimal**.
- **Show Unique Messages** — Select this option to display the most recent instance of each message received on the selected channel. If you select this option, the tool displays a simplified version of the message traffic. In this view, messages do not scroll up, but each message refreshes its data with each timestamp. If you do not select this option, the tool displays all instances of all messages in the order that the selected channel receives them.

Help Menu

- **Documentation** — Select this option to see the documentation for the Vehicle CAN Bus Monitor.
- **About Vehicle Network Toolbox** — Select this option to view the toolbox version and release information.

Buttons

Start

Displays message activity on the selected channel.

Pause

Pauses the display of message activity on the selected channel.

Stop

Stops displaying messages on the selected channel.

Save messages

Click this button to save the current message list on the selected channel to a file.

Clear messages

Click this button to clear messages in the Vehicle CAN Bus Monitor window.

Show unique messages

Select this option to display the most recent instance of each message received on the selected channel. If you select this option, the tool displays a simplified version of the message traffic. In this view, messages do not scroll up, but each message refreshes its data with each timestamp. If

you do not select this option the tool displays all instances of all messages in the order that the selected channel receives them.

Docking

Click this button to dock the Vehicle CAN Bus Monitor to the MATLAB desktop. To undock, click



Undocking

Click this button to undock the Vehicle CAN Bus Monitor from the MATLAB desktop. To dock,

click .

Message Table

Timestamp

Displays the time, relative to the start time, that the device receives the message. The start time begins at 0 when you click **Start**.

ID

Displays the message ID. This field displays a number in hexadecimal format for the ID and:

- Displays numbers only for standard IDs.
- Appends an **x** for an extended ID.
- Displays an **r** for a remote frame.
- Displays **error** for messages with error frames.

To change the format to decimal, select **View > Number Format > Decimal**.

Name

Displays the name of the message, if available.

Length

Displays the length of the message in bytes.

Data

Displays the data in the message in hexadecimal format.

To change the format to decimal, select **View > Number Format > Decimal**.

If you are using a database on page 5-8, click the + sign to see signal information. The tool displays the signal name and the physical value of the message, as defined in the attached database.

See Also

More About

- “Using the Vehicle CAN Bus Monitor” on page 5-7

Using the Vehicle CAN Bus Monitor

In this section...

- “View Messages on a Channel” on page 5-7
- “Configure the Channel Bus Speed” on page 5-7
- “Filter CAN Messages in Vehicle CAN Bus Monitor” on page 5-7
- “Attach a Database” on page 5-8
- “Change the Message Count” on page 5-10
- “Change the Number Format” on page 5-10
- “View Unique Messages” on page 5-10
- “Save the Message Log File” on page 5-10

View Messages on a Channel

- 1 Open the Vehicle CAN Bus Monitor and select the device and channel connected to your CAN bus by selecting **Configure > Channel**.
- 2 The Vehicle CAN Bus Monitor defaults to the bus speed set in the device driver. You can also configure a new bus speed. See Configuring the Channel Bus Speed on page 5-7
- 3 Click **Start**, or select **Run > Start**.
- 4 To pause the display, click **Pause** or select **Run > Pause**.
- 5 To stop the display, click **Stop** or select **Run > Stop**.

Configure the Channel Bus Speed

Configure the bus speed when your network speed differs from the default value of the channel. You require initialization access for the channel to configure the bus speed.

To configure a new bus speed:

- 1 Select **Configure > Bus Speed**.
- 2 Type the desired value in the Specify bus speed dialog box.
- 3 Click **OK**.

The value you set takes effect once you start the CAN channel. If an error occurs when applying the new bus speed, the value reverts to the default value specified in the hardware.

Filter CAN Messages in Vehicle CAN Bus Monitor

Filter CAN messages to allow or block messages displayed in the Vehicle CAN Bus Monitor.

To set up filters:

- 1 Select **Configure > Message Filters**.
- 2 To set filters on standard message IDs, select:
 - a Allow All to set the hardware filter to allow all messages with standard IDs.

- b** Block All to set the hardware filter to block all messages with standard IDs.
 - c** Allow Only to set up custom filters. Type the standard IDs of the message you want to filter. You can type a range or single IDs. The default is 0:2047.
- 3** To set filters on extended message IDs, select:
 - a** Allow All to set the hardware filter to allow all messages extended IDs.
 - b** Block All to set the hardware filter to block all messages extended IDs.
 - c** Allow Only to set up custom filters. Type the extended IDs of the message you want to filter. You can type a range or single IDs. The default is 0:536870911.

Note If you are using a custom filter, change the default range to the desired range. The default range allows all messages and you should select Allow All to allow all incoming messages with extended IDs.

- 4** Click OK.

Attach a Database

Attach a database to the Vehicle CAN Bus Monitor to see signal information of the displayed messages.

- 1** Select **Run > Stop** to stop the message display in the Vehicle CAN Bus Monitor.
- 2** Select **Configure > Database**.
- 3** Select the database to attach and start the message display again.

When the tool displays the messages, it shows the message name in the Message table.

Timestamp	ID	Name	Length	Data
4.987068	1F4	TestMessage	4	54 6C 45 32
4.986069	1F4	TestMessage	4	AE B4 71 05
4.985070	1F4	TestMessage	4	AF 5C BC 65
4.983955	1F4	TestMessage	4	0B C1 3E 71
4.982890	1F4	TestMessage	4	59 26 95 43
4.981916	2EE		8	86 87 DC 7C 64 AB ...
4.980810	1F4	TestMessage	4	31 23 B2 18
4.979761	1F4	TestMessage	4	A0 C5 EE F8
4.978688	1F4	TestMessage	4	67 72 5D C3
4.977656	1F4	TestMessage	4	38 1B 1C 10
4.976542	2EE		8	7A A3 8B A5 8B B8 8...
4.975444	1F4	TestMessage	4	51 1E F0 A5
4.974363	1F4	TestMessage	4	94 8A DE 44
4.974068	1F4	TestMessage	4	D7 D4 41 9C
4.972282	1F4	TestMessage	4	C4 59 A9 6A
4.971323	2EE		8	35 B5 3C 1E 9B 73 7...
4.970226	1F4	TestMessage	4	A5 AD A2 F1
4.969202	1F4	TestMessage	4	AE 8B 6D A4
4.968161	1F4	TestMessage	4	30 49 17 93
4.967129	1F4	TestMessage	4	3E EA 45 C3
4.966171	2EE		8	2D B8 79 27 57 9B 3...
4.965073	1F4	TestMessage	4	52 C8 78 09
4.964065	1F4	TestMessage	4	76 6C 76 C4
4.963009	1F4	TestMessage	4	9A 63 EA 00
4.962066	1F4	TestMessage	4	58 C7 AC 02
4.961010	2EE		8	4A AB B1 11 41 39 A...
4.959896	1F4	TestMessage	4	A3 F4 3D AC
4.959068	1F4	TestMessage	4	75 DF 84 F1

- 4 Click the plus (+) sign to see the details of the message.

+	4.987068	1F4	TestMessage	4	54 6C 45 32
-	4.986069	1F4	TestMessage	4	AE B4 71 05
		Signal Name	Physical Value		
		Sig1	174.000000		
		Sig2	180.000000		
		Sig3	113.000000		
		Sig4	5.000000		

The tool displays the signal name as defined in the attached database and the signal's physical value.

Change the Message Count


You can change the maximum number of messages displayed to a value from 100 through 5000.

- 1 Select **View > Maximum Message Count**.
- 2 In the Specify maximum message count dialog box, type the number of messages you want displayed at one time.
- 3 Click **OK**.

Change the Number Format

By default the message data is displayed in hexadecimal format. To change the display to decimal format, select **View > Number Format > Decimal**.

View Unique Messages

To view the most recent instance of each unique message received on the channel, select **View > Show Unique Messages**. In this view, you do not see messages scroll up, but each message refreshes its data and timestamp with each new instance. You can also click .

Timestamp	ID	Name	Length	Data
6.372729	4B1		8	69 11 67 FE 6A 23 66...
6.367724	201		8	5C DF 00 00 00 00 2...


Use this feature to get a snapshot of message IDs that the selected channel receives. Use this information to analyze specific messages.

When you select **Show Unique Messages**, the tool continues to receive message actively. This simplified view allows you to focus on specific messages and analyze them.

To save messages when **Show Unique Messages** is selected, click **Pause** and then click **Save**. You cannot save just the unique message list. This operation saves the complete message log in the window.

Save the Message Log File

You can save a log file of the messages currently displayed. If running, you need to stop or pause the display before saving a log file.

To save a log file of the messages currently displayed in the window, select **File > Save Messages** or click .

The tool saves the messages in a MATLAB file in your current working folder by default. You can change the location by browsing to a different folder in the Save dialog box.

Each time you save the message log to a file, the Vehicle CAN Bus Monitor saves them as `VNT_CAN_Log.mat` with sequential numbering by default. You can change the name by typing a new name in Save dialog box.

See Also

More About

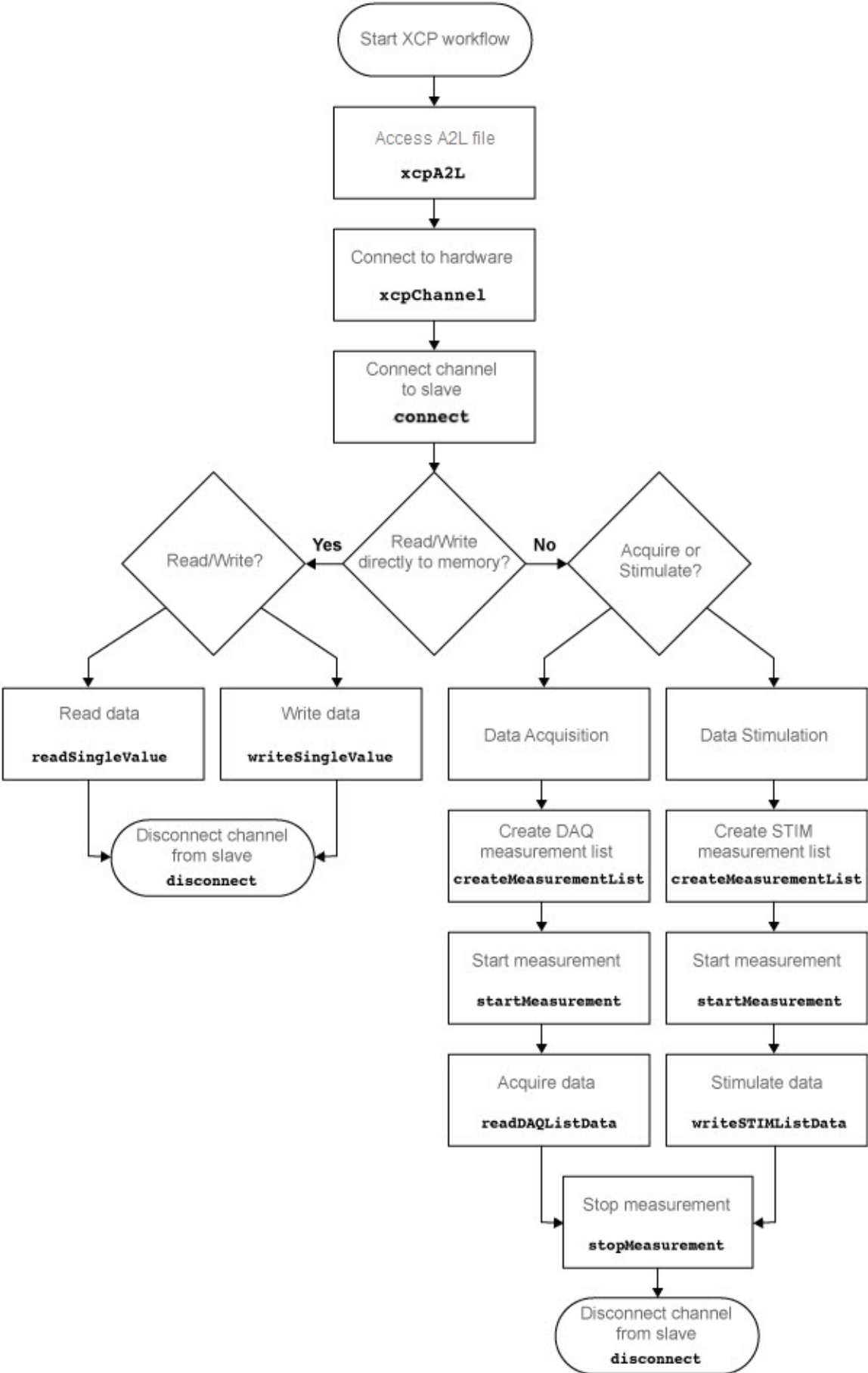
- “Vehicle CAN Bus Monitor” on page 5-2

XCP Communication Workflows

XCP Database and Communication Workflow

This workflow helps you:

- Manage an A2L database
- Connect to an XCP device
- Create an XCP channel
- Acquire and stimulate data
- Read and write to memory



See Also

Functions

[connect](#) | [createMeasurementList](#) | [disconnect](#) | [freeMeasurementLists](#) | [getEventInfo](#) | [getMeasurementInfo](#) | [isConnected](#) | [isMeasurementRunning](#) | [readDAQListData](#) | [readSingleValue](#) | [startMeasurement](#) | [stopMeasurement](#) | [viewMeasurementLists](#) | [writeSTIMListData](#) | [writeSingleValue](#) | [xcpA2L](#) | [xcpChannel](#)

Properties

[xcp.A2L Properties](#) | [xcp.Channel Properties](#)

Blocks

[XCP CAN Configuration](#) | [XCP CAN Data Acquisition](#) | [XCP CAN Data Stimulation](#) | [XCP CAN Transport Layer](#) | [XCP UDP Configuration](#) | [XCP UDP Data Acquisition](#) | [XCP UDP Data Stimulation](#)

A2L File

Inspect the Contents of an A2L File

In this section...

“Access an A2L File” on page 7-2
 “Access Measurement Information” on page 7-2
 “Access Event Information” on page 7-3

Access an A2L File

To use an A2L file, create a file object in your MATLAB session. At the Command Window prompt, type:

```
a2lfile = xcpA2L('filename.a2l')
```

Here `a2lfile` is a variable assigned with the A2L object, and `filename.a2l` is the name of your A2L file. If your A2L file is not in the current working directory, specify the necessary partial or full path to the file:

```
a2lfile = xcpA2L('path\filename.a2l');
```

Tip A2L file names containing non-alphanumeric characters such as equal signs or ampersands are not supported. You can use periods in your database name. Rename any A2L files with non-alphanumeric characters before you use them.

This command returns an A2L object that you can use for live communication with a slave module using XCP channels.

Access Measurement Information

This example shows how to open an A2L file and access measurement information.

Open an A2L file:

```
a2lfile = xcpA2L('XCPSIM.a2l');
```

Display properties of the A2L object:

```
a2lfile
```

```
A2L with properties:
```

```

    FileName: 'XCPSIM.a2l'
    FilePath: 'C:\work\XCPSIM.a2l'
    SlaveName: 'CPP'
    ProtocolLayerInfo: [1x1 xcp.ProtocolLayerInfo]
    DAQInfo: [1x1 xcp.DAQInfo]
    TransportLayerCANInfo: [1x1 xcp.TransportLayerCANInfo]
    TransportLayerUDPInfo: [1x1 xcp.TransportLayerUDPInfo]
    TransportLayerTCPInfo: []
    Events: {'Key T' '10 ms' '100ms' '1ms' 'FilterBypassDaq' 'FilterBypassSt'}
    Measurements: {1x45 cell}
    Characteristics: {1x16 cell}
    EventInfo: [1x6 xcp.Event]
    MeasurementInfo: [45x1 containers.Map]
    CharacteristicInfo: [16x1 containers.Map]
    AxisInfo: [1x1 containers.Map]

```

```
RecordLayouts: [41x1 containers.Map]
CompuMethods: [16x1 containers.Map]
CompuTabs: [0x1 containers.Map]
CompuVTabs: [2x1 containers.Map]
```

View all available measurements:

a2lfile.Measurements

ans =

```
1x45 cell array
Columns 1 through 6
    {'BitSlice'}    {'BitSlice0'}    {'BitSlice1'}    {'BitSlice2'}    {'Counter_B4'}    {'Counter_B5'}
Columns 7 through 12
    {'Counter_B6'}    {'Counter_B7'}    {'DtChannel1'}    {'FW1'}    {'KL10output'}    {'MaxChannel1'}
Columns 13 through 18
    {'MinChannel1'}    {'PWM'}    {'PWMFiltered'}    {'PWM_Level'}    {'ShiftByte'}    {'Shifter_B0'}
Columns 19 through 24
    {'Shifter_B1'}    {'Shifter_B2'}    {'Shifter_B3'}    {'TestStatus'}    {'Triangle'}    {'ampl'}
Columns 25 through 31
    {'bit12Counter'}    {'byte1'}    {'byte2'}    {'byte3'}    {'byte4'}    {'byteCounter'}    {'bytePWMFilter'}
Columns 32 through 37
    {'channel1'}    {'channel2'}    {'channel3'}    {'dwordCounter'}    {'limit'}    {'map1InputX'}
Columns 38 through 44
    {'map1InputY'}    {'map10output'}    {'offset'}    {'period'}    {'sbytePWMLLevel'}    {'v'}    {'vin'}
Column 45
    {'wordCounter'}
```

Get information about the 'Triangle' measurement:

```
getMeasurementInfo(a2lfile,'Triangle')
```

ans =

Measurement with properties:

```
Resolution: 0
Accuracy: 0
LocDataType: 'SBYTE'
Layout: 'ROW_DIR'
Name: 'Triangle'
LongIdentifier: 'Triangle test signal used for PWM output PWM'
ECUAddress: 4951377
ECUAddressExtension: 0
Conversion: [1x1 xcp.CompuMethodRational]
Dimension: 1
LowerLimit: -50
UpperLimit: 50
BitMask: []
```

Access Event Information

This example shows how to open an A2L file and access event information.

Open an A2L file:

```
a2lfile = xcpA2L('XCPSIM.a2l');
```

Display properties of the A2L object:

```
a2lfile
```

```
A2L with properties:
```

```

    FileName: 'XCPSIM.a2l'
    FilePath: 'C:\work\XCPSIM.a2l'
    SlaveName: 'CPP'
    ProtocolLayerInfo: [1x1 xcp.ProtocolLayerInfo]
    DAQInfo: [1x1 xcp.DAQInfo]
    TransportLayerCANInfo: [1x1 xcp.TransportLayerCANInfo]
    TransportLayerUDPInfo: [1x1 xcp.TransportLayerUDPInfo]
    TransportLayerTCPInfo: []
    Events: {'Key T' '10 ms' '100ms' '1ms' 'FilterBypassDaq' 'FilterBypassSt'}
    Measurements: {1x45 cell}
    Characteristics: {1x16 cell}
    EventInfo: [1x6 xcp.Event]
    MeasurementInfo: [45x1 containers.Map]
    CharacteristicInfo: [16x1 containers.Map]
    AxisInfo: [1x1 containers.Map]
    RecordLayouts: [41x1 containers.Map]
    CompuMethods: [16x1 containers.Map]
    CompuTabs: [0x1 containers.Map]
    CompuVTabs: [2x1 containers.Map]

```

View all available events:

```
a2lfile.Events
```

```
ans =
```

```
'Key T' '10 ms' '100ms' '1ms' 'FilterBypassDaq' 'FilterBypassSt'
```

Get information for the '10 ms' event:

```
getEventInfo(a2lfile,'10 ms')
```

```
ans =
```

```

    Name: '10 ms'
    Direction: 'DAQ_STIM'
    MaxDAQList: 255
    ChannelNumber: 1
    ChannelTimeCycle: 10
    ChannelTimeUnit: 6
    ChannelPriority: 0
    ChannelTimeCycleInSeconds: 0.0100

```

See Also

Functions

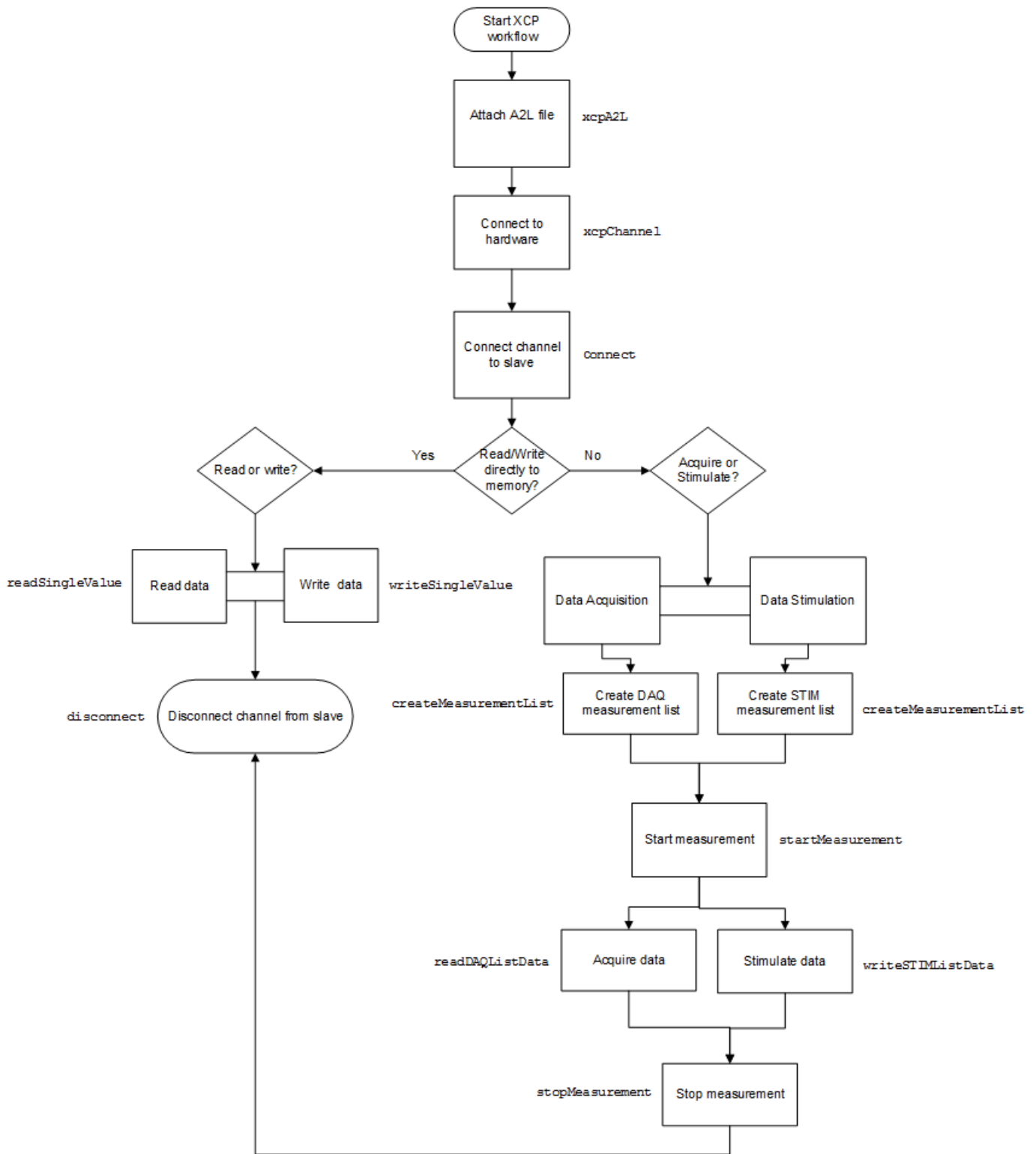
getEventInfo | getMeasurementInfo | xcpA2L

Universal Measurement & Calibration Protocol (XCP)

- “XCP Hardware Connection” on page 8-2
- “Read a Single Value” on page 8-6
- “Write a Single Value” on page 8-7
- “Read a Calibrated Measurement” on page 8-8
- “Acquire Measurement Data via Dynamic DAQ Lists” on page 8-9
- “Stimulate Measurement Data via Dynamic STIM Lists” on page 8-10

XCP Hardware Connection

You can connect your XCP master to a slave module using the CAN protocol. This allows you to use events and access measurements on the slave module.



Create XCP Channel Using CAN Device

This example shows how to create an XCP CAN channel connection and access channel properties. The example also shows how to unlock the slave using seed key security.

Access an A2L file that describes the slave module.

```
a2lfile = xcpA2L('C:\work\XCPSIM.a2l')
a2lfile =
  A2L with properties:
      FileName: 'XCPSIM.a2l'
      FilePath: 'C:\work\XCPSIM.a2l'
      SlaveName: 'CPP'
      ProtocolLayerInfo: [1x1 xcp.ProtocolLayerInfo]
      DAQInfo: [1x1 xcp.DAQInfo]
      TransportLayerCANInfo: [1x1 xcp.TransportLayerCANInfo]
      TransportLayerUDPInfo: [1x1 xcp.TransportLayerUDPInfo]
      TransportLayerTCPInfo: []
      Events: {'Key T' '10 ms' '100ms' '1ms' 'FilterBypassDaq' 'FilterBypassSt'}
      Measurements: {1x45 cell}
      Characteristics: {1x16 cell}
      EventInfo: [1x6 xcp.Event]
      MeasurementInfo: [45x1 containers.Map]
      CharacteristicInfo: [16x1 containers.Map]
      AxisInfo: [1x1 containers.Map]
      RecordLayouts: [41x1 containers.Map]
      CompuMethods: [16x1 containers.Map]
      CompuTabs: [0x1 containers.Map]
      CompuVTabs: [2x1 containers.Map]
```

Create an XCP channel using Vector virtual CAN channel 1.

```
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1)
```

```
xcpch =
  Channel with properties:
      SlaveName: 'CPP'
      A2LFileName: 'XCPSIM.a2l'
      TransportLayer: 'CAN'
      TransportLayerDevice: [1x1 struct]
      SeedKeyDLL: []
```

Configure the Channel to Unlock the Slave

This example shows how to configure the channel to unlock the slave using a dll that contains a seed and key security algorithm when your module is locked for Stimulation operations.

Create your XCP channel and set the channel SeedKeyDLL property.

```
xcpch.SeedKeyDLL = ('C:\work\SeedNKeyXcp.dll')
xcpch =
```

```
Channel with properties:
      SlaveName: 'CPP'
      A2LFileName: 'XCPSIM.a2l'
      TransportLayer: 'CAN'
```

```
TransportLayerDevice: [1x1 struct]
  SeedKeyDLL: 'C:\work\SeedNKeyXcp.dll'
```

Read a Single Value

This example shows how to access a single value by name. The value is read directly from memory.

Create an XCP channel with access to an A2L file.

```
a2lfile = xcpA2L('C:\work\XCPSIM.a2l');  
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);
```

Connect the slave.

```
connect(xcpch)
```

Read a single value of the Triangle measurement directly from memory.

```
readSingleValue(xcpch, 'Triangle')
```

```
ans =
```

```
50
```

Write a Single Value

This example shows how to write a single value by name. The value is written directly to memory.

Create an XCP channel linked to an A2L file.

```
a2lfile = xcpA2L('C:\work\XCPSIM.a2l');  
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);
```

Connect the slave.

```
connect(xcpch)
```

Write a single value.

```
writeSingleValue(xcpch, 'Triangle', 50)
```

Read a Calibrated Measurement

This example shows a typical workflow for reading a calibration file and using a translation table to calibrate a measurement reading.

Read the engine management ECU calibration file.

```
a2lobj = xcpA2L('ems.a2l');
```

Connect to the ECU.

```
ch = xcpChannel(a2lobj, 'UDP', '192.168.1.55', 5555);
```

Set the table that translates a pedal position to a torque demand.

```
writeCharacteristic(ch, 'tq_accel_request', ...  
[0 2 4 9 14 24 48 72 96 144 192 204 216 228 240]);
```

Set the pedal position to 50%.

```
writeMeasurement(ch, 'pedal_position', 50);
```

Read the demand.

```
value = readMeasurement(ch, 'tq_demand')
```

```
value =  
    96
```

See Also

Functions

readAxis | readCharacteristic | readMeasurement | writeAxis | writeCharacteristic | writeMeasurement

Acquire Measurement Data via Dynamic DAQ Lists

This example shows how to create a dynamic data acquisition list and assign measurements to the list. You can acquire data for measurements in this list from the slave.

Create an XCP channel linked to an A2L file and connect it to the slave.

```
a2lfile = xcpA2L('C:\work\XCPSIM.a2l');  
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);  
connect(xcpch)
```

Create a DAQ list for the '10 ms' event with 'PWMFiltered' and 'Triangle' measurements.

```
createMeasurementList(xcpch, 'DAQ', '10 ms', {'PWMFiltered', 'Triangle'});
```

Start measurement activity.

```
startMeasurement(xcpch)
```

Read 10 samples of data from the configured measurement list for the 'Triangle' measurement.

```
readDAQListData(xcpch, 'Triangle', 10)
```

```
18  18  18  18  18  18  18  18  18  18
```

Stimulate Measurement Data via Dynamic STIM Lists

This example shows how to create a dynamic data stimulation list and assign measurements to the list. You can stimulate data for specific measurements in this list.

Create an XCP channel linked to an A2L file and connect it.

```
a2lfile = xcpA2L('C:\work\XCPSIM.a2l');  
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);  
connect(xcpch)
```

Note If your module is locked for STIM operations, configure the channel to unlock the slave.

Create a STIM list for the '100ms' event with 'PWMFiltered' and 'Triangle' measurements.

```
createMeasurementList(xcpch, 'STIM', '100ms', {'PWMFiltered', 'Triangle'});
```

Start the measurement.

```
startMeasurement(xcpch)
```

Write 10 to the configured measurement list for the 'Triangle' measurement.

```
writeSTIMListData(xcpch, 'Triangle', 10);
```

J1939

- “J1939 Interface” on page 9-2
- “J1939 Parameter Group Format” on page 9-3
- “J1939 Network Management” on page 9-4
- “J1939 Transport Protocols” on page 9-5
- “J1939 Channel Workflow” on page 9-6

J1939 Interface

J1939 is a high-level protocol built on the CAN bus that provides serial data communication between electronic control units (ECUs) in heavy-duty vehicles. Applications of J1939 include:

- Diesel power-train applications
- In-vehicle networks for buses and trucks
- Agriculture and forestry machinery
- Truck-trailer connections
- Military vehicles
- Fleet management systems
- Recreational vehicles
- Marine navigation systems

The J1939 protocol uses CAN as the physical layer, which defines the communication between ECUs in the vehicle network. The protocol has a second data-link layer that defines rules of communication and error detection. A third application layer defines the data transferred over the network.

See Also

More About

- “J1939 Parameter Group Format” on page 9-3
- “J1939 Network Management” on page 9-4
- “J1939 Transport Protocols” on page 9-5
- “J1939 Channel Workflow” on page 9-6

J1939 Parameter Group Format

The application layer deals with parameter groups (PGs) sent and received over the network. J1939 protocol uses broadcast messages, or messages sent over the CAN bus without a defined destination. Devices on the same network can access these messages without permission or special requests. If a device requires a specific message, include the device destination address in the message identifier.

The message contains a group of parameters that define related messages. For example, a message sent to the engine controller can contain both engine speed and RPM. These parameters are represented in the CAN identifier by a parameter group number (PGN). Parameter groups use 29-bit identifiers with this message structure:

Parameter	Priority	Reserved	Data Page	PDU Format	PDU Specific	Source Address
Size	3 bits	1 bit	1 bit	8 bits	8 bits	8 bits

- First three bits represent the priority of the message on the network. Zero is the highest priority.
- The next bit is reserved for future use. For transmit messages, set this to zero.
- The next bit is the data page, which extends the maximum number of possible PGs in the identifier.
- The next 8 bits are the protocol data unit (PDU) format, which specifies whether the message is targeted for a single device or is broadcast. If the PDU is less than 240, then the message is sent to a specific device and if it over 240, it is sent to the entire network.
- The next 8 bits are the PDU specific, which contains the address of the device when the PDU format is less than 240. If PDU format is greater than 240, PDU specific contains group extension, or the number of extended broadcast messages in this parameter group.
- The last 8 bits contain the source address, which is the address of the device sending the parameter groups.

The protocol application layer transmits the PG on the CAN network. PG length can be up to 1785 bytes and is not limited by the length of a CAN message. However, PGs larger than 8 bytes must be transmitted using a transport protocol.

See Also

More About

- “J1939 Interface” on page 9-2
- “J1939 Network Management” on page 9-4
- “J1939 Transport Protocols” on page 9-5
- “J1939 Channel Workflow” on page 9-6

J1939 Network Management

Each device on a J1939 network has a unique address. The PDU Specific uses device addresses to send parameter groups (PG) to a specific device. Static addresses between zero and 253 are assigned for every device on the network. You can also assign 254, which is a null and 255, which is a global address.

Address Claiming

The application sending a PG must claim an ECU address. The application sends an address claiming PG first, and resumes sending other PGs if there is not address conflict. If the source application encounters an address conflict, it can send a PG to the global (255) address to request all devices to declare their addresses. It can then claim one of the unused addresses.

See Also

More About

- “J1939 Interface” on page 9-2
- “J1939 Parameter Group Format” on page 9-3
- “J1939 Transport Protocols” on page 9-5
- “J1939 Channel Workflow” on page 9-6

J1939 Transport Protocols

J1939 transport protocol breaks up PGs larger than 8 data bytes and up to 1785 bytes, into multiple packets. The transport protocol defines the rules for packaging, transmitting, and reassembling the data.

- Messages that have multiple packets are transmitted with a dedicated PGN, and have the same message ID and similar functionality.
- The length of each message in the packet must be 8 bytes or fewer.
- The first byte in the data field of a message specifies the sequence of the message (one to 255) and the next seven bytes contain the original data.
- All unused bytes in the data field are set to zero.
- A different PGN controls the message flow.

The data package is passed to the application layer after it is reassembled in the order specified by the first data-field byte.

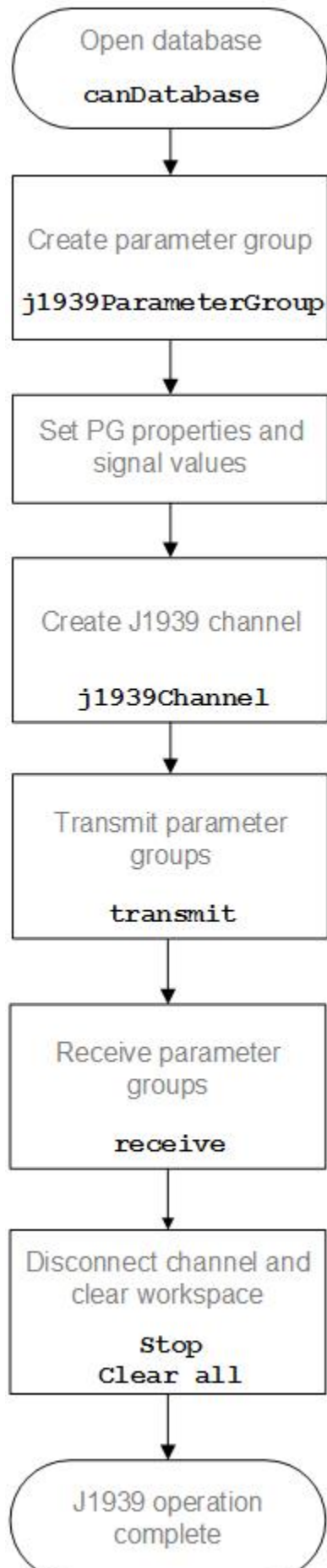
See Also

More About

- “J1939 Interface” on page 9-2
- “J1939 Parameter Group Format” on page 9-3
- “J1939 Network Management” on page 9-4
- “J1939 Transport Protocols” on page 9-5
- “J1939 Channel Workflow” on page 9-6

J1939 Channel Workflow

Transmit and receive parameter groups (PGs) using `j1939Channel` via a CAN network.



See Also

More About

- “J1939 Interface” on page 9-2
- “J1939 Parameter Group Format” on page 9-3
- “J1939 Network Management” on page 9-4
- “J1939 Transport Protocols” on page 9-5

CAN Communications in Simulink

- “Vehicle Network Toolbox Simulink Blocks” on page 10-2
- “CAN Communication Workflows in Simulink” on page 10-3
- “Open the Vehicle Network Toolbox Block Library” on page 10-6
- “Build CAN Communication Simulink Models” on page 10-7
- “Create Custom CAN Blocks” on page 10-15
- “Supported Block Features” on page 10-18

Vehicle Network Toolbox Simulink Blocks

This section describes how to use the Vehicle Network Toolbox CAN Communication block library. The library contains these blocks:

- **CAN Configuration** — Configure the settings of a CAN device.
- **CAN Log** — Logs messages to file.
- **CAN Pack** — Pack signals into a CAN message.
- **CAN Receive** — Receive CAN messages from a CAN bus.
- **CAN Replay**— Replays logged messages to CAN bus or output port.
- **CAN Transmit** — Transmit CAN messages to a CAN bus.
- **CAN Unpack** — Unpack signals from a CAN message.

The CAN FD Communication block library contains similar blocks for the CAN FD protocol.

The Vehicle Network Toolbox block library is a tool for simulating message traffic on a CAN network, as well for using the CAN bus to send and receive messages. You can use blocks from the block library with blocks from other Simulink libraries to create sophisticated models.

To use the Vehicle Network Toolbox block library, you require Simulink, a tool for simulating dynamic systems. Simulink is a model definition environment. Use Simulink blocks to create a block diagram that represents the computations of your system or application. Simulink is also a model simulation environment. Run the block diagram to see how your system behaves. If you are new to Simulink, see “Get Started with Simulink” (Simulink) to understand its functionality better.

For more detailed information about the blocks in the Vehicle Network Toolbox block library see “CAN Communication in Simulink”.

CAN Communication Workflows in Simulink

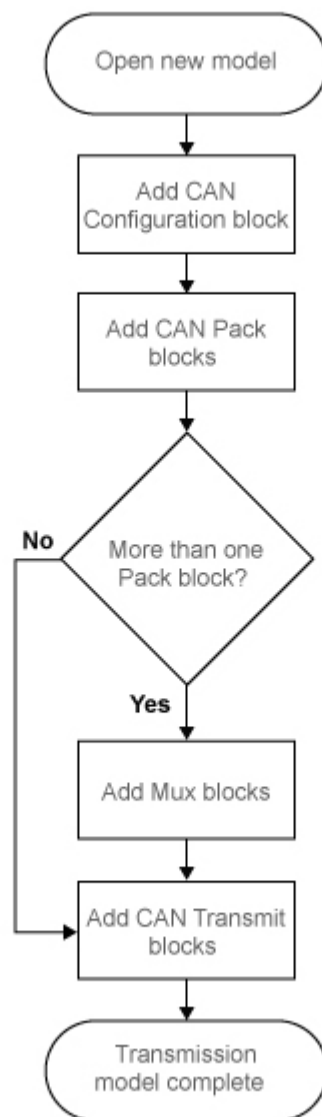
In this section...

“Message Transmission Workflow” on page 10-3

“Message Reception Workflow” on page 10-4

Message Transmission Workflow

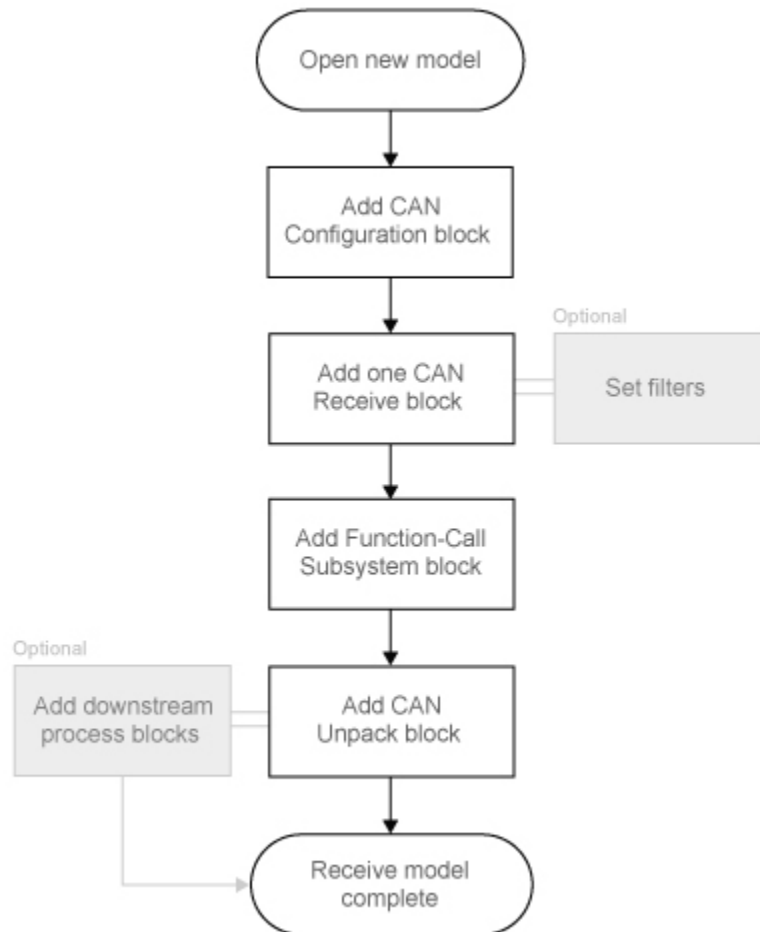
This workflow represents the most common CAN Transmit model. Adjust your model as needed. For more workflow examples, see “Build CAN Communication Simulink Models” on page 10-7 and the “Simulink Tutorials” in the Vehicle Network Toolbox examples.



Using Mux Blocks

- Use a Mux block to combine every message from the source if they are transmitted at the same rate.
- Use one CAN Transmit block for each configured Mux block.

Message Reception Workflow



Message Filtering

Set up filters to process only relevant messages. This ensures optimal simulation performance.

Do not set up filters if you need to parse all bus communications.

Function-Call Triggered Message Processing

Set up your CAN Unpack block:

- In a function-call triggered subsystem if you want to unpack every message received by your CAN Receive block.

- Without a function-call triggered subsystem if you want to unpack only the most recent message received by your CAN Receive block.
Set up this system if your receive block is filtering for a single message.

Downstream Processing

For any downstream processing using received messages, include blocks:

- Within the function-call subsystem if your downstream process must respond to all messages received in a single timestep in this model.
- Outside the function-call subsystem if your downstream process responds only to the most recent message received in a given timestep in this model.
In this case, the CAN Unpack block will not respond to any other messages received, irrespective of the messages ID.

Open the Vehicle Network Toolbox Block Library

In this section...
“Using the Simulink Library Browser” on page 10-6
“Using the MATLAB Command Window” on page 10-6

Using the Simulink Library Browser

To open the Vehicle Network Toolbox block library, start Simulink by entering the following at the MATLAB command prompt:

```
simulink
```

In the Simulink start page dialog, click **Blank Model**, and then **Create Model**. An empty, Editor window opens.

In the model Editor toolstrip **Simulation** tab, click **Library Browser**.

The Simulink Library Browser opens. Its left pane contains a tree of available block libraries in alphabetical order. Expand the Vehicle Network Toolbox node and click CAN Communication.

Using the MATLAB Command Window

To open the Vehicle Network Toolbox CAN Communications block library, enter `canlib` in the MATLAB Command window.

MATLAB displays the contents of the library in a separate window.

Build CAN Communication Simulink Models

Build the Message Transmit Part of the Model

This section shows how to build the part of the model to transmit CAN messages, using Vehicle Network Toolbox blocks with other blocks in the Simulink library.

Building a model to transmit CAN messages is detailed in the following steps:

- “Step 1: Create a New Model” on page 10-7
- “Step 2: Open the Block Library” on page 10-7
- “Step 3: Drag Vehicle Network Toolbox Blocks into the Model” on page 10-7
- “Step 4: Drag Other Blocks to Complete the Model” on page 10-8
- “Step 5: Connect the Blocks” on page 10-8
- “Step 6: Specify the Block Parameter Values” on page 10-8

For this portion of the example

- Use a MathWorks virtual CAN channel to transmit messages.
- Use the CAN Configuration block to configure your CAN channel.
- Use the Constant block to provide data to the CAN Pack block.
- Use the CAN Transmit block to send the data to the virtual CAN channel.

Use this section with “Build the Message Receive Part of the Model” on page 10-9 and “Save and Run the Model” on page 10-13 to build your complete model and run the simulation.

Step 1: Create a New Model

- 1 To start Simulink and create a new model, enter the following at the MATLAB command prompt:

```
simulink
```

In the Simulink start page dialog, click **Blank Model**, and then **Create Model**. An empty Editor window opens.

- 2 In the Editor toolstrip **Simulation** tab, click **Save > Save As** to assign a name to your new model.

Step 2: Open the Block Library

- 1 In the model Editor toolstrip **Simulation** tab, click **Library Browser**.
- 2 The Simulink Library Browser opens. Its left pane contains a tree of available block libraries in alphabetical order. Expand the **Vehicle Network Toolbox** node and click **CAN Communication**.

Step 3: Drag Vehicle Network Toolbox Blocks into the Model

To place a block into your model, click a block in the library and drag it into the editor. For this example, you need in your model one instance each of the following blocks:

- CAN Configuration

- CAN Pack
- CAN Transmit

Note The default configuration of each block in your model uses MathWorks Virtual 1 Channel 1. You can configure the blocks in your model to use virtual channels or hardware devices from other vendors.

Note By default, block names are not shown in the model. To display the block names while working in the model Editor, in the toolstrip **Format** tab click **Auto** and clear the **Hide Automatic Block Names** selection.

Step 4: Drag Other Blocks to Complete the Model

This example uses a Constant block as a source of data. From the Simulink > Commonly Used Blocks library, add a Constant block to your model.

Step 5: Connect the Blocks

Make a connection between the Constant block and the CAN Pack block input. When you move the pointer near the output port of the Constant block, the pointer becomes a crosshair. Click the Constant block output port and, holding the mouse button, drag the pointer to the input port of the CAN Pack block. Then release the button.

In the same way, make a connection between the output port of the CAN Pack block and the input port of the CAN Transmit block.

The CAN Configuration block does not connect to any other block. This block configures its CAN channel for communication.

Step 6: Specify the Block Parameter Values

You set parameters for each block in your model by double-clicking the block.

Configure the CAN Configuration Block

Double-click the CAN Configuration block to open its parameters dialog box. Verify or set the following parameters:

- **Device** to MathWorks Virtual 1 (Channel 1).
- **Bus speed** to 500000.
- **Acknowledge Mode** to Normal.
- Click **OK**.

Configure the CAN Pack Block

Double-click the CAN Pack block to open its parameters dialog box. Verify or set the following parameters:

- **Data is input as** to raw data.
- **Name** to the default value CAN Msg.

- **Identifier type** to the default Standard (11-bit identifier) type.
- **Identifier** to 500.
- **Length (bytes)** to the default length of 8.
- Click **OK**.

Configure the CAN Transmit Block

Double-click the CAN Transmit block to open its parameters dialog box. Verify or set the following parameters:

- **Device** to MathWorks Virtual 1 (Channel 1).

Click **OK**.

Configure the Constant Block

Double-click the Constant block to open its parameters dialog box.

On the **Main** tab, set:

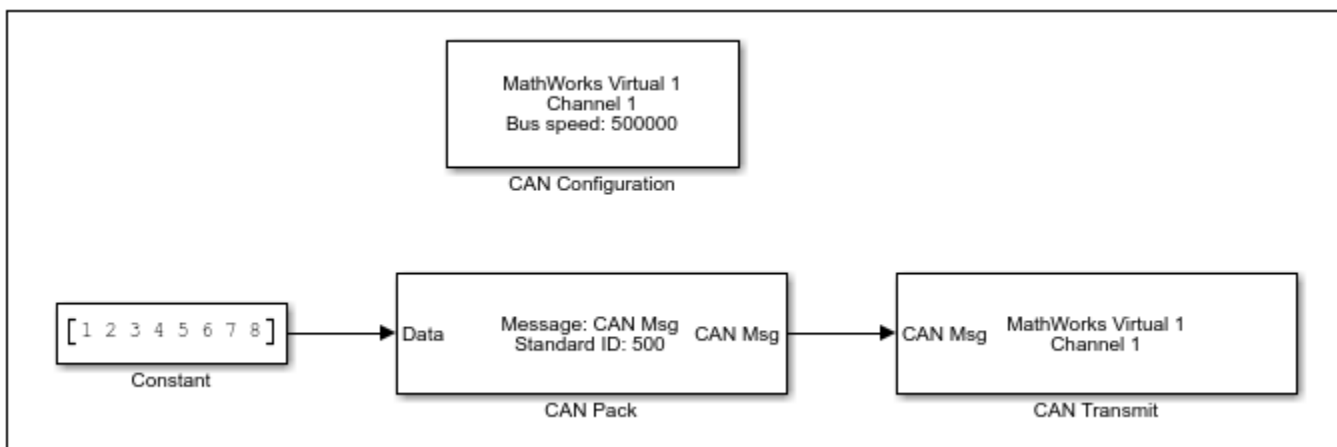
- **Constant value** to [1 2 3 4 5 6 7 8].
- **Sample time** to 0.01 seconds.

On the **Signal Attributes** tab, set:

- **Output data type** to uint8.

Click **OK**.

Your model looks like this figure.



Build the Message Receive Part of the Model

This section shows how to build the part of the model to receive CAN messages, using the Vehicle Network Toolbox blocks with other blocks in the Simulink library. This example illustrates how to receive data via a CAN network, in the following steps:

- “Step 7: Drag Vehicle Network Toolbox Blocks into the Model” on page 10-10

- “Step 8: Drag Other Blocks to Complete the Model” on page 10-10
- “Step 9: Connect the Blocks” on page 10-11
- “Step 10: Specify the Block Parameter Values” on page 10-12

For this portion of the example

- Use a MathWorks virtual CAN channel to receive messages.
- Use a CAN Configuration block to configure your virtual CAN channel.
- Use a CAN Receive block to receive the message.
- Use a Function-Call Subsystem block that contains the CAN Unpack block. This function takes the data from the CAN Receive block and uses the parameters of the CAN Unpack block to unpack your message data.
- Use a Scope block to display the received data.

Step 7: Drag Vehicle Network Toolbox Blocks into the Model

For this part of the example, start with one instance each of the following blocks from the Vehicle Network Toolbox CAN Communication block library:

- CAN Configuration
- CAN Receive

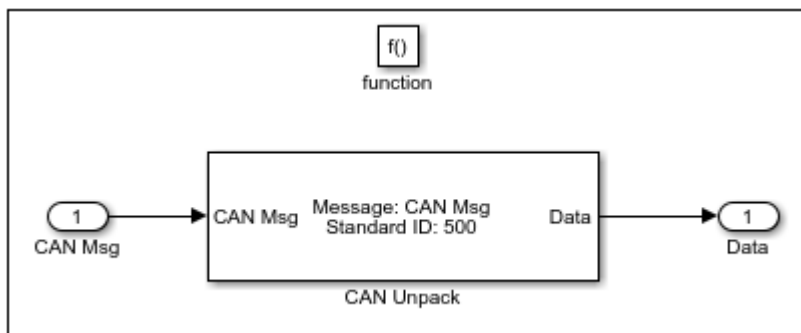
Tip Configure separate CAN channels for the CAN Receive and CAN Transmit blocks. Each channel needs its own CAN Configuration block.

Step 8: Drag Other Blocks to Complete the Model

Use the Function-Call Subsystem block from the Simulink **Ports & Subsystems** block library to build your CAN Message pack subsystem.

- 1 Drag the Function-Call Subsystem block into the model.
- 2 Double-click the Function-Call Subsystem block to open the subsystem editor.
- 3 Double-click the **In1** port label to rename it to **CAN Msg**.
- 4 Double-click the **Out1** port label to rename it to **Data**.
- 5 Drag and drop the CAN Unpack block from the Vehicle Network Toolbox block library into this subsystem. If placed between the input and output lines, they will automatically connect.

The inside of your Function-Call Subsystem block should now look like this figure.



The reason to place the CAN Unpack inside a Function-Call Subsystem is so that it can capture all possible messages.

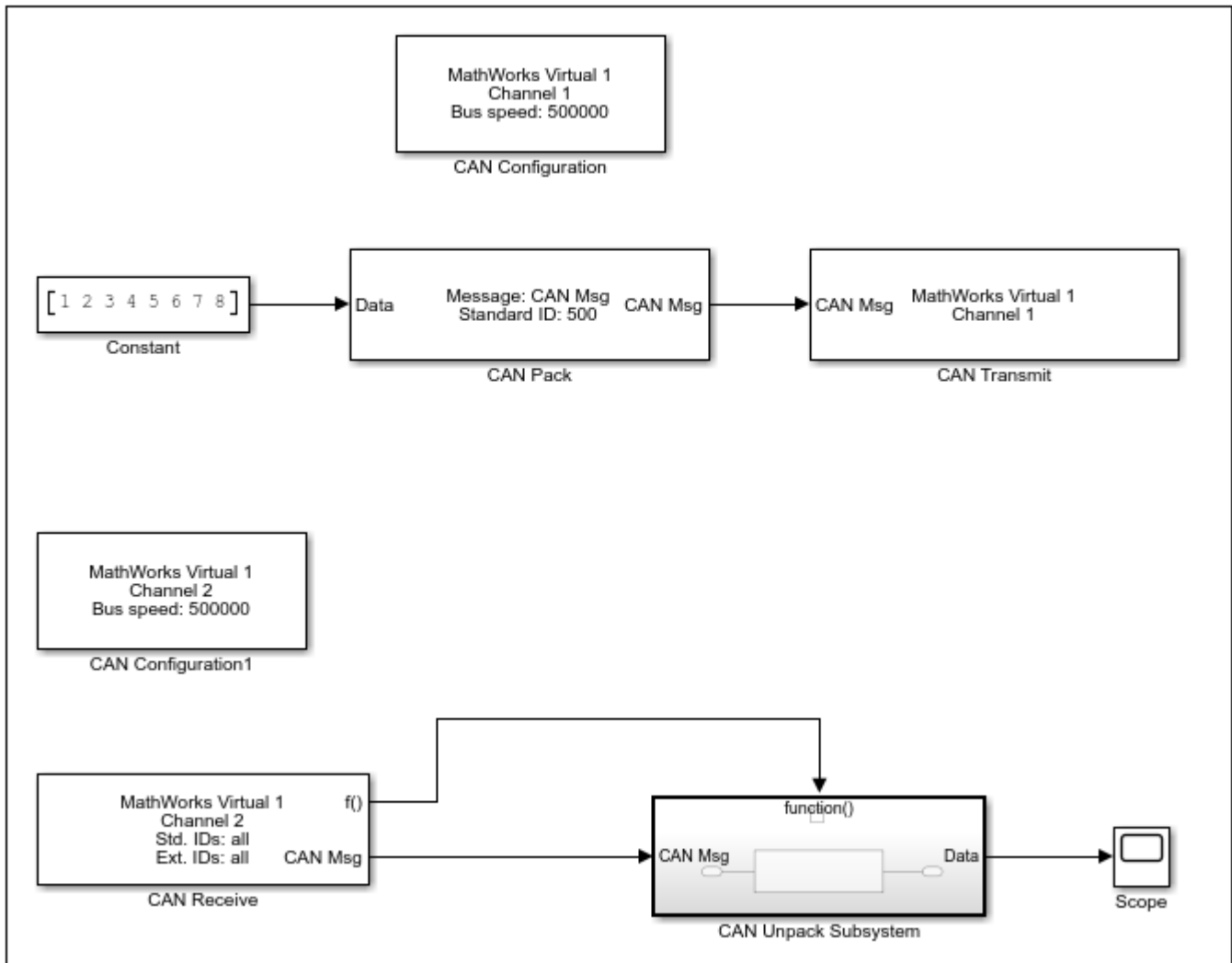
- 6 Click the back-arrow in the toolstrip to return to your model view.

Step 9: Connect the Blocks

- 1 Rename the Function-Call Subsystem block to **CAN Unpack Subsystem**.
- 2 Connect the **CAN Msg** output port of the CAN Receive block to the **In1** input port of the **CAN Unpack Subsystem** block.
- 3 Connect the **f()** output port of the CAN Receive block to the **function()** input port of the **CAN Unpack Subsystem** block.
- 4 For a visual display of the simulation results, drag the Scope block from the Simulink block library into your model.
- 5 Connect the **CAN Msg** output port of your **CAN Unpack Subsystem** block to the input port of the Scope block.

The CAN Configuration block does not connect to any other block. This block configures the CAN channel used by the CAN Receive block to receive the CAN message.

Your model looks like this figure.



Step 10: Specify the Block Parameter Values

Set parameters for the blocks in your model by double-clicking the block.

Configure the CAN Configuration1 Block

Double-click the CAN Configuration block to open its parameters dialog box. Set the:

- **Device** to MathWorks Virtual 1 (Channel 2).
- **Bus speed** to 500000.
- **Acknowledge Mode** to Normal.

Click **OK**.

Configure the CAN Receive Block

Double-click the CAN Receive block to open its Parameters dialog box. Set the:

- **Device** to MathWorks Virtual 1 (Channel 2).

- **Sample time** to 0.01.
- **Number of messages received at each timestep** to all.

Click **OK**.

Configure the CAN Unpack Subsystem

Double-click the CAN Unpack subsystem to open the Function-Call Subsystem editor. In the model, double-click the CAN Unpack block to open its parameters dialog box. Set the:

- **Data to be output as** to raw data.
- **Name** to the default value CAN Msg.
- **Identifier type** to the default Standard (11-bit identifier).
- **Identifier** to 500.
- **Length (bytes)** to the default length of 8.

Click **OK**.

Save and Run the Model

This section shows you how to save the model you built, “Build the Message Transmit Part of the Model” on page 10-7 and “Build the Message Receive Part of the Model” on page 10-9.

- “Step 11: Save the Model” on page 10-13
- “Step 12: Change Configuration Parameters” on page 10-13
- “Step 13: Run the Simulation” on page 10-13
- “Step 14: View the Results” on page 10-14

Step 11: Save the Model

Before you run the simulation, save your model by clicking the **Save** icon or selecting **Save** from the Editor toolbar **Simulation** tab.

Step 12: Change Configuration Parameters

- 1 In your model Editor toolbar **Modeling** tab, click **Model Settings**. The Configuration Parameters dialog box opens.
- 2 In the Solver Options section, select:
 - **Fixed-step** from the **Type** list.
 - **Discrete (no continuous states)** from the **Solver** list.

Step 13: Run the Simulation

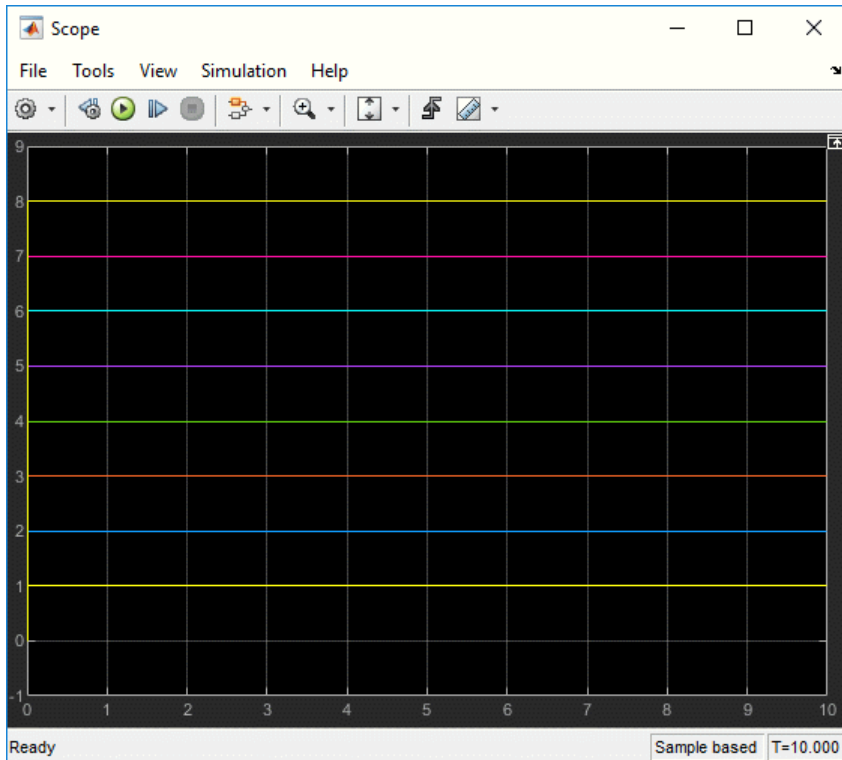
To run the simulation, click the **Run** button in the **Simulation** or **Modeling** tab of the Editor toolbar.

When you run the simulation, the CAN Transmit block gets the message from the CAN Pack block. It then transmits it via Virtual Channel 1. The CAN Receive block on Virtual Channel 2 receives this message and hands it to the CAN Unpack Subsystem block to unpack the message.

While the simulation is running, the status bar at the bottom of the model window updates the progress of the simulation.

Step 14: View the Results

Double-click the Scope block to view the message transfer on a graph. If you cannot see all the data on the graph, click the **Autoscale** toolbar button, which automatically scales the axes to display all stored simulation data.



In the graph, the horizontal axis represents the simulation time in seconds and the vertical axis represents the received data value. You configured the model to pack and transmit an array of constant values, [1 2 3 4 5 6 7 8], every 0.01 seconds of simulation time. These values are received and unpacked. The output in the Scope window represents the received data values.

See Also

More About

- “Build and Edit a Model Interactively” (Simulink)

Create Custom CAN Blocks

In this section...

“Blocks Using Simulink Buses” on page 10-15

“Blocks Using CAN Message Data Types” on page 10-16

You can create custom **Receive** and **Transmit** blocks to use with hardware currently not supported by Vehicle Network Toolbox. Choose one of the following work flows.

- “Blocks Using Simulink Buses” on page 10-15 (recommended) — Use Simulink bus signals to connect blocks. Create functions and blocks with S-Function Builder and S-Function blocks.
- “Blocks Using CAN Message Data Types” on page 10-16 — Use CAN message data types to share information. Write and compile your own C++ code to define functions, and MATLAB code to create blocks.

Blocks Using Simulink Buses

To create custom blocks for Vehicle Network Toolbox that use Simulink CAN buses, you can use the S-function builder. For full instructions on building S-functions and blocks this way, see “Use a Bus Signal with S-Function Builder to Create an S-Function” (Simulink). The following example uses the steps outlined in that topic.

This example shows you how to build two custom blocks for transmitting and receiving CAN messages. These blocks use a Simulink message bus to interact with CAN Pack and CAN Unpack blocks.

- 1 Create a Simulink message bus in the MATLAB workspace for CAN or CAN FD.

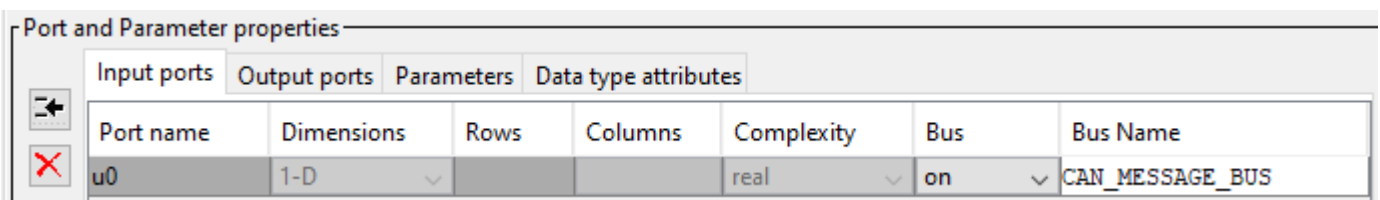
```
canMessageBusType
```

or

```
canFDMessageBusType
```

Each of these functions creates a variable in the workspace named `CAN_MESSAGE_BUS` or `CAN_FD_MESSAGE_BUS`, respectively. You use this variable later for building your S-functions.

- 2 Open a new blank model in Simulink, and add to your model an S-Function Builder block from the block library.
- 3 Double-click the S-Function Builder block to open its dialog box. The first function you build is for transmitting.
- 4 Among the settings in the dialog box, define a function name and specify usage of a Simulink bus.
 - S-function name: `CustomCANTransmit`
 - Data Properties: Input Ports: Bus: On, Bus Name: `CAN_MESSAGE_BUS`, as shown in the following figure.



For CAN FD, set the bus name to `CAN_FD_MESSAGE_BUS`.

In your function and block building, use the other tabs in the dialog box to define the code for interaction with your device driver, and remove unnecessary ports.

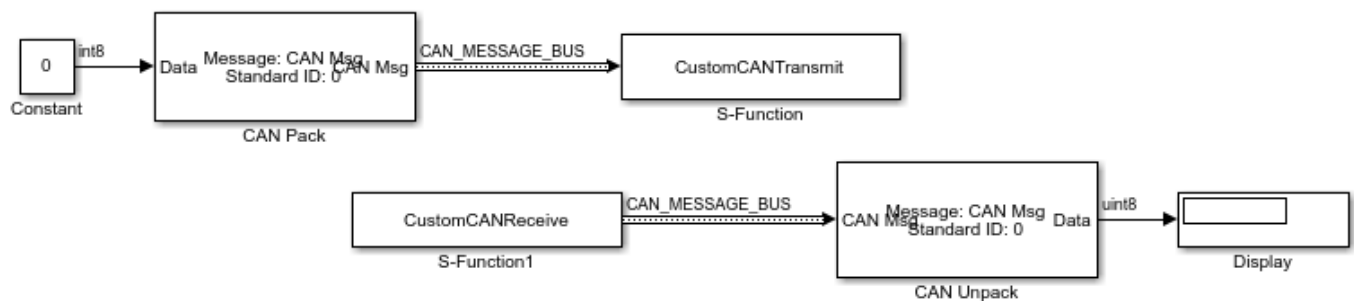
- 5 Click **Build**. The code files are placed in the current working folder of MATLAB.
- 6 Place a new S-Function Builder block in your model, and repeat the steps to build an S-function named CustomCANReceive. Use the same settings, except for input and output ports. The receive block output port uses the same bus name as the transmit function input.
- 7 Build the receive function, and remove both S-Function Builder blocks from your model. At this point, you can use the files generated by the S-Function Builder as a set of templates, which you can further edit and compile with your own tools. Alternatively, you can use S-Function blocks to run your functions.
- 8 Add two S-Function blocks to your model. Open each block, and set its Model Parameters S-function name field, so you have one each of CustomCANTransmit and CustomCANReceive.

At this point you could create a mask for each block to allow access to parameters for your hardware. This example does not need masks for these blocks.

- 9 Add other necessary blocks to your model, including:
 - CAN Pack or CAN FD Pack
 - CAN Unpack or CAN FD Unpack

- 10 Set the block parameters and connections.

A typical model might look like this. Here a Constant block and a Display block allow verification of connections and model behavior.



Blocks Using CAN Message Data Types

Note For ease of design and to take advantage of more Simulink features, it is recommended that you use Simulink buses instead of CAN message data types when possible. See “Blocks Using Simulink Buses” on page 10-15.

To create your own blocks for use with other Vehicle Network Toolbox blocks, you can use a custom CAN data type. Register this custom CAN data type in a C++ S-function.

Note You must use a C++ file type S-function (.cpp) to create custom blocks that use CAN message data types. Using a C-file type S-function (.c) might cause linker errors.

To register and use the custom CAN data type, in your S-function:

- 1 Define the `IMPORT_SCANUTIL` identifier that imports the required symbols when you compile the S-function:

```
#define IMPORT_SCANUTIL
```

- 2 Include the `can_datatype.h` header located in `matlabroot\toolbox\vnt\vntblks\include\candatatype` at the top of the S-function:

```
#include "can_datatype.h"
```

Note The header `can_message.h` included by `can_datatype.h` is located in `matlabroot\toolbox\shared\can\src\scanutil\`. See the `can_message.h` file for information on the `CAN_MESSAGE` and `CAN_DATATYPE` structures.

- 3 Link your S-function during build to the `scanutil.lib` located in the `matlabroot\toolbox\vnt\vntblks\lib\ARCH` folder. The shared library `scanutil.dll`, is located in the `matlabroot\bin\ARCH`

- 4 Call this function in `mdlInitializeSizes` to initialize the custom CAN data type:

```
mdlInitialize_CAN_datatype(S);
```

- 5 Get custom data type ID using `ssGetDataTypeId`:

```
dataTypeID = ssGetDataTypeId(S, SL_CAN_MESSAGE_DTYPE_NAME);
```

- 6 Do one of the following:

- To create a receive block, set output port data type to `CAN_MESSAGE`:

```
ssSetOutputPortDataType(S, portID, dataTypeID);
```

- To create a transmit block, set the input port to `CAN_MESSAGE`:

```
ssSetInputPortDataType(S, portID, dataTypeID);
```

See Also

Functions

`canFDMessageBusType` | `canMessageBusType`

More About

- “C/C++ S-Function Basics” (Simulink)
- “Use a Bus Signal with S-Function Builder to Create an S-Function” (Simulink)

Supported Block Features

The blocks of the Vehicle Network Toolbox block library support the following features.

CAN Communication

Block	Platforms	Simulink Accelerator™ and Rapid Accelerator	Code Generation	Additional Supporting Products	Simulink Bus Objects
CAN Configuration	Windows, Linux	Yes	For host computer only		Not applicable
CAN Receive	Windows, Linux	Yes	For host computer only		Recommended
CAN Transmit	Windows, Linux	Yes	For host computer only		Recommended
CAN Pack	Windows, Linux	Yes	Portable for signal information up to 32-bit length	Simulink Real-Time™, Embedded Coder®	Recommended
CAN Unpack	Windows, Linux	Yes	Portable for signal information up to 32-bit length	Simulink Real-Time, Embedded Coder	Recommended
CAN Replay	Windows, Linux	Yes	For host computer only		Recommended
CAN Log	Windows, Linux	Yes	For host computer only		Recommended

CAN FD Communication

Block	Platforms	Simulink Accelerator and Rapid Accelerator	Code Generation	Additional Supporting Products	Simulink Bus Object
CAN FD Configuration	Windows, Linux	Yes	For host computer only		Not applicable
CAN FD Receive	Windows, Linux	Yes	For host computer only		Required
CAN FD Transmit	Windows, Linux	Yes	For host computer only		Required
CAN FD Pack	Windows, Linux	Yes	Portable for signal information up to 32-bit length	Simulink Real-Time	Required

Block	Platforms	Simulink Accelerator and Rapid Accelerator	Code Generation	Additional Supporting Products	Simulink Bus Object
CAN FD Unpack	Windows, Linux	Yes	Portable for signal information up to 32-bit length	Simulink Real-Time	Required
CAN FD Replay	Windows, Linux	Yes	For host computer only		Required
CAN FD Log	Windows, Linux	Yes	For host computer only		Required

XCP Communication

Block	Platforms	Simulink Accelerator and Rapid Accelerator	Code Generation	Additional Supporting Products	Simulink Bus Object
XCP CAN Configuration	Windows	Yes	For host computer only	Simulink Real-Time	Not applicable
XCP CAN Transport Layer	Windows	Yes	For host computer only		Not applicable
XCP CAN Data Acquisition	Windows	Yes	For host computer only	Simulink Real-Time	Not applicable
XCP CAN Data Stimulation	Windows	Yes	For host computer only	Simulink Real-Time	Not applicable
XCP UDP Configuration	Windows	Yes	For host computer only	Simulink Real-Time	Not applicable
XCP UDP Data Acquisition	Windows	Yes	For host computer only	Simulink Real-Time	Not applicable
XCP UDP Data Stimulation	Windows	Yes	For host computer only	Simulink Real-Time	Not applicable
XCP UDP Bypass	Windows	Yes	For host computer only	Simulink Real-Time	Not applicable

J1939 Communication

Block	Platforms	Simulink Accelerator and Rapid Accelerator	Code Generation	Additional Supporting Products	Simulink Bus Object
J1939 Network Configuration	Windows	Yes	For Windows host computer only	Simulink Real-Time	Not applicable

Block	Platforms	Simulink Accelerator and Rapid Accelerator	Code Generation	Additional Supporting Products	Simulink Bus Object
J1939 Node Configuration	Windows	Yes	For Windows host computer only	Simulink Real-Time	Not applicable
J1939 CAN Transport Layer	Windows	Yes	For Windows host computer only	Simulink Real-Time	Not applicable
J1939 Transmit	Windows	Yes	For Windows host computer only	Simulink Real-Time	Not applicable
J1939 Receive	Windows	Yes	For Windows host computer only	Simulink Real-Time	Not applicable

See Also

More About

- “Platform Support” on page 11-6
- “Communication Protocols” (Simulink Real-Time)
- “Blocks for Embedded Targets” (Embedded Coder)

Hardware Limitations

This topic describes limitations of using hardware in the Vehicle Network Toolbox based on limitations placed by the hardware vendor:

- “Vector Hardware Limitations” on page 11-2
- “Kvaser Hardware Limitations” on page 11-3
- “National Instruments Hardware Limitations” on page 11-4
- “File Format Limitations” on page 11-5
- “Platform Support” on page 11-6
- “Troubleshooting MDF Applications” on page 11-7

Vector Hardware Limitations

You cannot have more than 64 physical or 32 virtual simultaneous connections using a Vector CAN device.

If you use more than the number of connections Vector allows, you might get an error:

- In MATLAB R2013a and later:
Unable to query hardware information for the selected CAN channel object.
- In MATLAB R2012b:
boost thread resource allocation error.
- In MATLAB R2012a and earlier:
An unhandled error occurred with CAN device.

To work around this issue in Simulink:

- Use only a single Receive block for message reception in Simulink and connect all downstream Unpack blocks to it.
- Use a Mux block to combine CAN messages from Unpack blocks transmitting at the same rate into a single Transmit block.

To work around this issue in MATLAB:

- Try reusing channels you have already created for your application in MATLAB.

Kvaser Hardware Limitations

You must connect your Kvaser device before starting MATLAB.

The normal workflow with a Kvaser device is to connect the device before starting MATLAB. If you connect a Kvaser device while MATLAB is already running, you might see the following message.

```
Vehicle Network Toolbox has detected a supported Kvaser device.
```

To enable the device, shut down MATLAB. Then with the device connected, restart MATLAB.

National Instruments Hardware Limitations

Limited number of connections to an NI-XNET channel

When using NI-XNET for CAN or CAN FD communication, there is a limit to the total number of connections to the channel from MATLAB or Simulink.

To work around this issue in Simulink:

- Use only a single Receive block for message reception in Simulink and connect all downstream Unpack blocks to it.
- Use a Mux block to combine CAN messages from Unpack blocks transmitting at the same rate into a single Transmit block.

To work around this issue in MATLAB:

- Try reusing channels you have already created for your application.

File Format Limitations

MDF-File

The following MDF-file functions are not supported on Linux systems:

- mdfSort
- mdfVisualize

CDFX-File

When using CDFX-files, the following limitations apply:

- SW-AXIS-CONT elements with the category COM_AXIS, CURVE_AXIS, or RES_AXIS must use the SW-INSTANCE-REF element, and the axis must be defined in a separate instance.
- Instances with the category VAL_BLK, MAP, CUBOID, CUBE_4, or CUBE_5 that represent multidimensional arrays must use the VG element to group the physical values.
- DTD-based headers are not supported. The file header must be of the form:

```
<?xml version="1.0" encoding="utf-8"?>
<MSRSW xmlns="http://www.asam.net/schema/CDF/r2.1"
xmlns:xsi="http://www.w3.org/2001/XMLSchema-instance"
xsi:schemaLocation="http://www.asam.net/schema/CDF/r2.1 cdf_v2.1.0.sl.xsd">
```

BLF-File

Although Vector BLF-files support many networks, Vehicle Network Toolbox support of BLF-files is limited to only CAN and CAN FD on Windows operating systems.

See Also

Functions

blfread | blfwrite | cdfx | mdf | mdfDatastore

More About

- “Platform Support” on page 11-6
- “Troubleshooting MDF Applications” on page 11-7

Platform Support

The following tables indicate which toolbox features are available for each operating system platform.

Vendor	Windows	Linux
MathWorks virtual channels	✓	✓
Vector	✓	
PEAK-System	✓	✓
Kvaser	✓	✓
National Instruments	✓	

File Format	Windows	Linux
BLF	✓	
CDF	✓	✓
MDF	✓	✓

See Also

More About

- “Vendor Limitations”
- “File Format Limitations” on page 11-5
- “Supported Block Features” on page 10-18

Troubleshooting MDF Applications

Error When Creating mdf Object

Issue

You might see an error when you try to create an object for access to the MDF-file with the `mdf` function.

Possible Solutions

- A likely cause is an MDF-file that is improperly formatted or that includes unsupported elements. Vector provides an MDF Validator tool for checking an MDF-file. To download the tool visit [MDF Validator](#).

Error When Reading an MDF-File

Issue

You might see an error when you try to read data from an MDF-file with the `read` function.

Possible Solutions

- A possible cause is an MDF-file that is improperly formatted or that includes unsupported elements. Vector provides an MDF Validator tool for checking an MDF-file. To download the tool visit [MDF Validator](#).
- Another possible cause is an unsorted MDF-file. Beginning in R2019b, accessing an unsorted MDF-file generates a recognizable error, and you can sort the file using the `mdfSort` function.
- When unable to read the entire file, you can read data one channel at a time. Use the `read` function with the form `data = read(mdfObj, chanGroupIndex, chanName)`

Error When Reading an MDFDatastore

Issue

You might see an error when you try to read data from an MDFDatastore with the `read` function.

Possible Solutions

- Those channels targeted for reading must have the same name and belong to the same channel group in each file of the MDF datastore. Assure uniformity across the MDF-files in the database for the channels you are reading.

Unable to Find Specific Channel

Issue

You might be unable to find and read a channel of interest in the MDF-file.

Possible Solutions

- To identify channels in the MDF-file, use the `channelList` function.

Unable to Save MDF Attachments**Issue**

The `saveAttachment` function fails to save a file attached to the MDF-file.

Possible Solutions

- The `saveAttachment` function works only with embedded attachments; external files are not saved because they are already on disk.
- If the attachment does not exist, check with the provider of the MDF-file.

Unable to Read Array Channel Structures**Issue**

Vehicle Network Toolbox does not support array channel structures.

Possible Solutions

- To read these channels, you must write a composition function to repackage the data.

Unable to Read MIME and CANopen Data**Issue**

Reading MDF-file channels with MIME or CANopen data generates an error.

Possible Solutions

- MIME and CANopen data are not supported by Vehicle Network Toolbox.

Table Column Names Do Not Match Channel Names**Issue**

When reading an MDF-file, the column names of the output timetable correspond to the channel names in the file, but they might not be identical. Table column names must be compliant with MATLAB variable names, so they are altered to limit their size and characters. Most unsupported characters are converted to underscores.

Possible Solutions

- The returned timetable preserves the ordering of the channels. So you can access data in the table with numerical indexing.
- The original names of the channels are embedded in the timetable properties. For example:

```
m = mdf('File01.mf4');  
tt = read(m);
```

```
t1 = tt{1};  
t1.Properties.VariableDescriptions  
  
ans =  
  
1x2 cell array  
  
    {'Sigend_Int16_LE_Offset_32'}    {'Unsigend_UInt32_LE_Master_Offset_0'}
```

See Also

Functions

channelList | mdf | mdfSort

More About

- “Standard File Formats”
- “File Format Limitations” on page 11-5

External Websites

- [MDF Validator](#)

XCP Communications in Simulink

- “Vehicle Network Toolbox XCP Simulink Blocks” on page 12-2
- “Open the Vehicle Network Toolbox XCP Block Libraries” on page 12-3

Vehicle Network Toolbox XCP Simulink Blocks

Vehicle Network Toolbox provides two sets of XCP block libraries, which provide blocks for handling XCP message traffic on a CAN network or by UDP. The CAN and UDP libraries contain the following blocks:

CAN:

- **XCP CAN Transport Layer**— Transmit and Receive XCP messages over CAN bus.
- **XCP CAN Configuration** — Configure XCP settings for CAN.
- **XCP CAN Data Acquisition** — Acquire XCP data over CAN.
- **XCP CAN Data Stimulation** — Stimulate XCP data over CAN.

UDP:

- **XCP UDP Configuration** — Configure XCP settings for UDP.
- **XCP UDP Data Acquisition** — Acquire XCP data over UDP.
- **XCP UDP Data Stimulation** — Stimulate XCP data over UDP.

You can use these blocks with blocks from other Simulink libraries to create sophisticated models.

To use the Vehicle Network Toolbox XCP block libraries, you require Simulink, a tool for simulating dynamic systems. Simulink is a model definition environment. Use Simulink blocks to create a block diagram that represents the computations of your system or application. Simulink is also a model simulation environment. Run the block diagram to see how your system behaves. If you are new to Simulink, read “Get Started with Simulink” (Simulink) to understand its functionality better.

See Also

Blocks

XCP CAN Configuration | XCP CAN Data Acquisition | XCP CAN Data Stimulation | XCP CAN Transport Layer | XCP UDP Configuration | XCP UDP Data Acquisition | XCP UDP Data Stimulation

More About

- “Open the Vehicle Network Toolbox XCP Block Libraries” on page 12-3
- “XCP Data Acquisition over CAN” on page 16-91

Open the Vehicle Network Toolbox XCP Block Libraries

Using the MATLAB Command Window

To open the Vehicle Network Toolbox XCP block libraries, enter `vntxcp.lib` in the MATLAB Command window.

The Simulink Library Browser opens in a separate window and displays two libraries for XCP blocks. Double-click either CAN or UDP for the protocol you want.

Using the Simulink Library Browser

To open the Vehicle Network Toolbox XCP block libraries using Simulink windows and menus, use the following steps.

- 1 Click **Simulink** in the MATLAB toolstrip **Home** tab.
- 2 In the Simulink Start Page hover over **Blank Model** and click **Create Model**, or open one of your existing models.
- 3 In the model Editor toolstrip **Simulation** tab, click **Library Browser**.
- 4 The left pane of the browser lists all available block libraries. Expand the **Vehicle Network Toolbox** and **XCP Communication** trees, then select either CAN or UDP for the protocol you want.

See Also

Blocks

XCP CAN Configuration | XCP CAN Data Acquisition | XCP CAN Data Stimulation | XCP CAN Transport Layer | XCP UDP Configuration | XCP UDP Data Acquisition | XCP UDP Data Stimulation

More About

- “Vehicle Network Toolbox XCP Simulink Blocks” on page 12-2
- “XCP Data Acquisition over CAN” on page 16-91

Functions

attachDatabase

Attach CAN database to messages and remove CAN database from messages

Syntax

```
attachDatabase (message, database)
attachDatabase (message, [])
```

Description

`attachDatabase (message, database)` attaches the specified database to the specified message. You can then use signal-based interaction with the message data, interpreting the message in its physical form.

`attachDatabase (message, [])` removes any attached database from the specified message. You can then interpret messages in their raw form.

Examples

Attach CAN Database to Message

Attach Database.dbc to a received CAN message.

```
candb = canDatabase('C:\Database.dbc')
message = receive(canch, Inf)
attachDatabase(message, candb)
```

Input Arguments

message — CAN message for attaching or removing database

CAN message object

The name of the CAN message that you want to attach the database to or remove the database from, specified as a CAN message object.

Example: `message = receive(canch, Inf)`

database — Handle of database to attach or remove

`canDatabase` handle

Handle of database (.dbc file) that you want to attach to the message or remove from the message, specified as a `canDatabase` handle.

Example: `candb = canDatabase('C:\Database.dbc')`

Tips

If the specified message is an array, then the database attaches itself to each entry in the array. The database attaches itself to the message even if the message you specified does not exist in the

database. The message then appears and operates like a raw message. To attach the database to the CAN channel directly, edit the Database property of the channel object.

See Also

Functions

canDatabase | receive

Introduced in R2009a

attributeInfo

Information about CAN database attributes

Syntax

```
info = attributeInfo(db, 'Database', AttrName)
info = attributeInfo(db, 'Node', AttrName, NodeName)
info = attributeInfo(db, 'Message', AttrName, MsgName)
info = attributeInfo(db, 'Signal', AttrName, MsgName, SignalName)
```

Description

`info = attributeInfo(db, 'Database', AttrName)` returns a structure containing information for the specified database attribute.

If no matches are found in the database, `attributeInfo` returns an empty attribute information structure.

`info = attributeInfo(db, 'Node', AttrName, NodeName)` returns a structure containing information for the specified node attribute.

`info = attributeInfo(db, 'Message', AttrName, MsgName)` returns a structure containing information for the specified message attribute.

`info = attributeInfo(db, 'Signal', AttrName, MsgName, SignalName)` returns a structure containing information for the specified signal attribute.

Examples

View Database Attribute Information

Create a CAN database object, and view information about its bus type and database version.

```
db = canDatabase('J1939DB.dbc');
db.Attributes

    'BusType'
    'DatabaseVersion'
    'ProtocolType'

info = attributeInfo(db, 'Database', 'BusType')

    Name: 'BusType'
    ObjectType: 'Database'
    DataType: 'Double'
    DefaultValue: 'CAN-test'
    Value: 'CAN'

info = attributeInfo(db, 'Database', 'DatabaseVersion')

    Name: 'DatabaseVersion'
    ObjectType: 'Database'
```



```

    DataType: 'Double'
    DefaultValue: '1.0'
    Value: '8.1'

```

View Node Attribute Information

View node attribute information from CAN database.

```

db = canDatabase('J1939DB.dbc');
db.Nodes

    'AerodynamicControl'
    'Aftertreatment_1_GasIntake'
    'Aftertreatment_1_GasOutlet'

db.NodeInfo(1).Attributes

    'ECU'
    'NmJ1939AAC'
    'NmJ1939Function'

info = attributeInfo(db, 'Node', 'ECU', 'AerodynamicControl')

    Name: 'ECU'
    ObjectType: 'Network node'
    DataType: 'Double'
    DefaultValue: 'ECU-1'
    Value: 'ECU-10'

```

View Message Attribute Information

View message attribute information from CAN database.

```

db = canDatabase('J1939DB.dbc');
db.Messages

    'A1'
    'A1DEFI'
    'A1DEFSI'

db.MessageInfo(1).Attributes

a = db.MessageInfo(1).Attributes
a =

    'GenMsgCycleTime'
    'GenMsgCycleTimeFast'
    'GenMsgDelayTime'
    'VFrameFormat'

info = attributeInfo(db, 'Message', 'GenMsgCycleTime', 'A1')

    Name: 'GenMsgCycleTime'
    ObjectType: 'Message'
    DataType: 'Undefined'

```

```

    DefaultValue: 0
    Value: 500

```

View Signal Attribute Information from Message

View message signal attribute information from CAN database.

```

db = canDatabase('J1939DB.dbc');
s = signalInfo(db,'A1')

```

```

s =
2x1 struct array with fields:
    Name
    Comment
    StartBit
    SignalSize
    ByteOrder
    Signed
    ValueType
    Class
    Factor
    Offset
    Minimum
    Maximum
    Units
    ValueTable
    Multiplexor
    Multiplexed
    MultiplexMode
    RxNodes
    Attributes
    AttributeInfo

```

s(1).Name

EngBlowerBypassValvePos

s(1).Attributes

```

    'GenSigEVName'
    'GenSigILSupport'
    'GenSigInactiveValue'

```

```

info = attributeInfo(db,'Signal','GenSigInactiveValue','A1','EngBlowerBypassValvePos')

```

```

    Name: 'GenSigInactiveValue'
    ObjectType: 'Signal'
    DataType: 'Undefined'
    DefaultValue: 0
    Value: 0

```

Input Arguments

db — CAN database

CAN database object

CAN database, specified as a CAN database object.

Example: `db = canDatabase(_____)`

AttrName — Attribute name

char vector | string

Attribute name, specified as a character vector or string.

Example: 'BusType'

Data Types: char | string

NodeName — Node name

char vector | string

Node name, specified as a character vector or string.

Example: 'AerodynamicControl'

Data Types: char | string

MsgName — Message name

char vector | string

Message name, specified as a character vector or string.

Example: 'A1'

Data Types: char | string

SignalName — Signal name

char vector | string

Signal name, specified as a character vector or string.

Example: 'EngBlowerBypassValvePos'

Data Types: char | string

Output Arguments

info — Attribute information

structure

Attribute information, returned as a structure with these fields:

Field	Description
Name	Attribute name
ObjectType	Type of attribute
DataType	Data class of attribute value
DefaultValue	Default value assigned to attribute
Value	Current value of attribute

See Also

Functions

canDatabase | messageInfo | nodeInfo | signalInfo | valueTableText

Properties

can.Database Properties

Introduced in R2015b

blfinfo

Get information about Vector BLF file

Syntax

```
binf = blfinfo(blfFile)
```

Description

`binf = blfinfo(blfFile)` parses general information about the format and contents of a Vector Binary Logging Format BLF-file and returns the information in the structure `binf`.

Examples

View Information about BLF-File

Retrieve and view information about a BLF-file.

```
binf = blfinfo("c:\DataFiles\MultiChannelFile.blf")

binf =

    struct with fields:

        Name: "MultiChannelFile.blf"
        Path: "c:\DataFiles\MultiChannelFile.blf"
        Application: "CANalyzer"
        ApplicationVersion: "10.0.114"
        Objects: 35
        StartTime: 18-Jul-2018 16:47:11.490
        EndTime: 18-Jul-2018 16:47:18.490
        ChannelList: [2x3 table]
```

```
binf.ChannelList
```

```
ans =

    2x3 table

    ChannelID    Protocol    Objects
    _____    _____    _____
         1         "CAN FD"         4
         2         "CAN"           4
```

Input Arguments

blfFile — Path to BLF-file

string | char

Path to BLF-file, specified as a string or character vector. The value can specify a file in the current folder, or a relative or full path name.

Example: "MultipleChannelFile.blf"

Data Types: char | string

Output Arguments

binf — Information from BLF-file

struct

Information from BLF-file, returned as a structure with the following fields.

Name
Path
Application
ApplicationVersion
Objects
StartTime
EndTime
ChannelList

See Also

Functions

blfread | blfwrite

Introduced in R2019a

blfread

Read data from Vector BLF-file

Syntax

```
mdata = blfread(blfFile)
bdata = blfread(blfFile,chanID)
bdata = blfread( ____,Name,Value)
```

Description

`mdata = blfread(blfFile)` reads all the data from the specified BLF-file and returns a cell array of timetables to the variable `bdata`. The index of each element in the cell array corresponds to the channel number of the data in the file.

`bdata = blfread(blfFile,chanID)` reads message data for the specified channel from the BLF-file and returns a timetable.

`bdata = blfread(____,Name,Value)` reads message data filtered by parameter options for CAN database and message IDs.

Examples

Read Data from BLF-File

Read message data from a BLF-file, applying optional filters.

```
data = blfread("myfile.blf",2)
candb = canDatabase("testdb.dbc");

data = blfread("myfile.blf", "Database", candb)
data = blfread("myfile.blf", "Database", candb, "CANStandardFilter", 1:10)
data = blfread("myfile.blf", "Database", candb, "CANExtendedFilter", 3:7)
data = blfread("myfile.blf", "Database", candb, "CANStandardFilter", 1:10, ...
              "CANExtendedFilter", 3:7)
data = blfread("myfile.blf", "CANStandardFilter", 1:10, "CANExtendedFilter", 3:7)
```

Input Arguments

blfFile — Path to BLF-file

string | char

Path to BLF-file, specified as a string or character vector. The value can specify a file in the current folder, or a relative or full path name.

Example: "MultipleChannelFile.blf"

Data Types: string | char

chanID — Channel ID

numeric

Channel ID, specified as a numeric scalar value, for which to read data from the BLF-file. If not specified, all channels are read.

Example: 2

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name`, `Value` arguments. `Name` is the argument name and `Value` is the corresponding value. `Name` must appear inside quotes. You can specify several name and value pair arguments in any order as `Name1, Value1, . . . , NameN, ValueN`.

Example: `"CANStandardFilter", 1:8`

Database — CAN database

`can.Database`

CAN database to use for message decoding, specified as a `can.Database` object.

Example: `candb()`

CANStandardFilter — Message standard IDs

numeric array

Message standard IDs, specified as an array of numeric values identifying which messages to import. Message IDs are general, and apply to both CAN and CAN FD bus types. The value can specify a scalar or an array of either a range or noncontiguous IDs. By default, all standard ID messages are imported.

Example: `[1:10 45 100:123]`

Data Types: `string` | `char`

CANExtendedFilter — Message extended IDs

numeric array

Message extended IDs, specified as an array of numeric values identifying which messages to import. Message IDs are general, and apply to both CAN and CAN FD bus types. The value can specify a scalar or an array of either a range or noncontiguous IDs. By default, all extended ID messages are imported.

Example: `[1 8:10 1001:1080]`

Data Types: `string` | `char`

Output Arguments

mdata — Message data from BLF-file

cell array of timetables | timetable

Message data from BLF-file, returned as a cell array of timetables. If you specify a single channel to read, this returns a timetable.

See Also

Functions

blfinfo | blfwrite | canDatabase

Introduced in R2019a

blfwrite

Write data to Vector BLF-file

Syntax

```
blfwrite(blfFile,data,chanID,prot)
```

Description

`blfwrite(blfFile,data,chanID,prot)` writes the specified timetables in data to the specified BLF-file. The function allows writing only to new files, so you cannot overwrite existing files or data.

Examples

Write Data to a BLF-File

Write timetables of data to specified channels.

Write one data set to a single channel.

```
blfwrite("newfile.blf",data,1,"CAN")
```

Write two data sets to the same channel.

```
blfwrite("newfile.blf",{data1,data2},[1,1],["CAN FD","CAN FD"])
```

Write two data sets to separate channels with different protocols.

```
blfwrite("newfile.blf",{data1,data2},[1,2],["CAN","CAN FD"])
```

Input Arguments

blfFile — Path to BLF-file

string | char

Path to BLF-file to write, specified as a string or character vector. The value can specify a file in the current folder, or a relative or full path name.

Example: "MultipleChannelFile.blf"

Data Types: string | char

data — Data to write to BLF-file

timetable

Data to write to BLF-file, specified as a timetable or cell array of timetables. You can write multiple tables for the same channel if the protocol is the same.

Data Types: timetable

chanID — Channel IDs

numeric

Channel IDs, specified as a numeric scalar or array value, identifying the channels on which the data is written.

Example: [1,2,4]

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64

prot — Message protocol`"CAN" "CAN FD"`

Message protocol, specified as "CAN", "CAN FD". When writing multiple sets of data, specify protocol as an array of strings corresponding to the data sets being written.

Example: ["CAN", "CAN FD", "CAN"]

Data Types: char | string

See Also**Functions**`blfinfo | blfread`**Introduced in R2019a**

canChannel

Construct CAN channel connected to specified device

Syntax

```
canch = canChannel(vendor,device,devicechannelindex)
canch = canChannel(vendor,device)
canch = canChannel( ____, 'ProtocolMode', 'CAN FD')
```

Description

`canch = canChannel(vendor,device,devicechannelindex)` returns a CAN channel connected to a device from a specified vendor.

For Vector products, `device` is a character vector that combines the device type and a device index, such as 'CANCaseXL 1'. For example, if there are two CANcardXL devices, `device` can be 'CANcardXL 1' or 'CANcardXL 2'.

Use `canch = canChannel(vendor,device)` for National Instruments and PEAK-System devices.

For National Instruments, `vendor` is the character vector 'NI', and the `devicenumber` is interface number defined in the NI Measurement & Automation Explorer.

For PEAK-System devices `vendor` is the character vector 'PEAK-System', and the `devicenumber` is device number defined for the channel.

`canch = canChannel(____, 'ProtocolMode', 'CAN FD')` returns a channel connected to a device supporting CAN FD. The default `ProtocolMode` setting is 'CAN', indicating standard CAN support. A channel configured for 'CAN' cannot transmit or receive CAN FD messages.

Examples

Create CAN Channels for Various Vendors

Create CAN channels for each of several vendors.

```
canch1 = canChannel('Vector','CANCaseXL 1',1);
canch2 = canChannel('Vector','Virtual 1',2);
canch3 = canChannel('NI','CAN1');
canch4 = canChannel('PEAK-System','PCAN_USBBUS1');
canch5 = canChannel('MathWorks','Virtual 1',2)
```

```
canch5 =
Channel with properties:
Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 2
    DeviceSerialNumber: 0
```

```

        ProtocolMode: 'CAN'
Status Information
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 0
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: [0x0 datetime]
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

Channel Information
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    BusSpeed: 500000
    SJW: []
    TSEG1: []
    TSEG2: []
    NumOfSamples: []

Other Information
    Database: []
    UserData: []

```

Create CAN FD Channel

Create a CAN FD channel on a MathWorks virtual device.

```
canch6 = canChannel('MathWorks','Virtual 1',2,'ProtocolMode','CAN FD')
```

canch6 =

```

Channel with properties:

Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 2
    DeviceSerialNumber: 0
    ProtocolMode: 'CAN FD'

Status Information
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 0
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: [0x0 datetime]
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

Bit Timing Information
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    ArbitrationBusSpeed: []
    DataBusSpeed: []

Other Information
    Database: []
    UserData: []

```

Input Arguments

vendor — CAN device vendor

'MathWorks' | 'Kvaser' | 'NI' | 'PEAK-System' | 'Vector'

CAN device vendor, specified as 'MathWorks', 'Kvaser', 'NI', 'PEAK-System', or 'Vector'.

Example: 'MathWorks'

Data Types: char | string

device — CAN to connect channel to

character vector | string

CAN device to connect channel to, specified as a character vector or string. Valid values depend on the specified vendor.

Example: 'Virtual 1'

Data Types: char | string

devicechannelindex — CAN device channel port or index

numeric value

CAN device channel port or index, specified as a numeric value.

Example: 1

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64

Output Arguments

canch — CAN device channel

CAN channel object

CAN device channel, returned as a `can.Channel` object, with `can.Channel` Properties.

Tips

- Use `canChannelList` to obtain a list of available devices.
- You cannot have more than one `canChannel` configured on the same NI-XNET or PEAK-System device channel.
- You cannot use the same variable to create multiple channels sequentially. Clear any channel in use before using the same variable to construct a new CAN channel.
- You cannot create arrays of CAN channel objects. Each object you create must exist as its own individual variable.

See Also

Functions

`canChannelList`

Properties

`can.Channel` Properties

Introduced in R2009a

CAN.ChannelInfo class

Package: CAN

Display device channel information

Note `can.ChannelInfo` will be removed in a future release. Use `canChannelList` instead.

Description

`vendor.ChannelInfo(index)` displays channel information for the device `vendor` with the specified `index`. Obtain the vendor information using `CAN.VendorInfo`.

Input Arguments

index — Device channel index

numeric value

Device channel index specified as a numeric value.

Properties

Device

Name of the device.

DeviceChannelIndex

Index number of the specified device channel.

DeviceSerialNumber

Serial number of the specified device.

ObjectConstructor

Information on how to construct a CAN channel using this device.

Examples

Examine Kvaser Device Channel Information

Get information on installed CAN devices.

```
info = canHWInfo
```

```
info =
```

```
CAN Devices Detected
```

Vendor	Device	Channel	Serial Number	Constructor
Kvaser	Virtual 1	1	0	canChannel('Kvaser', 'Virtual 1', 1)
Kvaser	Virtual 1	2	0	canChannel('Kvaser', 'Virtual 1', 2)
Vector	Virtual 1	1	0	canChannel('Vector', 'Virtual 1', 1)
Vector	Virtual 1	2	0	canChannel('Vector', 'Virtual 1', 2)

Save the Kvaser device information in an object.

```
vendor = info.VendorInfo(1);
```

Get information on the first channel of the specified device.

```
vendor.ChannelInfo(1)
```

```
ans =
```

```
ChannelInfo with properties:
```

```
Device: 'Virtual 1'  
DeviceChannelIndex: 1  
DeviceSerialNumber: 0  
ObjectConstructor: 'canChannel('Kvaser', 'Virtual 1', 1)'
```

See Also

Functions

can.VendorInfo | canHWInfo

canChannelList

Information on available CAN devices

Syntax

```
chans = canChannelList
```

Description

`chans = canChannelList` returns a table of information about available CAN devices.

Examples

View Available CAN Devices

View available CAN devices and programmatically read a device's supported protocol modes.

```
chans = canChannelList
```

```
chans =
```

```
4x6 table
```

Vendor	Device	Channel	DeviceModel	ProtocolMode	SerialNumber
"MathWorks"	"Virtual 1"	1	"Virtual"	"CAN, CAN FD"	"0"
"MathWorks"	"Virtual 1"	2	"Virtual"	"CAN, CAN FD"	"0"
"Vector"	"Virtual 1"	1	"Virtual"	"CAN"	"0"
"Vector"	"Virtual 1"	2	"Virtual"	"CAN"	"0"

```
pm = chans{3,5}
```

```
pm =
```

```
"CAN"
```

```
pm = chans{3, 'ProtocolMode' }
```

```
pm =
```

```
"CAN"
```

Output Arguments

chans — Information on available CAN devices

table

Information on available CAN devices, returned as a table. To access specific elements, you can index into the table.

See Also

Functions
canChannel

Introduced in R2017b

canDatabase

Create handle to CAN database file

Syntax

```
candb = canDatabase('dbfile.dbc')
```

Description

`candb = canDatabase('dbfile.dbc')` creates a handle to the specified database file `dbfile.dbc`. You can specify a file name, a full path, or a relative path. MATLAB looks for `dbfile.dbc` on the MATLAB path. Vehicle Network Toolbox supports Vector CAN database (`.dbc`) files.

Examples

Create CAN Database Object

Create objects for example database files.

```
candb = canDatabase([matlabroot] '\examples\vnt\demoVNT_CANdbFiles.dbc')
```

```
candb =
```

Database with properties:

```

        Name: 'demoVNT_CANdbFiles'
        Path: 'F:\matlab\examples\vnt\demoVNT_CANdbFiles.dbc'
        Nodes: {}
        NodeInfo: [0×0 struct]
        Messages: {5×1 cell}
        MessageInfo: [5×1 struct]
        Attributes: {}
        AttributeInfo: [0×0 struct]
        UserData: []

```

```
candb = canDatabase([matlabroot] '\examples\vnt\J1939.dbc')
```

```
candb =
```

Database with properties:

```

        Name: 'J1939'
        Path: 'F:\matlab\examples\vnt\J1939.dbc'
        Nodes: {2×1 cell}
        NodeInfo: [2×1 struct]
        Messages: {2×1 cell}
        MessageInfo: [2×1 struct]
        Attributes: {3×1 cell}

```

```
AttributeInfo: [3x1 struct]  
UserData: []
```

Input Arguments

dbfile.dbc — Database file name

char vector | string

Database file name, specified as a character vector or string.. You can specify just the name or the full path of the database file.

Example: 'J1939.dbc'

Data Types: char | string

Output Arguments

candb — CAN database

database object

CAN database, returned as a database object with `can.Database Properties`.

See Also

Functions

`canMessage`

Properties

`can.Database Properties`

Introduced in R2009a

canFDChannel

Construct CAN FD channel connected to specified device

Syntax

```
canch = canFDChannel(vendor,device,devicechannelindex)
canch = canFDChannel(vendor,device)
```

Description

`canch = canFDChannel(vendor,device,devicechannelindex)` returns a CAN FD channel connected to a device from a specified vendor.

For Vector and Kvaser products, `device` combines the device type and a device index, such as 'CANCaseXL 1'. For example, if there are two Vector devices, `device` can be 'VN1610 1' or 'VN1610 2'.

`canch = canFDChannel(vendor,device)` returns a CAN FD channel connected to a National Instruments or PEAK-System device.

For National Instruments, `vendor` is the character vector 'NI', and the `devicenumber` is the interface number defined in the NI Measurement & Automation Explorer.

For PEAK-System devices `vendor` is the character vector 'PEAK-System', and `devicenumber` is the device number defined for the channel.

Examples

Create CAN FD Channels for Various Vendors

Create CAN FD channels for each of several vendors.

```
ch1 = canFDChannel('Vector','VN1610 1',1);
ch2 = canFDChannel('Kvaser','USBcan Pro 1',1);
ch3 = canFDChannel('NI','CAN0');
ch4 = canFDChannel('PEAK-System','PCAN_USBBUS1');
ch5 = canFDChannel('MathWorks','Virtual 1',1)
```

ch5 =

Channel with properties:

```
Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 1
    DeviceSerialNumber: 0
    ProtocolMode: 'CAN FD'
```

```
Status Information
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 0
    MessagesTransmitted: 0
    InitializationAccess: 1
```

```
InitialTimestamp: [0x0 datetime]
FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

Bit Timing Information
  BusStatus: 'N/A'
  SilentMode: 0
  TransceiverName: 'N/A'
  TransceiverState: 'N/A'
  ReceiveErrorCount: 0
  TransmitErrorCount: 0
  ArbitrationBusSpeed: []
  DataBusSpeed: []

Other Information
  Database: []
  UserData: []
```

Input Arguments

vendor — CAN device vendor

'MathWorks' | 'Kvaser' | 'NI' | 'PEAK-System' | 'Vector'

CAN device vendor, specified as 'MathWorks', 'Kvaser', 'NI', 'PEAK-System', or 'Vector'.

Example: 'MathWorks'

Data Types: char | string

device — CAN FD device to connect channel to

character vector | string

CAN FD device to connect channel to, specified as a character vector or string. Valid values depend on the specified vendor.

Example: 'Virtual 1'

Data Types: char | string

devicechannelindex — CAN FD device channel port or index

numeric value

CAN FD device channel port or index, specified as a numeric value.

Example: 1

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64

Output Arguments

canch — CAN FD device channel

CAN FD channel object

CAN FD device channel returned as a CAN channel object, with the following properties.

CAN Channel Properties:

CAN Device Properties:

Bit Timing Properties:

Tips

- Use `canFDChannelList` to obtain a list of available device channels.
- You cannot have more than one CAN FD channel configured on the same NI-XNET or PEAK-System device channel.
- You cannot use the same variable to create multiple channels sequentially. Clear any channel in use before using the same variable to construct a new channel object.
- You cannot create arrays of channel objects. Each object you create must exist as its own individual variable.

See Also

Functions

`canFDChannelList`

Introduced in R2018b

canFDChannelList

Information on available CAN FD device channels

Syntax

```
chans = canFDChannelList
```

Description

`chans = canFDChannelList` returns a table of information about available CAN FD devices.

Examples

View Available CAN FD Device Channels

View available CAN FD device channels and programmatically read supported protocol modes.

```
chans = canFDChannelList
```

```
chans =
```

```
2x6 table
```

Vendor	Device	Channel	DeviceModel	ProtocolMode	SerialNumber
"MathWorks"	"Virtual 1"	1	"Virtual"	"CAN, CAN FD"	"0"
"MathWorks"	"Virtual 1"	2	"Virtual"	"CAN, CAN FD"	"0"

```
pm = chans{2,5}
```

```
pm =
```

```
"CAN, CAN FD"
```

```
pm = chans{2, 'ProtocolMode'}
```

```
pm =
```

```
"CAN, CAN FD"
```

Output Arguments

chans — Information on available CAN FD devices

table

Information on available CAN FD device channels, returned as a table. To access specific elements, you can index into the table.

See Also

Functions

`canFDChannel`

Introduced in R2018b

canFDMessage

Build CAN FD message based on user-specified structure

Syntax

```
message = canFDMessage(id,extended,datalength)
message = canFDMessage(candb,messagename)
```

Description

`message = canFDMessage(id,extended,datalength)` creates a CAN FD message object from the raw message information.

`message = canFDMessage(candb,messagename)` creates a message using the message definition in the specified database. Because `ProtocolMode` is defined in the message database, you cannot specify it as an argument to `canFDMessage` when using a database.

Examples

Create a CAN FD Message with Database Definitions

Create a CAN FD message using the definitions of a CAN database.

```
candb = canDatabase(string([(matlabroot) '\examples\vnt\CANFDExample.dbc']));
message3 = canFDMessage(candb,'CANFDMessage')
```

```
message3 =
```

```
Message with properties:
```

```
Message Identification
  ProtocolMode: 'CAN FD'
             ID: 1
  Extended: 0
  Name: 'CANFDMessage'
```

```
Data Details
  Timestamp: 0
  Data: [1x48 uint8]
  Signals: []
  Length: 48
  DLC: 14
```

```
Protocol Flags
  BRS: 1
  ESI: 0
  Error: 0
```

```
Other Information
  Database: [1x1 can.Database]
```

```
UserData: []
```

Create a CAN FD Message

Create a CAN FD message with a standard ID format.

```
message2 = canFDMessage(1000, false, 64)
```

```
message2 =
```

```
Message with properties:
```

```
Message Identification
  ProtocolMode: 'CAN FD'
           ID: 1000
  Extended: 0
  Name: ''
```

```
Data Details
  Timestamp: 0
  Data: [1×64 uint8]
  Signals: []
  Length: 64
  DLC: 15
```

```
Protocol Flags
  BRS: 0
  ESI: 0
  Error: 0
```

```
Other Information
  Database: []
  UserData: []
```

Input Arguments

id — ID of message

numeric value

ID of the message, specified as a numeric value. If this ID used an extended format, set the **extended** argument **true**.

Example: 2500

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

extended — Specify if message ID is extended

`true` | `false`

Specifies whether the message ID is of standard or extended type, specified as **true** or **false**. The logical value **true** indicates that the ID is of extended type (29 bits), **false** indicates standard type (11 bits).

Example: `true`

Data Types: `logical`

dataLength — Length of message data

integer value 0 to 64

The length of the message data, specified as an integer value of 0 through 64, inclusive.

Example: 64

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

candb — CAN database

CAN database object

CAN database, specified as a database object. The database contains the message definition.

Example: `candb = canDatabase('CANDatabase.dbc')`

messageName — Name of message

char vector | string

The name of the message definition in the database, specified as a character vector or string.

Example: `'VehicleDataMulti'`

Data Types: `char` | `string`

Output Arguments

message — CAN FD message

CAN message object

CAN FD message, returned as a CAN message object, with the following properties:

Property	Purpose
BRS	CAN FD bit rate switch, as true or false
Data	Data of CAN message or J1939 parameter group
Database	CAN database information
DLC	Data length code value
Error	CAN message error frame, as true or false
ESI	CAN FD error state indicator, as true or false
Extended	True or false indication of extended CAN Identifier type
ID	Identifier for CAN message
Length	Message length in bytes
Name	CAN message name
ProtocolMode	Protocol mode defined as CAN or CAN FD
Remote	Specify if CAN message is remote frame
Signals	Physical signals defined in CAN message or J1939 parameter group

Property	Purpose
Timestamp	Message received timestamp
UserData	Custom data

See Also

Functions

[attachDatabase](#) | [canDatabase](#) | [extractAll](#) | [extractRecent](#) | [extractTime](#) | [pack](#) | [unpack](#)

Introduced in R2018b

canFDMessageBusType

Create Simulink CAN FD message bus

Syntax

```
canFDMessageBusType
canFDMessageBusType(modelName)
```

Description

canFDMessageBusType creates a Simulink CAN FD message bus object named CAN_FD_MESSAGE_BUS in the base workspace. The values of the object properties are read-only, but useful for showing the structure of its data.

canFDMessageBusType(modelName) creates a Simulink CAN FD message bus object named CAN_FD_MESSAGE_BUS in the data dictionary associated with the specified model, modelName.

Examples

Create CAN FD Message Bus Object

Create and view the properties of a Simulink CAN FD message bus object.

```
canFDMessageBusType
CAN_FD_MESSAGE_BUS

CAN_FD_MESSAGE_BUS =

    Bus with properties:

    Description: ''
    DataScope: 'Auto'
    HeaderFile: ''
    Alignment: -1
    Elements: [12x1 Simulink.BusElement]
```

View the Elements properties of the bus.

```
CAN_FD_MESSAGE_BUS.Elements

ans =

    12x1 BusElement array with properties:

    Min
    Max
    DimensionsMode
    SampleTime
    Description
    Unit
    Name
```

DataType
Complexity
Dimensions

Input Arguments

modelName — Name of model

char vector | string

Name of model, specified as a character vector or string, whose data dictionary is updated with the bus object.

Example: 'CANFDModel'

Data Types: char | string

See Also

Blocks

CAN FD Pack | CAN FD Receive | CAN FD Replay

Topics

“Create Custom CAN Blocks” on page 10-15

“Composite Signals” (Simulink)

Introduced in R2018a

canFDMessageReplayBlockStruct

Convert CAN FD messages for use as CAN Replay block output

Syntax

```
msgstructofarrays = canFDMessageReplayBlockStruct(msgs)
```

Description

`msgstructofarrays = canFDMessageReplayBlockStruct(msgs)` formats the specified CAN FD messages for use with the CAN FD Replay block. The CAN FD Replay block requires a specific format for CAN FD messages, defined by a structure of arrays containing the ID, Extended, Data, and other message elements.

Use this function to assign the formatted message structure to a variable. Then save that variable to a MAT-file. The CAN FD Replay block mask allows selection of this MAT file and the variable within it, to replay the messages in a Simulink model.

Examples

Create Message Structure for CAN FD Replay Block

Create a message structure for the CAN FD Replay block, and save it to a MAT-file.

```
canMsgs = canFDMessageReplayBlockStruct(messages);  
save('ReplayBlockMessages.mat', 'canMsgs');
```

Input Arguments

msgs — Original CAN FD messages

CAN message objects | CAN FD message timetable

Original CAN FD messages, specified as a CAN FD message timetable or an array of CAN message objects.

Output Arguments

msgstructofarrays — Formatted CAN FD messages

struct

Formatted CAN FD messages, returned as structure of arrays containing the ID, Extended, Data, and other elements of the messages.

See Also

Functions

`canFDMessageTimetable` | `save`

Blocks
CAN Replay

Introduced in R2018b

canFDMessageTimetable

Convert CAN or CAN FD messages into timetable

Syntax

```
msgtimetable = canFDMessageTimetable(msg)
msgtimetable = canFDMessageTimetable(msg,database)
```

Description

`msgtimetable = canFDMessageTimetable(msg)` creates a CAN FD message timetable from an existing CAN FD message timetable, an array of CAN message objects, or a CAN FD message structure from the CAN FD Log block. The output message timetable contains the raw message information (ID, Extended, Data, etc.) from the messages. If CAN message objects are input which contain decoded information, that decoding is retained in the CAN FD message timetable.

`msgtimetable = canFDMessageTimetable(msg,database)` uses the database to decode the message names and signals for the timetable along with the raw message information. Specify multiple databases in an array to decode message names and signals in the timetable within a single call.

The input `msg` can also be a timetable of data created by using `read` on an `mdfDatastore` object. In this case, the function converts the timetable of ASAM standard logging format data to a Vehicle Network Toolbox CAN FD message timetable.

Examples

Convert Log Block Output to Timetable

Convert log block output to a CAN FD message timetable.

```
load LogBlockOutput.mat;
db = canDatabase('myDatabase.dbc');
msgTimetable = canFDMessageTimetable(canMsgs,db);
```

Convert Message Objects to CAN FD Message Timetable

Convert an array of CAN message objects to a CAN FD message timetable.

```
msgTimetable = canFDMessageTimetable(canMsgs);
```

Decode Message Timetable with Database

Decode an existing CAN FD message timetable with a database.

```
db = canDatabase('myDatabase.dbc')
msgTimetable = canFDMessageTimetable(msgTimetable,db)
```

The result is returned to the original timetable variable.

Convert an ASAM MDF Message Timetable

Convert an existing ASAM format message timetable, and decode using a database.

```
m = mdf('CANandCANFD.MF4');
db = canDatabase('CustomerDatabase.dbc');
mdfData = read(m);
msgTimetable = canFDMessageTimetable(mdfData{2},db);
```

Compare the two timetables.

```
mdfData{2}(1:4,1:6)
```

```
ans =
```

```
4×6 timetable
```

Time	CAN_DataFrame_BusChannel	CAN_DataFrame_FlagsEx	CAN_DataFrame_Dir	CAN_DataFrame_SingleWire	CAN_DataFrame_V
0.30022 sec	1	2.1095e+06	1	0	0
0.45025 sec	1	2.0972e+06	1	0	0
0.60022 sec	1	2.1095e+06	1	0	0
0.75013 sec	1	2.1095e+06	1	0	0

```
msgTimetable(1:4,1:8)
```

```
ans =
```

```
4×8 timetable
```

Time	ID	Extended	Name	ProtocolMode	Data	Length	DLC	Signals
0.30022 sec	768	false	''	'CAN FD'	[1×64 uint8]	64	15	[0×0 struct]
0.45025 sec	1104	false	''	'CAN'	[1×8 uint8]	8	8	[0×0 struct]
0.60022 sec	768	false	''	'CAN FD'	[1×64 uint8]	64	15	[0×0 struct]
0.75013 sec	1872	false	''	'CAN FD'	[1×24 uint8]	24	12	[0×0 struct]

Input Arguments

msg — Raw CAN messages

CAN FD message timetable, array, or structure

Raw CAN messages, specified as a CAN FD message timetable, an array of CAN message objects, a CAN message structure from the CAN log block, or an `asam.MDF` object..

Example: `canFDMessage()`

database — CAN database

database object

CAN database, specified as a database object.

Example: `database = canDatabase('CANDatabase.dbc')`

Output Arguments

msgtimetable — CAN FD message timetable

timetable

CAN FD messages returned as a timetable.

See Also

Functions

`canDatabase` | `canSignalTimetable` | `mdfDatastore` | `read (MDFDatastore)`

Introduced in R2018b

canHWInfo

(To be removed) Information on available CAN devices

Note canHWInfo will be removed in a future release. Use canChannelList instead.

Syntax

```
hw = canHWInfo
```

Description

hw = canHWInfo returns information about CAN devices, and displays the information organized by vendors and channels.

Examples

Detect CAN Devices

Detect the available CAN devices and investigate a device channel.

```
hw = canHWInfo
```

```
hw =
```

```
CAN Devices Detected
```

Vendor	Device	Channel	Serial Number	Constructor...
MathWorks	Virtual 1	1	0	canChannel(...)
MathWorks	Virtual 1	2	0	canChannel(...)
Kvaser	Virtual 1	1	0	canChannel(...)
Kvaser	Virtual 1	2	0	canChannel(...)
NI	Virtual (CAN256)	1	0	canChannel(...)
NI	Virtual (CAN257)	2	0	canChannel(...)
NI	Series 847X Sync USB (CAN0)	1	12345C	canChannel(...)
NI	9862 CAN/HS (CAN1)	1	12345A	canChannel(...)
Vector	Virtual 1	1	0	canChannel(...)
Vector	Virtual 1	2	0	canChannel(...)
PEAK-System	PCAN-USB Pro (PCAN_USBBUS1)	1	0	canChannel(...)
PEAK-System	PCAN-USB Pro (PCAN_USBBUS2)	2	0	canChannel(...)

View the Vector properties to see its VendorDriverVersion.

```
v = hw.VendorInfo(4)
```

```
v =
```

```
VendorInfo with properties:
```

```

        VendorName: 'Vector'
VendorDriverDescription: 'XL Driver Library'
        VendorDriverVersion: '9000022'
        ChannelInfo: [1x2 can.vector.ChannelInfo]
```

View the first Vector channel information.

```
c1 = hw.VendorInfo(4).ChannelInfo(1)
```

```
c1 =
```

```
ChannelInfo with properties:
```

```
          Device: 'Virtual 1'  
DeviceChannelIndex: 1  
DeviceSerialNumber: 0  
ObjectConstructor: 'canChannel('Vector','Virtual 1',1)'
```

Output Arguments

hw – CAN devices detected

can.HardwareInfo object

CAN devices detected, returned as a can.HardwareInfo object. You can programmatically access vendor and channel information by indexing into the output object VendorInfo property.

See Also

Functions

canChannel | canChannelList

Introduced in R2009a

canMessage

Build CAN message based on user-specified structure

Syntax

```
message = canMessage(id,extended,datalength)
message = canMessage(id,extended,datalength,'ProtocolMode','CAN FD')
message = canMessage(candb,messagename)
```

Description

`message = canMessage(id,extended,datalength)` creates a CAN message object from the raw message information.

`message = canMessage(id,extended,datalength,'ProtocolMode','CAN FD')` creates a CAN FD message. The default `ProtocolMode` is standard 'CAN'.

`message = canMessage(candb,messagename)` creates a message using the message definition in the specified database. Because `ProtocolMode` is defined in the message database, you cannot specify it as an argument to `canMessage` when using a database.

Examples

Create a CAN Message

Create a CAN message with an extended ID format.

```
message1 = canMessage(2500,true,4)
```

```
message1 =
```

```
  Message with properties:
```

```
  Message Identification
    ProtocolMode: 'CAN'
             ID: 2500
    Extended: 1
    Name: ''

  Data Details
    Timestamp: 0
    Data: [0 0 0 0]
    Signals: []
    Length: 4
```

```
  Protocol Flags
    Error: 0
    Remote: 0
```

```
  Other Information
```

```
Database: []  
UserData: []
```

Create a CAN FD Message

Create a CAN FD message with a standard ID format.

```
message2 = canMessage(1000,false,64,'ProtocolMode','CAN FD')
```

```
message2 =
```

```
Message with properties:
```

```
Message Identification  
  ProtocolMode: 'CAN FD'  
           ID: 1000  
  Extended: 0  
  Name: ''
```

```
Data Details  
  Timestamp: 0  
  Data: [1×64 uint8]  
  Signals: []  
  Length: 64  
  DLC: 15
```

```
Protocol Flags  
  BRS: 0  
  ESI: 0  
  Error: 0
```

```
Other Information  
  Database: []  
  UserData: []
```

Create a Message with Database Definitions

Create a message using the definitions of a CAN database.

```
candb = canDatabase(string([(matlabroot) '\examples\vnt\VehicleInfo.dbc']))  
message3 = canMessage(candb,'WheelSpeeds')
```

```
message3 =
```

```
Message with properties:
```

```
Message Identification  
  ProtocolMode: 'CAN'  
           ID: 1200  
  Extended: 0  
  Name: 'WheelSpeeds'
```

```
Data Details  
  Timestamp: 0  
  Data: [0 0 0 0 0 0 0 0]
```



```

    Signals: [1×1 struct]
    Length: 8

    Protocol Flags
    Error: 0
    Remote: 0

    Other Information
    Database: [1×1 can.Database]
    UserData: []

```

Input Arguments

id — ID of message

numeric value

ID of the message, specified as a numeric value. If this ID used an extended format, set the `extended` argument `true`.

Example: 2500

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

extended — Indicate if message ID is extended

`true` | `false`

Indicates whether the message ID is of standard or extended type, specified as `true` or `false`. The logical value `true` indicates that the ID is of extended type, `false` indicates standard type.

Example: `true`

Data Types: `logical`

dataLength — Length of message data

integer value 0-8

The length of the message data, specified as an integer value of 0 through 8, inclusive.

Example: 8

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

canDb — CAN database

CAN database object

CAN database, specified as a database object. The database contains the message definition.

Example: `canDb = canDatabase('CANdb.dbc')`

messageName — Name of message

char vector | string

The name of the message definition in the database, specified as a character vector or string.

Example: `'VehicleDataMulti'`

Data Types: `char` | `string`

Output Arguments

message — CAN message

CAN message object

CAN message, returned as a CAN message object, with `can.Message` Properties.

See Also

Functions

`attachDatabase` | `canDatabase` | `extractAll` | `extractRecent` | `extractTime` | `pack` | `unpack`

Properties

`can.Message` Properties

Introduced in R2009a

canMessageBusType

Create Simulink CAN message bus

Syntax

```
canMessageBusType
canMessageBusType(modelName)
```

Description

`canMessageBusType` creates a Simulink CAN message bus object named `CAN_MESSAGE_BUS` in the base workspace. The values of the object properties are read-only, but useful for showing the structure of its data.

`canMessageBusType(modelName)` creates a Simulink CAN message bus object of type `CAN_MESSAGE_BUS` in the data dictionary associated with the specified model, `modelName`.

Examples

Create CAN Message Bus Object

Create and view the properties of a Simulink CAN message bus object.

```
canMessageBusType
CAN_MESSAGE_BUS

CAN_MESSAGE_BUS =

    Bus with properties:

    Description: ''
    DataScope: 'Auto'
    HeaderFile: ''
    Alignment: -1
    Elements: [7×1 Simulink.BusElement]
```

View the `Elements` properties.

```
CAN_MESSAGE_BUS.Elements

ans =

    7×1 BusElement array with properties:

    Min
    Max
    DimensionsMode
    SampleTime
    Description
    Unit
    Name
```

DataType
Complexity
Dimensions

Input Arguments

modelName — Name of model

char vector | string

Name of model, specified as a character vector or string, whose data dictionary is updated with the bus object.

Example: 'CANModel'

Data Types: char | string

See Also

Blocks

CAN Pack | CAN Receive | CAN Replay

Topics

“Create Custom CAN Blocks” on page 10-15

“Composite Signals” (Simulink)

Introduced in R2017b

canMessageImport

Import CAN messages from third-party log file

Syntax

```
message = canMessageImport(file,vendor)
message = canMessageImport(file,vendor,candb)
message = canMessageImport( ____, 'OutputFormat', 'timetable')
```

Description

`message = canMessageImport(file,vendor)` imports CAN messages from the log file, `file`, from a third-party vendor, `vendor`. All the messages in the log file are imported as an array of CAN message objects.

After importing, you can analyze, transmit, or replay these messages.

`canMessageImport` assumes that the information in the imported log file is in a hexadecimal format, and that the timestamps in the imported log file are absolute values.

`message = canMessageImport(file,vendor,candb)` applies the information in the specified database to the imported CAN log messages.

To import Vector log files with symbolic message names, specify an appropriate database file.

`message = canMessageImport(____, 'OutputFormat', 'timetable')` returns a timetable of messages. This is the recommended output format for optimal performance and representation of CAN messages within MATLAB.

Examples

Import Raw Messages

Import raw messages from a log file.

```
message = canMessageImport('MsgLog.asc','Vector','OutputFormat','timetable');
```

Import Messages with Database

Import messages from a log file, using database information for physical messages.

```
candb = canDatabase('myDatabase.dbc');
message = canMessageImport('MsgLog.txt','Kvaser',candb,'OutputFormat','timetable');
```

Input Arguments

file — Name of CAN message log file

char vector | string

Name of CAN message log file, specified as a character vector or string.

Example: 'MsgLog.asc'

Data Types: char | string

vendor — Name of vendor

char vector | string

Name of vendor, specified as a character vector or string, whose CAN message log file you are importing from.

You can import message logs only in certain file formats: ASCII files from Vector, and text files from Kvaser.

Example: 'Vector'

Data Types: char | string

candb — CAN database

database object

CAN database, specified as a database object. This is the database whose information is applied to the imported log file messages.

Example: `candb = canDatabase('CANdb.dbc')`

Output Arguments

message — Imported messages

array of CAN message objects | timetable

Imported messages, returned as an array of CAN message objects or as a timetable of messages.

See Also

Functions

`canDatabase` | `receive` | `transmit`

Introduced in R2010b

canMessageReplayBlockStruct

Convert CAN messages for use as CAN Replay block output

Syntax

```
msgstructofarrays = canMessageReplayBlockStruct(msgs)
```

Description

`msgstructofarrays = canMessageReplayBlockStruct(msgs)` formats specified CAN messages for use with the CAN Replay block. The CAN Replay block requires a specific format for CAN messages, defined by a structure of arrays containing the ID, Extended, Data, and other message elements.

Use this function to assign the formatted message structure to a variable. Then save this variable to a MAT-file. The CAN Replay block mask allows selection of this MAT file and the variable within it, to define the messages to replay in a Simulink model.

Examples

Create CAN Replay Block Message Structure

Create a message structure for the CAN Replay block, and save it to a MAT-file.

```
canMsgs = canMessageReplayBlockStruct(messages);  
save('ReplayBlockMessages.mat', 'canMsgs');
```

Input Arguments

msgs — Original CAN messages

CAN message objects | CAN message timetable

Original CAN messages, specified as a CAN message timetable or an array of CAN message objects.

Output Arguments

msgstructofarrays — Formatted CAN messages

struct

Formatted CAN messages, returned as structure of arrays containing the ID, Extended, Data, and other elements of the messages.

See Also

Functions

canMessageTimetable | save

Blocks
CAN Replay

Introduced in R2017a

canMessageTimetable

Convert CAN messages into timetable

Syntax

```
msgtimetable = canMessageTimetable(msg)
msgtimetable = canMessageTimetable(msg,database)
```

Description

`msgtimetable = canMessageTimetable(msg)` creates a CAN message timetable from existing raw messages. The output message timetable contains the raw message information (ID, Extended, Data, etc.) from the messages. If CAN message objects are input which contain decoded information, that decoding is retained in the CAN message timetable. A timetable of CAN message data can often provide better performance than using CAN message objects.

`msgtimetable = canMessageTimetable(msg,database)` uses the database to decode the message names and signals for the timetable along with the raw message information. Specify multiple databases in an array to decode message names and signals in the timetable within a single call.

The input `msg` can also be a timetable of data created by using `read` on an `mdf` object. In this case, the function converts the timetable of ASAM standard logging format data to a Vehicle Network Toolbox CAN message timetable.

Examples

Convert Log Block Output to Timetable

Convert log block output to a CAN message timetable.

```
load LogBlockOutput.mat
db = canDatabase('myDatabase.dbc')
msgTimetable = canMessageTimetable(canMsgs,db)
```

Convert CAN Message Objects to Timetable

Convert legacy CAN message objects to a CAN message timetable.

```
msgTimetable = canMessageTimetable(canMsgs);
```

Decode Message Timetable with Database

Decode an existing CAN message timetable with a database.

```
db = canDatabase('myDatabase.dbc')
msgTimetable = canMessageTimetable(msgTimetable,db)
```

Convert an ASAM MDF Message Timetable

Convert an existing ASAM format message timetable, and decode using a database.

```
m = mdf('mdfFiles\CANonly.MF4');
db = canDatabase('dbFiles\dGenericVehicle.dbc');
mdfData = read(m);
msgTimetable = canMessageTimetable(mdfData{1},db);
```

Compare the two timetables.

```
mdfData{1}(1:4,1:6)
```

```
ans =
```

```
4x6 timetable
```

Time	CAN_DataFrame_DataLength	CAN_DataFrame_WakeUp	CAN_DataFrame_SingleWire	CAN_DataFrame_IDE	CAN_DataFrame_...
0.019968 sec	4	0	0	0	100
0.029964 sec	4	0	0	0	100
0.039943 sec	4	0	0	0	100
0.049949 sec	4	0	0	0	100

```
msgTimetable(1:4,1:6)
```

```
ans =
```

```
4x6 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
0.019968 sec	100	false	''	[1x4 uint8]	4	[0x0 struct]
0.029964 sec	100	false	''	[1x4 uint8]	4	[0x0 struct]
0.039943 sec	100	false	''	[1x4 uint8]	4	[0x0 struct]
0.049949 sec	100	false	''	[1x4 uint8]	4	[0x0 struct]

Input Arguments

msg — CAN message data

CAN message timetable, array, or structure

CAN message data, specified as a CAN message timetable, an array of CAN message objects, or a CAN message structure from the CAN log block.

database — CAN database

database handle

CAN database, specified as a database handle.

Output Arguments

msgtimetable — CAN message timetable

timetable

CAN messages returned as a timetable.

See Also

Functions

canDatabase | canSignalTimetable | mdf

Introduced in R2017a

canSignalImport

Import CAN log file into decoded signal timetables

Syntax

```
sigtimetable = canSignalImport(file,vendor,database)
sigtimetable = canSignalImport(file,vendor,database,msgnames)
```

Description

`sigtimetable = canSignalImport(file,vendor,database)` imports a CAN message log file from the specified vendor directly into decoded signal value timetables using the provided database. The function returns a structure with a field for each unique message in the timetable. Each field value is a timetable of all the signals in all instances of that message. Use this form of syntax to convert an entire set of messages in a single function call.

`sigtimetable = canSignalImport(file,vendor,database,msgnames)` returns signal timetables for only the messages specified by `msgnames`, which can specify one or more message names. Use this syntax form to import signals from only a subset of messages.

Examples

Import Signals from Log for All Messages

Create signal timetables from all messages in a log file.

```
db = canDatabase('MyDatabase.dbc');
sigtimetable = canSignalImport('MsgLog.asc','Vector',db);
```

Import Signals from Log for Specified Messages

Create signal timetables from specified messages in a log file.

```
db = canDatabase('MyDatabase.dbc');
sigtimetable1 = canSignalImport('MsgLog.asc','Vector',db,'Message1');
sigtimetable2 = canSignalImport('MsgLog.asc','Vector',db,{'Message1','Message2'});
```

Input Arguments

file — CAN message log file

character vector | string

CAN message log file, specified as a character vector or string.

Example: 'MyDatabase.dbc'

Data Types: char | string

vendor — Vendor file format`'Kvaser' | 'Vector'`

Vendor file format, specified as a character vector or string. The supported file formats are those defined by Vector and Kvaser.

Example: `'Vector'`

Data Types: `char | string`

database — CAN database`database handle`

CAN database, specified as a database handle.

msgnames — Message names`char | string | cell`

Message names, specified as a character vector, string, or array.

Example: `'message1'`

Data Types: `char | string | cell`

Output Arguments

sigtimetable — CAN signals`structure`

CAN signals, returned as a structure. The structure field names correspond to the messages of the input, and each field value is a timetable of CAN signals.

Data Types: `struct`

See Also

Functions`canDatabase | canMessageImport | canSignalTimetable`

Introduced in R2017a

canSignalTimetable

Create CAN signal timetable from CAN message timetable

Syntax

```
sigtimetable = canSignalTimetable(msgtimetable)
sigtimetable = canSignalTimetable(msgtimetable,msgnames)
```

Description

`sigtimetable = canSignalTimetable(msgtimetable)` converts a timetable of CAN message information into individual timetables of signal values. The function returns a structure with a field for each unique message in the timetable. Each field value is a timetable of all the signals in that message. Use this syntax form to convert an entire set of messages in a single function call.

`sigtimetable = canSignalTimetable(msgtimetable,msgnames)` returns signal timetables for only the messages specified by `msgnames`, which can specify one or more message names. Use this syntax form to quickly convert only a subset of messages into signal timetables.

Examples

Create CAN Signal Timetables from All Messages

Create CAN signal timetables from all messages in a CAN message timetable.

```
sigTable = canSignalTimetable(msgTimetable);
```

Create CAN Signal Timetable from Specified Messages

Create CAN signal timetables from only specified messages in a CAN message timetable.

```
sigTable1 = canSignalTimetable(msgTimetable,'Message1');
sigTable2 = canSignalTimetable(msgTimetable,{'Message1','Message2'});
```

Input Arguments

msgtimetable — CAN message timetable

timetable

CAN messages, specified as a timetable.

msgnames — Message names

char | string | cell

Message names, specified as a character vector, string, or array.

Data Types: char | string | cell

Output Arguments

sigtimetable – CAN signals

structure

CAN signals, returned as a structure. The structure field names correspond to the messages of the input, and each field value is a timetable of CAN signals.

Data Types: `struct`

See Also

Functions

`canMessageTimetable` | `canSignalImport`

Introduced in R2017a

canSupport

Generate technical support log

Syntax

```
canSupport
```

Description

canSupport generates diagnostic information for all installed CAN devices and saves the results to the text file `cansupport.txt` in the current working folder. The MATLAB Editor opens the file for you to view.

For online support, see the **Product Resources** section of the Vehicle Network Toolbox web page.

Examples

Generate Support Log

Generate a technical support log file and view it in the MATLAB editor.

```
canSupport
```

See Also

Functions

canChannelList

External Websites

Vehicle Network Toolbox

Introduced in R2009a

canTool

Open Vehicle CAN Bus Monitor

Syntax

```
canTool
```

Description

canTool starts the Vehicle CAN Bus Monitor, which displays live CAN message traffic. This app allows you to view message traffic using a selected CAN device and channel, and to save messages to a log file.

Examples

Open Vehicle CAN Bus Monitor

Open the Vehicle CAN Bus Monitor app.

```
canTool
```

See Also

Apps

Vehicle CAN Bus Monitor

Topics

“Using the Vehicle CAN Bus Monitor” on page 5-7

“Vehicle CAN Bus Monitor” on page 5-2

Introduced in R2009a

CAN.VendorInfo class

Package: CAN

Display available device vendor information

Note `can.VendorInfo` will be removed in a future release. Use `canChannelList` instead.

Syntax

```
info = canHWInfo
info.VendorInfo(index)
```

Description

`info = canHWInfo` creates an object with information of all available CAN hardware devices.

`info.VendorInfo(index)` displays available vendor information obtained from `canHWInfo` for the device with the specified `index`.

Input Arguments

index — Device channel index

numeric value

Device channel index specified as a numeric value.

Properties

VendorName

Name of the device vendor.

VendorDriverDescription

Description of the device driver installed for this vendor.

VendorDriverVersion

Version of the device driver installed for this vendor.

ChannelInfo

Information on the device channels available for this vendor.

Examples

Examine Kvaser Vendor Information

Get information on installed CAN devices.

```
info = canHWInfo
```

```
info =
```

```
CAN Devices Detected
```

Vendor	Device	Channel	Serial Number	Constructor
Kvaser	Virtual 1	1	0	canChannel('Kvaser', 'Virtual 1', 1)
Kvaser	Virtual 1	2	0	canChannel('Kvaser', 'Virtual 1', 2)
Vector	Virtual 1	1	0	canChannel('Vector', 'Virtual 1', 1)
Vector	Virtual 1	2	0	canChannel('Vector', 'Virtual 1', 2)

Use GET on the output of canHWInfo for more information.

Parse the objects VendorInfo class.

```
info.VendorInfo
```

```
ans =
```

```
1x2 heterogeneous VendorInfo (VendorInfo, VendorInfo) array with properties:
```

```
VendorName
VendorDriverDescription
VendorDriverVersion
ChannelInfo
```

See Also

Functions

CAN.ChannelInfo | canHWInfo

cdfx

Access information contained in CDFX-file

Syntax

```
cdfxObj = cdfx(CDFXfile)
```

Description

`cdfxObj = cdfx(CDFXfile)` creates an `asam.cdfx` object and imports the calibration data from the specified CDFX-file.

Examples

Access CDFX-File

Create an `asam.cdfx` object containing the calibration data from a CDFX-file.

```
cdfxObj = cdfx('c:\DataFiles\AllCategories_VCD.cdfx')
```

```
cdfxObj =
```

```
    CDFX with properties:
```

```
        Name: "AllCategories_VCD.cdfx"
```

```
        Path: "c:\DataFiles\AllCategories_VCD.cdfx"
```

```
        Version: "CDF20"
```

Input Arguments

CDFXfile — Calibration data format CDFX-file

char | string

Calibration data format CDFX-file, specified as a character vector or string. `CDFXfile` can specify the file name in the current folder, or the full or relative path to the CDFX-file. For restrictions on the file content, see “File Format Limitations” on page 11-5.

Example: 'ASAMCDFExample.cdfx'

Data Types: char | string

Output Arguments

cdfxObj — CDFX-file object

`asam.cdfx` object

CDFX-file object, returned as an `asam.cdfx` object. Use the object to access the calibration data.

See Also

Functions

getValue | instanceList | setValue | systemList | write

Introduced in R2019a

channelList

Information on available MDF groups and channels

Syntax

```
chans = channelList(mdfobj)
channelList(mdfObj, chanName)
channelList(mdfObj, chanName, 'ExactMatch', true)
```

Description

`chans = channelList(mdfobj)` returns a table of information about channels and groups in the specified MDF-file.

`channelList(mdfObj, chanName)` searches the MDF-file to generate a list of channels matching the specified channel name. The search by default is case-insensitive and identifies partial matches. A table is returned containing information about the matched channels and the containing channel groups. If no matches are found, an empty table is returned.

`channelList(mdfObj, chanName, 'ExactMatch', true)` searches the channels for an exact match, including case sensitivity. This is useful if a channel name is a substring of other channel names.

Examples

View Available MDF Channels

View all available MDF channels.

```
mdfObj = mdf('File01.mf4');
chans = channelList(mdfObj)
```

chans =

4×9 table

ChannelName	ChannelGroupNumber	ChannelGroupNumSamples
"Float_32_LE_Offset_64"	2	10000
"Float_64_LE_Master_Offset_0"	2	10000
"Sigend_Int16_LE_Offset_32"	1	10000
"Unsigend_UInt32_LE_Master_Offset_0"	1	10000

View Specific MDF Channels

Filter on channel names.

```
chans = channelList(mdfObj, 'Float')
```

chans =

2×9 table

ChannelName	ChannelGroupNumber	ChannelGroupNumSamples
"Float_32_LE_Offset_64"	2	10000
"Float_64_LE_Master_Offset_0"	2	10000

```
chans = channelList(mdfObj, 'Float', 'ExactMatch', true)
```

```
chans =
```

```
0×9 empty table
```

Input Arguments

mdfObj — MDF-file

MDF-file object

MDF-file, specified as an MDF-file object.

Example: `mdf('File01.mf4')`

chanName — Name of channel

char vector | string

Name of channel, specified as a character vector or string. By default, case-insensitive and partial matches are returned.

Example: `'Channel1'`

Data Types: `char` | `string`

Output Arguments

chans — Information on available MDF channels

table

Information on available MDF channels, returned as a table. To access specific elements, you can index into the table.

See Also

Functions

`mdf`

Introduced in R2018b

configBusSpeed

Set bit timing rate of CAN channel

Syntax

```
configBusSpeed(canch, busspeed)
```

```
configBusSpeed(canch, busspeed, SJW, TSeg1, TSeg2, numsamples)
```

```
configBusSpeed(canch, arbbusspeed, databusspeed)
```

```
configBusSpeed(canch, arbbusspeed, arbSJW, arbTSeg1, arbTSeg2, databusspeed,
dataSJW, dataTSeg1, dataTSeg2)
```

```
configBusSpeed(canch, clockfreq, arbBRP, arbSJW, arbTSeg1, arbTSeg2, dataBRP,
dataSJW, dataTSeg1, dataTSeg2)
```

Description

`configBusSpeed(canch, busspeed)` sets the speed of the CAN channel in a direct form that uses baseline bit timing calculation factors.

- Unless you have specific timing requirements for your CAN connection, use the direct form of `configBusSpeed`. Also note that you can set the bus speed only when the CAN channel is offline. The channel must also have initialization access to the CAN device.
- Synchronize all nodes on the network for CAN to work successfully. However, over time, clocks on different nodes will get out of sync, and must resynchronize. `SJW` specifies the maximum width (in time) that you can add to `TSeg1` (in a slower transmitter), or subtract from `TSeg2` (in a faster transmitter) to regain synchronization during the receipt of a CAN message.

`configBusSpeed(canch, busspeed, SJW, TSeg1, TSeg2, numsamples)` sets the speed of the CAN channel `canch` to `busspeed` using the specified bit timing calculation factors to control the timing in an advanced form.

Note Before you can start a channel to transmit or receive CAN FD messages, you must configure its bus speed.

`configBusSpeed(canch, arbbusspeed, databusspeed)` sets the arbitration and data bus speeds of `canch` using default bit timing calculation factors for CAN FD. This syntax supports NI and MathWorks virtual devices.

`configBusSpeed(canch, arbbusspeed, arbSJW, arbTSeg1, arbTSeg2, databusspeed, dataSJW, dataTSeg1, dataTSeg2)` sets the data and arbitration bus speeds of `canch` using the specified bit timing calculation factors in an advanced form for CAN FD. This syntax supports Kvaser and Vector devices.

`configBusSpeed(canch, clockfreq, arbBRP, arbSJW, arbTSeg1, arbTSeg2, dataBRP, dataSJW, dataTSeg1, dataTSeg2)` sets the data and arbitration bus speeds of `canch` using the specified bit timing calculation factors in an advanced form for CAN FD. This syntax supports PEAK-System devices.

Examples

Configure Bus Speed

Configure the bus speed using baseline bit timing calculation.

Configure for CAN.

```
canch = canChannel('Vector', 'CANCASEXL 1', 1);
configBusSpeed(canch, 250000)
```

Configure CAN FD on MathWorks virtual channel.

```
canch = canChannel('MathWorks', 'Virtual 1', 1, 'ProtocolMode', 'CAN FD');
configBusSpeed(canch, 1000000, 2000000)
```

Configure CAN FD on National Instruments device.

```
canch = canChannel('NI', 'CAN1', 'ProtocolMode', 'CAN FD');
configBusSpeed(canch, 1000000, 2000000)
```

Specify Bit Timing Parameters

Configure the bus speed, specifying the bit timing parameters.

Configure CAN on Kvaser device.

```
canch = canChannel('Kvaser', 'USBcan Professional 1', 1);
configBusSpeed(canch, 500000, 1, 4, 3, 1)
```

Configure CAN FD on Kvaser device.

```
canch = canChannel('Kvaser', 'USBcan Pro 1', 1, 'ProtocolMode', 'CAN FD');
configBusSpeed(canch, 1e6, 2, 6, 3, 2e6, 2, 6, 3)
```

Configure CAN FD on Vector device.

```
canch = canChannel('Vector', 'VN1610 1', 1, 'ProtocolMode', 'CAN FD');
configBusSpeed(canch, 1e6, 2, 6, 3, 2e6, 2, 6, 3)
```

Configure CAN FD on PEAK-System device.

```
canch = canChannel('PEAK-System', 'PCAN_USBBUS1', 'ProtocolMode', 'CAN FD');
configBusSpeed(canch, 20, 5, 1, 2, 1, 2, 1, 3, 1)
```

Input Arguments

canch — CAN channel

CAN channel object

CAN channel, specified as a CAN channel object.

busspeed — Bit rate for channel

double

Bit rate for channel, specified as a double. Provide the speed of the network in bits per second.

Example: 250000

Data Types: double

SJW — Synchronization jump width

double

Synchronization jump width, specified as a double. Define the length of a bit on the network.

Data Types: double

TSeg1 — Time segment 1

double

Time segment 1, specified as a double, which defines the section before a bit is sampled on the network.

Data Types: double

TSeg2 — Time segment 2

double

Time segment 2, specified as a double, which defines the section after a bit is sampled on a network.

Data Types: double

numsamples — Number of samples for bit state

double

Number of samples for bit state, specified as a double. Specify the number of samples used for determining the bit state of a network.

Data Types: double

arbusspeed — Arbitration bit rate for channel

double

Arbitration bit rate for channel, specified as a double. Provide the speed of the network in bits per second.

Example: 250000

Data Types: double

arbSJW — Arbitration synchronization jump width

double

Arbitration synchronization jump width, specified as a double. Define the length of a bit on the network.

Data Types: double

arbTSeg1 — Arbitration time segment 1

double

Arbitration time segment 1, specified as a double, which defines the section before a bit is sampled on the network.

Data Types: double

arbTSeg2 — Arbitration time segment 2

double

Arbitration time segment 2, specified as a double, which defines the section after a bit is sampled on a network.

Data Types: double

databusspeed — Data bit rate for channel

double

Data bit rate for channel, specified as a double. Provide the speed of the network in bits per second.

Example: 250000

Data Types: double

dataSJW — Data synchronization jump width

double

Data synchronization jump width, specified as a double. Define the length of a bit on the network.

Data Types: double

dataTSeg1 — Data time segment 1

double

Data time segment 1, specified as a double, which defines the section before a bit is sampled on the network.

Data Types: double

dataTSeg2 — Data time segment 2

double

Data time segment 2, specified as a double, which defines the section after a bit is sampled on a network.

Data Types: double

clockfreq — Clock frequency

double

Clock frequency for channel in MHz, specified as a double.

Example: 250000

Data Types: double

arbBRP — Arbitration clock prescalar for time quantum

double

Arbitration clock prescalar for time quantum, specified as a double.

Example: 250000

Data Types: double

dataBRP — Data clock prescalar for time quantum

double

Data clock prescalar for time quantum, specified as a double.

Example: 250000

Data Types: double

See Also

Functions

canChannel | start

Introduced in R2009a

configBusSpeed (J1939)

Configure bit timing of J1939 channel

Syntax

```
configBusSpeed(chan, busspeed)
configBusSpeed(chan, busspeed, SJW, TSeg1, TSeg2, numsamples)
```

Description

`configBusSpeed(chan, busspeed)` sets the speed of the J1939 channel `chan` to `busspeed` in a direct form that uses default bit timing calculation factors.

Note You can set bit timing only when the channel is offline and has initialization access to the device.

`configBusSpeed(chan, busspeed, SJW, TSeg1, TSeg2, numsamples)` sets the speed of the channel using specified bit timing calculation factors.

Note Unless you have specific timing requirements provided for your network, you should use the direct form of the function.

Examples

Set Bus Speed for Channel Directly

Use the direct form of syntax to configure a J1939 channel bus speed.

```
db = canDatabase('MyDatabase.dbc');
chan = j1939Channel(db, 'Vector', 'CANCaseXL 1', 1);
configBusSpeed(chan, 250000)
```

Set Bus Speed for Channel with Calculation Factors

Use the advanced form of syntax to configure a J1939 channel bus speed with specific calculation factors.

```
db = canDatabase('MyDatabase.dbc');
chan = j1939Channel(db, 'Vector', 'CANCaseXL 1', 1);
configBusSpeed(chan, 500000, 1, 4, 3, 1)
```

Input Arguments

chan — J1939 channel
channel object

J1939 channel, specified as a channel object. Use the `j1939Channel` function to create and define the channel.

busspeed — Bit rate for channel

double

Bit rate for channel, specified as a double. Provide the speed of the network in bits per second.

Example: 250000

Data Types: double

SJW — Synchronization jump width

double

Synchronization Jump Width, specified as a double. Define the length of a bit on a network.

Data Types: double

TSeg1 — Time segment 1

double

Time segment 1, specified as a double, which defines the section before a bit is sampled on a network.

Data Types: double

TSeg2 — Time segment 2

double

Time segment 2, specified as a double, which defines the section after a bit is sampled on a network.

Data Types: double

numSamples — Number of samples for bit state

double

Number of samples for bit state, specified as a double. Specify the number of samples used for determining the bit state of a network.

Data Types: double

See Also**Functions**

`j1939Channel` | `start` | `stop` | `transmit`

Introduced in R2015b

connect

Connect XCP channel to slave module

Syntax

```
connect(xcpch)
```

Description

`connect(xcpch)` creates an active connection between the XCP channel and the slave module, enabling active messaging between the channel and the slave.

Examples

Connect to a Slave Module

Create an XCP channel connected to a Vector CAN device on a virtual channel and connect it.

Link an A2L file to and create an XCP channel with it.

```
a2lfile = xcpA2L('XCPSIM.a2l')
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);
```

Connect the channel and verify that it is connected.

```
connect(xcpch)
isConnected(xcpch)
```

```
ans =
```

```
1
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

See Also

Functions

`readSingleValue` | `writeSingleValue` | `xcpA2L` | `xcpChannel`

Introduced in R2013a

createMeasurementList

Create measurement list for XCP channel

Syntax

```
createMeasurementList(xcpch, resource, eventName, measurementName)
createMeasurementList(xcpch, resource, eventName, {measurementName,
measurementName, measurementName})
```

Description

`createMeasurementList(xcpch, resource, eventName, measurementName)` creates a data stimulation list for the XCP channel with the specified event and measurement.

`createMeasurementList(xcpch, resource, eventName, {measurementName, measurementName, measurementName})` creates a data stimulation list for the XCP channel with the specified event and list of measurements.

Examples

Create a DAQ Measurement List

Create an XCP channel connected to a Vector CAN device on a virtual channel and set up a DAQ measurement list.

```
a2lfile = xcp.A2L('XCPSIM.a2l')
xcpch = xcp.Channel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1)
xcpch =
```

Channel with properties:

```
SlaveName: 'CPP'
A2LFileName: 'XCPSIM.a2l'
TransportLayer: 'CAN'
TransportLayerDevice: [1x1 struct]
SeedKeyDLL: []
```

Connect the channel to the slave module.

```
connect(xcpch)
```

Setup a data acquisition measurement list with the '10 ms' event and 'Triangle' measurement.

```
createMeasurementList(xcpch, 'DAQ', '10 ms', 'Triangle');
```

Create a Data Stimulation List

Create an XCP channel connected to a Vector CAN device on a virtual channel and set up a STIM measurement list.


```

a2l = xcp.A2L('XCPSIM.a2l')
xcpch = xcp.Channel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1)
xcpch =
    Channel with properties:
        SlaveName: 'CPP'
        A2LFileName: 'XCPSIM.a2l'
        TransportLayer: 'CAN'
        TransportLayerDevice: [1x1 struct]
        SeedKeyDLL: []

```

Connect the channel to the slave module.

```
connect(xcpch)
```

Setup a data stimulation measurement list with the '100ms' event and 'PWM' and 'ShiftByte' measurements.

```
createMeasurementList(xcpch, 'STIM', '100ms', {'PWM','ShiftByte'});
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

resource — Measurements list type

'DAQ' | 'STIM'

Measurement list type, specified as 'DAQ' or 'STIM'.

Example: 'DAQ'

Data Types: char | string

eventName — Name of event

character vector | string

Name of event, specified as a character vector or string. The event is used to trigger the specified measurement list. The list of available events depends on your A2L file.

Data Types: char | string

measurementName — Name of single XCP measurement

character vector | string | array

Name of a single XCP measurement, specified as a character vector or string; or a set of measurements, specified as a cell array of character vectors or array of strings. Make sure `measurementName` matches the corresponding measurement names defined in your A2L file.

See Also

`freeMeasurementLists` | `startMeasurement` | `viewMeasurementLists`

Introduced in R2013a

discard

Discard all messages from CAN channel

Syntax

```
discard(canch)
```

Description

`discard(canch)` discards messages that are available to receive on the channel `canch`.

Examples

Discard Messages Received by a CAN Channel

Set up a CAN channel to receive messages, then discard the messages.

Create a CAN channel to receive messages and start the channel.

```
rxCh = canChannel('Vector', 'CANcaseXL 1', 1);  
start (rxCh)
```

Discard all messages in this channel.

```
discard(rxCh);
```

Input Arguments

canch — CAN device channel

CAN channel object

CAN device channel, specified as a CAN channel object, that you want to discard the messages from.

Example: `canChannel('NI', 'CAN1')`

See Also

Functions

`canChannel`

Introduced in R2012a

discard (J1939)

Discard available parameter groups on J1939 channel

Syntax

```
discard(chan)
```

Description

`discard(chan)` deletes all parameter groups available on the J1939 channel `chan`. The channel also deactivates when it is cleared from memory.

Examples

Discard Parameter Groups on Channel

Delete all the parameter groups on a J1939 channel.

```
db = canDatabase('MyDatabase.dbc');  
chan = j1939Channel(db, 'Vector', 'CANCaseXL 1', 1);  
start(chan)
```

```
discard(chan)
```

Input Arguments

chan — J1939 channel

channel object

J1939 channel, specified as a channel object. Use the `j1939Channel` function to create and define the channel.

See Also

Functions

`j1939Channel` | `start`

Introduced in R2015b

disconnect

Disconnect from slave module

Syntax

```
disconnect(xcpch)
```

Description

`disconnect(xcpch)` disconnects the specified XCP channel from the slave module. Disconnecting the channel stops active messaging between the channel and the slave module.

Examples

Disconnect an Active XCP Connection

Create an XCP channel using a CAN module, connect the channel and disconnect it from the specified slave module.

Link an A2L file

```
a2l = xcpA2L('XCPSIM.a2l')
```

Create an XCP channel using a Vector CAN module's virtual channel. Check to see if channel is connected.

```
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);
```

Connect the channel and check to see if channel is connected.

```
connect(xcpch)
isConnected(xcpch)
```

```
ans =
```

```
    1
```

Disconnect the channel and check if connection is active.

```
disconnect(xcpch)
isConnected(xcpch)
```

```
ans =
```

```
    0
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

See Also

`connect` | `isConnected` | `xcpA2L` | `xcpChannel`

Introduced in R2013a

extractAll

Select all instances of CAN message from message array

Syntax

```
extracted = extractAll(message, messagename)
extracted = extractAll(message, id, extended)
[extracted, remainder] = extractAll( ___ )
```

Description

`extracted = extractAll(message, messagename)` parses the given array `message`, and returns all instances of messages matching the specified message name.

`extracted = extractAll(message, id, extended)` parses the given array `message`, and returns all instances of messages matching the specified ID value and type.

`[extracted, remainder] = extractAll(___)` assigns to `extracted` those messages that match the search, and returns to `remainder` those that do not match.

Examples

Extract Messages by Name and ID

Extract messages by matching name and IDs.

Extract messages by name.

```
msg0Out = extractAll(msgs, 'DoorControlMsg');
```

Extract all messages with IDs 200 and 5000. Note that 5000 requires an extended style ID.

```
msg0Out = extractAll(msgs, [200 5000], [false true]);
```

Extract messages and also return the remainder.

```
[msg0Out, remainder] = extractAll(msgs, {'DoorControlMsg', 'WindowControlMsg'});
```

Input Arguments

message — CAN messages to parse

array of CAN message objects

CAN messages to parse, specified as an array of CAN message objects. This is the collection from which you extract messages by specific names or IDs.

messagename — Name of message to extract

char vector | string | cell

Name of message to extract, specified as a character vector, string, or array that supports these types.

Example: 'DoorControlMsg'

Data Types: char | string | cell

id – ID of message to extract

numeric value or vector

ID of message to extract, specified as a numeric value or vector. Using this argument also requires that you specify an extended argument.

Example: [200 400]

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64

extended – Indication of extended ID type

true | false

Indication of extended ID type, specified as a logical true or false. Use a value true if the ID type is extended, or false if standard. This argument is required if you specify a message ID.

If the message ID is a numeric vector, use a logical vector of the same length for extended. For example, if you specify id and extended as [250 5000], [false true], then extractAll returns all instances of CAN messages 250 and 5000 found within in the message array.

Example: true

Data Types: logical

Output Arguments

extracted – Extracted CAN messages

array of CAN messages

Extracted CAN messages, returned as an array of CAN message objects. These are the messages whose name or ID matches the specified value.

remainder – Unmatched CAN messages

array of CAN messages

Unmatched CAN messages, returned as an array of CAN message objects. These are the messages in the original set whose name or ID does not match the specified value.

See Also

Functions

extractRecent | extractTime

Introduced in R2009a

extractAll (J1939)

Occurrences of specified J1939 parameter groups

Syntax

```
extractedPGs = extractAll(pgrp,pgname)
[extractedPGs,remainderPGs] = extractAll(pgrp,pgname)
```

Description

`extractedPGs = extractAll(pgrp,pgname)` returns all parameter groups whose name occurs in `pgname`.

`[extractedPGs,remainderPGs] = extractAll(pgrp,pgname)` also returns a parameter group array, `remainder`, containing all groups from the original array not matching the specified names in `pgname`.

Examples

Extract Parameter Groups

Extracts all the parameter groups with a name of 'PG1' or 'PG2'.

```
extractedPGs = extractAll(pgrp,{'PG1' 'PG2'})
```

Extract Parameter Groups and Remainder

Extract all parameter groups with a name of 'PG1' or 'PG2', and also return unmatched parameter groups to a different array.

```
[extractedPGs,remainderPGs] = extractAll(parameterGroups, {'PG1' 'PG2'})
```

Input Arguments

pgrp — J1939 parameter group

array of ParameterGroup objects

J1939 parameter groups, specified as an array of ParameterGroup objects. Use `thej1939ParameterGroup` or `receive` function to create ParameterGroup objects.

pgname — Names of J1939 parameter groups to extract

char vector | string | cell array of char vectors

Names of J1939 parameter groups to extract, specified as a character vector, string, or array of these.

Example: 'PG1'

Data Types: char | string | cell

Output Arguments

extractedPGs — Extracted parameter groups

array of ParameterGroup objects

Extracted parameter groups, returned as an array of ParameterGroup objects. These parameter groups have names matching any of those specified in the pgnam argument.

remainderPGs — Remainder of parameter groups

array of ParameterGroup objects

Remainder of parameter groups, returned as an array of ParameterGroup objects. These are all the parameter groups with names not matching any of those specified in the pgnam argument.

See Also

Functions

`extractRecent` | `extractTime` | `j1939ParameterGroup`

Introduced in R2015b

extractRecent

Select most recent CAN message from array of messages

Syntax

```
extracted = extractRecent(message)
extracted = extractRecent(message, messagename)
extracted = extractRecent(message, id, extended)
```

Description

`extracted = extractRecent(message)` parses the given array `message` and returns the most recent instance of each unique CAN message found in the array.

`extracted = extractRecent(message, messagename)` parses the specified array of messages and returns the most recent instance matching the specified message name.

`extracted = extractRecent(message, id, extended)` parses the given array `message` and returns the most recent instance of the message matching the specified ID value and type.

Examples

Extract Recent Messages

Extract most recent message for each name.

```
msgOut = extractRecent(msgs);
```

Extract recent messages for specific names.

```
msgOut1 = extractRecent(msgs, 'DoorControlMsg');
msgOut2 = extractRecent(msgs, {'DoorControlMsg' 'WindowControlMsg'});
```

Extract recent messages with IDs 200 and 5000. Note that 5000 requires an extended style ID.

```
msgOut = extractRecent(msgs, [200 5000], [false true]);
```

Input Arguments

message — CAN messages to parse

array of CAN message objects

CAN messages to parse, specified as an array of CAN message objects. This is the collection from which you extract recent messages.

messagename — Name of message to extract

char vector | string | cell

Name of message to extract, specified as a character vector, string, or array that supports these types.

Example: 'DoorControlMsg'

Data Types: `char` | `string` | `cell`

id — ID of message to extract

numeric value or vector

ID of message to extract, specified as a numeric value or vector. Using this argument also requires that you specify an `extended` argument.

Example: `[200 400]`

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

extended — Indication of extended ID type

`true` | `false`

Indication of extended ID type, specified as a logical `true` or `false`. Use a value `true` if the ID type is extended, or `false` if standard. This argument is required if you specify a message ID.

If the message ID is a numeric vector, use a logical vector of the same length for `extended`. For example, if you specify `id` and `extended` as `[250 5000]`, `[false true]`, then `extractAll` returns all instances of CAN messages 250 and 5000 found within in the message array.

Example: `true`

Data Types: `logical`

Output Arguments

extracted — Extracted CAN messages

array of CAN messages

Extracted CAN messages, returned as an array of CAN message objects. These are the most recent messages matching the search criteria.

See Also

Functions

`extractAll` | `extractTime`

Introduced in R2009a

extractRecent (J1939)

Occurrences of most recent J1939 parameter groups

Syntax

```
extractedPGs = extractRecent(pgrp)
extractedPGs = extractRecent(pgrp, pgroupName)
```

Description

`extractedPGs = extractRecent(pgrp)` returns the most recent instance of each unique parameter group found in the array `pgrp`, based on the parameter group timestamps.

`extractedPGs = extractRecent(pgrp, pgroupName)` returns the most recent instance of parameter groups whose names match any of those specified in `pgname`.

Examples

Extract Most Recent Parameter Groups

Extract the most recent of each parameter group.

```
extractedPGs = extractRecent(pgrp)
```

Extract Most Recent Parameter Groups for Specific Names

Extract the most recent of each parameter group named 'PG1' or 'PG2'.

```
extractedPGs = extractRecent(pgrp, {'PG1' 'PG2'})
```

Input Arguments

pgrp — J1939 parameter group

array of ParameterGroup objects

J1939 parameter groups, specified as an array of ParameterGroup objects. Use the `j1939ParameterGroup` or `receive` function to create ParameterGroup objects.

pgname — Names of J1939 parameter groups to extract

char vector | string | array

Names of J1939 parameter groups to extract, specified as a character vector, string, or array of these.

Example: 'PG1'

Data Types: char | string | cell

Output Arguments

extractedPGs — Extracted parameter groups

array of ParameterGroup objects

Extracted parameter groups, returned as an array of ParameterGroup objects.

See Also

Functions

`extractAll` | `extractTime` | `j1939ParameterGroup`

Introduced in R2015b

extractTime

Select CAN messages occurring within specified time range

Syntax

```
extracted = extractTime(message, starttime, endtime)
```

Description

`extracted = extractTime(message, starttime, endtime)` parses the array `message` and returns all messages with a timestamp value within the specified `starttime` and `endtime`, inclusive.

Examples

Extract Messages Within Time Range

Extract messages in first 10 seconds of channel being on.

```
msgRange = extractTime(msgs, 0, 10);
```

Input Arguments

message — CAN messages to parse

array of CAN message objects

CAN messages to parse, specified as an array of CAN message objects. This is the collection from which you extract recent messages.

starttime, endtime — Time range in seconds

numeric values

Time range in seconds, specified as numeric values. The function returns messages with timestamps that fall within the range defined by `starttime` and `endtime`, inclusive.

Specify the time range in increasing order from `starttime` to `endtime`. If you must specify the largest available time, set `endtime` to `Inf`. The earliest time you can specify for `starttime` is `0`.

Example: `0, 10`

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

Output Arguments

extracted — Extracted CAN messages

array of CAN messages

Extracted CAN messages, returned as an array of CAN message objects. These are the messages within the specified time range.

See Also

Functions

`extractAll` | `extractRecent`

Introduced in R2009a

extractTime (J1939)

Occurrences of J1939 parameter groups within time range

Syntax

```
extractedPGs = extractTime(pgrp,starttime,endtime)
```

Description

`extractedPGs = extractTime(pgrp,starttime,endtime)` returns the parameter groups found in the array `pgrp`, with timestamps between the specified `starttime` and `endtime`, inclusive.

Examples

Extract Parameter Groups Within Specified Time Range

Extract the parameter groups according to start and stop timestamps.

Extract parameter groups between 5 and 10.5 seconds.

```
extractedPGs = extractTime(pgrp,5,10.5)
```

Extract all parameter groups within the first minute.

```
extractedPGs = extractTime(pgrp,0,60)
```

Extract all parameter groups after 150 seconds.

```
extractedPGs = extractTime(pgrp,150,Inf)
```

Input Arguments

pgrp — J1939 parameter group

array of `ParameterGroup` objects

J1939 parameter groups, specified as an array of `ParameterGroup` objects. Use `thej1939ParameterGroup` or `receive` function to create `ParameterGroup` objects.

starttime,endtime — Start time and end time

numeric value

Start time and end time, specified as numeric values. These arguments define the range of time from which to extract parameter groups, inclusively. For the earliest possible `starttime` use `0`, for the latest possible `endtime` use `Inf`. The `endtime` value must be greater than the `starttime` value.

Data Types: `double` | `single`

Output Arguments

extractedPGs — Extracted parameter groups

array of ParameterGroup objects

Extracted parameter groups, returned as an array of ParameterGroup objects. These parameter groups fall within the specified time range, inclusively.

See Also

Functions

[extractAll](#) | [extractRecent](#) | [j1939ParameterGroup](#)

Introduced in R2015b

filterAllowAll

Allow all CAN messages of specified identifier type

Syntax

```
filterAllowAll(canch, type)
```

Description

`filterAllowAll(canch, type)` opens the filter on the specified CAN channel to allow all messages matching the specified identifier type to pass the acceptance filter.

Examples

Allow Standard and Extended ID Messages

Allow all standard and extended ID messages to pass the filter.

```
canch = canChannel('Vector', 'CANCaseXL 1', 1);  
filterAllowAll(canch, 'Standard')  
filterAllowAll(canch, 'Extended')
```

```
canch.FilterHistory
```

```
'Standard ID Filter: Allow All | Extended ID Filter: Allow All'
```

Input Arguments

canch — CAN device channel

CAN channel object

CAN device channel, specified as a CAN channel object, on which to filter.

Example: `canch = canChannel('NI', 'CAN1')`

type — Identifier type

'standard' | 'extended'

Identifier type by which to filter, specified as a character vector or string. CAN messages identifier types are 'Standard' and 'Extended'.

Example: 'Standard'

Data Types: char | string

See Also

Functions

`canChannel` | `canMessage` | `filterAllowOnly` | `filterBlockAll`

Introduced in R2011b

filterAllowAll (J1939)

Open parameter group filters on J1939 channel

Syntax

```
filterAllowAll(chan)
```

Description

`filterAllowAll(chan)` opens all parameter group filters on the specified channel, making all parameter groups receivable.

Examples

Allow All Parameter Groups to Be Received

Open the filter to allow all J1939 parameter groups on the channel.

```
db = canDatabase('MyDatabase.dbc');  
chan = j1939Channel(db, 'Vector', 'CANCaseXL 1', 1);  
filterAllowAll(chan)
```

Input Arguments

chan — J1939 channel

channel object

J1939 channel, specified as a channel object. Use the `j1939Channel` function to create and define the channel.

See Also

Functions

`filterAllowOnly` | `filterBlockOnly` | `j1939Channel`

Introduced in R2015b

filterAllowOnly

Configure CAN message filter to allow only specified messages

Syntax

```
filterAllowOnly(canch, name)
filterAllowOnly(canch, IDs, type)
```

Description

`filterAllowOnly(canch, name)` configures the filter on the channel `canch` to pass only messages with the specified name.

Set the channel object `Database` property to attach a database to allow filtering by message names.

`filterAllowOnly(canch, IDs, type)` configures the filter on the channel `canch` to pass only messages of the specified identifier type and values.

Examples

Filter by Message Name

Filter a database defined message with the name 'EngineMsg'

```
canch = canChannel('Vector', 'CANCaseXL 1', 1);
canch.Database = canDatabase('candatabase.dbc');
filterAllowOnly(canch, 'EngineMsg')
```

Filter by Message IDs

Filter messages by identifiers.

```
canch = canChannel('Vector', 'CANCaseXL 1', 1);
filterAllowOnly(canch, [602 612], 'Standard')
```

Input Arguments

canch — CAN device channel

CAN channel object

CAN device channel, specified as a CAN channel object, on which to filter.

Example: `canch = canChannel('NI', 'CAN1')`

name — Name of CAN messages

char vector | string

Name of CAN messages that you want to allow, specified as a character vector, string, or supporting array of these types.

Example: 'EngineMsg'

Data Types: char | string | cell

IDs — CAN message IDs

numeric value

CAN message IDs that you want to allow, specified as a numeric value or vector.

Specify IDs as a decimal value. To convert a hexadecimal to a decimal value, use the `hex2dec` function.

Example: 600, [600,610], [600:800], [200:400,600:800]

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64

type — Identifier type

'standard' | 'extended'

Identifier type by which to filter, specified as a character vector or string. CAN messages identifier types are 'Standard' and 'Extended'.

Example: 'Standard'

Data Types: char | string

See Also

Functions

`canChannel` | `canDatabase` | `filterAllowAll` | `filterBlockAll` | `hex2dec`

Introduced in R2011b

filterAllowOnly (J1939)

Allow only specified parameter groups to pass J1939 channel filter

Syntax

```
filterAllowOnly(chan,pgname)
```

Description

`filterAllowOnly(chan,pgname)` configures the filter on the channel `chan` to pass only the parameter groups specified by `pgname`.

Examples

Allow Only Some Parameter Groups to Be Received

Configure the channel filter to allow only specified J1939 parameter groups to be received on the channel.

```
db = canDatabase('MyDatabase.dbc');  
chan = j1939Channel(db,'Vector','CANCaseXL 1',1);  
filterAllowOnly(chan,{'PG1' 'PG2'})
```

Input Arguments

chan — J1939 channel

channel object

J1939 channel, specified as a channel object. Use the `j1939Channel` function to create and define the channel.

pgname — Allowed J1939 parameter groups

char vector | string | array

Allowed J1939 parameter groups, specified as a character vector, string, or array of these.

Example: 'PG1'

Data Types: char | string | cell

See Also

Functions

`filterAllowAll` | `filterBlockOnly` | `j1939Channel`

Introduced in R2015b

filterBlockAll

Configure filter to block CAN messages with specified identifier type

Syntax

```
filterBlockAll(canch, type)
```

Description

`filterBlockAll(canch, type)` configures the CAN message filter to block all messages matching the specified identifier type.

Examples

Block All Standard ID Messages

Block all standard ID message types.

```
canch = canChannel('Vector', 'CANCaseXL 1', 1)
filterBlockAll(canch, 'Standard')
```

Input Arguments

canch — CAN device channel

CAN channel object

CAN device channel, specified as a CAN channel object, on which to filter.

Example: `canch = canChannel('NI', 'CAN1')`

type — Identifier type

'standard' | 'extended'

Identifier type by which to filter, specified as a character vector or string. CAN messages identifier types are 'Standard' and 'Extended'.

Example: 'Standard'

Data Types: char | string

See Also

Functions

`canChannel` | `filterAllowAll` | `filterAllowOnly`

Introduced in R2011b

filterBlockOnly (J1939)

Block only specified parameter groups on J1939 channel filter

Syntax

```
filterBlockOnly(chan,pgname)
```

Description

`filterBlockOnly(chan,pgname)` configures the filter on the channel `chan` to block only the parameter groups specified by `pgname`.

Examples

Block Only Some Parameter Groups on Channel

Configure the channel filter to block only specified J1939 parameter groups on the channel.

```
db = canDatabase('MyDatabase.dbc');  
chan = j1939Channel(db,'Vector','CANCaseXL 1',1);  
filterBlockOnly(chan,{'PG1' 'PG2'})
```

Input Arguments

chan — J1939 channel

channel object

J1939 channel, specified as a channel object. Use the `j1939Channel` function to create and define the channel.

pgname — Blocked J1939 parameter groups

char vector | string | array

Blocked J1939 parameter groups, specified as a character vector, string, or array of these.

Example: 'PG1'

Data Types: char | string | cell

See Also

Functions

`filterAllowAll` | `filterAllowOnly` | `j1939Channel`

Introduced in R2015b

freeMeasurementLists

Remove all measurement lists from XCP channel

Syntax

```
freeMeasurementLists(xcpch)
```

Description

`freeMeasurementLists(xcpch)` removes all configured measurement lists from the specified XCP channel.

Examples

Free DAQ Lists

Create two data acquisition lists and remove them.

Create an object to parse an A2L file and connect that to an XCP channel.

```
a2lfile = xcpA2L('XCPSIM.a2l')
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);
```

Connect the channel to the slave module.

```
connect(xcpch)
```

Setup a data acquisition measurement list with the '10 ms' event and 'PMW' measurement.

```
createMeasurementList(xcpch, 'DAQ', '10 ms', {'BitSlice0','PWMFiltered','Triangle'})
```

Create another measurement list with the '100ms' event and 'PWMFiltered', and 'Triangle' measurements.

```
createMeasurementList(xcpch, 'DAQ', '100ms', {'PWMFiltered','Triangle'})
```

view details of the measurement lists.

```
viewMeasurementLists(xcpch)
```

```
DAQ List #1 using the "10 ms" event @ 0.010000 seconds and the following measurements:
  PWM
```

```
DAQ List #2 using the "100ms" event @ 0.100000 seconds and the following measurements:
  PWMFiltered
  Triangle
```

Free the measurement lists.

`freeMeasurementLists(xcpch)`

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

See Also

`createMeasurementList` | `viewMeasurementLists` | `xcpA2L` | `xcpChannel`

Introduced in R2013a

getCharacteristicInfo

Get information about specific characteristic from A2L file

Syntax

```
info = getCharacteristicInfo(a2lFile,characteristic)
```

Description

`info = getCharacteristicInfo(a2lFile,characteristic)` returns information about the specified characteristic from the specified A2L file, and stores it in the `xcp.Characteristic` object, `info`.

Examples

Get XCP Characteristic Information

Create a handle to parse an A2L file and get information about the `curve1_8_uc` characteristic.

```
a2lfile = xcpA2L('C:\XCPSIM.a2l');
info = getCharacteristicInfo(a2lfile,'curve1_8_uc')
```

```
info =
```

```
Characteristic with properties:
    CharacteristicType: 'VAL_BLK'
    Deposit: [1x1 xcp.RecordLayout]
    AxisConversion: {}
    Name: 'curve1_8_uc'
    LongIdentifier: '8 BYTE shared axis Curve2'
    ECUAddress: 1131912
    ECUAddressExtension: 0
    Conversion: [1x1 xcp.CompuMethodRational]
    Dimension: [8 1 1]
    LowerLimit: 0
    UpperLimit: 255
    BitMask: []
```

Input Arguments

a2lFile — A2L file

`xcp.A2L` object

A2L file, specified as an `xcp.A2L` object, used in this connection. You can create an A2L file object using `xcpA2L`.

characteristic — XCP channel characteristic name

char vector | string

XCP channel characteristic name, specified as a character vector or string.

Example: 'curve1_8_uc'

Data Types: char | string

Output Arguments

info – XCP characteristic information

xcp.Characteristic object

XCP characteristic information, returned as an xcp.Characteristic object, containing characteristic details such as type, identifier, and conversion.

See Also

getEventInfo | getMeasurementInfo | xcpA2L

Topics

“Inspect the Contents of an A2L File” on page 7-2

“XCP Database and Communication Workflow” on page 6-2

Introduced in R2018a

getEventInfo

Get event information about specific event from A2L file

Syntax

```
info = getEventInfo(a2lFile,eventName)
```

Description

`info = getEventInfo(a2lFile,eventName)` returns information about the specified event from the specified A2L file, and stores it in the `xcp.Event` object, `info`.

Examples

Get XCP Event Information

Create a handle to parse an A2L file and get information about the '10 ms' event.

```
a2lfile = xcpA2L('C:\XCPSIM.a2l')
info = getEventInfo(a2lfile,'10 ms')

info =
    Event with properties:
        Name: '10 ms'
        Direction: 'DAQ_STIM'
        MaxDAQList: 255
        ChannelNumber: 1
        ChannelTimeCycle: 10
        ChannelTimeUnit: 6
        ChannelPriority: 0
        ChannelTimeCycleInSeconds: 0.0100
```

Input Arguments

a2lFile — A2L file

`xcp.A2L` object

A2L file, specified as an `xcp.A2L` object, used in this connection. You can create an A2L file object using `xcpA2L`.

eventName — XCP event name

character vector | string

XCP event name, specified as a character vector or string. Make sure `eventName` matches the corresponding event name defined in your A2L file.

Output Arguments

info — XCP event information

xcp.Event object

XCP event information, returned as xcp.Event object, containing event details such as timing and priority.

See Also

Functions

getCharacteristicInfo | getMeasurementInfo | xcpA2L

Topics

“Inspect the Contents of an A2L File” on page 7-2

“XCP Database and Communication Workflow” on page 6-2

Introduced in R2013a

getMeasurementInfo

Get information about specific measurement from A2L file

Syntax

```
info = getMeasurementInfo(a2lFile,measurementName)
```

Description

`info = getMeasurementInfo(a2lFile,measurementName)` returns information about the specified measurement from the specified A2L file, and stores it in the `xcp.Measurement` object, `info`.

Examples

Get XCP Measurement Information

Create a handle to parse an A2L file and get information about the `channel1` measurement.

```
a2lfile = xcpA2L('C:\XCPSIM.a2l')
info = getMeasurementInfo(a2lfile,'channel1')
```

`info =` Measurement with properties:

```
    Resolution: 0
    Accuracy: 0
    LocDataType: 'FLOAT32_IEEE'
    Name: 'channel1'
    LongIdentifier: 'FLOAT demo signal (sine wave)'
    ECUAddress: 1155080
    ECUAddressExtension: 0
    Conversion: [1x1 xcp.CompuMethodRational]
    Dimension: 1
    LowerLimit: -1.0000e+12
    UpperLimit: 1.0000e+12
    BitMask: []
```

Input Arguments

a2lFile — A2L file

`xcp.A2L` object

A2L file, specified as an `xcp.A2L` object, used in this connection. You can create an A2L file object using `xcpA2L`.

measurementName — Name of single XCP measurement

character vector | string

Name of a single XCP measurement specified as a character vector or string. Make sure `measurementName` matches the corresponding measurement name defined in your A2L file.

Data Types: `char` | `string`

Output Arguments

info – XCP measurement information

xcp.Measurement object

XCP measurement information, returned as an xcp.Measurement object, containing measurement details such as memory address, identifier, and limits.

See Also

getCharacteristicInfo | getEventInfo | xcpA2L

Topics

“Inspect the Contents of an A2L File” on page 7-2

“XCP Database and Communication Workflow” on page 6-2

Introduced in R2013a

getValue

Retrieve instance value from CDFX object

Syntax

```
iVal = getValue(cdfxObj,instName)
iVal = getValue(cdfxObj,instName,sysName)
```

Description

`iVal = getValue(cdfxObj,instName)` returns the value of the unique instance whose `ShortName` is specified by `instName`. If multiple instances share the same `ShortName`, the function returns an error.

`iVal = getValue(cdfxObj,instName,sysName)` returns the value of the instance whose `ShortName` is specified by `instName` and is contained in the system specified by `sysName`.

Examples

Retrieve Value of Instance

Create an `asam.cdfx` object and read the value of its `VALUE_NUMERIC` instance.

```
cdfxObj = cdfx('c:\DataFiles\AllCategories_VCD.cdfx');
iVal = getValue(cdfxObj, 'VALUE_NUMERIC')
```

```
iVal =
    12.2400
```

Input Arguments

cdfxObj — CDFX-file object

`asam.cdfx` object

CDFX-file object, specified as an `asam.cdfx` object. Use the object to access the calibration data.

Example: `cdfx()`

instName — Instance name

`char` | `string`

Instance name, specified as a character vector or string.

Example: `'NUMERIC_VALUE'`

Data Types: `char` | `string`

sysName — Parent system name

`char` | `string`

Parent system name, specified as a character vector or string.

Example: 'System2'

Data Types: char | string

Output Arguments

iVal – Instance value

instance type

Instance value, returned as the instance type.

See Also

Functions

cdfx | instanceList | setValue | systemList | write

Introduced in R2019a

hasdata (MDFDatastore)

Determine if data is available to read from MDF datastore

Syntax

```
tf = hasdata(mdfds)
```

Description

`tf = hasdata(mdfds)` returns logical 1 (true) if there is data available to read from the MDF datastore specified by `mdfds`. Otherwise, it returns logical 0 (false).

Examples

Check MDF Datastore for Readable Data

Use `hasdata` in a loop to control read iterations.

```
mdfds = mdfDatastore(fullfile(matlabroot, 'examples', 'vnt', 'CANape.MF4'));  
while hasdata(mdfds)  
    m = read(mdfds);  
end
```

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

Output Arguments

tf — Indicator of data to read

1 | 0

Indicator of data to read, returned as a logical 1 (true) or 0 (false).

See Also

Functions

`mdfDatastore` | `read` | `readall` | `reset`

Introduced in R2017b

instanceList

Parameter instances in the CDFX object

Syntax

```
iList = instanceList(cdfxObj)
iList = instanceList(cdfxObj, instName)
iList = instanceList(cdfxObj, instName, sysName)
```

Description

`iList = instanceList(cdfxObj)` returns a table of every parameter instance in the CDFX object.

`iList = instanceList(cdfxObj, instName)` returns a table of every parameter instance in the CDFX object whose `ShortName` matches `instName`.

`iList = instanceList(cdfxObj, instName, sysName)` returns a table of every parameter instance in the CDFX object whose `ShortName` matches `instName` and whose parent `System` matches `sysName`.

Examples

View CDFX Object Instances

Create an `asam.cdfx` object and view its parameter instances.

```
cdfxObj = cdfx('c:\DataFiles\AllCategories_VCD.cdfx');
iList = instanceList(cdfxObj);
iList(1:4,1:4)
```

ans =

4x4 table

ShortName	System	Category	Value
"VALUE_NUMERIC"	"System1"	"VALUE"	[12.2400]
"VALUE_TEXT"	"System1"	"VALUE"	["Text_Value"]
"BLOB_HEX"	"System1"	"BLOB"	["0102030405060708 090A0B0C0D0E0F10"]
"BOOLEAN_TEXT"	"System1"	"BOOLEAN"	[1]

```
iList = instanceList(cdfxObj, "VALUE_NUMERIC")
```

iList =

1x6 table

ShortName	System	Category	Value	Units	FeatureReference
"VALUE_NUMERIC"	"System1"	"VALUE"	[12.2400]	"	"model1"

```
iList = instanceList(cdfxObj, "VALUE_NUMERIC", "System1")
```

iList =

1×6 table

ShortName	System	Category	Value	Units	FeatureReference
"VALUE_NUMERIC"	"System1"	"VALUE"	[12.2400]	" "	"model1"

Input Arguments

cdfxObj — CDFX-file object

asam.cdfx object

CDFX-file object, specified as an `asam.cdfx` object. Use the object to access the calibration data.

Example: `cdfx()`

instName — Instance name

string

Instance name, specified as a string.

Example: "NUMERIC_VALUE"

Data Types: string

sysName — Parent system name

string

Parent system name, specified as a string.

Example: "System2"

Data Types: string

Output Arguments

iList — Instance list

table

Instance list, returned as a table.

See Also

Functions

`cdfx` | `getValue` | `setValue` | `systemList` | `write`

Introduced in R2019a

isConnected

Return connection status

Syntax

```
isConnected(xcpch)
```

Description

`isConnected(xcpch)` returns a boolean value to indicate active connection to the slave.

Examples

Verify if XCP Channel is Connected

Create a new XCP channel and see if it is connected.

```
a2l = xcpA2L('XCPSIM.a2l')
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1)
isConnected(xcpch)
```

```
ans =
```

```
    0
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

See Also

`xcpChannel`

Introduced in R2013a

isMeasurementRunning

Indicate if measurement is active

Syntax

```
isMeasurementRunning(xcpch)
```

Description

`isMeasurementRunning(xcpch)` returns a boolean indicating if the configured measurements are active and running.

Examples

Verify if Configured Measurement List is Active

Set up a DAQ measurement list and start it. Verify if this list is running.

Create an XCP channel with a CAN slave module.

```
a2l = xcpA2L('XCPSIM.a2l')
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);
```

Setup a data acquisition measurement list with the '10 ms' event and 'Bitslice' measurement and verify if measurement is running.

```
createMeasurementList(xcpch, 'DAQ', '10 ms', 'BitSlice')
isMeasurementRunning(xcpch)
```

```
ans =
     0
```

Start your measurement and verify if measurement is running.

```
startMeasurement(xcpch)
isMeasurementRunning(xcpch)
```

```
ans =
     1
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

See Also

startMeasurement

Introduced in R2013a

j1939Channel

Create J1939 CAN channel

Syntax

```
j1939Ch = j1939Channel(database, 'vendor', 'device')
j1939Ch = j1939Channel(database, 'vendor', 'device', chanIndex)
```

Description

`j1939Ch = j1939Channel(database, 'vendor', 'device')` creates a J1939 channel connected to the specified CAN device. Use this syntax for National Instruments and PEAK-System devices, which do not require a channel index argument.

`j1939Ch = j1939Channel(database, 'vendor', 'device', chanIndex)` creates a J1939 CAN channel connected to the specified CAN device and channel index. Use this syntax for Vector and Kvaser devices that support a channel index specifier.

Examples

Create a J1939 CAN Channel for a Vector Device

Specify a database.

```
db = canDatabase('C:\J1939DB.dbc');
```

Create the channel object.

```
j1939Ch = j1939Channel(db, 'Vector', 'Virtual 1', 1)
```

```
j1939Ch =
```

```
Channel with properties:
```

```
Device Information:
```

```
-----
```

```
DeviceVendor: 'Vector'
Device: 'Virtual 1'
DeviceChannelIndex: 1
DeviceSerialNumber: 0
```

```
Data Details:
```

```
-----
```

```
ParameterGroupsAvailable: 0
ParameterGroupsReceived: 0
ParameterGroupsTransmitted: 0
FilterPassList: []
FilterBlockList: []
```

```
Channel Information:
```

```
-----
```

```

        Running: 0
        BusStatus: 'N/A'
InitializationAccess: 1
        InitialTimestamp: [0x0 datetime]
        SilentMode: 0
        TransceiverName: ''
        TransceiverState: 0
        BusSpeed: 500000
        SJW: 1
        TSEG1: 4
        TSEG2: 3
        NumOfSamples: 1

Other Information:
-----
        UserData: []

```

Create a J1939 CAN Channel for a National Instruments Device

Specify a database.

```
db = canDatabase('C:\J1939DB.dbc');
```

Create the channel object.

```
j1939Ch = j1939Channel(db, 'NI', 'CAN1');
```

Input Arguments

database – CAN database

CAN database object

CAN database specified as a CAN database object. The specified database contains J1939 parameter group definitions.

Example: `database = canDatabase('C:\database.dbc')`

vendor – Name of device vendor

'Vector' | 'NI' | 'Kvaser' | 'Peak-System'

Name of device vendor, specified as a character vector or string.

Example: 'Vector'

Data Types: char | string

device – Name of CAN device

char vector | string

Name of CAN device attached to the J1939 CAN channel, specified as a character vector or string.

For Kvaser and Vector products, `device` is a combination of the device type and a device index. For example, a Kvaser device might be 'USBcanProfessional 1'; if you have two Vector CANcardXL devices, `device` can be 'CANcardXL 1' or 'CANcardXL 2'.

For National Instruments devices the `devicenumber` is the interface number defined in the NI Measurement & Automation Explorer.

For PEAK-System devices the `devicenumber` is the alphanumeric device number defined for the channel.

Example: `'Virtual 1'`

Data Types: `char` | `string`

chanIndex — Channel number of CAN device

numeric

Channel number of the CAN device attached to the J1939 CAN channel, specified as a numeric value. Use this argument with Kvaser and Vector devices.

Example: `1`

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

Output Arguments

j1939Ch — J1939 CAN channel

J1939 CAN channel object

J1939 CAN channel returned as a `j1939.Channel` object, with `j1939.Channel` Properties.

See Also

Functions

`canDatabase` | `j1939ParameterGroup` | `receive` | `transmit`

Properties

`j1939.Channel` Properties

Topics

“J1939 Channel Workflow” on page 9-6

Introduced in R2015b

j1939ParameterGroup

Create J1939 parameter group

Syntax

```
pg = j1939ParameterGroup(database, name)
```

Description

pg = j1939ParameterGroup(database, name) creates a parameter group using the name defined in the specified database.

Examples

Create a Parameter Group

This example shows how to attach a database to a parameter group name and view the signal information in the group.

Create a database handle.

```
db = canDatabase('C:\j1939Demo.dbc');
```

Create a parameter group.

```
pg = j1939ParameterGroup(db, 'PackedData')
```

```
pg =
```

```
ParameterGroup with properties:
```

```
Protocol Data Unit Details:
```

```
-----
                Name: 'PackedData'
                PGN: 57344
                Priority: 6
                PDUFormatType: 'Peer-to-Peer (Type 1)'
                SourceAddress: 50
                DestinationAddress: 255
```

```
Data Details:
```

```
-----
                Timestamp: 0
                Data: [255 255 255 255 255 255 255 255]
                Signals: [1x1 struct]
```

```
Other Information:
```

```
-----
                UserData: []
```

Examine the signals in the parameter group.

```
pg.Signals
```

```
ans =
```

```
    ToggleSwitch: -1
    SliderSwitch: -1
    RockerSwitch: -1
    RepeatingStairs: 255
    PushButton: 1
```

Input Arguments

database — Handle to CAN database

CAN database object

Handle to CAN database, specified as a CAN database object. The specified database contains J1939 parameter group definitions.

Example: `db = canDatabase('C:\database.dbc')`

name — Parameter group name

character vector | string

Parameter group name, specified as a character vector or string. The name must match the name specified in the attached CAN database.

Example: `'pgName'`

Data Types: `char` | `string`

Output Arguments

pg — J1939 parameter group

parameter group object

J1939 parameter group, returned as a parameter group object, with `j1939.ParameterGroup` Properties.

See Also

Functions

`canDatabase` | `j1939Channel`

Properties

`j1939.ParameterGroup` Properties

Topics

"J1939 Interface" on page 9-2

"J1939 Parameter Group Format" on page 9-3

Introduced in R2015b

j1939ParameterGroupImport

Import J1939 log file

Syntax

```
pgs = j1939ParameterGroupImport(file,vendor,database)
```

Description

`pgs = j1939ParameterGroupImport(file,vendor,database)` reads the input file as a CAN message log file from the specified vendor. Using the specified CAN database, the CAN messages are converted into J1939 parameter groups, and assigns the output to the array `pgs`.

Examples

Import Log Data to J1939 Parameter Groups

Read a CAN message log file, and generate J1939 parameter groups according to a CAN database.

```
db = canDatabase('MyDatabase.dbc');  
pgs = j1939ParameterGroupImport('MsgLog.asc','Vector',db);
```

Input Arguments

file — CAN message log file

character vector | string

CAN message log file, specified as a character vector or string.

Example: 'MyDatabase.dbc'

Data Types: char | string

vendor — Vendor file format

'Kvaser' | 'Vector'

Vendor file format, specified as a character vector or string. The supported file formats are those defined by Vector and Kvaser.

Example: 'Vector'

Data Types: char | string

database — CAN database

database handle

CAN database, specified as a database handle.

Output Arguments

pgs — J1939 parameter groups

parameter group array

J1939 parameter groups, returned as a parameter group array.

See Also

Functions

canDatabase

Introduced in R2017a

mdf

Access information contained in MDF-file

Syntax

```
mdfObj = mdf(mdfFileName)
```

Description

The `mdf` function creates an object for accessing a measurement data format (MDF) file. See “Measurement Data Format (MDF)” on page 13-128.

`mdfObj = mdf(mdfFileName)` identifies a measurement data format (MDF) file and returns an MDF-file object, which you can use to access information and data contained in the file. You can specify a full or partial path to the file.

Examples

Create MDF-File Object for Specified MDF-File

Create an MDF object for a given file, and view the object display.

```
mdfObj = mdf('MDFFile.mf4')
```

MDF with properties:

```
File Details
    Name: 'MDFFile.mf4'
    Path: 'c:\temp\MDFFile.mf4'
    Author: 'HOK'
    Department: 'Research'
    Project: 'MDF'
    Subject: 'CAN bus'
    Comment: 'This file contains CAN messages'
    Version: '4.10'
    DataSize: 32100
    InitialTimestamp: 2016-02-27 12:09:02

Creator Details
    ProgramIdentifier: 'mddff.04'
    Creator: [1x1 struct]

File Contents
    Attachment: [1x1 struct]
```

```
ChannelNames: {6×1 cell}
ChannelGroup: [1×6 struct]
```

Input Arguments

mdfFileName — MDF-file name

char vector | string

MDF-file name, specified as a character vector or string, including the necessary full or relative path.

Example: 'MDFFile.mf4'

Data Types: char | string

Output Arguments

mdfObj — MDF-file

MDF-file object

MDF-file, returned as an MDF-file object. The object provides access to the MDF-file information contained in the following properties.

Property	Description
Name	Name of the MDF-file, including extension
Path	Full path to the MDF-file, including file name
Author	Author who originated the MDF-file
Department	Department that originated the MDF-file
Project	Project that originated the MDF-file
Subject	Subject matter in the MDF-file
Comment	Open comment field from the MDF-file
Version	MDF standard version of the file
DataSize	Total size of the data in the MDF-file, in bytes
InitialTimestamp	Time when file data acquisition began in UTC or local time
ProgramIdentifier	Originating program of the MDF-file
Creator	Structure containing details about creator of the MDF-file, with these fields: VendorName, ToolName, ToolVersion, UserName, and Comment
Attachment	Structure of information about attachments contained within the MDF-file, with these fields: Name, Path, Comment, Type, MIMEType, Size, EmbeddedSize, and MD5Checksum
ChannelNames	Cell array of the channel names in each channel group
ChannelGroup	Structure of information about channel groups contained within the MDF-file, with these fields: AcquisitionName, Comment, NumSamples, DataSize, Sorted, and Channel

More About

Measurement Data Format (MDF)

Measurement data format (MDF) files are binary format files for storing measurement data. The format standard is defined by the Association for Standardization of Automation and Measuring Systems (ASAM), which you can read about at [ASAM MDF](#).

Vehicle Network Toolbox and Powertrain Blockset™ provide access to MDF-files through an object you create with the `mdf` function.

See Also

Functions

`mdfInfo` | `mdfSort` | `mdfVisualize` | `read` | `saveAttachment`

Topics

“Access MDF Files” on page 16-96

“Reading Data from MDF Files” on page 16-101

“Data Analytics Application with Many MDF Files” on page 16-129

“File Format Limitations” on page 11-5

“Troubleshooting MDF Applications” on page 11-7

Introduced in R2016b

mdfDatastore

Datastore for collection of MDF-files

Description

Use the MDF datastore object to access data from a collection of MDF-files.

Creation

Syntax

```
mdfds = mdfDatastore(location)
mdfds = mdfDatastore(__, 'Name1', Value1, 'Name2', Value2, ...)
```

Description

`mdfds = mdfDatastore(location)` creates an `MDFDatastore` based on an MDF-file or a collection of files in the folder specified by `location`. All files in the folder with extensions `.mdf`, `.dat`, or `.mf4` are included.

`mdfds = mdfDatastore(__, 'Name1', Value1, 'Name2', Value2, ...)` specifies function options and properties of `mdfds` using optional name-value pairs.

Note This function is supported only on 64-bit Windows operating systems.

Input Arguments

location — Location of MDF datastore files

character vector | cell array | `DsFileSet` object

Location of MDF datastore files, specified as a character vector, cell array of character vectors, or `matlab.io.datastore.DsFileSet` object identifying either files or folders. The path can be relative or absolute, and can contain the wildcard character `*`. If `location` specifies a folder, by default the datastore includes all files in that folder with the extensions `.mdf`, `.dat`, or `.mf4`.

Example: `'CANape.MF4'`

Data Types: `char` | `cell` | `DsFileSet`

Name-Value Pair Arguments

Specify optional comma-separated pairs of `Name, Value` arguments to set file information or object “Properties” on page 13-130. Allowed options are `IncludeSubfolders`, `FileExtensions`, and the properties `ReadSize`, `SelectedChannelGroupNumber`, and `SelectedChannelNames`.

Example: `'SelectedChannelNames', 'Counter_B4'`

IncludeSubfolders — Include files in subfolders`false (default) | true`

Include files in subfolders, specified as a logical. Specify `true` to include files in each folder and recursively in subfolders.

Example: `'IncludeSubfolders', true`

Data Types: `logical`

FileExtensions — Custom extensions for filenames to include in MDF datastore`{'.mdf', '.dat', '.mf4'} (default) | char | cell`

Custom extensions for filenames to include in the MDF datastore, specified as a character vector or cell array of character vectors. By default, the supported extensions include `.mdf`, `.dat`, and `.mf4`. If your files have custom or nonstandard extensions, use this Name-Value setting to include files with those extensions.

Example: `'FileExtensions', {' .myformat1', '.myformat2' }`

Data Types: `char | cell`

Properties**ChannelGroups — All channel groups present in first MDF-file (read-only)**`table`

All channel groups present in first MDF-file, returned as a table.

Data Types: `table`

Channels — All channels present in first MDF-file (read-only)`table`

All channels present in first MDF-file, returned as a table.

Those channels targeted for reading must have the same name and belong to the same channel group in each file of the MDF datastore.

Data Types: `table`

Files — Files included in datastore`char | string | cell`

Files included in the datastore, specified as a character vector, string, or cell array.

Example: `{'file1.mf4', 'file2.mf4'}`

Data Types: `char | string | cell`

ReadSize — Size of data returned by read`'file' (default) | numeric | duration`

Size of data returned by the `read` function, specified as `'file'`, a numeric value, or a duration. A character vector value of `'file'` causes the entire file to be read; a numeric double value specifies the number of records to read; and a duration value specifies a time range to read.

If you later change the `ReadSize` property value type, the datastore resets.

Example: 50

Data Types: double | char | duration

SelectedChannelGroupNumber — Channel group to read

numeric scalar

Channel group to read, specified as a numeric scalar value.

Example: 1

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64

SelectedChannelNames — Names of channels to read

char | string | cell

Names of channels to read, specified as a character vector, string, or cell array.

Those channels targeted for reading must have the same name and belong to the same channel group in each file of the MDF datastore.

Example: 'Counter_B4'

Data Types: char | string | cell

Object Functions

read	Read data in MDF datastore
readall	Read all data in MDF datastore
preview	Subset of data from MDF datastore
reset	Reset MDF datastore to initial state
hasdata	Determine if data is available to read from MDF datastore
partition	Partition MDF datastore
numpartitions	Number of partitions for MDF datastore
combine (MATLAB)	Combine data from multiple datastores
transform (MATLAB)	Transform datastore
isPartitionable (MATLAB)	Determine whether datastore is partitionable
isShuffleable (MATLAB)	Determine whether datastore is shuffleable

Examples

Create an MDF Datastore

Create an MDF datastore from the sample file `CANape.MF4`, and read it into a timetable.

```
mdfds = mdfDatastore(fullfile(matlabroot, 'examples', 'vnt', 'CANape.MF4'));
while hasdata(mdfds)
    m = read(mdfds);
end
```

See Also

Topics

“Using MDF Files Via MDF Datastore” on page 16-107

Introduced in R2017b

mdfInfo

Information about MDF-file

Syntax

```
fileInfo = mdfInfo(mdfFileName)
```

Description

`fileInfo = mdfInfo(mdfFileName)` returns a struct that contains information about the specified MDF-file, including name, location, version, size, and initial timestamp of the data.

Examples

Access Information About MDF-File

Get the MDF-file information, and programmatically read its version.

```
fileInfo = mdfInfo('MDFFile.mdf');  
fileInfo.Version
```

```
ans =  
  
    '3.20'
```

Input Arguments

mdfFileName — MDF-file name

char vector | string

MDF-file name, specified as a character vector or string, including the necessary full or relative path.

Example: 'MDFFile.mf4'

Data Types: char | string

Output Arguments

fileInfo — MDF-file information

structure

MDF-file information, returned as a structure.

See Also

Functions

mdf

Introduced in R2019b

mdfSort

Create sorted copy of MDF-file

Syntax

```
sortedPath = mdfSort(UnsortedMDFFile,SortedMDFFile)
```

Description

`sortedPath = mdfSort(UnsortedMDFFile,SortedMDFFile)` creates a copy of an MDF-file with its data sorted according to ASAM standards for fast reading. If you get an error when trying to read an unsorted file, create a sorted file and read from that instead. The optional output argument, `sortedPath`, indicates the full path to the sorted file, including the file name.

Note This function is supported only on 64-bit Windows operating systems.

Examples

Sort and Read MDF-File

Create a sorted MDF-file and read its data.

```
sortedPath = mdfSort('UnsortedMDFFile.mf4','SortedMDFFile.mf4');  
M = mdf('SortedMDFFile.mf4');  
MD = read(M);
```

Input Arguments

UnsortedMDFFile — Original MDF-file without sorted data

string | char

Original MDF-file without sorted data, specified as a string or character vector. Full and relative path names are allowed.

Example: 'UnsortedMDFFile.mf4'

Data Types: char | string

SortedMDFFile — New copy of MDF-file with sorted data

string | char

New copy of MDF-file with sorted data, specified as a string or character vector. Full and relative path names are allowed.

Example: 'SortedMDFFile.mf4'

Data Types: char | string

Output Arguments

sortedPath — Path to new file

char

Full path to new file, returned as a character vector. The path includes the file name.

See Also

Functions

mdf | read

Introduced in R2019b

mdfVisualize

View channel data from MDF-file

Syntax

```
mdfVisualize(mdfFileName)
```

Description

`mdfVisualize(mdfFileName)` opens an MDF-file in the Simulation Data Inspector for viewing and interacting with channel data. `mdfFileName` is the name of the MDF-file, specified as a full or partial path.

Note This function is supported only on 64-bit Windows operating systems.

Examples

View MDF Data

View the data from a specified MDF-file in the Simulation Data Inspector.

```
mdfVisualize('File01.mf4')
```

Input Arguments

mdfFileName — MDF-file name

char vector | string

MDF-file name, specified as a character vector or string, including the necessary full or relative path.

Example: 'MDFFile.mf4'

Data Types: char | string

See Also

Functions

mdf | read

Topics

“View and Analyze Simulation Results” (Simulink)

Introduced in R2019a

messageInfo

Information about CAN database messages

Syntax

```
msgInfo = messageInfo(candb)
msgInfo = messageInfo(candb, msgName)
msgInfo = messageInfo(candb, id, msgIsExtended)
```

Description

`msgInfo = messageInfo(candb)` returns a structure with information about the CAN messages in the specified database `candb`.

`msgInfo = messageInfo(candb, msgName)` returns information about the specified message '`msgName`'.

`msgInfo = messageInfo(candb, id, msgIsExtended)` returns information about the message with the specified standard or extended ID.

Examples

Get All Messages

Get information from all messages in a CAN database.

```
candb = canDatabase('J1939DB.dbc');
msgInfo = messageInfo(candb)
```

```
msgInfo =
3x1 struct array with fields:
    Name
    Comment
    ID
    Extended
    J1939
    Length
    Signals
    SignalInfo
    TxNodes
    Attributes
    AttributeInfo
```

You can index into the structure for information on a particular message.

Get One Message by Name

Get information from one message in a CAN database using the message name.

```

candb = canDatabase('J1939DB.dbc');
msgInfo = messageInfo(candb, 'A1')

msgInfo =
    Name: 'A1'
    Comment: 'This is an A1 message'
    ID: 419364350
    Extended: 1
    J1939: [1x1 struct]
    Length: 8
    Signals: {2x1 cell}
    SignalInfo: [2x1 struct]
    TxNodes: {'AerodynamicControl'}
    Attributes: {4x1 cell}
    AttributeInfo: [4x1 struct]

```

Get One Message by ID

Get information from one message in a CAN database using the message ID.

```

candb = canDatabase('J1939DB.dbc');
msgInfo = messageInfo(candb, 419364350, true)

msgInfo =
    Name: 'A1'
    Comment: 'This is an A1 message'
    ID: 419364350
    Extended: 1
    J1939: [1x1 struct]
    Length: 8
    Signals: {2x1 cell}
    SignalInfo: [2x1 struct]
    TxNodes: {'AerodynamicControl'}
    Attributes: {4x1 cell}
    AttributeInfo: [4x1 struct]

```

Input Arguments

candb — CAN database

CAN database object

CAN database, specified as a CAN database object. `candb` identifies the database containing the CAN messages that you want information about.

Example: `candb = canDatabase(_____)`

msgName — Message name

character vector | string

Message name, specified as a character vector or string. Provide the name of the message you want information about.

Example: 'A1'

Data Types: char | string

id – Message ID

numeric value

Message ID, specified as a numeric value. `id` is the numeric identifier of the specified message, in either extended or standard form.

Example: 419364350

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

msgIsExtended – Message ID format`true` | `false`

Message ID format, specified as a logical. Specify whether the message ID is in standard or extended type. Use the logical value `true` if extended, or `false` if standard. There is no default; you must provide this argument when using a message ID.

Example: `true`

Data Types: `logical`

Output Arguments

msgInfo – Message information

structure

Message information, returned as a structure or array of structures for the specified CAN database and messages.

See Also

Functions`attributeInfo` | `canDatabase` | `canMessage` | `nodeInfo` | `signalInfo`**Properties**`can.Database` Properties**Introduced in R2009a**

nodeInfo

Information about CAN database node

Syntax

```
info = nodeInfo(db)
info = nodeInfo(db,NodeName)
```

Description

`info = nodeInfo(db)` returns a structure containing information for all nodes found in the database db.

If no matches are found in the database, `nodeInfo` returns an empty node information structure.

`info = nodeInfo(db,NodeName)` returns a structure containing information for the specified node in the database db.

Examples

View Information from All Nodes

Create a CAN database object, and view information about its nodes.

```
db = canDatabase('c:\Database.dbc')
info = nodeInfo(db)
```

```
info =
3x1 struct array with fields:
    Name
    Comment
    Attributes
    AttributeInfo
```

View name of first node.

```
n = info(1).Name
n =
AerodynamicControl
```

View Information from One Node

Create a CAN database object, and view information about its first node, listed in the previous example.

```
db = canDatabase('c:\Database.dbc')
info = nodeInfo(db,'AerodynamicControl')
```

```
info =
    Name: 'AerodynamicControl'
    Comment: 'This is an AerodynamicControl node'
    Attributes: {3x1 cell}
    AttributeInfo: [3x1 struct]
```

Input Arguments

db — CAN database

CAN database object

CAN database, specified as a CAN database object.

Example: db = canDatabase(____)

nodeName — Node name

char vector | string

Node name, specified as a character vector or string.

Example: 'AerodynamicControl'

Data Types: char | string

Output Arguments

info — Node information

structure

Node information, returned as a structure with these fields:

Field	Description
Name	Node name
Comment	Text about node

See Also

Functions

attributeInfo | canDatabase | messageInfo | signalInfo

Properties

can.Database Properties

Introduced in R2015b

numpartitions (MDFDatastore)

Number of partitions for MDF datastore

Syntax

```
N = numpartitions(mdfds)
N = numpartitions(mdfds,pool)
```

Description

`N = numpartitions(mdfds)` returns the recommended number of partitions for the MDF datastore `mdfds`. Use the result as an input to the `partition` function.

`N = numpartitions(mdfds,pool)` returns a reasonable number of partitions to parallelize `mdfds` over the parallel pool, `pool`, based on the number of files in the datastore and the number of workers in the pool.

Examples

Find Recommended Number of Partitions for MDF Datastore

Determine the number of partitions you should use for your MDF datastore.

```
mdfds = mdfDatastore(fullfile(matlabroot,'examples','vnt','CANape.MF4'));
N = numpartitions(mdfds);
```

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

pool — Parallel pool

parallel pool object

Parallel pool specified as a parallel pool object.

Example: `gcp`

Output Arguments

N — Number of partitions

double

Number of partitions, returned as a double. This number is the calculated recommendation for the number of partitions for your MDF datastore. Use this when partitioning your datastore with the `partition` function.

See Also

Functions

mdfDatastore | partition | read | reset

Introduced in R2017b

pack

Pack signal data into CAN message

Syntax

```
pack(message, value, startbit, signalsize, byteorder)
```

Description

`pack(message, value, startbit, signalsize, byteorder)` takes specified input parameters and packs them into the message.

Examples

Pack a CAN Message

Pack a CAN message with a 16-bit integer value of 1000.

```
message = canMessage(500, false, 8);
pack(message, int16(1000), 0, 16, 'LittleEndian')
message.Data
```

1×8 uint8 row vector

```
232    3    0    0    0    0    0    0
```

Note that $1000 = (3 \times 256) + 232$.

Pack a CAN message with a double value of 3.14. A double requires 64 bits.

```
pack(message, 3.14, 0, 64, 'LittleEndian')
```

Pack a CAN message with a single value of -40. A single requires 32 bits.

```
pack(message, single(-40), 0, 32, 'LittleEndian')
```

Input Arguments

message — CAN message

CAN message object

CAN message, specified as a CAN message object.

Example: `canMessage`

value — Value of signal to pack into message

numeric value

Value of signal to pack into message, specified as a numeric value. The value is assumed decimal, and distributed among the 8 bytes of the message `Data` property. You should convert the value into the data type expected for transmission.

Example: `int16(1000)`

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

startbit – Signal starting bit in data

`single` | `double`

Signal starting bit in the data, specified as a single or double value. This is the least significant bit position in the signal data. Accepted values for `startbit` are from 0 through 63, inclusive.

Example: 0

Data Types: `single` | `double`

signalsize – Length of signal in bits

numeric value

Length of the signal in bits, specified as a numeric value. Accepted values for `signalsize` are from 1 through 64, inclusive.

Example: 16

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

byteorder – Signal byte order format

'LittleEndian' | 'BigEndian'

Signal byte order format, specified as 'LittleEndian' or 'BigEndian'.

Example: 'LittleEndian'

Data Types: `char` | `string`

See Also

Functions

`canMessage` | `extractAll` | `extractRecent` | `extractTime` | `unpack`

Introduced in R2009a

partition (MDFDatastore)

Partition MDF datastore

Syntax

```
subds = partition(mdfds,N,index)
subds = partition(mdfds,'Files',index)
subds = partition(mdfds,'Files',filename)
```

Description

`subds = partition(mdfds,N,index)` partitions the MDF datastore `mdfds` into the number of parts specified by `N`, and returns the partition corresponding to the index `index`.

`subds = partition(mdfds,'Files',index)` partitions the MDF datastore by files and returns the partition corresponding to the file of index `index` in the `Files` property.

`subds = partition(mdfds,'Files',filename)` partitions the datastore by files and returns the partition corresponding to the specified filename.

Examples

Partition an MDF Datastore into Default Parts

Partition an MDF datastore from the sample file `CANape.MF4`, and return the first part.

```
mdfds = mdfDatastore(fullfile(matlabroot,'examples','vnt','CANape.MF4'));
N = numpartitions(mdfds);
subds1 = partition(mdfds,N,1);
```

Partition an MDF Datastore by Its Files

Partition an MDF datastore according to its files, and return partitions by index and file name.

```
cd c:\temp
mdfds = mdfDatastore({'CANape1.MF4','CANape2.MF4','CANape3.MF4'});
mdfds.Files

ans =
    3×1 cell array
    'c:\temp\CANape1.MF4'
    'c:\temp\CANape2.MF4'
    'c:\temp\CANape3.MF4'
```

```
subds2 = partition(mdfds,'files',2);  
subds3 = partition(mdfds,'files','c:\temp\CANape3.MF4');
```

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

N — Number of partitions

positive integer

Number of partitions, specified as a double of positive integer value. Use the `numpartitions` function for the recommended number or partitions.

Example: `numpartitions(mdfds)`

Data Types: double

index — Index

positive integer

Index, specified as a double of positive integer value. When using the 'files' partition scheme, this value corresponds to the index of the MDF datastore object `Files` property.

Example: 1

Data Types: double

filename — File name

character vector

File name, specified as a character vector. The argument can specify a relative or absolute path.

Example: `'CANape.MF4'`

Data Types: char

Output Arguments

subds — MDF datastore partition

MDF datastore object

MDF datastore partition, returned as an MDF datastore object. This output datastore is of the same type as the input datastore `mdfds`.

See Also

Functions

`mdfDatastore` | `numpartitions` | `read` | `reset`

Introduced in R2017b

preview (MDFDatastore)

Subset of data from MDF datastore

Syntax

```
data = preview(mdfds)
```

Description

`data = preview(mdfds)` returns a subset of data from MDF datastore `mdfds` without changing the current position in the datastore.

Examples

Examine Preview of MDF Datastore

```
mdfds = mdfDatastore(fullfile(matlabroot, 'examples', 'vnt', 'CANape.MF4'));
data = preview(mdfds)
```

```
data2 =
```

```
10x74 timetable
```

	Time	Counter_B4	Counter_B5	Counter_B6	Counter_B7	PWM
	0.0008254 sec	0	0	1	0	100
	0.010826 sec	0	0	1	0	100
	0.020826 sec	0	0	1	0	100
	0.030826 sec	0	0	1	0	100
	0.040826 sec	0	0	1	0	100
	0.050826 sec	0	0	1	0	100
	0.060826 sec	0	0	1	0	100
	0.070826 sec	0	0	1	0	100

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

Output Arguments

data — Subset of data

timetable

Subset of data, returned as a timetable of MDF records.

See Also

Functions

hasdata | mdfDatastore | read

Introduced in R2017b

read

Read channel data from MDF-file

Syntax

```
data = read(mdfObj)
data = read(mdfObj,chanList)
data = read(mdfObj,chanGroupIndex,chanName)
data = read(mdfObj,chanGroupIndex,chanName,startPosition)
data = read(mdfObj,chanGroupIndex,chanName,startPosition,endPosition)
data = read(mdfObj,chanGroupIndex,chanName,startPosition,
endPosition,'OutputFormat',fmtType)
[data,time] = read(mdfObj,chanGroupIndex,chanName,startPosition,
endPosition,'OutputFormat','Vector')
```

Description

`data = read(mdfObj)` reads all data for all channels from the MDF-file identified by the MDF-file object `mdfObj`, and assigns the output to `data`. If the file data is one channel group, the output is a timetable; multiple channel groups are returned as a cell array of timetables, where the cell array index corresponds to the channel group number.

`data = read(mdfObj,chanList)` reads all data for all channels specified in the channel list table `chanList`.

`data = read(mdfObj,chanGroupIndex,chanName)` reads all data for the specified channel from the MDF-file identified by the MDF-file object `mdfObj`.

`data = read(mdfObj,chanGroupIndex,chanName,startPosition)` reads data from the position specified by `startPosition`.

`data = read(mdfObj,chanGroupIndex,chanName,startPosition,endPosition)` reads data for the range specified from `startPosition` to `endPosition`.

`data = read(mdfObj,chanGroupIndex,chanName,startPosition,endPosition,'OutputFormat',fmtType)` returns data with the specified output format.

`[data,time] = read(mdfObj,chanGroupIndex,chanName,startPosition,endPosition,'OutputFormat','Vector')` returns two vectors of channel data and corresponding timestamps.

Examples

Read All Data from MDF-File

Read all available data from the MDF-file.

```
mdfObj = mdf('MDFFile.mf4');  
data = read(mdfObj);
```

Read All Data from Specified Channel List

Read all available data from the MDF-file for channels specified as part of a channel list.

```
mdfObj = mdf('MDFFile.mf4');  
chanList = channelList(mdfObj) % Channel table  
data = read(mdfObj,chanList(1:3,:)); % First 3 channels
```

Read All Data from Multiple Channels

Read all available data from the MDF-file for specified channels.

```
mdfObj = mdf('MDFFile.mf4');  
data = read(mdfObj,1,{'Channel1','Channel2'});
```

Read Range of Data from Specified Index Values

Read a range of data from the MDF-file using indexing for startPosition and endPosition to specify the data range.

```
mdfObj = mdf('MDFFile.mf4');  
data = read(mdfObj,1,{'Channel1','Channel2'},1,10);
```

Read Range of Data from Specified Time Values

Read a range of data from the MDF-file using time values for startPosition and endPosition to specify the data range.

```
mdfObj = mdf('MDFFile.mf4');  
data = read(mdfObj,1,{'Channel1','Channel2'},seconds(5.5),seconds(7.3));
```

Read All Data in Vector Format

Read all available data from the MDF-file, returning data and time vectors.

```
mdfObj = mdf('MDFFile.mf4');  
[data,time] = read(mdfObj,1,'Channel1','OutputFormat','Vector');
```

Read All Data in Time Series Format

Read all available data from the MDF-file, returning time series data.

```
mdfObj = mdf('MDFFile.mf4');
data = read(mdfObj,1,'Channel1','OutputFormat','TimeSeries');
```

Read Data from Channel List Entry

Read data from a channel identified by the `channelList` function.

Get list of channels and display their names and group numbers.

```
mdfObj = mdf('File05.mf4');
chlist = channelList(mdfObj);
chlist(1:2,1:2) % Display 2 channels, 2 columns
```

```
2x2 table
```

ChannelName	ChannelGroupNumber
"Float_32_LE_Offset_64"	2
"Float_64_LE_Master_Offset_0"	2

Read data from the first channel in the list.

```
data = read(mdfObj,chlist{1,2},chlist{1,1});
data(1:5,:)
```

```
5x1 timetable
```

Time	Float_32_LE_Offset_64
0 sec	5
0.01 sec	5.1
0.02 sec	5.2
0.03 sec	5.3
0.04 sec	5.4

Input Arguments

mdfObj — MDF-file

MDF-file object

MDF-file, specified as an MDF-file object.

Example: `mdf('MDFFile.mf4')`

chanList — List of channels

table

List of channels, specified as a table in the format returned by the `channelList` function.

Example: `channelList()`

Data Types: table

chanGroupIndex — Index of the channel group

numeric value

Index of channel group, specified as a numeric value that identifies the channel group from which to read.

Example: 1

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

chanName — Name of channel

char vector | string

Name of channel, specified as a character vector, string, or array. `chanName` identifies the name of a channel in the channel group. Use a cell array of character vectors or array of string to identify multiple channels.

Example: `'Channel1'`

Data Types: `char` | `string` | `cell`

startPosition — First position of channel data

numeric value | duration

First position of channel data, specified as a numeric value or duration. The `startPosition` option specifies the first position from which to read channel data. Provide a numeric value to specify an index position; use a duration to specify a time position. If only `startPosition` is provided without the `endPosition` option, the data value at that location is returned. When used with `endPosition` to specify a range, the function returns data from the `startPosition` (inclusive) to the `endPosition` (noninclusive).

Example: 1

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64` | `duration`

endPosition — Last position of channel data range

numeric value | duration

Last position of channel data range, specified as a numeric value or duration. The `endPosition` option specifies the last position for reading a range of channel data. Provide both the `startPosition` and `endPosition` to specify retrieval of a range of data. The function returns up to but not including `endPosition` when reading a range. Provide a numeric value to specify an index position; use a duration to specify a time position.

Example: 1000

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64` | `duration`

fmtType — Format for output data

'Timetable' (default) | 'Vector' | 'TimeSeries'

Format for output data, specified as a character vector or string. This option formats the output according to the following table.

OutputFormat	Description
'Timetable'	Return a timetable from one or more channels into one output variable. This is the only format allowed when reading from multiple channels at the same time. (Default.) Note: The timetable format includes columns for the MDF channels. Because the column titles must be valid MATLAB identifiers, they might not be exactly the same as those values in the MDF object ChannelNames property. The column headers are derived from the property using the function <code>matlab.lang.makeValidName</code> . The original channel names are available in the VariableDescriptions property of the timetable object.
'Vector'	Return a vector of numeric data values, and optionally a vector of time values from one channel. Use one output variable to return only data, or two output variables to return both data and time vectors.
'TimeSeries'	Return a time series of data from one channel.

Example: 'Vector'

Data Types: char | string

Output Arguments

data — Channel data

timetable (default) | double | time series | cell array

Channel data, returned as vector of doubles, a time series, a timetable, or cell array of timetables, according to the 'OutputFormat' option setting and the number of channel groups.

time — Channel data times

double

Channel data times, returned as a vector of double elements. The time vector is returned only when the 'OutputFormat' is set to 'Vector'.

See Also

Functions

channelList | mdf | mdfInfo | mdfSort | mdfVisualize | saveAttachment

Topics

“Access MDF Files” on page 16-96

“Reading Data from MDF Files” on page 16-101

“Time Series”

“Represent Dates and Times in MATLAB”

“Tables”

Introduced in R2016b

read (MDFDatastore)

Read data in MDF datastore

Syntax

```
data = read(mdfds)
[data,info] = read(mdfds)
```

Description

`data = read(mdfds)` returns data from the MDF datastore `mdfds` into the timetable `data`.

The `read` function returns a subset of data from the datastore. The size of the subset is determined by the `ReadSize` property of the datastore object. On the first call, `read` starts reading from the beginning of the datastore, and subsequent calls continue reading from the endpoint of the previous call. Use `reset` to read from the beginning again.

`[data,info] = read(mdfds)` also returns to the output argument `info` information, including metadata, about the extracted data.

Examples

Read Datastore by Files

Read data from an MDF datastore one file at a time.

```
mdfds = mdfDatastore({'CANape1.MF4','CANape2.MF4','CANape3.MF4'});
mdfds.ReadSize = 'file';
data = read(mdfds);
```

Read the second file and view information about the data.

```
[data2,info2] = read(mdfds);
info2

    struct with fields:

        Filename: 'CANape2.MF4'
        FileSize: 57592
        MDFFileProperties: [1x1 struct]
```

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

Output Arguments

data — Output data

timetable

Output data, returned as a timetable of MDF records.

info — Information about data

structure array

Information about data, returned as a structure array with the following fields:

Filename
FileSize
MDFFileProperties

See Also

Functions

hasdata | mdfDatastore | preview | readall | reset

Topics

“Using MDF Files Via MDF Datastore” on page 16-107

Introduced in R2017b

readall (MDFDatastore)

Read all data in MDF datastore

Syntax

```
data = readall(mdfds)
```

Description

`data = readall(mdfds)` reads all the data in the datastore specified by `mdfds` and returns it to timetable data.

After the `readall` function returns all the data, it resets `mdfds` to point to the beginning of the datastore.

If all the data in the datastore does not fit in memory, then `readall` returns an error.

Examples

Read All Data in Datastore

Read all the data from a multiple file MDF datastore into a timetable.

```
mdfds = mdfDatastore({'CANape1.MF4', 'CANape2.MF4', 'CANape3.MF4'});  
data = readall(mdfds);
```

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

Output Arguments

data — Output data

timetable

Output data, returned as a timetable of MDF records.

See Also

Functions

[hasdata](#) | [mdfDatastore](#) | [preview](#) | [read](#) | [reset](#)

Topics

“Using MDF Files Via MDF Datastore” on page 16-107

Introduced in R2017b

readAxis

Read and scale specified axis value from direct memory

Syntax

```
value = readAxis(chanObj,axis)
```

Description

`value = readAxis(chanObj,axis)` reads and scales a value for the specified `axis` through the XCP channel object `chanObj`. This action performs a direct read from memory on the slave module.

Examples

Read Value from XCP Channel Axis

Read the value from an XCP channel axis, identifying the axis by name.

```
a2lObj = xcpA2L('myA2Lfile.a2l');  
chanObj = xcpChannel(a2lObj,'CAN','Vector','Virtual 1',1);  
connect(chanObj);  
value = readAxis(chanObj,'pedal_position');
```

Alternatively, create an axis object and read its value.

```
axisObj = a2lObj.AxisXs('pedal_position');  
value = readAxis(chanObj,axisObj);
```

Input Arguments

chanObj — XCP channel

channel object

XCP channel, specified as an XCP channel object.

Example: `xcpChannel()`

axis — XCP channel axis

axis object | char

XCP channel axis, specified as a character vector or axis object.

Example: `'pedal_position'`

Data Types: char

Output Arguments

value — Value from axis read

axis value

Value from axis read, returned as type supported by the axis.

See Also

Functions

`readCharacteristic` | `readMeasurement` | `writeAxis` | `writeCharacteristic` | `writeMeasurement`

Introduced in R2018a

readCharacteristic

Read and scale specified axis value from direct memory

Syntax

```
value = readCharacteristic(chanObj,characteristic)
```

Description

`value = readCharacteristic(chanObj,characteristic)` reads and scales a value for the specified `characteristic` through the XCP channel object `chanObj`. This action performs a direct read from memory on the slave module.

Examples

Read Value from XCP Channel Characteristic

Read the value from an XCP channel characteristic, identifying the characteristic by name.

```
a2lObj = xcpA2L('myA2Lfile.a2l');  
chanObj = xcpChannel(a2lObj,'CAN','Vector','Virtual 1',1);  
connect(chanObj);  
value = readCharacteristic(chanObj,'torque_demand');
```

Alternatively, create a characteristic object and read its value.

```
charObj = a2lObj.CharacteristicInfo('torque_demand');  
value = readCharacteristic(chanObj,charObj);
```

Input Arguments

chanObj — XCP channel

channel object

XCP channel, specified as an XCP channel object.

Example: `xcpChannel()`

characteristic — XCP channel characteristic

characteristic object | char

XCP channel characteristic, specified as a character vector or characteristic object.

Example: `'torque_demand'`

Data Types: char

Output Arguments

value — Value from characteristic read

characteristic value

Value from characteristic read, returned as a type supported by the characteristic.

See Also

Functions

`readAxis` | `readMeasurement` | `writeAxis` | `writeCharacteristic` | `writeMeasurement`

Introduced in R2018a

readDAQ

Read scaled samples of specified measurement from DAQ list

Syntax

```
value = readDAQ(xcpch,measurementName)
value = readDAQ(xcpch,measurementName,count)
```

Description

`value = readDAQ(xcpch,measurementName)` reads and scales all acquired DAQ list data from the XCP channel object `xcpch`, for the specified `measurementName`, and stores the results in the variable `value`. If the measurement has no data, the function returns an empty value.

`value = readDAQ(xcpch,measurementName,count)` reads the quantity of data specified by `count`. If fewer than `count` samples are available, it returns only those.

Examples

Acquire Data from DAQ List

Create an XCP channel connected to a Vector CAN device on a virtual channel. Set up a DAQ measurement list and acquire 10 data values, then all data.

```
a2lObj = xcpA2L('myFile.a2l');
channelObj = xcpChannel(a2lObj,'CAN','Vector','CANcaseXL 1',1);
connect(channelObj);
createMeasurementList(channelObj,'DAQ','Event1','Measurement1');
startMeasurement(channelObj);
data = readDAQ(channelObj,'Measurement1',10);
data_all = readDAQ(channelObj,'Measurement1');
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

measurementName — Name of single XCP measurement

character vector | string

Name of a single XCP measurement specified as a character vector or string. Make sure `measurementName` matches the corresponding measurement name defined in your A2L file.

Data Types: char | string

count — Number of samples to read

numeric value

Number of samples to read, specified as a numeric value, for the specified measurement name. If the number of samples in the measurement is less than the specified count, only the available number of samples are returned.

Output Arguments

value — Values from specified measurement

numeric array

Values from the specified measurement, returned as a numeric array.

See Also

`readSingleValue`

Introduced in R2018b

readDAQListData

Read samples of specified measurement from DAQ list

Syntax

```
value = readDAQListData(xcpch,measurementName)
value = readDAQListData(xcpch,measurementName,count)
```

Description

`value = readDAQListData(xcpch,measurementName)` reads all acquired DAQ list data from the XCP channel object `xcpch`, for the specified `measurementName`, and stores the results in the variable `value`. If the measurement has no data, the function returns an empty value.

`value = readDAQListData(xcpch,measurementName,count)` reads the quantity of data specified by `count`. If fewer than `count` samples are available, it returns only those.

Examples

Acquire Data for Triangle Measurement in a DAQ List

Create an XCP channel connected to a Vector CAN device on a virtual channel. Set up a DAQ measurement list and acquire data from a '100ms' events 'Triangle' measurement.

Create an object to parse an A2L file and connect that to an XCP channel.

```
a2lfile = xcp.A2L('XCPSIM.a2l')
xcpch = xcp.Channel(a2lfile,'CAN','Vector','Virtual 1',1);
```

Connect the channel to the slave.

```
connect(xcpch)
```

Create a measurement list with a '100ms' event and 'PMW', 'PWMFiltered', and 'Triangle' measurements.

```
createMeasurementList(xcpch,'DAQ','100ms',{'PMW','PWMFiltered','Triangle'})
```

Start the measurement.

```
startMeasurement(xcpch)
```

Acquire data for the 'Triangle' measurement for 5 counts.

```
value = readDAQListData(xcpch,'Triangle',5)
```

```
value =  
    -50  -50  -50  -50  -50
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

measurementName — Name of single XCP measurement

character vector | string

Name of a single XCP measurement specified as a character vector or string. Make sure `measurementName` matches the corresponding measurement name defined in your A2L file.

Data Types: `char` | `string`

count — Number of samples to read

numeric value

Number of samples to read, specified as a numeric value, for the specified measurement name. If the number of samples in the measurement is less than the specified count, only the available number of samples are returned.

Output Arguments

value — Values from specified measurement

numeric array

Values from the specified measurement, returned as a numeric array.

See Also

`readSingleValue`

Topics

“Acquire Measurement Data via Dynamic DAQ Lists” on page 8-9

Introduced in R2013a

readMeasurement

Read and scale specified measurement value from direct memory

Syntax

```
value = readMeasurement(chanObj, measurement)
```

Description

`value = readMeasurement(chanObj, measurement)` reads and scales a value for the specified measurement through the XCP channel object `chanObj`. This action performs a direct read from memory on the slave module.

Examples

Read Value from XCP Channel Measurement

Read the value from an XCP channel measurement, identifying the measurement by name.

```
a2lObj = xcpA2L('myA2Lfile.a2l');  
chanObj = xcpChannel(a2lObj, 'CAN', 'Vector', 'Virtual 1', 1);  
connect(chanObj);  
value = readMeasurement(chanObj, 'limit')
```

```
100
```

Alternatively, create a measurement object and read its value.

```
measObj = a2lObj.MeasurementInfo('limit');  
value = readMeasurement(chanObj, measObj)
```

```
100
```

Input Arguments

chanObj — XCP channel

channel object

XCP channel, specified as an XCP channel object.

Example: `xcpChannel()`

measurement — XCP channel measurement

measurement object | char

XCP channel measurement, specified as a character vector or measurement object.

Example: `'limit'`

Data Types: char

Output Arguments

value — Value from measurement read

measurement value

Value from measurement read, returned as a type supported by the measurement.

See Also

Functions

readAxis | readCharacteristic | writeAxis | writeCharacteristic | writeMeasurement

Introduced in R2018a

readSingleValue

Read single sample of specified measurement from memory

Syntax

```
value = readSingleValue(xcpch, 'measurementName')
```

Description

`value = readSingleValue(xcpch, 'measurementName')` acquires a single value for the specified measurement through the configured XCP channel and stores it in a variable for later use. The values are read directly from memory.

Examples

Acquire a Single Value for Triangle Measurement

Read a single value from a '100ms' events 'Triangle' measurement.

Create an object to parse an A2L file and connect that to an XCP channel.

```
a2lfile = xcpA2L('XCPSIM.a2l')
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);
```

Connect the channel to the slave module.

```
connect(xcpch)
```

Acquire data for the 'Triangle' measurement.

```
value = readSingleValue(xcpch, 'Triangle')
```

```
value =
```

```
    14
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

measurementName — Name of single XCP measurement

character vector | string

Name of a single XCP measurement specified as a character vector or string. Make sure `measurementName` matches the corresponding measurement name defined in your A2L file.

Data Types: char | string

Output Arguments

value – Value of the measurement

numeric value

Value of the selected measurement, returned as a numeric value.

See Also

readDAQListData

Introduced in R2013a

receive

Receive messages from CAN bus

Syntax

```
message = receive(canch,messagesrequested,'OutputFormat','timetable')  
message = receive(canch,messagesrequested)
```

Description

`message = receive(canch,messagesrequested,'OutputFormat','timetable')` returns a timetable of CAN messages received on the CAN channel `canch`. The number of messages returned is less than or equal to `messagesrequested`. If fewer messages are available than `messagesrequested` specifies, the function returns the currently available messages. If no messages are available, the function returns an empty array. If `messagesrequested` is `Inf`, the function returns all available messages.

To understand the elements of a message, refer to `canMessage`.

Specifying the `'OutputFormat'` option value of `'timetable'` results in a timetable of messages. This output format is recommended for optimal performance and representation of CAN messages within MATLAB.

`message = receive(canch,messagesrequested)` returns an array of CAN message objects instead of a timetable if the channel `ProtocolMode` is `'CAN'`.

Note If the channel `ProtocolMode` is `'CAN FD'` the `receive` function returns a timetable, whether you specify an `'OutputFormat'` or not.

Examples

Receive CAN Messages

You can receive CAN messages as a timetable or as an array of message objects.

Receive all available messages as a timetable.

```
canch = canChannel('Vector','CANCaseXL 1',1);  
start(canch)  
message = receive(canch,Inf,'OutputFormat','timetable');
```

Receive up to five messages as an array of message objects.


```
message = receive(canch,5);
```

Input Arguments

canch — CAN channel

CAN channel object

CAN channel, specified as a CAN channel object. This is the channel by which you access the CAN bus.

Example: `canChannel`

messagesrequested — Maximum number of messages to receive

numeric value | `Inf`

Maximum number of messages to receive, specified as a positive numeric value or `Inf`.

Example: `Inf`

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

Output Arguments

message — CAN messages

timetable | CAN message object array

CAN messages from the channel, returned as a timetable of messages or an array of CAN message objects.

See Also

Functions

`canChannel` | `canMessage` | `transmit`

Introduced in R2009a

receive (J1939)

Receive parameter groups from J1939 bus

Syntax

```
pgrp = receive(chan,count)
```

Description

`pgrp = receive(chan,count)` receives parameter groups from the bus via channel `chan`. The number of received parameter groups is limited to the value of `count`.

Examples

Receive Parameter Groups from Bus

Receive all the available parameter groups from the bus by specifying a count of `Inf`.

```
db = canDatabase('MyDatabase.dbc')
chan = j1939Channel(db,'Vector','CANCaseXL 1',1)
start(chan)
pgrp = receive(chan,Inf)
```

Input Arguments

chan — J1939 channel

channel object

J1939 channel, specified as a channel object. Use the `j1939Channel` function to create and define the channel.

count — Maximum number of parameter groups

double

Maximum number of parameter groups to receive, specified as a double. `count` must be a positive value, or `Inf` to specify all available parameter groups.

Data Types: double

Output Arguments

pgrp — J1939 parameter groups

array of `ParameterGroup` objects

J1939 parameter groups, returned as an array of `ParameterGroup` objects.

See Also

Functions

j1939Channel | start | transmit

Introduced in R2015b

replay

Retransmit messages from CAN bus

Syntax

```
replay(canch, message)
```

Description

`replay(canch, message)` retransmits the message or messages `message` on the channel `canch`, based on the relative differences of their timestamps. The `replay` function also replays messages from MATLAB to Simulink.

To understand the elements of a message, refer to `canMessage`.

Examples

Replay Messages on CAN Channel

Use a loopback connection between two channels, so that:

- The first channel transmits messages 2 seconds apart.
- The second channel receives them.
- The `replay` function retransmits the messages with the original delay.

The timestamp differentials between messages in the two receive arrays, `msgRx1` and `msgRx2`, are equal.

```
ch1 = canChannel('Vector', 'CANcaseXL 1', 1);
ch2 = canChannel('Vector', 'CANcaseXL 1', 2);
start(ch1)
start(ch2)
msgTx1 = canMessage(500, false, 8);
msgTx2 = canMessage(750, false, 8);

% The first channel transmits messages 2 seconds apart.
transmit(ch1, msgTx1)
pause(2)
transmit(ch1, msgTx2)
%The second channel receives them
msgRx1 = receive(ch2, Inf);

% The replay function retransmits the messages with the original delay.
replay(ch2, msgRx1)
pause(2)
msgRx2 = receive(ch1, Inf);
```

Input Arguments

canch — CAN device channel

CAN channel object

CAN device channel, specified as a CAN channel object, on which to retransmit.

Example: `canChannel('NI', 'CAN1')`

message – Messages to replay

array of message objects

Messages to replay, specified as an array of message objects.

See Also

Functions

`canMessage` | `transmit`

Introduced in R2009a

reset (MDFDatastore)

Reset MDF datastore to initial state

Syntax

```
reset(mdfds)
```

Description

`reset(mdfds)` resets the MDF datastore specified by `mdfds` to its initial read state, where no data has been read from it. Resetting allows your to reread from the same datastore.

Examples

Reset MDF Datastore

Reset an MDF datastore so that you can read from it again.

```
mdfds = mdfDatastore(fullfile(matlabroot, 'examples', 'vnt', 'CANape.MF4'));  
data = read(mdfds);  
reset(mdfds);  
data = read(mdfds);
```

Input Arguments

mdfds — MDF datastore

MDF datastore object

MDF datastore, specified as an MDF datastore object.

Example: `mdfds = mdfDatastore('CANape.MF4')`

See Also

Functions

`hasdata` | `mdfDatastore` | `read`

Introduced in R2017b

saveAttachment

Save attachment from MDF-file

Syntax

```
saveAttachment(mdfObj,AttachmentName)
saveAttachment(mdfObj,AttachmentName,DestFile)
```

Description

`saveAttachment(mdfObj,AttachmentName)` saves the specified attachment from the MDF-file to the current MATLAB working folder. The attachment is saved with its existing name.

`saveAttachment(mdfObj,AttachmentName,DestFile)` saves the specified attachment from the MDF-file to the given destination. You can specify relative or absolute paths to place the attachment in a specific folder.

Examples

Save Attachment with Original Name

Save an MDF-file attachment with its original name in the current folder.

```
mdfObj = mdf('MDFFile.mf4');
saveAttachment(mdfObj,'AttachmentName.ext')
```

Save Attachment with New Name

Save an MDF-file attachment with a new name in the current folder.

```
mdfObj = mdf('MDFFile.mf4');
saveAttachment(mdfObj,'AttachmentName.ext','MyFile.ext')
```

Save Attachment in Parent Folder

Save an MDF-file attachment in a folder specified with a relative path name, in this case in the parent of the current folder.

```
mdfObj = mdf('MDFFile.mf4');
saveAttachment(mdfObj,'AttachmentName.ext','..\MyFile.ext')
```

Save Attachment in Specified Folder

This example saves an MDF-file attachment using an absolute path name.

```
mdfObj = mdf('MDFFile.mf4');  
saveAttachment(mdfObj, 'AttachmentName.ext', 'C:\MyDir\MyFile.ext')
```

Input Arguments

mdfObj — MDF-file

MDF-file object

MDF-file, specified as an MDF-file object.

Example: `mdf('MDFFile.mf4')`

AttachmentName — MDF-file attachment name

char vector | string

MDF-file attachment name, specified as a character vector or string. The name of the attachment is available in the `Name` field of the MDF-file object `Attachment` property.

Example: `'file1.dbc'`

Data Types: `char` | `string`

DestFile — Destination file name for the saved attachment

existing attachment name (default) | char vector | string

Destination file name for the saved attachment, specified as a character vector or string. The specified destination can include an absolute or relative path, otherwise the attachment is saved in the current folder.

Example: `'MyFile.ext'`

Data Types: `char` | `string`

See Also

Functions

`mdf` | `read`

Introduced in R2016b

setValue

Set instance value in CDFX object

Syntax

```
setValue(cdfxObj, instName, iVal)  
setValue(cdfxObj, instName, sysName, iVal)
```

Description

`setValue(cdfxObj, instName, iVal)` sets the value of the unique instance whose `ShortName` is specified by `instName` to `iVal`. If multiple instances share the same `ShortName`, the function returns an error.

`setValue(cdfxObj, instName, sysName, iVal)` sets the value of the instance whose `ShortName` is specified by `instName` and is contained in the system specified by `sysName`.

Note `setValue` does not write the instance value in the original CDFX-file. Use the `write` function to update the CDFX-file or to create a new file.

Examples

Set Value of Instance

Create an `asam.cdfx` object and set the value of its `VALUE_NUMERIC` instance.

```
cdfxObj = cdfx('c:\DataFiles\AllCategories_VCD.cdfx');  
setValue(cdfxObj, 'VALUE_NUMERIC', 55)
```

Read back the value to verify it.

```
iVal = getValue(cdfxObj, 'VALUE_NUMERIC')
```

```
iVal =
```

```
    55
```

Input Arguments

cdfxObj – CDFX-file object

`asam.cdfx` object

CDFX-file object, specified as an `asam.cdfx` object. Use the object to access the calibration data.

Example: `cdfx()`

instName – Instance name

`char` | `string`

Instance name, specified as a character vector or string.

Example: 'NUMERIC_VALUE'

Data Types: char | string

sysName — Parent system name

char | string

Parent system name, specified as a character vector or string.

Example: 'System2'

Data Types: char | string

iVal — Instance value

instance type

Instance value, specified as the type supported by the instance.

Example: 55

See Also

Functions

cdfx | getValue | instanceList | systemList | write

Introduced in R2019a

signalInfo

Information about signals in CAN message

Syntax

```
SigInfo = signalInfo(candb,msgName)
SigInfo = signalInfo(candb,id,extended)
SigInfo = signalInfo(candb,id,extended,signalName)
```

Description

`SigInfo = signalInfo(candb,msgName)` returns information about the signals in the specified CAN message `msgName` in the specified database `candb`.

`SigInfo = signalInfo(candb,id,extended)` returns information about the signals in the message with the specified standard or extended ID `id` in the specified database `candb`.

`SigInfo = signalInfo(candb,id,extended,signalName)` returns information about the specified signal '`signalName`' in the message with the specified standard or extended ID `id` in the specified database `candb`.

Examples

Use Message Name to Get Information

Get signal information from the message 'Battery_Voltage'.

```
SigInfo = signalInfo(candb,'Battery_Voltage');
```

Use Message ID to Get Information

Get signal information from the message with ID 196608.

```
SigInfo = signalInfo(candb,196608,true);
```

Use Signal Name to Get Information

Get information from the signal named 'BatVlt' from message 196608.

```
SigInfo = signalInfo(candb,196608,true,'BatVlt');
```

Input Arguments

candb — CAN database

CAN database object

CAN database, specified as a CAN database object, that contains the signals that you want information about.

Example: `canDb = canDatabase('C:\Database.dbc')`

msgName — Message name

character vector | string

Message name, specified as a character vector or string. Provide the name of the message that contains the signals that you want information about.

Example: `'Battery_Voltage'`

Data Types: `char` | `string`

id — Message identifier

numeric value

Message identifier, specified as a numeric value. Provide the numeric identifier of the specified message that contains the signals you want information about.

Example: `196608`

extended — Extended message indicator

`true` | `false`

Extended message indicator, specified as `true` or `false`. Indicate whether the message ID is standard or extended type. Use the logical value `true` if extended, or `false` if standard.

Example: `true`

Data Types: `logical`

signalName — Name of signal

char vector | string

Name of the signal, specified as a character vector or string. Provide the name of the specific signal that you want information about.

Example: `'BatVlt'`

Data Types: `char` | `string`

Output Arguments**SigInfo — Signal information**

struct or array of struct

Signal information, returned as a structure or array of structures.

Data Types: `struct`

See Also**Functions**

`canDatabase` | `canMessage` | `messageInfo`

Properties

can.Database Properties

Introduced in R2009a

start

Set CAN channel online

Syntax

```
start(canch)
```

Description

`start(canch)` starts the CAN channel `canch` on the CAN bus to send and receive messages. The CAN channel remains online until:

- You call `stop` on this channel.
- You clear the channel from the workspace.

Note Before you can start a channel to transmit or receive CAN FD messages, you must configure its bus speed with `configBusSpeed`.

Examples

Start a CAN Channel

Start a virtual device CAN channel.

```
canch = canChannel('MathWorks','Virtual 1',1);  
start(canch)
```

Input Arguments

canch — CAN device channel

CAN channel object

CAN device channel, specified as a CAN channel object, that you want to start.

Example: `canChannel('NI','CAN1')`

See Also

Functions

`canChannel` | `configBusSpeed` | `stop`

Introduced in R2009a

start (J1939)

Start channel connection to J1939 bus

Syntax

```
start(chan)
```

Description

`start(chan)` activates the channel `chan` on a J1939 bus. The channel remains activated until `stop` is called or it is cleared from the memory.

Examples

Start J1939 Channel

Activate a channel on a J1939 bus.

```
db = canDatabase('MyDatabase.dbc');  
chan = j1939Channel(db, 'Vector', 'CANCASEXL 1', 1);  
start(chan)
```

Input Arguments

chan — J1939 channel

channel object

J1939 channel, specified as a channel object. Use the `j1939Channel` function to create and define the channel.

See Also

Functions

`j1939Channel` | `stop`

Introduced in R2015b

startMeasurement

Start configured DAQ and STIM lists

Syntax

```
startMeasurement(xcpch)
```

Description

`startMeasurement(xcpch)` starts all configured data acquisition and stimulation lists on the specified XCP channel. When you start the measurement, configured DAQ lists begin acquiring data values from the slave module and STIM lists begin transmitting data values to the slave model.

Examples

Start a DAQ Measurement

Create an XCP channel connected to a Vector CAN device on a virtual channel. Set up a DAQ measurement list and start measuring data.

```
a2l = xcpA2L('XCPSIM.a2l')
xcpch = xcpChannel(a2l, 'CAN', 'Vector', 'Virtual 1', 1),
xcpch =
```

Channel with properties:

```
SlaveName: 'CPP'
A2LFileName: 'XCPSIM.a2l'
TransportLayer: 'CAN'
TransportLayerDevice: [1x1 struct]
SeedKeyCallbackFcn: []
KeyValue: []
```

Connect the channel to the slave module.

```
connect(xcpch)
```

Setup a data acquisition measurement list with the '10 ms' event and 'Bitslice' measurement.

```
createMeasurementList(xcpch, 'DAQ', '10 ms', 'BitSlice')
```

Start your measurement.

```
startMeasurement(xcpch);
```

Start a STIM Measurement

Create an XCP channel connected to a Vector CAN device on a virtual channel. Set up a DAQ measurement list and start measuring data.


```
a2l = xcpA2L('XCPSIM.a2l')
xcpch = xcpChannel(a2l, 'CAN', 'Vector', 'Virtual 1', 1)
xcpch =
```

Channel with properties:

```
    SlaveName: 'CPP'
    A2LFileName: 'XCPSIM.a2l'
    TransportLayer: 'CAN'
    TransportLayerDevice: [1x1 struct]
    SeedKeyCallbackFcn: []
    KeyValue: []
```

Connect the channel to the slave module.

```
connect(xcpch)
```

Setup a data stimulation measurement list with the '100ms' event and 'BitSlice0', 'PWMFiletered', and 'Triangle' measurements.

```
createMeasurementList(xcpch, 'STIM', '100ms', {'BitSlice0', 'PWMFiletered', 'Triangle'})
```

Start your measurement.

```
startMeasurement(xcpch);
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

See Also

`stopMeasurement` | `xcpChannel`

Introduced in R2013a

stop

Set CAN channel offline

Syntax

```
stop(canch)
```

Description

`stop(canch)` stops the CAN channel `canch` on the CAN bus. The CAN channel also stops running when you clear `canch` from the workspace.

Examples

Stop a CAN Channel

Stop a virtual device CAN channel.

```
canch = canChannel('MathWorks','Virtual 1',1);  
start(canch)  
stop(canch)
```

Input Arguments

canch — CAN device channel

CAN channel object

CAN device channel, specified as a CAN channel object, that you want to stop.

Example: `canChannel('NI','CAN1')`

See Also

`canChannel` | `start`

Introduced in R2009a

stop (J1939)

Stop channel connection to J1939 bus

Syntax

```
stop(chan)
```

Description

`stop(chan)` deactivates the channel `chan` on a J1939 bus. The channel also deactivates when it is cleared from the memory.

Examples

Stop J1939 Channel

Deactivate a channel on a J1939 bus.

```
db = canDatabase('MyDatabase.dbc');  
chan = j1939Channel(db, 'Vector', 'CANCaseXL 1', 1);  
start(chan)  
  
stop(chan)
```

Input Arguments

chan — J1939 channel

channel object

J1939 channel, specified as a channel object. Use the `j1939Channel` function to create and define the channel.

See Also

Functions

`j1939Channel` | `start`

Introduced in R2015b

stopMeasurement

Stop configured DAQ and STIM lists

Syntax

```
stopMeasurement(xcpch)
```

Description

`stopMeasurement(xcpch)` stops all configured data acquisition and stimulation lists on the specified XCP channel. When you stop the measurement, configured DAQ lists stop acquiring data values from the slave module and STIM lists stop transmitting data values to the slave model.

Examples

Stop a DAQ Measurement

Create an XCP channel connected to a Vector CAN device on a virtual channel. Set up a DAQ measurement list and start and stop measuring data.

```
a2l = xcp2L('XCPSIM.a2l')  
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1)
```

```
xcpch =
```

```
Channel with properties:
```

```
SlaveName: 'CPP'  
A2LFileName: 'XCPSIM.a2l'  
TransportLayer: 'CAN'  
TransportLayerDevice: [1x1 struct]  
SeedKeyCallbackFcn: []  
KeyValue: []
```

Connect the channel to the slave module.

```
connect(xcpch)
```

Setup a data acquisition measurement list with the '10 ms' event and 'BitSlice' measurement and start your measurement.

```
createMeasurementList(xcpch, 'DAQ', '10 ms', 'BitSlice')  
startMeasurement(xcpch);
```

Stop your measurement.

```
stopMeasurement(xcpch);
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

See Also

`startMeasurement` | `xcpChannel`

Introduced in R2013a

systemList

ECU systems in the CDFX object

Syntax

```
sList = systemList(cdfxObj)
sList = systemList(cdfxObj, sysName)
```

Description

`sList = systemList(cdfxObj)` returns a table listing every electronic control unit (ECU) system in the CDFX object.

`sList = systemList(cdfxObj, sysName)` returns a table listing every ECU system in the CDFX object whose `ShortName` matches `SysName`.

Examples

View CDFX Object Systems

Create an `asam.cdfx` object and view its ECU systems.

List all systems.

```
cdfxObj = cdfx('c:\DataFiles\AllCategories_VCD.cdfx');
sList = systemList(cdfxObj)
```

```
sList =
```

```
1×3 table
```

ShortName	Instances	Metadata
"System1"	[1×16 string]	" "

Match a specified system.

```
sList = systemList(cdfxObj, 'System1');
```

Input Arguments

cdfxObj — CDFX-file object

`asam.cdfx` object

CDFX-file object, specified as an `asam.cdfx` object. Use the object to access the calibration data.

Example: `cdfx()`

sysName — Parent system name

string

Parent system name, specified as a string.

Example: "System2"

Data Types: `string`

Output Arguments

sList – ECU system list

table

ECU system list, returned as a table.

See Also

Functions

`cdfx` | `getValue` | `instanceList` | `setValue` | `write`

Introduced in R2019a

transmit

Send CAN messages to CAN bus

Syntax

```
transmit(canch,message)
```

Description

`transmit(canch,message)` sends the message or array of messages onto the bus via the CAN channel.

For more information on the elements of a message, see `canMessage`.

Note The `transmit` function ignores the `Timestamp` property and the `Error` property.

CAN is a peer-to-peer network, so when transmitting messages on a physical bus at least one other node must be present to properly acknowledge the message. Without another node, the transmission will fail as an error frame, and the device will continually retry to transmit.

Examples

Transmit a CAN Message

Define a CAN message and transmit it to the CAN bus.

```
message = canMessage(250,false,8);  
message.Data = ([45 213 53 1 3 213 123 43]);  
canch = canChannel('MathWorks','Virtual 1',1);  
start(canch)  
transmit(canch,message)
```

Transmit an Array of Messages

Transmit an array of three CAN messages.

```
transmit(canch,[message0,message1,message2])
```

Transmit Messages on a Remote Frame

Transmit a CAN message on a remote frame, using the message `Remote` property.

```
message = canMessage(250,false,8);  
message.Data = ([45 213 53 1 3 213 123 43]);  
message.Remote = true;  
canch = canChannel('MathWorks','Virtual 1',1);  
start(canch)  
transmit(canch,message)
```


Input Arguments

canch — CAN channel

CAN channel object

CAN channel, specified as a CAN channel object. This is the channel by which you access the CAN bus.

message — Message to transmit

CAN message object or array of objects

Message to transmit, specified as a CAN message object or array of message objects. These messages are transmitted via a CAN channel to the bus.

See Also

Functions

canChannel | canMessage | receive

Introduced in R2009a

transmit (J1939)

Send parameter groups via channel to J1939 bus

Syntax

```
transmit(chan,pgrp)
```

Description

`transmit(chan,pgrp)` sends the specified parameter groups in the array `pgrp` onto the J1939 bus via the channel `chan`.

Examples

Send Parameter Groups onto Bus

Send the parameter group 'MyParameterGroup' to the bus.

```
db = canDatabase('MyDatabase.dbc');  
chan = j1939Channel(db,'Vector','CANCaseXL 1',1);  
start(chan)  
pgrp = j1939ParameterGroup(db,'MyParameterGroup')  
transmit(chan,pgrp)
```

Input Arguments

chan — J1939 channel

channel object

J1939 channel, specified as a channel object. Use the `j1939Channel` function to create and define the channel.

pgrp — J1939 parameter groups

array of `ParameterGroup` objects

J1939 parameter groups, specified as an array of `ParameterGroup` objects. Use the `j1939ParameterGroup` function to create and define the `ParameterGroup` objects.

See Also

Functions

`j1939Channel` | `j1939ParameterGroup` | `receive` | `start`

Introduced in R2015b

transmitConfiguration

Display messages configured for automatic transmission

Syntax

```
transmitConfiguration(canch)
```

Description

`transmitConfiguration(canch)` displays information about all messages in the CAN channel, `canch`, configured for periodic transmit or event-based transmit.

For more information on periodic transmit of messages, refer to `transmitPeriodic`.

For more information on event-based transmit of messages, refer to `transmitEvent`.

Examples

Configure and View Message Transmit Settings

Create two messages with different transmit settings, then view those settings.

Create a CAN channel with two messages.

```
canch = canChannel('Vector', 'Virtual 1', 1);
msg1 = canMessage(500, false, 8);
msg2 = canMessage(750, false, 8);
```

Configure the transmit settings for `msg1` and `msg2`.

```
transmitEvent(canch, msg1, 'On');
transmitPeriodic(canch, msg2, 'On', 1);
```

Display the transmit configuration for the messages on `canch`.

```
transmitConfiguration(canch)
```

Periodic Messages

ID	Extended Name	Data	Rate (seconds)
750	false	0 0 0 0 0 0 0 0	1.000000

Event Messages

ID	Extended Name	Data
----	---------------	------

```
-----  
500 false          0 0 0 0 0 0 0 0
```

Input Arguments

canch — CAN channel

CAN channel object

CAN channel, specified as a CAN channel object. This is the channel by which you access the CAN bus for periodic or event-based transmission.

See Also

Functions

`canChannel` | `canMessage` | `transmitEvent` | `transmitPeriodic`

Introduced in R2010b

transmitEvent

Configure messages for event-based transmission

Syntax

```
transmitEvent(canch, msg, state)
```

Description

`transmitEvent(canch, msg, state)` enables or disables an event-based transmit of the CAN message, `msg`, on the channel, according to the `state` argument of 'On' or 'Off'. A typical event that triggers a transmission is a change to the message `Data` property.

Examples

Enable an Event-Based Message

Configure a channel with an event-based message.

Construct a CAN channel and configure a message on the channel.

```
canch = canChannel('MathWorks', 'Virtual 1', 1);  
msg = canMessage(200, false, 4);
```

Enable the message for event-based transmit, start the channel, and pack the message to trigger the event-based transmit.

```
transmitEvent(canch, msg, 'On');  
start(canch);  
pack(msg, int32(1000), 0, 32, 'LittleEndian')
```

Input Arguments

canch — CAN channel

CAN channel object

CAN channel, specified as a CAN channel object. This is the channel by which you access the CAN bus, and the channel on which the specified message is enabled for event-based transmit.

msg — Message to transmit

CAN message object or array of objects

Message to transmit, specified as a CAN message object or array of message objects. This is the message enabled for event-based transmission on the specified CAN channel.

state — Enable event-based transmission

'On' | 'Off'

Enable event-based transmission, specified as 'On' or 'Off'.

Example: 'On'

Data Types: char | string

See Also

Functions

canChannel | canMessage | transmitConfiguration | transmitPeriodic

Introduced in R2010b

transmitPeriodic

Configure messages for periodic transmission

Syntax

```
transmitPeriodic(canch,msg,'On',period)
transmitPeriodic(canch,msg,'Off')
```

Description

`transmitPeriodic(canch,msg,'On',period)` enables periodic transmit of the message, `msg`, on the channel, `canch`, to transmit at the specified period, `period`.

You can enable and disable periodic transmit even when the channel is running, allowing you to make changes to the state of the channel without stopping it.

`transmitPeriodic(canch,msg,'Off')` disables periodic transmission of the message, `msg`.

Examples

Transmit a Message Periodically

Configure a channel to transmit messages periodically.

Construct a CAN channel and message.

```
canch = canChannel('MathWorks','Virtual 1',1);
msg = canMessage(500,false,4);
```

Enable the message for periodic transmission on the channel, with a period of 1 second. Start the channel, and pack the message you want to send periodically.

```
transmitPeriodic(canch,msg,'On',1);
start(canch);
pack(msg,int32(1000),0,32,'LittleEndian')
```

Input Arguments

canch — CAN channel

CAN channel object

CAN channel, specified as a CAN channel object. This is the CAN channel for which you are controlling periodic transmission.

msg — Message to transmit

CAN message object or array of objects

Message to transmit, specified as a CAN message object or array of message objects. This is the message enabled for periodic transmission on the specified CAN channel.

period – Period of transmissions

0.500 (default) | numeric value

Period of transmissions, specified in seconds as a numeric value. This argument is optional, with a default of 0.5 seconds.

Example: 1.0

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64

See Also**Functions**

canChannel | canMessage | transmitConfiguration | transmitEvent

Introduced in R2010b

unpack

Unpack signal data from CAN message

Syntax

```
value = unpack(message, startbit, signalsize, byteorder, datatype)
```

Description

`value = unpack(message, startbit, signalsize, byteorder, datatype)` takes a set of input parameters to unpack the signal value from the message and returns the value as output.

Examples

Unpack Data from a CAN Message

Unpack the data value from a CAN message.

Unpack a 16-bit integer value.

```
message = canMessage(500, false, 8);  
pack(message, int16(1000), 0, 16, 'LittleEndian')  
value = unpack(message, 0, 16, 'LittleEndian', 'int16')
```

```
value =
```

```
    int16
```

```
    1000
```

Unpack a 32-bit single value.

```
pack(message, single(-40), 0, 32, 'LittleEndian')  
value = unpack(message, 0, 32, 'LittleEndian', 'single')
```

```
value =
```

```
    single
```

```
    -40
```

Unpack a 64-bit double value.

```
pack(message, 3.14, 0, 64, 'LittleEndian')  
value = unpack(message, 0, 64, 'LittleEndian', 'double')
```

```
value =  
    3.1400
```

Input Arguments

message — CAN message

CAN message object

CAN message, specified as a CAN message object, from which to unpack the data.

Example: `canMessage`

startbit — Signal starting bit in data

`single` | `double`

Signal starting bit in the data, specified as a single or double value. This is the least significant bit position in the signal data. Accepted values for `startbit` are from 0 through 63, inclusive.

Example: 0

Data Types: `single` | `double`

signalsize — Length of signal in bits

numeric value

Length of the signal in bits, specified as a numeric value. Accepted values for `signalsize` are from 1 through 64, inclusive.

Example: 16

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

byteorder — Signal byte order format

`'LittleEndian'` | `'BigEndian'`

Signal byte order format, specified as `'LittleEndian'` or `'BigEndian'`.

Example: `'LittleEndian'`

Data Types: `char` | `string`

datatype — Data type of unpacked value

`char vector` | `string`

Data type of unpacked value, specified as a character vector or string. The supported values are `'uint8'`, `'int8'`, `'uint16'`, `'int16'`, `'uint32'`, `'int32'`, `'uint64'`, `'int64'`, `'single'`, and `'double'`.

Example: `'double'`

Data Types: `char` | `string`

Output Arguments

value — Value of message data

numeric value

Value of message data, returned as a numeric value of the specified data type.

See Also

Functions

canMessage | extractAll | extractRecent | extractTime | pack

Introduced in R2009a

valueTableText

Look up value of table text for signal

Syntax

```
vtt = valueTableText(db,MsgName,SignalName,TableVal)
```

Description

`vtt = valueTableText(db,MsgName,SignalName,TableVal)` returns the text from the value table for a specified message signal.

Examples

View Table Text for Signal

Create a CAN database object, and select a message and signal to retrieve their table text.

Identify a message.

```
db = canDatabase('J1939DB.dbc');
m = db.MessageInfo(1)

m =
    Name: 'A1'
    Comment: 'This is a A1message'
    ID: 419364350
    Extended: 1
    J1939: [1x1 struct]
    Length: 8
    Signals: {2x1 cell}
    SignalInfo: [2x1 struct]
    TxNodes: {'AerodynamicControl'}
    Attributes: {4x1 cell}
    AttributeInfo: [4x1 struct]
```

Select one of the message signals.

```
s = m.signalInfo(2)

s =
    Name: 'EngGasSupplyPress'
    Comment: 'Gage pressure of gas supply to fuel metering device.'
    StartBit: 8
    SignalSize: 16
    ByteOrder: 'LittleEndian'
    Signed: 0
    ValueType: 'Integer'
    Class: 'uint16'
    Factor: 0.5000
    Offset: 0
    Minimum: 0
    Maximum: 3.2128e+04
    Units: 'kPa'
    ValueTable: [4x1 struct]
    Multiplexor: 0
```

```

    Multiplexed: 0
    MultiplexMode: 0
    RxNodes: {'Aftertreatment_1_GasIntake'}
    Attributes: {3x1 cell}
    AttributeInfo: [3x1 struct]

```

Retrieve second table text for specified signal.

```
vtt = valueTableText(db,m.Name,s.Name,2)
```

```
vtt =
pump error
```

Input Arguments

db — CAN database

CAN database object

CAN database, specified as a CAN database object.

Example: db = canDatabase(____)

MsgName — Message name

char vector | string

Message name, specified as a character vector or string. You can view available message names from the `db.Messages` property.

Example: 'A1'

Data Types: char | string

SignalName — Signal name

char vector | string

Signal name, specified as a character vector or string. You can view available signal names from the `db.MessageInfo(n).Signals` property.

Example: 'EngGasSupplyPress'

Data Types: char | string

TableVal — Table value

numeric value

Table value, specified as a numeric value.

Example: 2

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64

Output Arguments

vtt — Table text

table text

Table text, returned as a character vector.

See Also

Functions

attributeInfo | canDatabase | messageInfo | nodeInfo | signalInfo

Properties

can.Database Properties

Introduced in R2015b

Vehicle CAN Bus Monitor

Monitor vehicle CAN bus message traffic

Description

The Vehicle CAN Bus Monitor displays live CAN message traffic.

Using this app, you can:

- View message traffic for a specified CAN device and channel.
- Save CAN bus messages to a log file.

Notes The Vehicle CAN Bus Monitor does not support the CAN FD protocol.

You cannot programmatically configure the Vehicle CAN Bus Monitor. However, you can use it to independently visualize bus traffic generated on CAN channels by MATLAB or Simulink CAN blocks.

Timestamp	ID	Name	Length	Data
687.484363	64	EngineMsg	8	8E 88 00 00 34 00 00 ...
		Signal Name	Physical Value	
		EngineRPM	3745.800000	
		VehicleSpeed	52.000000	
687.459402	C8	TransmissionMsg	8	04 00 00 00 00 00 00 ...
		Signal Name	Physical Value	
		Gear	5.000000	
687.459385	64	EngineMsg	8	8E 88 00 00 34 00 00 ...
687.434392	190	DoorControlMsg	8	02 00 00 00 00 00 00 ...
		Signal Name	Physical Value	
		PassengerDoorLock	0.000000	
		DriverDoorLock	1.000000	
687.434375	64	EngineMsg	8	8E 88 00 00 34 00 00 ...
		Signal Name	Physical Value	
		EngineRPM	3745.800000	
		VehicleSpeed	52.000000	
687.409398	C8	TransmissionMsg	8	04 00 00 00 00 00 00 ...
		Signal Name	Physical Value	
		Gear	5.000000	
687.409390	64	EngineMsg	8	8E 88 00 00 34 00 00 ...
687.384379	64	EngineMsg	8	78 7F 00 00 37 00 00 ...
687.359410	C8	TransmissionMsg	8	04 00 00 00 00 00 00 ...

Open the Vehicle CAN Bus Monitor App

- MATLAB Toolstrip: On the **Apps** tab, under **Test and Measurement**, click the app.
- MATLAB command prompt: Enter `canTool`.

Examples

- “Using the Vehicle CAN Bus Monitor” on page 5-7

See Also

Functions

canTool

Topics

“Using the Vehicle CAN Bus Monitor” on page 5-7

“Vehicle CAN Bus Monitor” on page 5-2

Introduced in R2009a

viewMeasurementLists

View configured measurement lists on XCP channel

Syntax

```
viewMeasurementLists(xcpch)
```

Description

`viewMeasurementLists(xcpch)` shows you all configured measurement list sets for this XCP channel.

Examples

View DAQ Measurement Lists

Create an XCP channel and configure a data acquisition measurement list, then view the configured measurement list.

Create an object to parse an A2L file and connect that to an XCP channel.

```
a2lfile = xcpA2L('XCPSIM.a2l')
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1)
```

```
xcpch =
```

```
Channel with properties:
```

```
    SlaveName: 'CPP'
    A2LFileName: 'XCPSIM.a2l'
    TransportLayer: 'CAN'
    TransportLayerDevice: [1x1 struct]
    SeedKeyCallbackFcn: []
    KeyValue: []
```

Connect the channel to the slave module.

```
connect(xcpch)
```

Setup a data acquisition measurement list with the '10 ms' event and 'PMW' measurement.

```
createMeasurementList(xcpch, 'DAQ', '10 ms', {'BitSlice0', 'PWMFiltered', 'Triangle'});
```

Create another measurement list with the '100ms' event and 'PWMFiltered' and 'Triangle' measurements.

```
createMeasurementList(xcpch, 'DAQ', '100ms', {'PWMFiltered', 'Triangle'});
```

view details of the measurement list.

```
viewMeasurementLists(xcpch)
```

```
DAQ List #1 using the "10 ms" event @ 0.010000 seconds and the following measurements:
    PMW
```

DAQ List #2 using the "100ms" event @ 0.100000 seconds and the following measurements:
 PWMFiltered
 Triangle

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

See Also

`createMeasurementList` | `freeMeasurementLists`

Introduced in R2013a

write

Export data of CDFX object to file

Syntax

```
write(cdfxObj)
write(cdfxObj,CDFXfile)
```

Description

`write(cdfxObj)` exports the data contents of the `asam.cdfx` object to the file specified by the `Path` property of the object.

`write(cdfxObj,CDFXfile)` exports the contents of the `asam.cdfx` object to the CDFX-file specified by `CDFXfile`.

Examples

Write Modified Data to New CDFX-File

Create an `asam.cdfx` object with data from a file, modify the data in the object, and write it out to a new file.

```
cdfxObj = cdfx('c:\DataFiles\AllCategories_VCD.cdfx');
setValue(cdfxObj, 'VALUE_NUMERIC',55)
write(cdfxObj, 'c:\DataFiles\AllCategories_NEW_VCD.cdfx')
```

Input Arguments

cdfxObj – CDFX-file object

`asam.cdfx` object

CDFX-file object, specified as an `asam.cdfx` object. Use the object to access the calibration data.

Example: `cdfx()`

CDFXfile – Calibration data format CDFX-file location

`char` | `string`

Calibration data format CDFX-file location, specified as a character vector or string. `CDFXfile` can specify the file name in the current folder, or the full or relative path to the CDFX-file.

Example: `'ASAMCDFExample.cdfx'`

Data Types: `char` | `string`

See Also

Functions

`cdfx` | `getValue` | `instanceList` | `setValue` | `systemList`

Introduced in R2019a

writeAxis

Scale and write specified axis value to direct memory

Syntax

```
writeAxis(chanObj,axis,value)
```

Description

`writeAxis(chanObj,axis,value)` scales and writes a value for the specified axis through the XCP channel object `chanObj`. This action performs a direct write to memory on the slave module.

Examples

Write Value to XCP Channel Axis

Write a value to an XCP axis and verify the value.

Read original value.

```
a2lObj = xcpA2L('myA2Lfile.a2l');
chanObj = xcpChannel(a2lObj,'CAN','Vector','Virtual 1',1);
connect(chanObj);
axisObj = a2lObj.AxisXs('pedal_position');
value = readAxis(chanObj,axisObj)
```

25

Write new value.

```
newValue = 50;
writeAxis(chanObj,axisObj,newValue);
```

Read value again to verify.

```
readAxis(chanObj,axisObj)
```

50

Input Arguments

chanObj — XCP channel

channel object

XCP channel, specified as an XCP channel object.

Example: `xcpChannel()`

axis — XCP channel axis

axis object | char

XCP channel axis, specified as a character vector or axis object.

Example: 'pedal_position'

Data Types: char

value — Value for axis write

axis value

Value for axis write, specified as type supported by the axis.

See Also

Functions

readAxis | readCharacteristic | readMeasurement | writeCharacteristic | writeMeasurement

Introduced in R2018a

writeCharacteristic

Scale and write specified characteristic value to direct memory

Syntax

```
writeCharacteristic(chanObj, characteristic, value)
```

Description

`writeCharacteristic(chanObj, characteristic, value)` scales and writes a value for the specified `characteristic` through the XCP channel object `chanObj`. This action performs a direct write to memory on the slave module.

Examples

Write Value to an XCP Channel Characteristic

Write a value to an XCP characteristic and verify the value.

Read the original value.

```
a2lObj = xcpA2L('myA2Lfile.a2l');
chanObj = xcpChannel(a2lObj, 'CAN', 'Vector', 'Virtual 1', 1);
connect(chanObj);
charObj = a2lObj.CharacteristicInfo('torque_demand');
value = readCharacteristic(chanObj, charObj)'
```

```
100
```

Write new value.

```
newValue = 200;
writeCharacteristic(chanObj, charObj, newValue)';
```

Read value again to verify change.

```
readCharacteristic(chanObj, charObj)'
```

```
200
```

Input Arguments

chanObj — XCP channel

channel object

XCP channel, specified as an XCP channel object.

Example: `xcpChannel()`

characteristic — XCP channel characteristic

characteristic object | char

XCP channel characteristic, specified as a character vector or characteristic object.

Example: 'torque_demand'

Data Types: char

value — Value for characteristic write

characteristic value

Value for characteristic write, specified as a type supported by the characteristic.

See Also

Functions

readAxis | readCharacteristic | readMeasurement | writeAxis | writeMeasurement

Introduced in R2018a

writeMeasurement

Scale and write specified measurement value to direct memory

Syntax

```
writeMeasurement(chanObj, measurement, value)
```

Description

`writeMeasurement(chanObj, measurement, value)` scales and writes a value for the specified measurement through the XCP channel object `chanObj`. This action performs a direct write to memory on the slave module.

Examples

Write Value to an XCP Channel Measurement

Write a value to an XCP measurement, and verify the value.

Read original value.

```
a2lObj = xcpA2L('myA2Lfile.a2l');
chanObj = xcpChannel(a2lObj, 'CAN', 'Vector', 'Virtual 1', 1);
connect(chanObj);
measObj = a2lObj.MeasurementInfo('limit');
value = readMeasurement(chanObj, measObj)
```

```
100
```

Write a new value.

```
newValue = 120;
writeMeasurement(chanObj, measObj, newValue);
```

Read the value again to verify the change.

```
readMeasurement(chanObj, measObj)
```

```
120
```

Input Arguments

chanObj — XCP channel

channel object

XCP channel, specified as an XCP channel object.

Example: `xcpChannel()`

measurement — XCP channel measurement

measurement object | char

XCP channel measurement, specified as a character vector or measurement object.

Example: 'curve1_8_uc'

Data Types: char

value — Value for measurement write

measurement value

Value for measurement write, specified as a data type supported by the measurement.

See Also

Functions

readAxis | readCharacteristic | readMeasurement | writeAxis | writeCharacteristic

Introduced in R2018a

writeSingleValue

Write single sample to specified measurement

Syntax

```
writeSingleValue(xcpch, measurementName, value)
```

Description

`writeSingleValue(xcpch, measurementName, value)` writes a single value to the specified measurement through the configured XCP channel. The values are written directly to the memory on the slave module.

Examples

Write a single value

Create an XCP channel and write a single value for the `Triangle` measurement directly to memory.

Link an A2L file to your session.

```
a2l = xcpA2L('XCPSIM.a2l')
```

Create an XCP channel and connect it to the slave module

```
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);  
connect(xcpch)
```

Write the value 10 to the `Triangle` measurement.

```
writeSingleValue(xcpch, 'Triangle', 10)
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

measurementName — Name of single XCP measurement

character vector | string

Name of a single XCP measurement specified as a character vector or string. Make sure `measurementName` matches the corresponding measurement name defined in your A2L file.

Data Types: char | string

value — Value of the measurement

numeric value

Value of the selected measurement, returned as a numeric value.

See Also

`writeSTIMListData`

Introduced in R2013a

writeSTIM

Write scaled value of specified measurement to STIM list

Syntax

```
writeSTIM(xcpch, measurementName, value)
```

Description

`writeSTIM(xcpch, measurementName, value)` writes the scaled value to the specified measurement on the XCP channel.

Examples

Write Scaled Data to a Measurement in a Stimulation List

Create an XCP channel connected to a Vector CAN device on a virtual channel. Set up a data stimulation list and write to a specified measurement.

```
a2lObj = xcpA2L('myFile.a2l');  
channelObj = xcpChannel(a2lObj, 'CAN', 'Vector', 'CANcaseXL 1', 1);  
connect(channelObj);  
createMeasurementList(channelObj, 'STIM', 'Event1', 'Measurement1');  
startMeasurement(channelObj);  
writeSTIM(channelObj, 'Measurement1', newValue);
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

measurementName — Name of single XCP measurement

character vector | string

Name of a single XCP measurement specified as a character vector or string. Make sure `measurementName` matches the corresponding measurement name defined in your A2L file.

Data Types: `char` | `string`

value — Value of the measurement

numeric value

Value of the measurement, specified as a numeric value.

See Also

`writeSingleValue`

Introduced in R2018b

writeSTIMListData

Write to specified measurement

Syntax

```
writeSTIMListData(xcpch, measurementName, value)
```

Description

`writeSTIMListData(xcpch, measurementName, value)` writes the specified value to the specified measurement on the XCP channel.

Examples

Write Data to a Measurement in a Stimulation List

Create an XCP channel connected to a Vector CAN device on a virtual channel. Set up data stimulation list and write to a '100ms' event's 'Triangle' measurement.

Create an object to parse an A2L file and connect that to an XCP channel.

```
a2lfile = xcp.A2L('XCPSIM.a2l')
xcpch = xcp.Channel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);
```

Connect the channel to the slave.

```
connect(xcpch)
```

Create a measurement list with the '100ms' event and 'Bitslice0', 'PWMFiltered', and 'Triangle' measurements.

```
createMeasurementList(xcpch, 'STIM', '100ms', {'BitSlice0', 'PWMFiltered', 'Triangle'});
```

Start the measurement.

```
startMeasurement(xcpch)
```

Write data to the 'Triangle' measurement.

```
writeSTIMListData(xcpch, 'Triangle', 10)
```

Input Arguments

xcpch — XCP channel

XCP channel object

XCP channel, specified as an XCP channel object created using `xcpChannel`. The XCP channel object can then communicate with the specified slave module defined by the A2L file.

measurementName — Name of single XCP measurement

character vector | string

Name of a single XCP measurement specified as a character vector or string. Make sure `measurementName` matches the corresponding measurement name defined in your A2L file.

Data Types: `char` | `string`

value — Value of the measurement

numeric value

Value of the selected measurement, specified as a numeric value.

See Also

`writeSingleValue`

Introduced in R2013a

xcpA2L

Access A2L file

Syntax

```
a2lfile = xcpA2L(filename)
```

Description

`a2lfile = xcpA2L(filename)` creates an object that accesses an A2L file. The object can parse the contents of the file and view events and measurement information.

Examples

Link to an A2L File

Create an A2L file object.

```
a2lfile = xcpA2L('XCPSIM.a2l')
```

```
a2lfile =
```

```
  A2L with properties:
```

```
      FileName: 'XCPSIM.a2l'
      FilePath: 'c:\XCPSIM.a2l'
      SlaveName: 'CPP'
      ProtocolLayerInfo: [1x1 xcp.ProtocolLayerInfo]
      DAQInfo: [1x1 xcp.DAQInfo]
      TransportLayerCANInfo: [1x1 xcp.TransportLayerCANInfo]
      TransportLayerUDPInfo: [1x1 xcp.TransportLayerUDPInfo]
      TransportLayerTCPInfo: []
      Events: {'Key T' '10 ms' '100ms' '1ms' 'FilterBypassDaq' 'FilterBypassSt'}
      Measurements: {1x45 cell}
      Characteristics: {'KF2' 'KF3' 'KF4' 'KF5' 'KF6' 'KF7' 'KL1' 'KL2' 'KL5' 'a0' 'b0' 'c0' 'map1' 'map1Counter' 'map2'}
      EventInfo: [1x6 xcp.Event]
      MeasurementInfo: [45x1 containers.Map]
      CharacteristicInfo: [16x1 containers.Map]
      AxisInfo: [1x1 containers.Map]
      RecordLayouts: [41x1 containers.Map]
      CompuMethods: [16x1 containers.Map]
      CompuTabs: [0x1 containers.Map]
      CompuVTabs: [2x1 containers.Map]
```

Input Arguments

filename — A2L file name

character vector | string

A2L file name, specified as a character vector or string. You must provide the file ending `.a2l` with the name. You can also provide a partial or full path to the file with the name.

Data Types: char | string

Output Arguments

a2lfile – A2L file

xcp.A2L object

A2L file, returned as an xcp.A2L object, with xcp.A2L Properties.

See Also

Functions

getEventInfo | getMeasurementInfo | xcpChannel

Properties

xcp.A2L Properties

Topics

“Inspect the Contents of an A2L File” on page 7-2

“XCP Database and Communication Workflow” on page 6-2

External Websites

ASAM MCD-2 MC Technical Content

Introduced in R2013a

xcpChannel

Create XCP channel

Syntax

```
xcpch = xcpChannel(a2lFile, 'CAN', vendor, deviceID)
xcpch = xcpChannel(a2lFile, 'CAN', vendor, deviceID, deviceChannelIndex)
xcpch = xcpChannel(a2lFile, 'TCP', IPAddr, portNmbr)
xcpch = xcpChannel(a2lFile, 'UDP', IPAddr, portNmbr)
xcpch = xcpChannel(a2lFile, 'TCP')
xcpch = xcpChannel(a2lFile, 'UDP')
```

Description

`xcpch = xcpChannel(a2lFile, 'CAN', vendor, deviceID)` creates a channel connected to the CAN bus via the specified vendor and device. The XCP channel accesses the slave module via the CAN bus, parsing the attached A2L file.

Use this syntax for vendor 'PEAK-System' or 'NI'. With National Instruments CAN devices, the `deviceID` argument must include the interface number defined for the channel in the NI Measurement & Automation Explorer.

`xcpch = xcpChannel(a2lFile, 'CAN', vendor, deviceID, deviceChannelIndex)` creates a channel for the vendor 'Vector', 'Kvaser', or 'MathWorks'. Specify a numeric `deviceChannelIndex` for the channel.

`xcpch = xcpChannel(a2lFile, 'TCP', IPAddr, portNmbr)` or `xcpch = xcpChannel(a2lFile, 'UDP', IPAddr, portNmbr)` creates an XCP channel connected via Ethernet using TCP or UDP on the specified IP address and port.

Note XCP communication over UDP or TCP assumes a generic Ethernet adaptor. It is not supported on Ethernet connections of devices from specific vendors.

`xcpch = xcpChannel(a2lFile, 'TCP')` and `xcpch = xcpChannel(a2lFile, 'UDP')` use the IP address and port number defined in the A2L file.

Examples

Create an XCP Channel Using a CAN Slave Module

Create an XCP channel using a Vector CAN module virtual channel.

Link an A2L file to your session.

```
a2l = xcpA2L('XCPSIM.a2l');
```

Create an XCP channel.

```
xcpch = xcpChannel(a2l, 'CAN', 'Vector', 'Virtual 1', 1)
xcpch =
    Channel with properties:
        SlaveName: 'CPP'
        A2LFileName: 'XCPSIM.a2l'
        TransportLayer: 'CAN'
        TransportLayerDevice: [1x1 struct]
        SeedKeyDLL: []
```

Create an XCP Channel for Ethernet

Create an XCP channel for TCP communication via Ethernet.

Link an A2L file to your session.

```
a2l = xcpA2L('XCPSIM.a2l');
```

Create an XCP channel.

```
xcpch = xcpChannel(a2l, 'TCP', '10.255.255.255', 80)
xcpch =
    Channel with properties:
        SlaveName: 'CPP'
        A2LFileName: 'XCPSIM.a2l'
        TransportLayer: 'TCP'
        TransportLayerDevice: [1x1 struct]
        SeedKeyDLL: []
```

Input Arguments

a2lFile – A2L file

xcp.A2L object

A2L file, specified as an xcp.A2L object, used in this connection. You can create an A2L file object using xcpA2L.

vendor – Device vendor

'NI' | 'Kvaser' | 'Vector' | 'PEAK-System' | 'MathWorks'

Device vendor name, specified as a character vector or string.

Example: 'Vector'

Data Types: char | string

deviceID – Device to connect to

character vector | string

Device on the interface to connect to, specified as a character vector or string.

For National Instruments CAN devices, this must include the interface number for the device channel, defined in the NI Measurement & Automation Explorer.

Example: 'Virtual 1'

Data Types: char | string

deviceChannelIndex — Index of channel on device

numeric value

Index of channel on the device, specified as a numeric value.

Example: 1

IPAddr — IP address of device

char vector | string

IP address of the device, specified as a character vector or string

Example: '10.255.255.255'

Data Types: char | string

portNmbr — Port number for device connection

numeric

Port number for device connection, specified as a numeric value.

Example: 80

Output Arguments

xcpch — XCP channel

xcp.Channel object

XCP channel, returned as an xcp.Channel object with xcp.Channel Properties.

See Also

Functions

connect | disconnect | isConnected | xcpA2L

Properties

xcp.Channel Properties

Introduced in R2013a

Properties by Class

can.Channel Properties

Properties of the `can.Channel` object

Description

Use the following properties to examine or configure CAN channel settings. Use `canChannel` to create a CAN channel object.

Properties

Device Information

DeviceVendor — Device vendor name

char vector

The `DeviceVendor` property indicates the name of the device vendor.

Values are automatically defined when you configure the channel with the `canChannel` or `j1939Channel` function.

Data Types: char

Device — Channel device type

char vector

This property is read-only.

For National Instruments devices, the `Device` property displays the device number on the hardware.

For all other vendors, the `Device` property displays information about the device type to which the CAN or J1939 channel is connected.

Values are automatically defined when you configure the channel with the `canChannel` or `j1939Channel` function.

Data Types: char

DeviceChannelIndex — Device channel index

double

This property is read-only.

The `DeviceChannelIndex` property indicates the channel index on which the specified CAN or J1939 channel is configured.

Values are automatically defined when you configure the channel with the `canChannel` or `j1939Channel` function.

Data Types: double

DeviceSerialNumber — Device serial number

double | char

This property is read-only.

The `DeviceSerialNumber` property displays the serial number of the device connected to the CAN or J1939 channel.

Values are automatically defined when you configure the channel with the `canChannel` or `j1939Channel` function.

Data Types: `double` | `char`

ProtocolMode — Protocol mode of CAN channel

`'CAN'` (default) | `'CAN FD'`

This property is read-only.

The `ProtocolMode` property indicates the communication protocol for which the CAN channel is configured, either CAN or CAN FD.

The value is defined when you configure the channel with the `canChannel` function.

Data Types: `char`

Status Information

Running — Indicate running status of channel

`false` (0) | `true` (1)

This property is read-only.

The `Running` property indicates the state of the CAN or J1939 channel, according to the following values:

- `false` (default) — The channel is offline.
- `true` — The channel is online.

Use the `start` function to set your channel online.

Data Types: `logical`

MessagesAvailable — Number of messages available to be received by CAN channel

`double`

This property is read-only.

The `MessagesAvailable` property displays the total number of messages available to be received by a CAN channel. The value is 0 when no messages are available.

Data Types: `double`

MessagesReceived — Number of messages received by CAN channel

`double`

This property is read-only.

The `MessagesReceived` property indicates the total number of messages received since the channel was last started. The value is 0 when no messages have been received, and increments based on the number of messages the channel receives.

Data Types: double

MessagesTransmitted — Number of messages transmitted by CAN channel

double

This property is read-only.

The `MessagesTransmitted` property indicates the total number of messages transmitted since the channel was last started. The default value is 0 when no messages have been sent, and increments based on the number of messages the channel transmits.

Data Types: double

MessageReceivedFcn — Callback function to run when messages available

function handle | char | string

Configure `MessageReceivedFcn` as a callback function to run, specified as a character vector, string, or a function handle, when a required number of messages are available.

The `MessageReceivedFcnCount` property defines the required number of messages available before the configured `MessageReceivedFcn` runs.

For example, to specify the callback function to execute:

```
canch.MessageReceivedFcn = @Myfunction;
```

Data Types: char | string | function_handle

MessageReceivedFcnCount — Specify number of messages available before callback is triggered

numeric

Configure `MessageReceivedFcnCount` to the number of messages that must be available before the `MessageReceivedFcn` callback function is triggered.

The default value is 1. You can specify a positive integer for your `MessageReceivedFcnCount`. For example, to specify the message count required to trigger a callback:

```
canch.MessageReceivedFcnCount = 55;
```

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64

InitializationAccess — Indicate control of device channel

true (1) | false (0)

This property is read-only.

The `InitializationAccess` property indicates if the configured CAN or J1939 channel object has full control of the device channel, according to the following values:

- `true` — Has full control of the hardware channel and can change the property values.
- `false` — Does not have full control and cannot change property values.

You can change some property values of the hardware channel only if the object has full control over the hardware channel.

Note Only the first channel created on a device is granted initialization access.

Data Types: `logical`

InitialTimestamp — Indicate when channel started

`datetime`

This property is read-only.

The `InitialTimestamp` property indicates when the channel was set online with the `start` function or when its start trigger was received. For National Instruments devices, the time is obtained from the device driver; for devices from other vendors the time is obtained from the operating system where MATLAB is running.

Data Types: `datetime`

FilterHistory — Indicate settings of message acceptance filters

`char`

This property is read-only.

Indicate settings of message acceptance filters, returned as a character vector. This property indicates the settings implemented by the functions `filterAllowOnly`, `filterAllowAll`, and `filterBlockAll`.

Example: `'Standard ID Filter: Allow All | Extended ID Filter: Allow All'`

Data Types: `char`

Channel Information

BusStatus — Status of bus

`char`

This property is read-only.

The `BusStatus` property displays information about the state of the CAN bus or the J1939 bus.

- `'N/A'` — Property not supported by vendor.
- `'ErrorActive'` — Node transmits Active Error Flags when it detects errors. Note: This status does not necessarily indicate that an error actually exists, but indicates how an error is handled.
- `'ErrorPassive'` — Node transmits Passive Error Flags when it detects errors.
- `'BusOff'` — Node will not transmit anything on the bus.

Data Types: `char`

SilentMode — Specify if channel is active or silent

`false` (default) | `true`

Specify whether the channel operates silently, according to the following values:

- `false` (default) — The channel is in normal or active mode. In this mode, the channel both transmits and receives messages normally and performs other tasks on the network such as acknowledging messages and creating error frames.

- `true` — The channel is in silent mode. You can observe all message activity on the network and perform analysis without affecting the network state or behavior. In this mode, you can only receive messages and not transmit any.

Data Types: `logical`

TransceiverName — Name of device transceiver

`char`

This property is read-only.

`TransceiverName` indicates the name of the device transceiver. The device transceiver translates the digital bit stream going to and coming from the bus into the real electrical signals present on the bus.

Data Types: `char`

TransceiverState — Specify state or mode of transceiver

`numeric`

If your CAN or J1939 transceiver allows you to control its mode, you can use the `TransceiverState` property to set the mode.

The numeric property value for each mode is defined by the transceiver manufacturer. Refer to your CAN transceiver documentation for the appropriate transceiver modes. Possible modes representing the numeric value specified are:

- `high speed`
- `high voltage`
- `sleep`
- `wake up`

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

ReceiveErrorCount — Number of errors during message reception

`double`

This property is read-only.

The `ReceiveErrorCount` property indicates the total number of errors during message reception since the channel was last started. The default value is 0, and increments based on the number of errors.

Data Types: `double`

TransmitErrorCount — Number of errors during message transmission

`double`

This property is read-only.

The `TransmitErrorCount` property indicates the total number of errors during message transmission since the channel was last started. The default value is 0, and increments based on the number of errors.

Data Types: `double`

BusSpeed — Bit rate of bus transmission

double

This property is read-only.

The `BusSpeed` property indicates the speed at which messages are transmitted in bits per second. The default value is assigned by the vendor driver.

You can set `BusSpeed` to a supported bit rate using the `configBusSpeed` function, specifying the channel name and the bit rate value as input parameters. For example, to change the bus speed of the CAN channel object `canch` to 250,000 bits per second, and view the result, type

```
configBusSpeed(canch, 250000);
bs = canch.BusSpeed
```

Data Types: double

SJW — Synchronization jump width (SJW) of bit time segment

double

This property is read-only.

`SJW` displays the synchronization jump width of the bit time segment. To adjust the on-chip bus clock, the controller can shorten or prolong the length of a bit by an integral number of time segments. The maximum value of these bit time adjustments are termed the synchronization jump width or `SJW`.

Note This property is not available for National Instruments CAN devices. The channel displays NaN for the value.

Data Types: double

TSEG1, TSEG2 — Allowed number of bits segments to lengthen and shorten sample time

double

This property is read-only.

The `TSEG1` and `TSEG2` properties indicate the amount in bit time segments that the channel can lengthen and shorten the sample time, respectively, to resynchronize or compensate for delay times in the network. The value is inherited when you configure the bus speed of your CAN channel.

Note This property is not available for National Instruments CAN devices. The channel displays NaN for the value.

Data Types: double

NumOfSamples — Number of samples available to channel

double

This property is read-only.

The `NumOfSamples` property is a bit timing parameter that indicates the number of bit samples performed for a single bit read on the network. The value is a positive integer based on the driver settings for the channel.

Note This property is not available for National Instruments CAN devices. The channel displays NaN for the value.

Data Types: double

BusLoad — Load on CAN bus

double

This property is read-only.

The `BusLoad` property provides information about the load on the CAN network for message traffic on Kvaser devices. The current message traffic on a CAN network is represented as a percentage ranging from 0.00% to 100.00%.

Data Types: double

OnboardTermination — Configure bus termination on device

true (1) | false | (0)

The `OnboardTermination` property specifies whether the NI-XNET device uses its onboard termination of the CAN bus. For more information on the behavior and characteristics of a specific device, refer to its vendor documentation.

Data Types: logical

StartTriggerTerminal — Specify start trigger source terminal

char | string

The `StartTriggerTerminal` property specifies a synchronization trigger connection to start the NI-XNET channel on the connected source terminal.

To configure an NI-XNET CAN module (such as NI 9862) to start acquisition on an external signal triggering event provided at an external chassis terminal, set the CAN channel `StartTriggerTerminal` property to the appropriate terminal name. Form the property value character vector by combining the chassis name from the NI MAX utility and the trigger terminal name; for example, `'/cDAQ3/PFI0'`.

Note This property can be configured only once. After it is assigned, the property is read-only and cannot be changed. The only way to set a different value is to clear the channel object, recreate the channel with `canChannel`, and configure its properties.

Examples

Configure an NI-XNET CAN module start trigger on terminal `/cDAQ3/PFI0`.

```
ch1 = canChannel('NI', 'CAN1')
ch1.StartTriggerTerminal = '/cDAQ3/PFI0'
start(ch1) % Acquisition begins on hardware trigger
```

With a hardware triggering configuration, the `InitialTimestamp` value represents the absolute time the CAN channel acquisition was triggered. The `Timestamp` values of the received CAN messages are relative to the trigger moment.

```
ch1.InitialTimestamp
messages = receive(ch1,Inf);
messages(1).Timestamp
```

Data Types: char | string

Other Information

DataBase – CAN database information

struct

The `DataBase` property stores information about an attached CAN database. If your channel message is not attached to a database, the property value is an empty structure, `[]`. You can edit the CAN channel `DataBase` property, but cannot edit the CAN message `DataBase` property.

To see information about the database attached to your CAN message, type:

```
message.Database
```

To set the database information on your CAN channel to `C:\Database.dbc`, type:

```
channel.Database = canDatabase('C:\Database.dbc')
```

Tip CAN database file names containing non-alphanumeric characters such as equal signs and ampersands are incompatible with Vehicle Network Toolbox. You can use a period in your database name. Rename any CAN database files with non-alphanumeric characters before you use them.

Data Types: struct

UserData – Custom data

any data

Enter custom data to be stored in your CAN message or a J1939 parameter group, channel, or database object using the `UserData` property. When you save an object with `UserData` specified, you automatically save the custom data. When you load an object with `UserData` specified, you automatically load the custom data.

Tip To avoid unexpected results when you save and load an object with `UserData`, specify your custom data in simple data types and constructs.

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64 | logical | char | string | struct | table | cell | function_handle | categorical | datetime | duration | calendarDuration | fi
Complex Number Support: Yes

See Also

Functions

canChannel | configBusSpeed | receive | transmit

Topics

“CAN and CAN FD Communication”

Introduced in R2009a

can.Message Properties

Properties of the `can.Message` object

Description

Use the following properties to examine or configure CAN and CAN FD message settings. Use `canMessage` to create a CAN message.

Properties

Message Identification

ProtocolMode — Protocol mode of CAN channel

'CAN' (default) | 'CAN FD'

This property is read-only.

The `ProtocolMode` property indicates the communication protocol for which the CAN message is configured, either CAN or CAN FD.

The value is defined when you configure the message with the `canChannel` function.

Data Types: `char`

ID — Identifier for CAN message

`double`

This property is read-only.

The ID property represents a numeric identifier for a CAN message. The values range:

- 0 through 2047 for a standard identifier
- 0 through 536,870,911 for an extended identifier

You can configure the message ID when constructing it. For example, to set a standard identifier of value 300 and a data length of eight bytes, type:

```
message = canMessage(300, false, 8)
```

For hexadecimal values, convert using the `hex2dec` function.

Data Types: `double`

Extended — Identifier type for CAN message

0 (false) (default) | 1 (true)

This property is read-only.

The `Extended` property is the identifier type for a CAN message. It can either be a standard identifier or an extended identifier, according to the following values:

- `false` — The identifier type is standard (11 bits).
- `true` — The identifier type is extended (29 bits).

You can configure the message extended property when constructing it. For example, to set the message identifier type to extended, with the ID set to 2350, and the data length to eight bytes, type:

```
message = canMessage(2350, true, 8)
```

Data Types: `logical`

Name — CAN message name

`char`

This property is read-only.

The `Name` property displays the name of the message, as a character vector value. This value is acquired from the name of the message you defined in the database. You cannot edit this property if you are defining raw messages.

Data Types: `char`

Data Details

Timestamp — Time when message received

`double`

This property is read-only.

The `Timestamp` property displays the time at which the message was received on a CAN channel. This time is based on the receiving channel start time.

You might want to set the value when constructing a message. For example, to set the time stamp of a message to 12, type:

```
message.Timestamp = 12
```

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64` | `fi`

Data — CAN message raw data

`uint8` array

Use the `Data` property to define the raw data in a CAN message. The data is an array of `uint8` values, based on the data length you specify in the message.

For example, to create a CAN message and define its data:

```
message = canMessage(2500, true, 8)  
message.Data = [23 43 23 43 54 34 123 1]
```

If you are using a CAN database for your message definitions, you can directly specify values in the `Signals` property structure.

You can also use the `pack` function to load data into your message.

Data Types: `uint8`

Signals — Physical signals defined in CAN message

struct

The `Signals` property allows you to view and edit decoded signal values defined for a CAN message. This property displays an empty structure if the message has no defined signals or a database is not attached to the message. The input values for this property depend on the signal type.

Create a CAN message.

```
message = canMessage(canDb, 'messageName');
```

Display message signals.

```
message.Signals
```

```
    VehicleSpeed: 0
    EngineRPM: 250
```

Change the value of a signal.

```
message.Signals.EngineRPM = 300
```

Data Types: struct

Length — Length of CAN message

uint8

Length of the CAN message in bytes, specified as a uint8 value. This indicates the number of elements in the `Data` vector. For CAN messages this is limited to 8 bytes; for CAN FD messages the length can be 0-8, 12, 16, 20, 24, 32, 48, or 64 bytes.

Data Types: uint8

DLC — CAN message data length code

uint8

This property is read-only.

Length code of the CAN FD message data, returned as a uint8 value. This relates to the `Length` property: for sizes up to 8 bytes they are the same, but DLC values ranging from 9 (binary 1001) to 15 (binary 1110) are used to specify the data lengths of 12, 16, 20, 24, 32, 48, and 64 bytes. For more information, see CAN FD - Some Protocol Details.

Data Types: uint8

Protocol Flags**BRS — CAN FD message bit rate switch**

0 (false) | 1 (true)

The `BRS` property indicates that the CAN FD message bit rate switch is set. This determines whether the bit rate for the data phase of the message is faster (`true`) or the same (`false`) as the bit rate of the arbitration phase. For more information, see CAN FD - Some Protocol Details.

Data Types: logical

ESI — CAN FD message error state indicator

0 (false) | 1 (true)

This property is read-only.

The ESI property indicates that the CAN FD message error state indicator flag is set. For more information, see CAN FD - Some Protocol Details.

Data Types: `logical`

Error — CAN message error frame indicator

`0 (false) | 1 (true)`

This property is read-only.

The Error property indicates if true that the CAN message is an error frame.

Data Types: `logical`

Remote — Specify CAN message remote frame

`false (default) | true`

Use the Remote property to specify the CAN message as a remote frame.

- `false` (default) — The message is not a remote frame.
- `true` — The message is a remote frame.

To change the default value of Remote and make the message a remote frame, type:

```
message.Remote = true
```

Data Types: `logical`

Other Information**DataBase — CAN database information**

`struct`

The Database property stores information about an attached CAN database. If your channel message is not attached to a database, the property value is an empty structure, `[]`. You can edit the CAN channel Database property, but cannot edit the CAN message Database property.

To see information about the database attached to your CAN message, type:

```
message.Database
```

To set the database information on your CAN channel to `C:\Database.dbc`, type:

```
channel.Database = canDatabase('C:\Database.dbc')
```

Tip CAN database file names containing non-alphanumeric characters such as equal signs and ampersands are incompatible with Vehicle Network Toolbox. You can use a period in your database name. Rename any CAN database files with non-alphanumeric characters before you use them.

Data Types: `struct`

UserData — Custom data

`any data`

Enter custom data to be stored in your CAN message or a J1939 parameter group, channel, or database object using the `UserData` property. When you save an object with `UserData` specified, you automatically save the custom data. When you load an object with `UserData` specified, you automatically load the custom data.

Tip To avoid unexpected results when you save and load an object with `UserData`, specify your custom data in simple data types and constructs.

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64` | `logical` | `char` | `string` | `struct` | `table` | `cell` | `function_handle` | `categorical` | `datetime` | `duration` | `calendarDuration` | `fi`
Complex Number Support: Yes

See Also

Functions

`canChannel` | `canMessage` | `pack` | `receive` | `transmit` | `unpack`

Topics

“CAN and CAN FD Communication”

External Websites

CAN FD - Some Protocol Details

Introduced in R2009a

can.Database Properties

Properties of the `can.Database` object

Description

Use the following properties to examine or configure CAN database settings. Use `canDatabase` to create a CAN database object.

Properties

can.Database

Name — CAN database name

char

This property is read-only.

The `Name` property displays the name of the database, as a character vector value. This value is acquired from the database file name.

Data Types: char

Path — Path to CAN database file

char

This property is read-only.

The `Path` property displays the path of the database including the DBC-file, as a character vector.

Data Types: char

Nodes — Node names from CAN database

cell

This property is read-only.

The `Nodes` property stores the names of all nodes defined in the specified CAN database, as a cell array of character vectors. For example, to examine and index into the database nodes:

```
db = canDatabase('CANex.dbc');  
db.Nodes
```

3×1 cell array

```
    {'AerodynamicControl'          }  
    {'Aftertreatment_1_GasIntake'}  
    {'Aftertreatment_1_GasOutlet'}
```

```
db.Nodes{1}
```

```
'AerodynamicControl'
```

Data Types: cell

NodeInfo — Information on CAN database nodes

struct

This property is read-only.

The `NodeInfo` property is a structure with information about all nodes defined in the specified CAN database. The `NodeInfo` property is a read-only structure. Use indexing to access the information of each node. For example:

```
db = canDatabase('CANex.dbc');
db.NodeInfo
```

3×1 struct array with fields:

```
    Name
    Comment
    Attributes
    AttributeInfo
```

```
db.NodeInfo(1).Name
```

```
'AerodynamicControl'
```

Data Types: struct

Messages — Message names from CAN database

cell

This property is read-only.

The `Messages` property stores the names of all messages defined in the specified CAN database, as a cell array of character vectors.

```
db = canDatabase('CANex.dbc');
db.Messages
```

3×1 cell array

```
    {'A1'      }
    {'A1DEFI'  }
    {'A1DEFSI' }
```

```
db.Messages{1}
```

```
'A1'
```

Data Types: cell

MessageInfo — Information on CAN database messages

struct

This property is read-only.

The `MessageInfo` property is a structure with information about all messages defined in the specified CAN database.

Use indexing to access the information of each message. For example:

```
db = canDatabase('CANFDex.dbc');  
db.MessageInfo
```

3×1 struct array with fields:

```
    Name: 'CANFDMessage'  
ProtocolMode: 'CAN FD'  
    Comment: ''  
        ID: 1  
Extended: 0  
    J1939: []  
    Length: 48  
        DLC: 14  
        BRS: 1  
    Signals: {2×1 cell}  
SignalInfo: [2×1 struct]  
    TxNodes: {0×1 cell}  
    Attributes: {2×1 cell}  
AttributeInfo: [2×1 struct]
```

```
db.MessageInfo(1).Name
```

```
'CANFDMessage'
```

Data Types: struct

Attributes — Attribute names from CAN database

cell

This property is read-only.

The `Attributes` property stores the names of all attributes defined in the specified CAN database, as a cell array of character vectors.

Use indexing to access the information of each attribute. For example:

```
db = canDatabase('CANex.dbc');  
db.Attributes
```

3×1 cell array

```
    {'BusType'      }  
    {'DatabaseVersion'}  
    {'ProtocolType' }
```

```
db.Attributes{1}
```

```
'BusType'
```

Data Types: cell

AttributeInfo — Information on CAN database attributes

struct

This property is read-only.

The `AttributeInfo` property is a structure with information about all attributes defined in the specified CAN database.

Use indexing to access the information of each attribute.

```
db = canDatabase('CANex.dbc');
db.AttributeInfo
```

3×1 struct array with fields:

```
Name
ObjectType
DataType
DefaultValue
Value
```

```
db.AttributeInfo(1).Name
```

```
'BusType'
```

Data Types: struct

UserData – Custom data

any data

Enter custom data to be stored in your CAN message or a J1939 parameter group, channel, or database object using the `UserData` property. When you save an object with `UserData` specified, you automatically save the custom data. When you load an object with `UserData` specified, you automatically load the custom data.

Tip To avoid unexpected results when you save and load an object with `UserData`, specify your custom data in simple data types and constructs.

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64 | logical | char | string | struct | table | cell | function_handle | categorical | datetime | duration | calendarDuration | fi
Complex Number Support: Yes

See Also

Functions

[attachDatabase](#) | [canDatabase](#) | [canMessage](#) | [j1939Channel](#) | [j1939ParameterGroup](#)

Introduced in R2009a

j1939.Channel Properties

Properties of the `j1939.Channel` object

Description

Use the following properties to examine or configure J1939 channel settings. Use `j1939Channel` to create a channel.

Properties

Device Information

DeviceVendor — Device vendor name

char vector

This property is read-only.

The `DeviceVendor` property indicates the name of the device vendor.

Values are automatically defined when you configure the channel with the `canChannel` or `j1939Channel` function.

Data Types: char

Device — Channel device type

char vector

This property is read-only.

For National Instruments devices, the `Device` property displays the device number on the hardware.

For all other vendors, the `Device` property displays information about the device type to which the CAN or J1939 channel is connected.

Values are automatically defined when you configure the channel with the `canChannel` or `j1939Channel` function.

Data Types: char

DeviceChannelIndex — Device channel index

double

This property is read-only.

The `DeviceChannelIndex` property indicates the channel index on which the specified CAN or J1939 channel is configured.

Values are automatically defined when you configure the channel with the `canChannel` or `j1939Channel` function.

Data Types: double

DeviceSerialNumber — Device serial number

double | char

This property is read-only.

The `DeviceSerialNumber` property displays the serial number of the device connected to the CAN or J1939 channel.

Values are automatically defined when you configure the channel with the `canChannel` or `j1939Channel` function.

Data Types: double | char

Data Details**ParameterGroupsAvailable — Number of parameter groups available to be received**

double

This property is read-only.

The `ParameterGroupsAvailable` property displays the total number of parameter groups available to be received by the channel.

Data Types: double

ParameterGroupsReceived — Number of parameter groups received by channel

double

This property is read-only.

The `ParameterGroupsReceived` property indicates the total number of parameter groups received since the channel was last started.

Data Types: double

ParameterGroupsTransmitted — Number of parameter groups transmitted by channel

double

This property is read-only.

The `ParameterGroupsTransmitted` property indicates the total number of parameter groups transmitted since the channel was last started.

Data Types: double

FilterPassList — List of parameter groups to pass

char | cell

This property is read-only.

`FilterPassList` displays a list of parameter group names and numbers that the channel can pass to the network. The list displays parameter group names and numbers as character vectors or cell arrays of character vectors and numbers.

To change the values, use one of the filtering functions: `filterAllowOnly`, `filterAllowAll`, or `filterBlockAll`

Data Types: char | cell

FilterBlockList — List of parameter groups to block

char | cell

This property is read-only.

`FilterBlockList` displays a list of parameter group names and numbers blocked by the channel. The list displays parameter group names and numbers as character vectors or cell arrays of character vectors and numbers. To change the values, use one of the filtering functions.

To change the values, use one of the filtering functions: `filterAllowOnly`, `filterAllowAll`, or `filterBlockAll`

Data Types: char | cell

Channel Information**Running — Indicate running status of channel**

false (0) | true (1)

This property is read-only.

The `Running` property indicates the state of the CAN or J1939 channel, according to the following values:

- `false` (default) — The channel is offline.
- `true` — The channel is online.

Use the `start` function to set your channel online.

Data Types: logical

BusStatus — Status of bus

char

This property is read-only.

The `BusStatus` property displays information about the state of the CAN bus or the J1939 bus.

- `'N/A'` — Property not supported by vendor.
- `'ErrorActive'` — Node transmits Active Error Flags when it detects errors. Note: This status does not necessarily indicate that an error actually exists, but indicates how an error is handled.
- `'ErrorPassive'` — Node transmits Passive Error Flags when it detects errors.
- `'BusOff'` — Node will not transmit anything on the bus.

Data Types: char

InitializationAccess — Indicate control of device channel

true (1) | false (0)

This property is read-only.

The `InitializationAccess` property indicates if the configured CAN or J1939 channel object has full control of the device channel, according to the following values:

- `true` — Has full control of the hardware channel and can change the property values.

- `false` — Does not have full control and cannot change property values.

You can change some property values of the hardware channel only if the object has full control over the hardware channel.

Note Only the first channel created on a device is granted initialization access.

Data Types: `logical`

InitialTimestamp — Indicate when channel started

`datetime`

This property is read-only.

The `InitialTimestamp` property indicates when the channel was set online with the `start` function or when its start trigger was received. For National Instruments devices, the time is obtained from the device driver; for devices from other vendors the time is obtained from the operating system where MATLAB is running.

Data Types: `datetime`

SilentMode — Specify if channel is active or silent

`false` (default) | `true`

Specify whether the channel operates silently, according to the following values:

- `false` (default) — The channel is in normal or active mode. In this mode, the channel both transmits and receives messages normally and performs other tasks on the network such as acknowledging messages and creating error frames.
- `true` — The channel is in silent mode. You can observe all message activity on the network and perform analysis without affecting the network state or behavior. In this mode, you can only receive messages and not transmit any.

Data Types: `logical`

TransceiverName — Name of device transceiver

`char`

This property is read-only.

`TransceiverName` indicates the name of the device transceiver. The device transceiver translates the digital bit stream going to and coming from the bus into the real electrical signals present on the bus.

Data Types: `char`

TransceiverState — Specify state or mode of transceiver

`numeric`

If your CAN or J1939 transceiver allows you to control its mode, you can use the `TransceiverState` property to set the mode.

The numeric property value for each mode is defined by the transceiver manufacturer. Refer to your CAN transceiver documentation for the appropriate transceiver modes. Possible modes representing the numeric value specified are:

- high speed
- high voltage
- sleep
- wake up

Data Types: `single` | `double` | `int8` | `int16` | `int32` | `int64` | `uint8` | `uint16` | `uint32` | `uint64`

BusSpeed – Bit rate of bus transmission

`double`

This property is read-only.

The `BusSpeed` property indicates the speed at which messages are transmitted in bits per second. The default value is assigned by the vendor driver.

You can set `BusSpeed` to a supported bit rate using the `configBusSpeed` function, specifying the channel name and the bit rate value as input parameters. For example, to change the bus speed of the CAN channel object `canch` to 250,000 bits per second, and view the result, type

```
configBusSpeed(canch, 250000);  
bs = canch.BusSpeed
```

Data Types: `double`

SJW – Synchronization jump width (SJW) of bit time segment

`double`

This property is read-only.

SJW displays the synchronization jump width of the bit time segment. To adjust the on-chip bus clock, the controller can shorten or prolong the length of a bit by an integral number of time segments. The maximum value of these bit time adjustments are termed the synchronization jump width or SJW.

Note This property is not available for National Instruments CAN devices. The channel displays NaN for the value.

Data Types: `double`

TSEG1, TSEG2 – Allowed number of bits segments to lengthen and shorten sample time

`double`

This property is read-only.

The `TSEG1` and `TSEG2` properties indicate the amount in bit time segments that the channel can lengthen and shorten the sample time, respectively, to resynchronize or compensate for delay times in the network. The value is inherited when you configure the bus speed of your CAN channel.

Note This property is not available for National Instruments CAN devices. The channel displays NaN for the value.

Data Types: double

NumOfSamples — Number of samples available to channel

double

This property is read-only.

The NumOfSamples property is a bit timing parameter that indicates the number of bit samples performed for a single bit read on the network. The value is a positive integer based on the driver settings for the channel.

Note This property is not available for National Instruments CAN devices. The channel displays NaN for the value.

Data Types: double

Other Information

UserData — Custom data

any data

Enter custom data to be stored in your CAN message or a J1939 parameter group, channel, or database object using the UserData property. When you save an object with UserData specified, you automatically save the custom data. When you load an object with UserData specified, you automatically load the custom data.

Tip To avoid unexpected results when you save and load an object with UserData, specify your custom data in simple data types and constructs.

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64 | logical | char | string | struct | table | cell | function_handle | categorical | datetime | duration | calendarDuration | fi

Complex Number Support: Yes

See Also

Functions

configBusSpeed | filterAllowAll | filterAllowOnly | filterBlockAll | j1939Channel | j1939ParameterGroup | receive | transmit

Properties

j1939.ParameterGroup Properties

Topics

“J1939 Communication”

Introduced in R2015b

j1939.ParameterGroup Properties

Properties of the `j1939.ParameterGroup` object

Description

Use the following properties to examine or configure J1939 parameter group settings. Use `j1939ParameterGroup` to create a parameter group object.

Properties

Protocol Data Unit Details

Name — J1939 parameter group name

char

This property is read-only.

The `Name` property displays the name of the J1939 parameter group as a character vector. This value is acquired from the name you define when you create the parameter group.

Data Types: char

PGN — J1939 parameter group number

uint32

This property is read-only.

The `PGN` property displays the number of the parameter group as a uint32 value. This value is automatically assigned when you create the parameter group.

Data Types: uint32

Priority — Priority of parameter group

numeric

The `Priority` property specifies the precedence of the parameter group on the J1939 network. `Priority` takes a numeric value of 0 (highest priority) to 7 (lowest priority), which specifies the order of importance of the parameter group.

Data Types: uint32

PDUFormatType — J1939 parameter group PDU format

char

This property is read-only.

The `PDUFormatType` property displays the J1939 protocol data unit format of the parameter group, as a character vector. This value is automatically assigned when you create the parameter group.

Data Types: char

SourceAddress — Address of parameter group source

numeric

Address of the J1939 parameter group source. `SourceAddress` identifies the parameter group source on the J1939 network. This allows the destinations to identify the sender and respond appropriately.

Specify `SourceAddress` of the parameter group as a number between 0 and 253. 254 is a null value and is used by your application to detect available addresses on the J1939 network.

Data Types: `uint32`

DestinationAddress — Address of parameter group destination

numeric

Address of the J1939 parameter group destination. `DestinationAddress` identifies the parameter group destination on the J1939 network. The source uses the specified destination address to send parameter groups.

Specify `DestinationAddress` of the parameter group as a number from 0 through 253. 254 is a null value and is used by your application to detect available addresses on the J1939 network. To send a parameter group to all devices on the network, use 255, which is the global value.

Data Types: `uint32`

Data Details

Timestamp — Time when parameter group received

double

This property is read-only.

The `Timestamp` property displays the time at which the parameter group was received on a J1939 channel. This time is based on the hardware log.

Data Types: `double`

Data — CAN message raw data

`uint8` array

Use the `Data` property to view or define the raw data in a J1939 parameter group. The data is an array of `uint8` values.

For example, create a parameter group and specify data:

```
pg = j1939ParameterGroup(db, 'PackedData')
pg.Data(1:2) = [50 0]
```

Data Types: `uint8`

Signals — Physical signals defined in parameter group

struct

The `Signals` property allows you to view and edit decoded signal values defined for a parameter group. The input values for this property depend on the signal type.

For example, create a parameter group.

```
pg = j1939ParameterGroup(db, 'PackedData')
```

Display the parameter group signals

```
pg.Signals
```

```
    ToggleSwitch: -1
    SliderSwitch: -1
    RockerSwitch: -1
    RepeatingStairs: 255
    PushButton: 1
```

Change the value of the repeating stairs.

```
pg.Signals.RepeatingStairs = 200
```

```
    ToggleSwitch: -1
    SliderSwitch: -1
    RockerSwitch: -1
    RepeatingStairs: 200
    PushButton: 1
```

Data Types: struct

Other Information

UserData — Custom data

any data

Enter custom data to be stored in your CAN message or a J1939 parameter group, channel, or database object using the `UserData` property. When you save an object with `UserData` specified, you automatically save the custom data. When you load an object with `UserData` specified, you automatically load the custom data.

Tip To avoid unexpected results when you save and load an object with `UserData`, specify your custom data in simple data types and constructs.

Data Types: single | double | int8 | int16 | int32 | int64 | uint8 | uint16 | uint32 | uint64 | logical | char | string | struct | table | cell | function_handle | categorical | datetime | duration | calendarDuration | fi
Complex Number Support: Yes

See Also

Functions

canDatabase | j1939Channel | j1939ParameterGroup

Properties

j1939.Channel Properties

Topics

“J1939 Communication”

External Websites

J1939 Standards Overview

Introduced in R2015b

xcp.A2L Properties

Properties of the `xcp.A2L` file object

Description

Use the following properties to examine `xcp.A2L` file object settings. Use `xcpA2L` to create an A2L-file object.

Properties

xcp.A2L

FileName — Name of referenced A2L file

`char`

This property is read-only.

The `FileName` property displays the name of the referenced A2L file as a character vector.

Data Types: `char`

FilePath — Path of A2L file

`char`

This property is read-only.

The `FilePath` property displays the full file path to the A2L file, including the A2L-file name, as a character vector.

Data Types: `char`

SlaveName — Name of connected slave

`char`

This property is read-only.

The `SlaveName` property displays the name of the slave node as specified in the A2L file, as a character vector.

Data Types: `char`

ProtocolLayerInfo — Protocol layer information

`xcp.ProtocolLayerInfo`

This property is read-only.

The `ProtocolLayerInfo` property displays an `xcp.ProtocolLayerInfo` object containing general information about the XCP protocol implementation of the slave as defined in the A2L file. For example:

```
a2lfile = xcpA2L('XCPSIM.a2l');  
pli = a2lfile.ProtocolLayerInfo
```

```
pli =
```

```
ProtocolLayerInfo with properties:
```

```
AddressGranularity: 'ADDRESS_GRANULARITY_BYTE'
ByteOrder: 'BYTE_ORDER_MSB_LAST'
MaxCT0: 8
MaxDT0: 8
T1: 1000
T2: 200
T3: 0
T4: 0
T5: 0
T6: 0
T7: 0
```

```
Data Types: xcp.ProtocolLayerInfo
```

DAQInfo – DAQ related information

```
xcp.DAQInfo object
```

This property is read-only.

DAQ related information, returned as a DAQInfo object. For example:

```
a2lfile = xcpA2L('XCPSIM.a2l');
di = a2lfile.DAQInfo
```

```
di =
```

```
DAQInfo with properties:
```

```
AddressExtension: 'ADDRESS_EXTENSION_FREE'
ConfigType: 'DYNAMIC'
GranularityODTEntrySizeDAQ: 'GRANULARITY_ODT_ENTRY_SIZE_DAQ_BYTE'
IdentificationFieldType: 'IDENTIFICATION_FIELD_TYPE_ABSOLUTE'
MaxDAQ: 0
MaxEventChannels: 6
MaxODTEntrySizeDAQ: 7
MinDAQ: 0
OptimizationType: 'OPTIMISATION_TYPE_DEFAULT'
OverloadIndication: 'OVERLOAD_INDICATION_PID'
STIM: [1x1 struct]
PrescalerSupported: 'PRESCALER_SUPPORTED'
ResumeSupported: 'RESUME_NOT_SUPPORTED'
Timestamp: [1x1 struct]
```

```
Data Types: xcp.DAQInfo
```

TransportLayerCANInfo – CAN specific transport layer information

```
xcp.TransportLayerCANInfo object
```

This property is read-only.

CAN specific transport layer information, returned as a TransportLayerCANInfo object. For example,

```
a2lfile = xcpA2L('XCPSIM.a2l');
tlci = a2lfile.TransportLayerCANInfo
```

```
tlci =
```

```
    TransportLayerCANInfo with properties:
```

```
        BaudRate: 500000
        SamplePoint: 62
        SampleRate: 'SINGLE'
        BTLCycles: 8
        SJW: 1
        SyncEdge: 'SINGLE'
        MaxDLCRequired: []
        CANIDMaster: 1
        CANIDMasterIsExtended: 0
        CANIDSlave: 2
        CANIDSlaveIsExtended: 0
```

```
Data Types: xcp.TransportLayerCANInfo
```

TransportLayerUDPInfo — UDP transport layer information

```
xcp.TransportLayerUDPInfo object
```

This property is read-only.

UDP transport layer information, returned as an `xcp.TransportLayerUDPInfo` object. For example:

```
a2lfile = xcpA2L('XCPSIM.a2l');
tlui = a2lfile.TransportLayerUDPInfo
tlui = a2lfile.TransportLayerUDPInfo
tlui =
```

```
    TransportLayerUDPInfo with properties:
```

```
        Address: 2.1307e+09
        AddressString: '127.0.0.1'
        Port: 5555
```

```
Data Types: xcp.TransportLayerUDPInfo
```

TransportLayerTCPInfo — TCP transport layer information

```
xcp.TransportLayerTCPInfo object
```

This property is read-only.

TCP transport layer information, returned as a `xcp.TransportLayerTCPInfo` object.

```
Data Types: xcp.TransportLayerTCPInfo
```

Events — Event names

```
cell
```

This property is read-only.

Event names, returned as a cell array of character vectors. For example:

```
a2lfile = xcpA2L('XCPSIM.a2l');
a2lfile.Events
```

```
ans =
    1x6 cell array
    {'Key T'}    {'10 ms'}    {'100ms'}    {'1ms'}    {'FilterBypassDaq'}    {'FilterBypassSt'}
```

Data Types: cell

Measurements — Measurement names

cell

This property is read-only.

Measurement names, returned as a cell array of character vectors. For example:

```
a2lfile = xcpA2L('XCPSIM.a2l');
a2lfile.Measurements(10:15)
```

```
ans =
    1x6 cell array
    {'FW1'}    {'KL10output'}    {'MaxChannel1'}    {'MinChannel1'}    {'PWM'}    {'PWMFiltered'}
```

Data Types: cell

Characteristics — Names of characteristics

cell

This property is read-only.

Names of characteristics, returned as a cell array of character vectors. For example:

```
a2lfile = xcpA2L('XCPSIM.a2l');
a2lfile.Characteristics(10:15)
```

```
ans =
    1x6 cell array
    {'a0'}    {'b0'}    {'c0'}    {'map1'}    {'map1Counter'}    {'map4_80_uc'}
```

Data Types: cell

EventInfo — Event information

array of xcp.Event object

This property is read-only.

Event information, returned as an array of xcp.Event objects. For example:

```
a2lfile = xcpA2L('XCPSIM.a2l');
ei = a2lfile.EventInfo(1)
```

```
ei =
```

Event with properties:

```

                Name: 'Key T'
            Direction: 'DAQ'
        MaxDAQList: 255
        ChannelNumber: 0
    ChannelTimeCycle: 0
        ChannelTimeUnit: 6
```

```
ChannelPriority: 0
ChannelTimeCycleInSeconds: 0
```

Data Types: xcp.Event

MeasurementInfo — Measurement information

containers.Map object

This property is read-only.

Measurement information, returned as a Map object. For example:

```
a2lfile = xcpA2L('XCPSIM.a2l');
mi = a2lfile.MeasurementInfo
```

```
mi =
```

```
Map with properties:
```

```
Count: 45
KeyType: char
ValueType: any
```

Data Types: containers.Map

CharacteristicInfo — Characteristic information

containers.Map object

This property is read-only.

Characteristic information, returned as a Map object. For example:

```
a2lfile = xcpA2L('XCPSIM.a2l');
ci = a2lfile.CharacteristicInfo
```

```
ci =
```

```
Map with properties:
```

```
Count: 16
KeyType: char
ValueType: any
```

Data Types: containers.Map

AxisInfo — Axis information

containers.Map object

This property is read-only.

Axis information, returned as a Map object. For example:

```
a2lfile = xcpA2L('XCPSIM.a2l');
ai = a2lfile.AxisInfo
```

```
ai =
```

```
Map with properties:
```



```

    Count: 1
    KeyType: char
    ValueType: any

```

Data Types: containers.Map

RecordLayouts — Container for characteristic objects

containers.Map object

This property is read-only.

Container for characteristic objects, returned as a containers.Map object. For example:

```

a2lfile = xcpA2L('XCPSIM.a2l');
rl = a2lfile.RecordLayouts

rl =

```

Map with properties:

```

    Count: 41
    KeyType: char
    ValueType: any

```

Data Types: containers.Map

CompuMethods — Container for computation method objects

containers.Map object

This property is read-only.

Container for computation method objects, returned as a containers.Map object. For example:

```

a2lfile = xcpA2L('XCPSIM.a2l');
cm = a2lfile.CompuMethods

cm =

```

Map with properties:

```

    Count: 16
    KeyType: char
    ValueType: any

```

Data Types: containers.Map

CompuTabs — Container for ComputationTAB method objects

containers.Map object

This property is read-only.

Container for ComputationTAB (conversion table) method objects used for interp, returned as a containers.Map object. For example:

```

a2lfile = xcpA2L('XCPSIM.a2l');
ct = a2lfile.CompuTabs

ct =

```

Map with properties:

```
Count: 0
KeyType: char
ValueType: any
```

Data Types: `containers.Map`

CompuVTabs — Container for ComputationVTAB method objects

`containers.Map` object

This property is read-only.

Container for ComputationVTAB (verbal conversion table) method objects used for enum, returned as a `containers.Map` object. For example:

```
a2lfile = xcpA2L('XCPSIM.a2l');
cvt = a2lfile.CompuVTabs
```

`cvt =`

Map with properties:

```
Count: 2
KeyType: char
ValueType: any
```

Data Types: `containers.Map`

See Also

Functions

`getCharacteristicInfo` | `getEventInfo` | `getMeasurementInfo` | `xcpA2L`

Properties

`xcp.Channel` Properties

Topics

“XCP Communication”
“A2L File Management”

External Websites

ASAM MCD-2 MC Technical Content

Introduced in R2013a

xcp.Channel Properties

Properties of the `xcp.Channel` object

Description

Use the following properties to examine or configure `xcp.Channel` object settings. Use `xcpChannel` to create an XCP channel object.

Properties

`xcp.Channel`

SlaveName — Name of connected slave

char

This property is read-only.

Name of the slave node as specified in the A2L file, returned as a character vector. For example:

```
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);
sn = xcpch.SlaveName
```

```
sn =
```

```
    'CPP'
```

Data Types: char

A2LFileName — Name of referenced A2L file

char

This property is read-only.

Name of the referenced A2L file, returned as a character vector.

Data Types: char

TransportLayer — Type of transport layer used for XCP connection

char

This property is read-only.

Type of transport layer used for XCP connection, returned as a character vector. For example:

```
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1', 1);
tl = xcpch.TransportLayer
```

```
tl =
```

```
    'CAN'
```

Data Types: char

TransportLayerDevice — XCP transport layer connection details

struct

This property is read-only.

XCP transport layer connection details, including information about the device through which the channel communicates with the slave, returned as a structure. For example:

```
xcpch = xcpChannel(a2lfile, 'CAN', 'Vector', 'Virtual 1',1);  
tld = xcpch.TransportLayerDevice
```

tld =

struct with fields:

```
Vendor: 'Vector'  
Device: 'Virtual 1'  
ChannelIndex: 1
```

Data Types: struct

SeedKeyDLL — DLL-file containing seed and key access algorithm

char

The SeedKeyDLL property indicates the name of the DLL-file that contains the seed and key security algorithm used to unlock an XCP slave module. The file defines the algorithm for generating the access key from a given seed according to ASAM standard definitions. For information on the file format and API, see the Vector web page [Steps to Use Seed&Key Option in CANape](#) or "Seed and Key Algorithm" in National Instruments CAN ECU Measurement and Calibration Toolkit User Manual.

Note: The DLL must be the same bitness as MATLAB (64-bit).

Data Types: char

See Also**Functions**

xcpA2L | xcpChannel

Properties

xcp.A2L Properties

Topics

"XCP Communication"

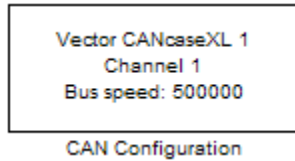
"A2L File Management"

Introduced in R2013a

Blocks

CAN Configuration

Configure parameters for specified CAN device



Library

Vehicle Network Toolbox: CAN Communication

Description

The CAN Configuration block configures parameters for a CAN device that you can use to transmit and receive messages.

Specify the configuration of your CAN device before you configure other CAN blocks.

Use one CAN Configuration block to configure each device that sends and receives messages in your model. If you use a CAN Receive or a CAN Transmit block to receive and send messages on a device, your model requires a corresponding CAN Configuration block for the specified device.

Note You need a license for both Vehicle Network Toolbox and Simulink software to use this block.

Other Supported Features

The CAN Configuration block supports the use of Simulink Accelerator and Rapid Accelerator mode. Using this feature, you can speed up the execution of Simulink models.

For more information on this feature, see the Simulink documentation.

The CAN Configuration block supports the use of code generation when you use it with the CAN Receive and CAN Transmit blocks.

Parameters

Device

Select the CAN device and a channel on the device that you want to use from the list. Use this device to transmit and/or receive messages. The device driver determines the default bus speed.

Bus speed

Set the BusSpeed property for the selected device, in bits per second. The default bus speed is the default assigned by the selected device.

Enable bit parameters manually

Note This option is enabled only for supporting vendors.

Select this check box to specify bit parameter settings manually. The bit parameter settings include:

Synchronization jump width, Time segment 1, Time segment 2, and Number of samples. If you do not select this option, the device automatically assigns the bit parameters depending on the bus speed setting.

Tip Use the default bit parameter settings unless you have specific timing requirements for your CAN connection.

Synchronization jump width

Specify the maximum value of the bit time adjustments. The specified value must be a positive integer. If you do not specify a value, the selected bus speed setting determine the default value. To change this value, select the **Enable bit parameters manually** check box first.

Time segment 1

Specify the amount of bit time segments that the channel can lengthen the sample time. The specified value must be a positive integer. If you do not specify a value, the selected bus speed setting determines the default value. To change this value, select the **Enable bit parameters manually** check box first.

Time segment 2

Specify the amount of bit time segments that the channel can shorten the sample time to resynchronize. The specified value must be a positive integer. If you do not specify a value, the selected bus speed setting determines the default value. To change this value, select the **Enable bit parameters manually** check box first.

Number of samples

Specify the total number of samples available to this channel. The specified value must be a positive integer. If you do not specify a value, the selected bus speed setting determines the default value. To change this value, select the **Enable bit parameters manually** check box first.

Verify bit parameter settings validity

If you have set the bit parameter settings manually, click this button to see if your settings are valid. The block then runs a check to see if the combination of your bus speed setting and the bit parameter value forms a valid value for the CAN device. If the new bit parameter values do not form a valid combination, the verification fails and displays an error message.

Acknowledge mode

Specify whether the channel is in Normal or Silent mode. By default **Acknowledge mode** is Normal. In this mode, the channel both receives and transmits messages normally and performs other tasks on the network such as acknowledging messages and creating error frames. To observe all message activity on the network and perform analysis, without affecting the network state or behavior, select **Silent**. In Silent mode, you can only receive messages and not transmit.

Notes

- You cannot specify the mode if you are using NI virtual channels.
 - Use Silent mode only if you want to observe and analyze your network activity.
-

See Also

Blocks

CAN Receive | CAN Transmit

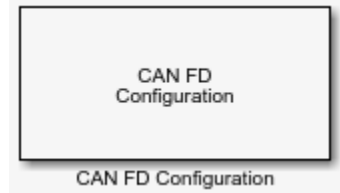
Properties

can.Channel Properties

Introduced in R2009a

CAN FD Configuration

Configure parameters for specified CAN FD device



Library

Vehicle Network Toolbox: CAN FD Communication

Description

The CAN FD Configuration block configures parameters for a CAN FD device that you can use to transmit and receive messages.

Specify the configuration of your CAN FD device before you configure other CAN FD blocks.

Use one CAN FD Configuration block to configure each device that sends and receives messages in your model. If you use a CAN FD Receive or a CAN FD Transmit block to receive and send messages on a device, your model checks to see if there is a corresponding CAN FD Configuration block for the specified device.

Note You need a license for both Vehicle Network Toolbox and Simulink software to use this block.

Other Supported Features

The CAN FD Configuration block supports the use of Simulink Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information, see “Acceleration” (Simulink).

The CAN FD Configuration block supports the use of code generation when you use it with the CAN FD Receive and CAN FD Transmit blocks.

Parameters

Device

Select the CAN FD device and a channel on the device that you want to use from the list. Use this device to transmit and/or receive messages. The device driver determines the default bus speed.

Arbitration Bus speed

Set arbitration bus speed for the selected device, in bits per second. The default speed is assigned by the selected device.

Data Bus speed

Set data bus speed for the selected device, in bits per second. The default speed is assigned by the selected device.

Bus frequency

(PEAK-System only.) Set the bus frequency, in megahertz.

Arbitration/Data bit rate prescaler

(PEAK-System only.) Set separate prescaler values for arbitration and data bit rates.

For Vector and PEAK-System devices, the next three parameters are available in two sets for manually setting bit parameters for data and arbitration bus speeds.

Synchronization jump width

Specify the maximum value of the bit time adjustments. The specified value must be a positive integer. If you do not specify a value, the selected bus speed setting determine the default value.

Time segment 1

Specify the amount of bit time segments that the channel can lengthen the sample time. The specified value must be a positive integer. If you do not specify a value, the selected bus speed setting determines the default value.

Time segment 2

Specify the amount of bit time segments that the channel can shorten the sample time to resynchronize. The specified value must be a positive integer. If you do not specify a value, the selected bus speed setting determines the default value.

Verify bit parameter settings validity

If you have set the bit parameter settings separately, click this button to see if your settings are valid. The block runs a check to see if the combination of your bus speed settings and the bit parameter values form a valid value for the device. If the new bit parameter values do not form a valid combination, the verification fails and displays an error message.

Acknowledge mode

Specify whether the channel is in Normal or Silent mode. By default **Acknowledge mode** is Normal. In this mode, the channel both receives and transmits messages normally and performs other tasks on the network such as acknowledging messages and creating error frames. To observe all message activity on the network and perform analysis, without affecting the network state or behavior, select **Silent**. In Silent mode, you can only receive messages and not transmit.

Notes

- You cannot specify the mode if you are using NI virtual channels.
 - Use Silent mode only if you want to observe and analyze your network activity.
-

See Also**Blocks**

CAN FD Receive | CAN FD Transmit | CAN FD Unpack | CAN FD Pack

Properties

can.Channel Properties

Introduced in R2018a

CAN FD Log

Log received CAN FD messages



Library

Vehicle Network Toolbox: CAN FD Communication

Description

The CAN FD Log block logs CAN FD messages from the CAN network or messages sent to the blocks input port to a .mat file. You can load the saved messages into MATLAB for further analysis or into another Simulink model.

Configure your CAN FD Log block to log from the Simulink input port. For more information, see “Log and Replay CAN Messages” on page 16-87.

The Log block appends the specified filename with the current date and time, creating unique log files for repeated logging.

If you want to use messages logged using Simulink blocks in the MATLAB Command window, use `canFDMessage` to convert messages to the correct format.

Note You need a license for both Vehicle Network Toolbox and Simulink software to use this block.

Note You cannot have more than one CAN FD Log block in a model using the same PEAK-System device channel.

Other Supported Features

- The CAN FD Log block supports the use of Simulink Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information on this feature, see “Acceleration” (Simulink).
- The CAN FD Log block supports the use of code generation along with the `packNGo` function to group required source code and dependent shared libraries. For more information, see “Code Generation” on page 15-8.

Code Generation

Vehicle Network Toolbox Simulink blocks allow you to generate code, enabling models containing these blocks to run in Accelerator, Rapid Accelerator, External, and Deployed modes.

Code Generation with Simulink Coder

You can use Vehicle Network Toolbox, Simulink Coder™, and Embedded Coder software together to generate code on the host end that you can use to implement your model. For more information on code generation, see “Build Process” (Simulink Coder).

Shared Library Dependencies

The block generates code with limited portability. The block uses precompiled shared libraries, such as DLLs, to support I/O for specific types of devices. With this block, you can use the `packNGo` function supported by Simulink Coder to set up and manage the build information for your models. The `packNGo` function allows you to package model code and dependent shared libraries into a zip file for deployment. You do not need MATLAB installed on the target system, but the target system needs to be supported by MATLAB.

To set up `packNGo`:

```
set_param(gcs, 'PostCodeGenCommand', 'packNGo(buildInfo)');
```

In this example, `gcs` is the current model that you want to build. Building the model creates a zip file with the same name as model name. You can move this zip file to another machine and there build the source code in the zip file to create an executable which can run independent of MATLAB and Simulink. The generated code compiles with both C and C++ compilers. For more information, see “Build Process Customization” (Simulink Coder).

Note On Linux platforms, you need to add the folder where you unzip the libraries to the environment variable `LD_LIBRARY_PATH`.

Parameters

Tip If you are logging from the network, you need to configure your CAN channel with a CAN FD Configuration block.

File name

Type the name and path of the file to log CAN FD messages to, or click **Browse** to browse to a file location.

The model appends the log file name with the current date and time in the YYYY-MM-DD_hhmmss format. You can also open the block mask and specify a unique name to differentiate between your files for repeated logging.

Variable name

Type the variable saved in the MAT-file that holds the CAN FD message information.

Maximum number of messages to log

Specify the maximum number of messages this block can log from the selected device or port. The specified value must be a positive integer. If you do not specify a value the block uses the default value of 10,000 messages. The log file saves the most recent messages up to the specified maximum number.

Log messages from

Select the source of the messages logged by the block. Possible values are CAN FD Bus or Input port. To log messages from the network, you must specify a device.

Device

Select the device on the CAN network that you want to log messages from. This field is unavailable if you select Input port for **Log messages from** option.

Sample time

Specify the sampling time of the block during simulation, which is the simulation time as described by the Simulink documentation. This value defines the frequency at which the CAN FD Log block runs during simulation. If the block is inside a triggered subsystem or to inherit sample time, you can specify -1 as your sample time. You can also specify a MATLAB variable for sample time. The default value is 0.01 (in seconds).

See Also**Blocks**

CAN FD Replay

Functions

canFDMessage

Introduced in R2018b

CAN FD Pack

Pack individual signals into message for CAN FD bus



Library

Vehicle Network Toolbox > CAN FD Communication

Description

The CAN FD Pack block loads signal data into a message at specified intervals during the simulation.

To use this block, you also need a license for Simulink software.

The CAN FD Pack block has one input port by default. The number of block inputs is dynamic and depends on the number of signals that you specify for the block. For example, if your block has four signals, it has four block inputs.

This block has one output port, Msg. The CAN FD Pack block takes the specified input parameters and packs the signals into a bus message.

The block outputs CAN FD messages as a Simulink bus signal. For more information on Simulink bus objects, see “Composite Signals” (Simulink).

The CAN FD Pack block supports:

- The use of Simulink Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information, see “Design Your Model for Effective Acceleration” (Simulink).
- Code generation to deploy models to targets. Code generation is not supported if your signal information consists of signed or unsigned integers greater than 32 bits long.

Dialog Box

Use the Function Block Parameters dialog box to select your CAN FD Pack block parameters.

Parameters

Data is input as

Select your data signal:

- **raw data:** Input data as a uint8 vector array. If you select this option, you only specify the message fields. All other signal parameter fields are unavailable. This option opens only one input port on your block.
- **manually specified signals:** Allows you to specify data signal definitions. If you select this option, use the **Signals** table to create your signals. The number of block inputs depends on the number of signals you specify.
- **CANdb specified signals:** Allows you to specify a CAN database file that contains message and signal definitions. If you select this option, select a CANdb file. The number of block inputs depends on the number of signals specified in the CANdb file for the selected message.

The block supports the following input signals data types: single, double, int8, int16, int32, int64, uint8, uint16, uint32, uint64, and boolean. The block does not support fixed-point data types.

CANdb file

This option is available if you specify that your data is input via a CANdb file in the **Data is input as** list. Click **Browse** to find the CANdb file on your system. The message list specified in the CANdb file populates the **Message** section of the dialog box. The CANdb file also populates the **Signals** table for the selected message. File names that contain non-alphanumeric characters such as equal signs, ampersands, and so forth are not valid CAN database file names. You can use periods in your database name. Rename CAN database files with non-alphanumeric characters before you use them.

Message list

This option is available if you specify that your data is input via a CANdb file in the **Data is input as** field and you select a CANdb file in the **CANdb file** field. Select the message to display signal details in the **Signals** table.

Message

Name

Specify a name for your CAN FD message. The default is Msg. This option is available if you choose to input raw data or manually specify signals. This option is unavailable if you choose to use signals from a CANdb file.

Protocol mode

Specify the message protocol mode as CAN FD or CAN.

Identifier type

Specify whether your message identifier is a Standard or an Extended type. The default is Standard. A standard identifier is an 11-bit identifier and an extended identifier is a 29-bit identifier. This option is available if you choose to input raw data or manually specify signals. For CANdb specified signals, the **Identifier type** inherits the type from the database.

Identifier

Specify your message ID. This number must be a positive integer from 0 through 2047 for a standard identifier and from 0 through 536870911 for an extended identifier. You can also specify hexadecimal values using the hex2dec function. This option is available if you choose to input raw data or manually specify signals.

Length (bytes)

Specify the length of your message. For CAN messages the value can be 0-8 bytes; for CAN FD the value can be 0-8, 12, 16, 20, 24, 32, 48, or 64 bytes. If you are using CANdb specified signals for your data input, the CANdb file defines the length of your message. This option is available if you choose to input raw data or manually specify signals.

Remote frame

(Disabled for CAN FD protocol mode.) Specify the CAN message as a remote frame.

Bit Rate Switch (BRS)

(Disabled for CAN protocol mode.) Enable bit rate switch.

Signals Table

This table appears if you choose to specify signals manually or define signals using a CANdb file.

If you are using a CANdb file, the data in the file populates this table automatically and you cannot edit the fields. To edit signal information, switch to manually specified signals.

If you have selected to specify signals manually, create your signals manually in this table. Each signal you create has the following values:

Name

Specify a descriptive name for your signal. The Simulink block in your model displays this name. The default is Signal [row number].

Start bit

Specify the start bit of the data. The start bit is the least significant bit counted from the start of the message data. For CAN the start bit must be an integer from 0 through 63, for CAN FD 0 through 511, within the number of bits in the message. (Note that message length is specified in bytes.)

Length (bits)

Specify the number of bits the signal occupies in the message. The length must be an integer from 1 through 64. The sum of all the signal lengths in a message is limited to the number of bits in the message length; that is, all signals must cumulatively fit within the length of the message. (Note that message length is specified in bytes and signal length in bits.)

Byte order

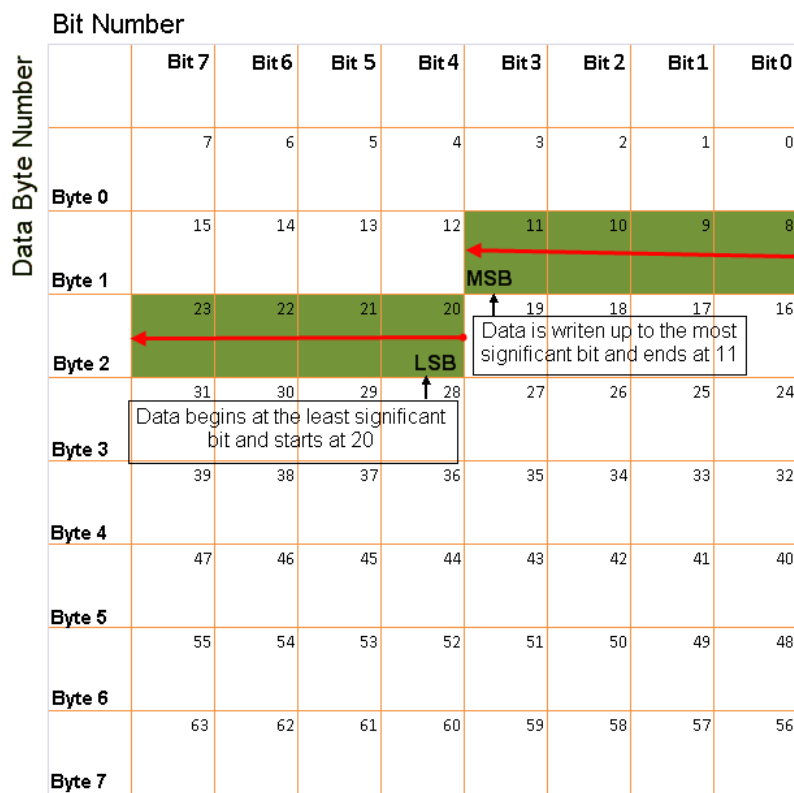
Select either of the following options:

- LE: Where the byte order is in little-endian format (Intel®). In this format you count bits from the least-significant bit to the most significant bit and proceeding to the next higher byte as you cross a byte boundary. For example, if you pack one byte of data in little-endian format, with the start bit at 20, the data bit table resembles this figure.

Bit Number		Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
Data Byte Number	Byte 0	7	6	5	4	3	2	1	0
	Byte 1	15	14	13	12	11	10	9	8
	Byte 2	23	22	21	20	19	18	17	16
	Byte 3	31	30	29	28	27	26	25	24
	Byte 4	39	38	37	36	35	34	33	32
	Byte 5	47	46	45	44	43	42	41	40
	Byte 6	55	54	53	52	51	50	49	48
	Byte 7	63	62	61	60	59	58	57	56

Little-Endian Byte Order Counted from the Least Significant Bit to the Highest Address

- BE: Where byte order is in big-endian format (Motorola®). In this format you count bits from the least-significant bit to the most-significant bit and proceeding to the next lower byte as you cross a byte boundary. For example, if you pack one byte of data in big-endian format, with the start bit at 20, the data bit table resembles this figure.



Big-Endian Byte Order Counted from the Least Significant Bit to the Lowest Address

Data type

Specify how the signal interprets the data in the allocated bits. Choose from:

- signed (default)
- unsigned
- single
- double

Note: If you have a double signal that does not align exactly to the message byte boundaries, to generate code with Embedded Coder you must check **Support long long** under **Device Details** in the **Hardware Implementation** pane of the Configuration Parameters dialog.

Multiplex type

Specify how the block packs the signals into the message at each time step:

- Standard: The signal is packed at each time step.
- Multiplexor: The Multiplexor signal, or the mode signal is packed. You can specify only one Multiplexor signal per message.
- Multiplexed: The signal is packed if the value of the Multiplexor signal (mode signal) at run time matches the configured **Multiplex value** of this signal.

For example, a message has four signals with these types and values.

Signal Name	Multiplex Type	Multiplex Value
Signal-A	Standard	Not applicable
Signal-B	Multiplexed	1
Signal-C	Multiplexed	0
Signal-D	Multiplexor	Not applicable

In this example:

- The block packs Signal-A (Standard signal) and Signal-D (Multiplexor signal) in every time step.
- If the value of Signal-D is 1 at a particular time step, then the block packs Signal-B along with Signal-A and Signal-D in that time step.
- If the value of Signal-D is 0 at a particular time step, then the block packs Signal-C along with Signal-A and Signal-D in that time step.
- If the value of Signal-D is not 1 or 0, the block does not pack either of the Multiplexed signals in that time step.

Multiplex value

This option is available only if you have selected the **Multiplex type** to be **Multiplexed**. The value you provide here must match the **Multiplexor** signal value at run time for the block to pack the **Multiplexed** signal. The **Multiplex value** must be a positive integer or zero.

Factor

Specify the **Factor** value to apply to convert the physical value (signal value) to the raw value packed in the message. See “Conversion Formula” on page 15-16 to understand how physical values are converted to raw values packed into a message.

Offset

Specify the **Offset** value to apply to convert the physical value (signal value) to the raw value packed in the message. See “Conversion Formula” on page 15-16 to understand how physical values are converted to raw values packed into a message.

Min, Max

Define a range of signal values. The default settings are **-Inf** (negative infinity) and **Inf**, respectively. For **CANdb specified signals**, these settings are read from the CAN database. For **manually specified signals**, you can specify the minimum and maximum physical value of the signal. By default, these settings do not clip signal values that exceed them.

Conversion Formula

The conversion formula is

$$\text{raw_value} = (\text{physical_value} - \text{Offset}) / \text{Factor}$$

where **physical_value** is the original value of the signal, and **raw_value** is the packed signal value.

See Also

Blocks

CAN FD Configuration | CAN FD Transmit | CAN FD Unpack

Functions

canFDMessageBusType

Introduced in R2018a

CAN FD Receive

Receive CAN FD messages from specified CAN FD device



Library

Vehicle Network Toolbox: CAN FD Communication

Description

The CAN FD Receive block receives messages from the CAN network and delivers them to the Simulink model. It outputs one message or all messages at each timestep, depending on the block parameters.

Note You need a license for both Vehicle Network Toolbox and Simulink software to use this block.

The CAN FD Receive block has two output ports:

- The `f()` output port is a trigger to a Function-Call subsystem. If the block receives a new message, it triggers a Function-Call from this port. You can then connect to a Function-Call Subsystem to unpack and process a message.
- The `Msg` output port contains a CAN message received at that particular timestep. The block outputs messages as a Simulink bus signal. For more information on Simulink bus objects, see “Composite Signals” (Simulink).

The CAN FD Receive block stores CAN messages in a first-in, first-out (FIFO) buffer. The FIFO buffer delivers the messages to your model in the queued order at every timestep.

Note You cannot have more than one CAN FD Receive block in a model using the same PEAK-System device channel.

Other Supported Features

The CAN FD Receive block supports the use of Simulink Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information, see “Acceleration” (Simulink).

The CAN FD Receive block supports the use of code generation along with the `packNGo` function to group required source code and dependent shared libraries. For more information, see “Code Generation” on page 15-19.

Code Generation

Vehicle Network Toolbox Simulink blocks allow you to generate code, enabling models containing these blocks to run in Accelerator, Rapid Accelerator, External, and Deployed modes.

Code Generation with Simulink Coder

You can use Vehicle Network Toolbox, Simulink Coder, and Embedded Coder software together to generate code on the host end that you can use to implement your model. For more information on code generation, see “Build Process” (Simulink Coder).

Shared Library Dependencies

The block generates code with limited portability. The block uses precompiled shared libraries, such as DLLs, to support I/O for specific types of devices. With this block, you can use the `packNGo` function supported by Simulink Coder to set up and manage the build information for your models. The `packNGo` function allows you to package model code and dependent shared libraries into a zip file for deployment. You do not need MATLAB installed on the target system, but the target system needs to be supported by MATLAB.

To set up `packNGo`:

```
set_param(gcs, 'PostCodeGenCommand', 'packNGo(buildInfo)');
```

In this example, `gcs` is the current model that you want to build. Building the model creates a zip file with the same name as model name. You can move this zip file to another machine and there build the source code in the zip file to create an executable which can run independent of MATLAB and Simulink. The generated code compiles with both C and C++ compilers. For more information, see “Build Process Customization” (Simulink Coder).

Note On Linux platforms, you need to add the folder where you unzip the libraries to the environment variable `LD_LIBRARY_PATH`.

Parameters

Tip Configure your CAN FD Configuration block before you configure the CAN FD Receive block parameters.

Device

Select the CAN device and a channel on the device you want to receive CAN messages from. This field lists all the devices installed on the system. It displays the vendor name, the device name, and the channel ID. The default is the first available device on your system.

Standard IDs Filter

Select the filter on this block for standard IDs. Valid choices are:

- **Allow all** (default): Allows all standard IDs to pass the filter.
- **Allow only**: Allows only ID or range of IDs specified in the text field. You can specify a single ID or an array of IDs. You can also specify disjointed IDs or arrays separated by a comma. For example, to accept IDs from 400 through 500, and 600 through 650, enter `[400:500]`

[600:650]]. Standard IDs must be positive integers from 0 to 2047. You can also specify hexadecimal values with the `hex2dec` function.

- `Block all`: Blocks all standard IDs from passing the filter.

Extended IDs Filter

Select the filter on this block for extended IDs. Valid choices are:

- `Allow all` (default): Allows all extended IDs to pass the filter.
- `Allow only`: Allows only those IDs specified in the text field. You can specify a single ID or an array of IDs. You can also specify disjointed IDs or arrays separated by a comma. For example, to accept IDs from 3000 through 3500, and 3600 through 3620, enter `[[3000:3500][3600:3620]]`. Extended IDs must be positive integers from 0 to 536870911. You can also specify hexadecimal values using the `hex2dec` function.
- `Block all`: Blocks all extended IDs from passing the filter.

Sample time

Specify the sampling time of the block during simulation, which is the simulation time as described by the Simulink documentation. This value defines the frequency at which the CAN FD Receive block runs during simulation. If the block is inside a triggered subsystem or to inherit sample time, you can specify `-1` as your sample time. You can also specify a MATLAB variable for sample time. The default value is 0.01 (in seconds).

Number of messages received at each timestep

Select how many messages the block receives at each specified timestep. Valid choices are:

- `all` (default): The CAN FD Receive block delivers all available messages in the FIFO buffer to the model during a specific timestep. The block generates one function call for each delivered message. The output port always contains one CAN message at a time.
- `1`: The CAN FD Receive block delivers one message per timestep from the FIFO buffer to the model.

If the block does not receive any messages before the next timestep, it outputs the last received message.

See Also

Blocks

CAN FD Configuration | CAN FD Transmit | CAN FD Unpack

Functions

`canFDMessageType`

Introduced in R2018a

CAN FD Replay

Replay logged CAN FD messages



Library

Vehicle Network Toolbox: CAN FD Communication

Description

The CAN FD Replay block replays logged messages from a `.mat` file to a CAN network or to Simulink as a bus signal. For more information on Simulink bus objects, see “Composite Signals” (Simulink). You need a CAN FD Configuration block to replay to the network.

To replay messages logged in the MATLAB Command window in your Simulink model, convert them into a compatible format using `vntslgate` and save it to a separate file. For more information, see “Log and Replay CAN Messages” on page 16-87.

Note You need a license for both Vehicle Network Toolbox and Simulink software to use this block.

Replay Timing

When you replay logged messages, Simulink uses the original timestamps on the messages. When you replay to a network, the timestamps correlate to real time, and when you replay to the Simulink input port it correlates to simulation time. If the timestamps in the messages are all 0, all messages are replayed as soon as the simulation starts, because simulation time and real time will be ahead of the timestamps in the replayed messages.

Other Supported Features

- The CAN FD Replay block supports the use of Simulink Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information on this feature, see “Acceleration” (Simulink).
- The CAN FD Replay block supports the use of code generation along with the `packNGo` function to group required source code and dependent shared libraries. For more information, see “Code Generation” on page 15-21.

Code Generation

Vehicle Network Toolbox Simulink blocks allow you to generate code, enabling models containing these blocks to run in Accelerator, Rapid Accelerator, External, and Deployed modes.

Code Generation with Simulink Coder

You can use Vehicle Network Toolbox, Simulink Coder, and Embedded Coder software together to generate code on the host end that you can use to implement your model. For more information on code generation, see “Build Process” (Simulink Coder).

Shared Library Dependencies

The block generates code with limited portability. The block uses precompiled shared libraries, such as DLLs, to support I/O for specific types of devices. With this block, you can use the `packNGo` function supported by Simulink Coder to set up and manage the build information for your models. The `packNGo` function allows you to package model code and dependent shared libraries into a zip file for deployment. You do not need MATLAB installed on the target system, but the target system needs to be supported by MATLAB.

To set up `packNGo`:

```
set_param(gcs, 'PostCodeGenCommand', 'packNGo(buildInfo)');
```

In this example, `gcs` is the current model that you want to build. Building the model creates a zip file with the same name as model name. You can move this zip file to another machine and there build the source code in the zip file to create an executable which can run independent of MATLAB and Simulink. The generated code compiles with both C and C++ compilers. For more information, see “Build Process Customization” (Simulink Coder).

Note On Linux platforms, you need to add the folder where you unzip the libraries to the environment variable `LD_LIBRARY_PATH`.

Parameters

Tip Configure your CAN FD Configuration block before you configure the CAN FD Receive block parameters.

File name

Specify the name and path of the file that contains logged CAN FD messages that you can replay. You can click **Browse** to browse to a file location and select the file.

Variable name

Specify the variable saved in the MAT-file that holds the CAN FD message information.

Number of times to replay messages

Specify the number of times you want the message replayed in your model. You can specify any positive integer, including `Inf`. Specifying `Inf` continuously replays messages until simulation stops.

Replay messages to

Specify if the model is replaying messages to the CAN network or an output port. If replaying to the CAN network, you must also specify a device. If replaying to the model through an output port, the output is a Simulink bus signal.

Device

Select the device on the CAN network to replay messages to. This field is unavailable if you select **Input port** for **Replay message to** option.

Sample time

Specify the sampling time of the block during simulation, which is the simulation time as described by the Simulink documentation. This value defines the frequency at which the CAN FD Replay block runs during simulation. If the block is inside a triggered subsystem or to inherit sample time, you can specify -1 as your sample time. You can also specify a MATLAB variable for sample time. The default value is 0.01 (in seconds).

See Also**Functions**

`canFDMessageBusType` | `canFDMessageReplayBlockStruct`

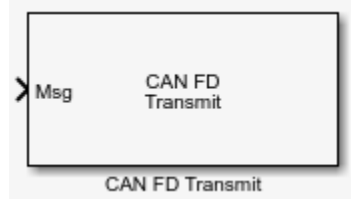
Blocks

CAN FD Log

Introduced in R2018b

CAN FD Transmit

Transmit CAN FD message to selected CAN FD device



Library

Vehicle Network Toolbox: CAN FD Communication

Description

The CAN FD Transmit block transmits messages to the CAN network using the specified CAN device. The CAN FD Transmit block can transmit a single message or an array of messages during a given timestep. To transmit an array of messages from a signal bus, use a Bus Creator or Vector Concatenate, Matrix Concatenate block from the Simulink block library.

Note You need a license for both Vehicle Network Toolbox and Simulink software to use this block.

The CAN FD Transmit block has one input port. This port accepts a CAN message packed using the CAN FD Pack block. It has no output ports.

CAN is a peer-to-peer network, so when transmitting messages on a physical bus at least one other node must be present to properly acknowledge the message. Without another node, the transmission will fail as an error frame, and the device will continually retry to transmit.

Other Supported Features

The CAN FD Transmit block supports the use of Simulink Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information, see “Acceleration” (Simulink).

The CAN FD Transmit block supports the use of code generation along with the packNGo function to group required source code and dependent shared libraries. For more information, see Code Generation on page 15-24.

Code Generation

Vehicle Network Toolbox Simulink blocks allow you to generate code, enabling models containing these blocks to run in Accelerator, Rapid Accelerator, External, and Deployed modes.

Code Generation with Simulink Coder

You can use Vehicle Network Toolbox, Simulink Coder, and Embedded Coder software together to generate code on the host end that you can use to implement your model. For more information on code generation, see “Build Process” (Simulink Coder).

Shared Library Dependencies

The block generates code with limited portability. The block uses precompiled shared libraries, such as DLLs, to support I/O for specific types of devices. With this block, you can use the `packNGo` function supported by Simulink Coder to set up and manage the build information for your models. The `packNGo` function allows you to package model code and dependent shared libraries into a zip file for deployment. You do not need MATLAB installed on the target system, but the target system needs to be supported by MATLAB.

To set up `packNGo`:

```
set_param(gcs, 'PostCodeGenCommand', 'packNGo(buildInfo)');
```

In this example, `gcs` is the current model that you want to build. Building the model creates a zip file with the same name as model name. You can move this zip file to another machine and there build the source code in the zip file to create an executable which can run independent of MATLAB and Simulink. The generated code compiles with both C and C++ compilers. For more information, see “Build Process Customization” (Simulink Coder).

Note On Linux platforms, you need to add the folder where you unzip the libraries to the environment variable `LD_LIBRARY_PATH`.

Parameters

Tip Configure your CAN FD Configuration block before you configure the CAN FD Transmit block parameters.

Device

Select the CAN device and channel for transmitting CAN messages to the network. This list shows all the devices installed on the system. It displays the vendor name, the device name, and the channel ID. The default is the first available device on your system.

Note: When using PEAK-System devices, CAN FD Transmit blocks in multiple enabled subsystems might skip some messages. If possible, replace the enabled subsystems with a different type of conditional subsystem, such as an if-action, switch-case-action, or triggered subsystem; or redesign your model so that all the CAN FD Transmit blocks are contained within a single enabled subsystem.

Transmit Options: On data change

When event-based transmission is enabled, messages are transmitted only at those time steps when a change in message data is detected. When the input data matches the most recent transmission for a given message ID, the message is not re-transmitted.

Event and periodic transmission can both be enabled to work together simultaneously. If neither is selected, the default behavior is to transmit the current input at each time step.

Transmit Options: Periodic

Select this option to enable periodic transmission of the message on the configured channel at the specified message period. The period references real time, regardless of the Simulink model time step size (fundamental sample time) or block execution sample time. This is equivalent to the MATLAB function `transmitPeriodic`.

The periodic transmission is a nonbuffered operation. Only the last CAN message or set of messages present at the input of the CAN FD Transmit block is sent when the time period occurs.

Transmit Options: Message period (in seconds)

Specify a period in seconds. This value is used to transmit the message in the specified period. By default this value is 1.000 seconds.

See Also**Blocks**

CAN FD Configuration | CAN FD Receive | CAN FD Pack

Introduced in R2018a

CAN FD Unpack

Unpack individual signals from CAN FD messages



Library

Vehicle Network Toolbox > CAN FD Communication

Description

The CAN FD Unpack block unpacks a CAN FD message into signal data by using the specified output parameters at every time step. Data is output as individual signals.

To use this block, you also need a license for Simulink software.

The CAN FD Unpack block has one output port by default. The number of output ports is dynamic and depends on the number of signals you specify for the block to output. For example, if your block has four signals, it has four output ports.

The CAN FD Unpack block supports:

- Simulink Accelerator mode. You can speed up the execution of Simulink models. For more information, see “Design Your Model for Effective Acceleration” (Simulink).
- Code generation to deploy models to targets. Code generation is not supported if your signal information consists of signed or unsigned integers greater than 32 bits long.

Dialog Box

Use the Function Block Parameters dialog box to select your message unpacking parameters.

Parameters

Data to be output as

Select your data signal:

- **raw data:** Output data as a uint8 vector array. If you select this option, you only specify the message fields. The other signal parameter fields are unavailable. This option opens only one output port on your block.
- **manually specified signals:** Allows you to specify data signals. If you select this option, use the Signals table to create your signals message manually.

The number of output ports on your block depends on the number of signals you specify. For example, if you specify four signals, your block has four output ports.

- **CANdb specified signals:** Allows you to specify a CAN database file that contains data signals. If you select this option, select a CANdb file.

The number of output ports on your block depends on the number of signals specified in the CANdb file. For example, if the selected message in the CANdb file has four signals, your block has four output ports.

For manually or CANdb specified signals, the default output signal data type is double. To specify other types, use a Signal Specification block. This allows the block to support the following output signal data types: single, double, int8, int16, int32, int64, uint8, uint16, uint32, uint64, and boolean. The block does not support fixed-point types.

CANdb file

This option is available if you specify that your data is input via a CANdb file in the **Data to be output as** list. Click **Browse** to find the CANdb file on your system. The messages and signal definitions specified in the CANdb file populate the **Message** section of the dialog box. The signals specified in the CANdb file populate **Signals** table. File names that contain non-alphanumeric characters such as equal signs, ampersands, and so forth are not valid CAN database file names. You can use periods in your database name. Rename CAN database files with non-alphanumeric characters before you use them.

Message list

This option is available if you specify that your data is to be output as a CANdb file in the **Data to be output as** list and you select a CANdb file in the **CANdb file** field. You can select the message that you want to view. The **Signals** table then displays the details of the selected message.

Message

Name

Specify a name for your message. The default is Msg. This option is available if you choose to output raw data or manually specify signals.

Protocol mode

Specify the message protocol mode as CAN FD or CAN.

Identifier type

Specify whether your message identifier is a **Standard** or an **Extended** type. The default is **Standard**. A standard identifier is an 11-bit identifier and an extended identifier is a 29-bit identifier. This option is available if you choose to output raw data or manually specify signals. For CANdb-specified signals, the **Identifier type** inherits the type from the database.

Identifier

Specify your message ID. This number must be a integer from 0 through 2047 for a standard identifier and from 0 through 536870911 for an extended identifier. If you specify **-1**, the block unpacks the messages that match the length specified for the message. You can also specify hexadecimal values using the hex2dec function. This option is available if you choose to output raw data or manually specify signals.

Length (bytes)

Specify the length of your message. For CAN messages the value can be 0-8 bytes; for CAN FD the value can be 0-8, 12, 16, 20, 24, 32, 48, or 64 bytes. If you are using **CANdb specified signals** for your output data, the CANdb file defines the length of your message. This option is available if you choose to output raw data or manually specify signals.

Signals Table

This table appears if you choose to specify signals manually or define signals using a CANdb file.

If you are using a CANdb file, the data in the file populates this table automatically and you cannot edit the fields. To edit signal information, switch to manually specified signals.

If you have selected to specify signals manually, create your signals manually in this table. Each signal you create has the following values:

Name

Specify a descriptive name for your signal. The Simulink block in your model displays this name. The default is Signal [row number].

Start bit

Specify the start bit of the data. The start bit is the least significant bit counted from the start of the message data. For CAN the start bit must be an integer from 0 through 63, for CAN FD 0 through 511, within the number of bits in the message. (Note that message length is specified in bytes.)

Length (bits)

Specify the number of bits the signal occupies in the message. The length must be an integer from 1 through 64. The sum of all the signal lengths in a message is limited to the number of bits in the message length; that is, all signals must cumulatively fit within the length of the message. (Note that message length is specified in bytes and signal length in bits.)

Byte order

Select either of the following options:

- LE: Where the byte order is in little-endian format (Intel). In this format you count bits from the least-significant bit to the most-significant bit and proceeding to the next higher byte as you cross a byte boundary. For example, if you pack one byte of data in little-endian format, with the start bit at 20, the data bit table resembles this figure.

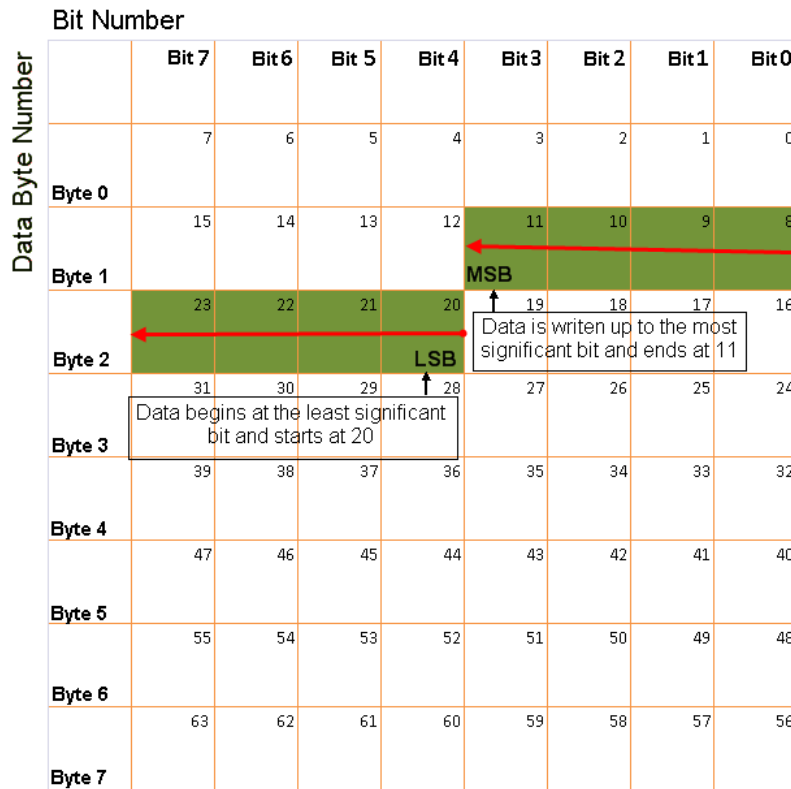
		Bit Number							
		Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
Data Byte Number	Byte 0	7	6	5	4	3	2	1	0
	Byte 1	15	14	13	12	11	10	9	8
	Byte 2	23	22	21	20	19	18	17	16
	Byte 3	31	30	29	28	27	26	25	24
	Byte 4	39	38	37	36	35	34	33	32
	Byte 5	47	46	45	44	43	42	41	40
	Byte 6	55	54	53	52	51	50	49	48
	Byte 7	63	62	61	60	59	58	57	56

Data begins at the least significant bit and starts at 20

Data is written up to the most significant bit and ends at 27

Little-Endian Byte Order Counted from the Least Significant Bit to the Highest Address

- BE: Where the byte order is in big-endian format (Motorola). In this format you count bits from the least-significant bit to the most-significant bit and proceeding to the next lower byte as you cross a byte boundary. For example, if you pack one byte of data in big-endian format, with the start bit at 20, the data bit table resembles this figure.



Big-Endian Byte Order Counted from the Least Significant Bit to the Lowest Address

Data type

Specify how the signal interprets the data in the allocated bits. Choose from:

- signed (default)
- unsigned
- single
- double

Note: If you have a double signal that does not align exactly to the message byte boundaries, to generate code with Embedded Coder you must check **Support long long** under **Device Details** in the **Hardware Implementation** pane of the Configuration Parameters dialog.

Multiplex type

Specify how the block unpacks the signals from the message at each time step:

- Standard: The signal is unpacked at each time step.
- Multiplexor: The Multiplexor signal, or the mode signal is unpacked. You can specify only one Multiplexor signal per message.
- Multiplexed: The signal is unpacked if the value of the Multiplexor signal (mode signal) at run time matches the configured **Multiplex value** of this signal.

For example, a message has four signals with these values.

Signal Name	Multiplex Type	Multiplex Value
Signal-A	Standard	Not applicable
Signal-B	Multiplexed	1
Signal-C	Multiplexed	0
Signal-D	Multiplexor	Not applicable

In this example:

- The block unpacks Signal-A (Standard signal) and Signal-D (Multiplexor signal) in every time step.
- If the value of Signal-D is 1 at a particular time step, then the block unpacks Signal-B along with Signal-A and Signal-D in that time step.
- If the value of Signal-D is 0 at a particular time step, then the block unpacks Signal-C along with Signal-A and Signal-D in that time step.
- If the value of Signal-D is not 1 or 0, the block does not unpack either of the Multiplexed signals in that time step.

Multiplex value

This option is available only if you have selected the **Multiplex type** to be **Multiplexed**. The value you provide here must match the **Multiplexor** signal value at run time for the block to unpack the **Multiplexed** signal. The **Multiplex value** must be a positive integer or zero.

Factor

Specify the **Factor** value applied to convert the unpacked raw value to the physical value (signal value). For more information, see “Conversion Formula” on page 15-33.

Offset

Specify the **Offset** value applied to convert the physical value (signal value) to the unpacked raw value. For more information, see “Conversion Formula” on page 15-33.

Min, Max

Define a range of raw signal values. The default settings are **-Inf** (negative infinity) and **Inf**, respectively. For **CANdb specified signals**, these settings are read from the CAN database. For **manually specified signals**, you can specify the minimum and maximum physical value of the signal. By default, these settings do not clip signal values that exceed them.

Output Ports

Selecting an **Output ports** option adds an output port to your block.

Output identifier

Select this option to output a message identifier. The data type of this port is **uint32**.

Output remote

(Disabled for CAN FD protocol.) Select this option to output the message remote frame status. This option adds a new output port to the block. The data type of this port is **uint8**.

Output timestamp

Select this option to output the message time stamp. This option adds a new output port to the block. The data type of this port is **double**.

Output length

Select this option to output the length of the message in bytes. This option adds a new output port to the block. The data type of this port is **uint8**.

Output error

Select this option to output the message error status. This option adds a new output port to the block. An output value of 1 on this port indicates that the incoming message is an error frame. If the output value is 0, there is no error. The data type of this port is **uint8**.

Output status

Select this option to output the message received status. The status is 1 if the block receives new message and 0 if it does not. This option adds a new output port to the block. The data type of this port is **uint8**.

Output Bit Rate Switch (BRS)

(Disabled for CAN protocol.) Select this option to output the message bit rate switch. This option adds a new output port to the block. The data type of this port is **boolean**.

Output Error Status Indicator (ESI)

(Disabled for CAN protocol.) Select this option to output the message error status. This option adds a new output port to the block. The data type of this port is **boolean**.

Output Data Length Code (DLC)

(Disabled for CAN protocol.) Select this option to output the message data length. This option adds a new output port to the block. The data type of this port is **double**.

If you do not select an **Output ports** option, the number of output ports on your block depends on the number of signals that you specify.

Conversion Formula

The conversion formula is:

$$\text{physical_value} = \text{raw_value} * \text{Factor} + \text{Offset}$$

where `raw_value` is the unpacked signal value and `physical_value` is the scaled signal value.

See Also**Blocks**

CAN FD Configuration | CAN FD Receive | CAN FD Pack

Introduced in R2018a

CAN Log

Log received CAN messages



Library

Vehicle Network Toolbox: CAN Communication

Description

The CAN Log block logs CAN messages from the CAN network or messages sent to the blocks input port to a `.mat` file. You can load the saved messages into MATLAB for further analysis or into another Simulink model.

Configure your CAN Log block to log from the Simulink input port. For more information, see “Log and Replay CAN Messages” on page 16-87.

The Log block appends the specified filename with the current date and time, creating unique log files for repeated logging.

If you want to use messages logged using Simulink blocks in the MATLAB Command window, use `canMessage` to convert messages to the correct format.

Note You need a license for both Vehicle Network Toolbox and Simulink software to use this block.

Note You cannot have more than one CAN Log block in a model using the same PEAK-System device channel.

Other Supported Features

The CAN Log block supports the use of Simulink Accelerator and Rapid Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information on this feature, see the Simulink documentation.

The CAN Log block supports the use of code generation along with the `packNGo` function to group required source code and dependent shared libraries. For more information, see “Code Generation” on page 15-34.

Code Generation

Vehicle Network Toolbox Simulink blocks allow you to generate code, enabling models containing these blocks to run in Accelerator, Rapid Accelerator, External, and Deployed modes.

Code Generation with Simulink Coder

You can use Vehicle Network Toolbox, Simulink Coder, and Embedded Coder software together to generate code on the host end that you can use to implement your model. For more information on code generation, see “Build Process” (Simulink Coder).

Shared Library Dependencies

The block generates code with limited portability. The block uses precompiled shared libraries, such as DLLs, to support I/O for specific types of devices. With this block, you can use the `packNGo` function supported by Simulink Coder to set up and manage the build information for your models. The `packNGo` function allows you to package model code and dependent shared libraries into a zip file for deployment. You do not need MATLAB installed on the target system, but the target system needs to be supported by MATLAB.

To set up `packNGo`:

```
set_param(gcs, 'PostCodeGenCommand', 'packNGo(buildInfo)');
```

In this example, `gcs` is the current model that you want to build. Building the model creates a zip file with the same name as model name. You can move this zip file to another machine and there build the source code in the zip file to create an executable which can run independent of MATLAB and Simulink. The generated code compiles with both C and C++ compilers. For more information, see “Build Process Customization” (Simulink Coder).

Note On Linux platforms, you need to add the folder where you unzip the libraries to the environment variable `LD_LIBRARY_PATH`.

Parameters

Tip If you are logging from the network, you need to configure your CAN channel with a CAN Configuration block.

File name

Type the name and path of the file to log CAN messages to, or click **Browse** to browse to a file location.

The model appends the log file name with the current date and time in the YYYY-MM-DD_hhmmss format. You can also open the block mask and specify a unique name to differentiate between your files for repeated logging.

Variable name

Type the variable saved in the MAT-file that holds the CAN message information.

Maximum number of messages to log

Specify the maximum number of messages this block can log from the selected device or port. The specified value must be a positive integer. If you do not specify a value the block uses the default value of 10,000 messages. The log file saves the most recent messages up to the specified maximum number.

Log messages from

Select the source of the messages logged by the block. Possible values are CAN Bus or Input port. To log messages from the network, you must specify a device.

Device

Select the device on the CAN network that you want to log messages from. This field is unavailable if you select Input port for **Log messages from** option.

Sample time

Specify the sampling time of the block during simulation, which is the simulation time as described by the Simulink documentation. This value defines the frequency at which the CAN Log block runs during simulation. If the block is inside a triggered subsystem or to inherit sample time, you can specify -1 as your sample time. You can also specify a MATLAB variable for sample time. The default value is 0.01 (in seconds).

See Also**Blocks**

CAN Replay

Topics

“Log and Replay CAN Messages” on page 16-87

Introduced in R2011b

CAN Pack

Pack individual signals into CAN message



Library

Vehicle Network Toolbox > CAN Communication

Embedded Coder > Embedded Targets > Host Communication

Description

The CAN Pack block loads signal data into a message at specified intervals during the simulation.

To use this block, you must have a license for Simulink software.

CAN Pack block has one input port by default. The number of block inputs is dynamic and depends on the number of signals you specify for the block. For example, if your block has four signals, it has four block inputs.

This block has one output port, CAN Msg. The CAN Pack block takes the specified input parameters and packs the signals into a message.

The CAN Pack block supports:

- Simulink Accelerator rapid accelerator mode. You can speed up the execution of Simulink models.
- Model referencing. Your model can include other Simulink models as modular components.
- Code generation to deploy models to targets. If your signal information consists of signed or unsigned integers greater than 32 bits long, code generation is not supported.

For more information, see “Design Your Model for Effective Acceleration” (Simulink).

Dialog Box

To select your CAN Pack block parameters, use the Function Block Parameters dialog box.

Parameters

Data is input as

Select your data signal:

- **raw data:** Input data as a uint8 vector array. If you select this option, you only specify the message fields. all other signal parameter fields are unavailable. This option opens only one input port on your block.

- **manually specified signals:** Allows you to specify data signal definitions. If you select this option, use the **Signals** table to create your signals. The number of block inputs depends on the number of signals you specify.
- **CANdb specified signals:** Allows you to specify a CAN database file that contains message and signal definitions. If you select this option, select a CANdb file. The number of block inputs depends on the number of signals specified in the CANdb file for the selected message.

The block supports the following input signal data types: single, double, int8, int16, int32, int64, uint8, uint16, uint32, uint64, and boolean. The block does not support fixed-point data types.

CANdb file

This option is available if you specify that your data is input through a CANdb file in the **Data is input as** list. Click **Browse** to find the CANdb file on your system. The message list specified in the CANdb file populates the **Message** section of the dialog box. The CANdb file also populates the **Signals** table for the selected message.

File names that contain non-alphanumeric characters such as equal signs, ampersands, and so on are not valid CAN database file names. You can use periods in your database name. Before you use the CAN database files, rename them with non-alphanumeric characters.

Message list

This option is available if you specify that your data is input through a CANdb file in the **Data is input as** field and you select a CANdb file in the **CANdb file** field. Select the message to display signal details in the **Signals** table.

Message

Name

Specify a name for your CAN message. The default is `CAN Msg`. This option is available if you choose to input raw data or manually specify signals. This option is not available if you choose to use signals from a CANdb file.

Identifier type

Specify whether your CAN message identifier is a `Standard` or an `Extended` type. The default is `Standard`. A standard identifier is an 11-bit identifier and an extended identifier is a 29-bit identifier. This option is available if you choose to input raw data or manually specify signals. For **CANdb specified signals**, the **Identifier type** inherits the type from the database.

Identifier

Specify your CAN message ID. This number must be a positive integer from 0 through 2047 for a standard identifier and from 0 through 536870911 for an extended identifier. You can also specify hexadecimal values by using the `hex2dec` function. This option is available if you choose to input raw data or manually specify signals.

Length (bytes)

Specify the length of your CAN message from 0 to 8 bytes. If you are using **CANdb specified signals** for your data input, the CANdb file defines the length of your message. If not, this field defaults to 8. This option is available if you choose to input raw data or manually specify signals.

Remote frame

Specify the CAN message as a remote frame.

Output as bus

Select this option for the block to output CAN messages as a Simulink bus signal. For more information on Simulink bus objects, see “Composite Signals” (Simulink).

Signals Table

This table appears if you choose to specify signals manually or define signals by using a CANdb file.

If you are using a CANdb file, the data in the file populates this table and you cannot edit the fields. To edit signal information, switch to manually specified signals.

If you have selected to specify signals manually, create your signals in this table. Each signal that you create has these values:

Name

Specify a descriptive name for your signal. The Simulink block in your model displays this name. The default is Signal [row number].

Start bit

Specify the start bit of the data. The start bit is the least significant bit counted from the start of the message data. The start bit must be an integer from 0 through 63.

Length (bits)

Specify the number of bits the signal occupies in the message. The length must be an integer from 1 through 64.

Byte order

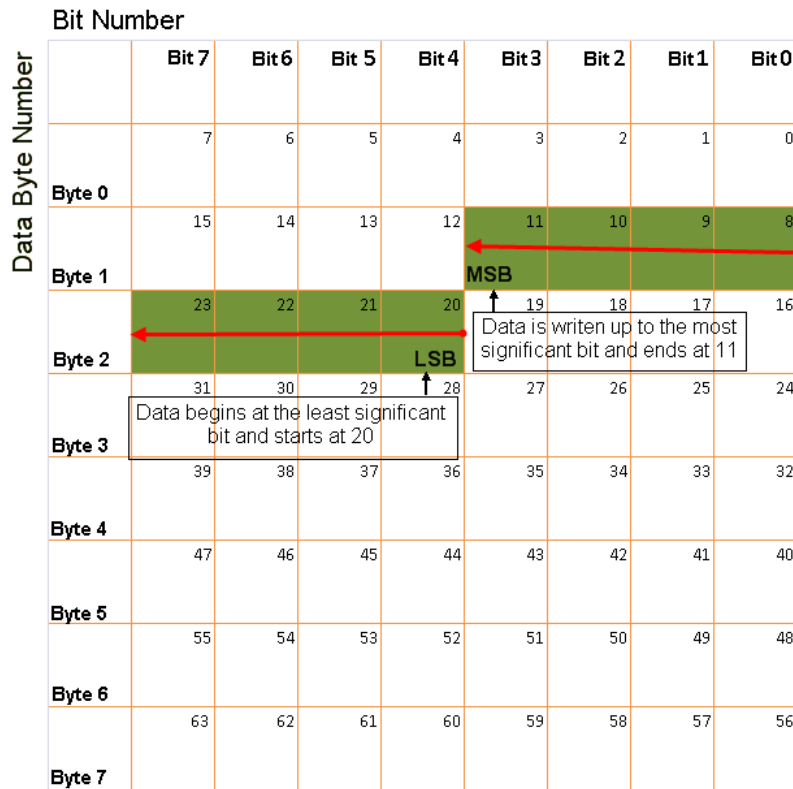
Select either of these options:

- LE: Where the byte order is in little-endian format (Intel). In this format you count bits from the least significant bit, to the most significant bit. For example, if you pack one byte of data in little-endian format, with the start bit at 20, the data bit table resembles this figure.

Bit Number		Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
Data Byte Number	Byte 0	7	6	5	4	3	2	1	0
	Byte 1	15	14	13	12	11	10	9	8
	Byte 2	23	22	21	20	19	18	17	16
	Byte 3	31	30	29	28	27	26	25	24
	Byte 4	39	38	37	36	35	34	33	32
	Byte 5	47	46	45	44	43	42	41	40
	Byte 6	55	54	53	52	51	50	49	48
	Byte 7	63	62	61	60	59	58	57	56

Little-Endian Byte Order Counted from the Least-Significant Bit to the Highest Address

- BE: Where byte order is in big-endian format (Motorola). In this format you count bits from the least-significant bit to the most-significant bit. For example, if you pack one byte of data in big-endian format, with the start bit at 20, the data bit table resembles this figure.



Big-Endian Byte Order Counted from the Least Significant Bit to the Lowest Address

Data type

Specify how the signal interprets the data in the allocated bits. Choose from:

- signed (default)
- unsigned
- single
- double

Multiplex type

Specify how the block packs the signals into the CAN message at each time step:

- Standard: The signal is packed at each time step.
- Multiplexor: The Multiplexor signal, or the mode signal is packed. You can specify only one Multiplexor signal per message.
- Multiplexed: The signal is packed if the value of the Multiplexor signal (mode signal) at run time matches the configured **Multiplex value** of this signal.

For example, a message has these signals with the following types and values.

Signal Name	Multiplex Type	Multiplex Value
Signal-A	Standard	Not applicable

Signal Name	Multiplex Type	Multiplex Value
Signal-B	Multiplexed	1
Signal-C	Multiplexed	0
Signal-D	Multiplexor	Not applicable

In this example:

- The block packs Signal-A (Standard signal) and Signal-D (Multiplexor signal) in every time step.
- If the value of Signal-D is 1 at a particular time step, then the block packs Signal-B along with Signal-A and Signal-D in that time step.
- If the value of Signal-D is 0 at a particular time step, then the block packs Signal-C along with Signal-A and Signal-D in that time step.
- If the value of Signal-D is not 1 or 0, the block does not pack either of the Multiplexed signals in that time step.

Multiplex value

This option is available only if you have selected the **Multiplex type** to be **Multiplexed**. The value you provide must match the **Multiplexor** signal value at run time for the block to pack the **Multiplexed** signal. The **Multiplex value** must be a positive integer or zero.

Factor

Specify the **Factor** value to apply to convert the physical value (signal value) to the raw value packed in the message. For more information, see “Conversion Formula” on page 15-42.

Offset

Specify the **Offset** value to apply to convert the physical value (signal value) to the raw value packed in the message. For more information, see “Conversion Formula” on page 15-42.

Min, Max

Define a range of signal values. The default settings are `-Inf` (negative infinity) and `Inf`, respectively. For **CANdb specified signals**, these settings are read from the CAN database. For **manually specified signals**, you can specify the minimum and maximum physical value of the signal. By default, these settings do not clip signal values that exceed the settings.

Conversion Formula

The conversion formula is:

$$\text{raw_value} = (\text{physical_value} - \text{Offset}) / \text{Factor}$$

where `physical_value` is the original value of the signal and `raw_value` is the packed signal value.

See Also

Blocks

CAN Unpack

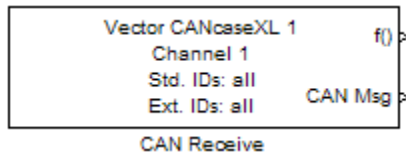
Functions

`canMessageBusType`

Introduced in R2009a

CAN Receive

Receive CAN messages from specified CAN device



Library

Vehicle Network Toolbox: CAN Communication

Description

The CAN Receive block receives messages from the CAN network and delivers them to the Simulink model. It outputs one message or all messages at each timestep, depending on the block parameters.

Note You need a license for both Vehicle Network Toolbox and Simulink software to use this block.

The CAN Receive block has two output ports:

- The `f()` output port is a trigger to a Function-Call subsystem. If the block receives a new message, it triggers a Function-Call from this port. You can then connect to a Function-Call Subsystem to unpack and process a message.
- The `CAN Msg` output port contains a CAN message received at that particular timestep.

The CAN Receive block stores CAN messages in a first-in, first-out (FIFO) buffer. The FIFO buffer delivers the messages to your model in the queued order at every timestep.

Note You cannot have more than one CAN Receive block in a model using the same PEAK-System device channel.

Other Supported Features

The CAN Receive block supports the use of Simulink Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information on this feature, see the Simulink documentation.

The CAN Receive block supports the use of code generation along with the `packNGo` function to group required source code and dependent shared libraries. For more information, see “Code Generation” on page 15-45.

Code Generation

Vehicle Network Toolbox Simulink blocks allow you to generate code, enabling models containing these blocks to run in Accelerator, Rapid Accelerator, External, and Deployed modes.

Code Generation with Simulink Coder

You can use Vehicle Network Toolbox, Simulink Coder, and Embedded Coder software together to generate code on the host end that you can use to implement your model. For more information on code generation, see “Build Process” (Simulink Coder).

Shared Library Dependencies

The block generates code with limited portability. The block uses precompiled shared libraries, such as DLLs, to support I/O for specific types of devices. With this block, you can use the `packNGo` function supported by Simulink Coder to set up and manage the build information for your models. The `packNGo` function allows you to package model code and dependent shared libraries into a zip file for deployment. You do not need MATLAB installed on the target system, but the target system needs to be supported by MATLAB.

To set up `packNGo`:

```
set_param(gcs, 'PostCodeGenCommand', 'packNGo(buildInfo)');
```

In this example, `gcs` is the current model that you want to build. Building the model creates a zip file with the same name as model name. You can move this zip file to another machine and there build the source code in the zip file to create an executable which can run independent of MATLAB and Simulink. The generated code compiles with both C and C++ compilers. For more information, see “Build Process Customization” (Simulink Coder).

Note On Linux platforms, you need to add the folder where you unzip the libraries to the environment variable `LD_LIBRARY_PATH`.

Parameters

Tip Configure your CAN Configuration block before you configure the CAN Receive block parameters.

Device

Select the CAN device and a channel on the device you want to receive CAN messages from. This field lists all the devices installed on the system. It displays the vendor name, the device name, and the channel ID. The default is the first available device on your system.

Standard IDs Filter

Select the filter on this block for standard IDs. Valid choices are:

- `Allow all` (default): Allows all standard IDs to pass the filter.
- `Allow only`: Allows only ID or range of IDs specified in the text field. You can specify a single ID or an array of IDs. You can also specify disjointed IDs or arrays separated by a comma. For example, to accept IDs from 400 through 500, and 600 through 650, enter `[400:500]`

[600:650]]. Standard IDs must be positive integers from 0 to 2047. You can also specify hexadecimal values with the `hex2dec` function.

- `Block all`: Blocks all standard IDs from passing the filter.

Extended IDs Filter

Select the filter on this block for extended IDs. Valid choices are:

- `Allow all` (default): Allows all extended IDs to pass the filter.
- `Allow only`: Allows only those IDs specified in the text field. You can specify a single ID or an array of IDs. You can also specify disjointed IDs or arrays separated by a comma. For example, to accept IDs from 3000 through 3500, and 3600 through 3620, enter `[[3000:3500][3600:3620]]`. Extended IDs must be positive integers from 0 to 536870911. You can also specify hexadecimal values using the `hex2dec` function.
- `Block all`: Blocks all extended IDs from passing the filter.

Sample time

Specify the sampling time of the block during simulation, which is the simulation time as described by the Simulink documentation. This value defines the frequency at which the CAN Receive block runs during simulation. If the block is inside a triggered subsystem or to inherit sample time, you can specify `-1` as your sample time. You can also specify a MATLAB variable for sample time. The default value is 0.01 (in seconds).

Number of messages received at each timestep

Select how many messages the block receives at each specified timestep. Valid choices are:

- `all` (default): The CAN Receive block delivers all available messages in the FIFO buffer to the model during a specific timestep. The block generates one function call for each delivered message. The output port always contains one CAN message at a time.
- `1`: The CAN Receive block delivers one message per timestep from the FIFO buffer to the model.

If the block does not receive any messages before the next timestep, it outputs the last received message.

Output as bus

Select this option for the block to output CAN messages as a Simulink bus signal. For more information on Simulink bus objects, see “Composite Signals” (Simulink).

See Also

Blocks

CAN Configuration | CAN Unpack

Functions

`canMessageBusType`

Introduced in R2009a

CAN Replay

Replay logged CAN messages



Library

Vehicle Network Toolbox: CAN Communication

Description

The CAN Replay block replays logged messages from a `.mat` file to a CAN network or to Simulink. You need a CAN Configuration block to replay to the network.

To replay messages logged in the MATLAB Command window in your Simulink model, convert them into a compatible format using `vntslgate` and save it to a separate file. For more information, see “Log and Replay CAN Messages” on page 16-87.

Note You need a license for both Vehicle Network Toolbox and Simulink software to use this block.

Replay Timing

When you replay logged messages, Simulink uses the original timestamps on the messages. When you replay to a network, the timestamps correlate to real time, and when you replay to the Simulink input port it correlates to simulation time. If the timestamps in the messages are all 0, all messages are replayed as soon as the simulation starts, because simulation time and real time will be ahead of the timestamps in the replayed messages.

Other Supported Features

The CAN Replay block supports the use of Simulink Accelerator Rapid Accelerator mode. Using this feature, you can speed up the execution of Simulink models.

For more information on this feature, see the Simulink documentation.

The CAN Replay block supports the use of code generation along with the `packNGo` function to group required source code and dependent shared libraries. For more information, see “Code Generation” on page 15-47.

Code Generation

Vehicle Network Toolbox Simulink blocks allow you to generate code, enabling models containing these blocks to run in Accelerator, Rapid Accelerator, External, and Deployed modes.

Code Generation with Simulink Coder

You can use Vehicle Network Toolbox, Simulink Coder, and Embedded Coder software together to generate code on the host end that you can use to implement your model. For more information on code generation, see “Build Process” (Simulink Coder).

Shared Library Dependencies

The block generates code with limited portability. The block uses precompiled shared libraries, such as DLLs, to support I/O for specific types of devices. With this block, you can use the `packNGo` function supported by Simulink Coder to set up and manage the build information for your models. The `packNGo` function allows you to package model code and dependent shared libraries into a zip file for deployment. You do not need MATLAB installed on the target system, but the target system needs to be supported by MATLAB.

To set up `packNGo`:

```
set_param(gcs, 'PostCodeGenCommand', 'packNGo(buildInfo)');
```

In this example, `gcs` is the current model that you want to build. Building the model creates a zip file with the same name as model name. You can move this zip file to another machine and there build the source code in the zip file to create an executable which can run independent of MATLAB and Simulink. The generated code compiles with both C and C++ compilers. For more information, see “Build Process Customization” (Simulink Coder).

Note On Linux platforms, you need to add the folder where you unzip the libraries to the environment variable `LD_LIBRARY_PATH`.

Parameters

Tip Configure your CAN Configuration block before you configure the CAN Receive block parameters.

File name

Specify the name and path of the file that contains logged CAN messages that you can replay. You can click **Browse** to browse to a file location and select the file.

Variable name

Specify the variable saved in the MAT-file that holds the CAN message information.

Number of times to replay messages

Specify the number of times you want the message replayed in your model. You can specify any positive integer, including `Inf`. Specifying `Inf` continuously replays messages until simulation stops.

Replay messages to

Specify if the model is replaying messages to the CAN network or an output port. Select a device to replay to the CAN network.

Device

Select the device on the CAN network to replay messages to. This field is unavailable if you select `Input port` for **Replay message to** option.

Sample time

Specify the sampling time of the block during simulation, which is the simulation time as described by the Simulink documentation. This value defines the frequency at which the CAN Replay block runs during simulation. If the block is inside a triggered subsystem or to inherit sample time, you can specify -1 as your sample time. You can also specify a MATLAB variable for sample time. The default value is 0.01 (in seconds).

Output as bus

Select this option for the block to output CAN messages as a Simulink bus signal. For more information on Simulink bus objects, see “Composite Signals” (Simulink).

See Also**Blocks**

CAN Log

Functions

canMessageBusType | canMessageReplayBlockStruct

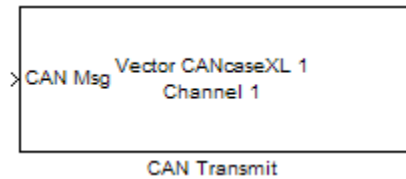
Topics

“Log and Replay CAN Messages” on page 16-87

Introduced in R2011b

CAN Transmit

Transmit CAN message to selected CAN device



Library

Vehicle Network Toolbox: CAN Communication

Description

The CAN Transmit block transmits messages to the CAN network using the specified CAN device. The CAN Transmit block can transmit a single message or an array of messages during a given timestep. To transmit an array of messages, use a mux (multiplex) block from the Simulink block library.

Note You need a license for both Vehicle Network Toolbox and Simulink software to use this block.

The CAN Transmit block has one input port. This port accepts a CAN message packed using the CAN Pack block. It has no output ports.

CAN is a peer-to-peer network, so when transmitting messages on a physical bus at least one other node must be present to properly acknowledge the message. Without another node, the transmission will fail as an error frame, and the device will continually retry to transmit.

Other Supported Features

The CAN Transmit block supports the use of Simulink Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information on this feature, see the Simulink documentation.

The CAN Transmit block supports the use of code generation along with the packNGo function to group required source code and dependent shared libraries. For more information, see Code Generation on page 15-50.

Code Generation

Vehicle Network Toolbox Simulink blocks allow you to generate code, enabling models containing these blocks to run in Accelerator, Rapid Accelerator, External, and Deployed modes.

Code Generation with Simulink Coder

You can use Vehicle Network Toolbox, Simulink Coder, and Embedded Coder software together to generate code on the host end that you can use to implement your model. For more information on code generation, see “Build Process” (Simulink Coder).

Shared Library Dependencies

The block generates code with limited portability. The block uses precompiled shared libraries, such as DLLs, to support I/O for specific types of devices. With this block, you can use the `packNGo` function supported by Simulink Coder to set up and manage the build information for your models. The `packNGo` function allows you to package model code and dependent shared libraries into a zip file for deployment. You do not need MATLAB installed on the target system, but the target system needs to be supported by MATLAB.

To set up `packNGo`:

```
set_param(gcs, 'PostCodeGenCommand', 'packNGo(buildInfo)');
```

In this example, `gcs` is the current model that you want to build. Building the model creates a zip file with the same name as model name. You can move this zip file to another machine and there build the source code in the zip file to create an executable which can run independent of MATLAB and Simulink. The generated code compiles with both C and C++ compilers. For more information, see “Build Process Customization” (Simulink Coder).

Note On Linux platforms, you need to add the folder where you unzip the libraries to the environment variable `LD_LIBRARY_PATH`.

Parameters

Tip Configure your CAN Configuration block before you configure the CAN Transmit block parameters.

Device

Select the CAN device and channel for transmitting CAN messages to the network. This list shows all the devices installed on the system. It displays the vendor name, the device name, and the channel ID. The default is the first available device on your system.

Note: When using PEAK-System devices, CAN Transmit blocks in multiple enabled subsystems might skip some messages. If possible, replace the enabled subsystems with a different type of conditional subsystem, such as an if-action, switch-case-action, or triggered subsystem; or redesign your model so that all the CAN Transmit blocks are contained within a single enabled subsystem.

Transmit Options: On data change

When event-based transmission is enabled, messages are transmitted only at those time steps when a change in message data is detected. When the input data matches the most recent transmission for a given message ID, the message is not re-transmitted.

Event and periodic transmission can both be enabled to work together simultaneously. If neither is selected, the default behavior is to transmit the current input at each time step.

Transmit Options: Periodic

Select this option to enable periodic transmission of the message on the configured channel at the specified message period. The period references real time, regardless of the Simulink model time step size (fundamental sample time) or block execution sample time. This is equivalent to the MATLAB function `transmitPeriodic`.

The periodic transmission is a nonbuffered operation. Only the last CAN message or set of muxed messages present at the input of the CAN Transmit block is sent when the time period occurs.

Transmit Options: Message period (in seconds)

Specify a period in seconds. This value is used to transmit the message in the specified period. By default this value is 1.000 seconds.

See Also

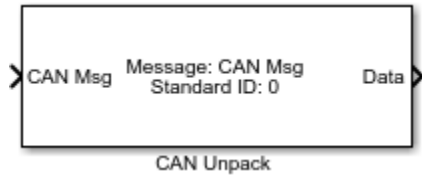
Blocks

CAN Configuration | CAN Pack

Introduced in R2009a

CAN Unpack

Unpack individual signals from CAN messages



Library

Vehicle Network Toolbox > CAN Communication

Embedded Coder > Embedded Targets > Host Communication

Description

The CAN Unpack block unpacks a CAN message into signal data using the specified output parameters at every time step. Data is output as individual signals.

To use this block, you also need a license for Simulink software.

The CAN Unpack block has one output port by default. The number of output ports is dynamic and depends on the number of signals that you specify for the block to output. For example, if your block has four signals, the block has four output ports.

The CAN Unpack block supports:

- The use of Simulink Accelerator Rapid Accelerator mode. Using this feature, you can speed up the execution of Simulink models.
- The use of model referencing. Using this feature, your model can include other Simulink models as modular components.
- Code generation to deploy models to targets. Code generation is not supported if your signal information consists of signed or unsigned integers greater than 32 bits long.

For more information on these features, see “Design Your Model for Effective Acceleration” (Simulink).

Dialog Box

To select your CAN message unpacking parameters, use the Function Block Parameters dialog box .

Parameters

Data to be output as

Select your data signal:

- **raw data:** Output data as a uint8 vector array. If you select this option, you specify only the message fields. The other signal parameter fields are unavailable. This option opens only one output port on your block.
- **manually specified signals:** You can specify data signals. If you select this option, use the **Signals** table to create your signals message manually. The number of output ports on your block depends on the number of signals that you specify. For example, if you specify four signals, your block has four output ports.
- **CANdb specified signals:** You can specify a CAN database file that contains data signals. If you select this option, select a CANdb file. The number of output ports on your block depends on the number of signals specified in the CANdb file. For example, if the selected message in the CANdb file has four signals, your block has four output ports.

For manually or CANdb specified signals, the default output signal data type is double. To specify other types, use a Signal Specification block. This allows the block to support the following output signal data types: single, double, int8, int16, int32, int64, uint8, uint16, uint32, uint64, and boolean. The block does not support fixed-point types.

CANdb file

This option is available if you specify that your data is input via a CANdb file in the **Data to be output as** list. Click **Browse** to find the CANdb file on your system. The messages and signal definitions specified in the CANdb file populate the **Message** section of the dialog box. The signals specified in the CANdb file populate **Signals** table.

File names that contain non-alphanumeric characters such as equal signs, ampersands, and so forth are not valid CAN database file names. You can use periods in your database name. Rename CAN database files with non-alphanumeric characters before you use them.

Message list

This option is available if you specify in the **Data to be output as** list that your data is to be output as a CANdb file and you select a CANdb file in the **CANdb file** field. You can select the message that you want to view. The **Signals** table then displays the details of the selected message.

Message

Name

Specify a name for your CAN message. The default is `CAN Msg`. This option is available if you choose to output raw data or manually specify signals.

Identifier type

Specify whether your CAN message identifier is a **Standard** or an **Extended** type. The default is **Standard**. A standard identifier is an 11-bit identifier and an extended identifier is a 29-bit identifier. This option is available if you choose to output raw data or manually specify signals. For CANdb-specified signals, the **Identifier type** inherits the type from the database.

Identifier

Specify your CAN message ID. This number must be a integer from 0 through 2047 for a standard identifier and from 0 through 536870911 for an extended identifier. If you specify `-1`, the block unpacks the messages that match the length specified for the message. You can also specify hexadecimal values by using the `hex2dec` function. This option is available if you choose to output raw data or manually specify signals.

Length (bytes)

Specify the length of your CAN message from 0 to 8 bytes. If you are using **CANdb specified signals** for your output data, the CANdb file defines the length of your message. If not, this field defaults to 8. This option is available if you choose to output raw data or manually specify signals.

Signals Table

If you choose to specify signals manually or define signals by using a CANdb file, this table appears.

If you are using a CANdb file, the data in the file populates this table and you cannot edit the fields. To edit signal information, switch to **specified signals**.

If you have selected to specify signals manually, create your signals manually in this table. Each signal that you create has these values:

Name

Specify a descriptive name for your signal. The Simulink block in your model displays this name. The default is **Signal [row number]**.

Start bit

Specify the start bit of the data. The start bit is the least significant bit counted from the start of the message. The start bit must be an integer from 0 through 63.

Length (bits)

Specify the number of bits the signal occupies in the message. The length must be an integer from 1 through 64.

Byte order

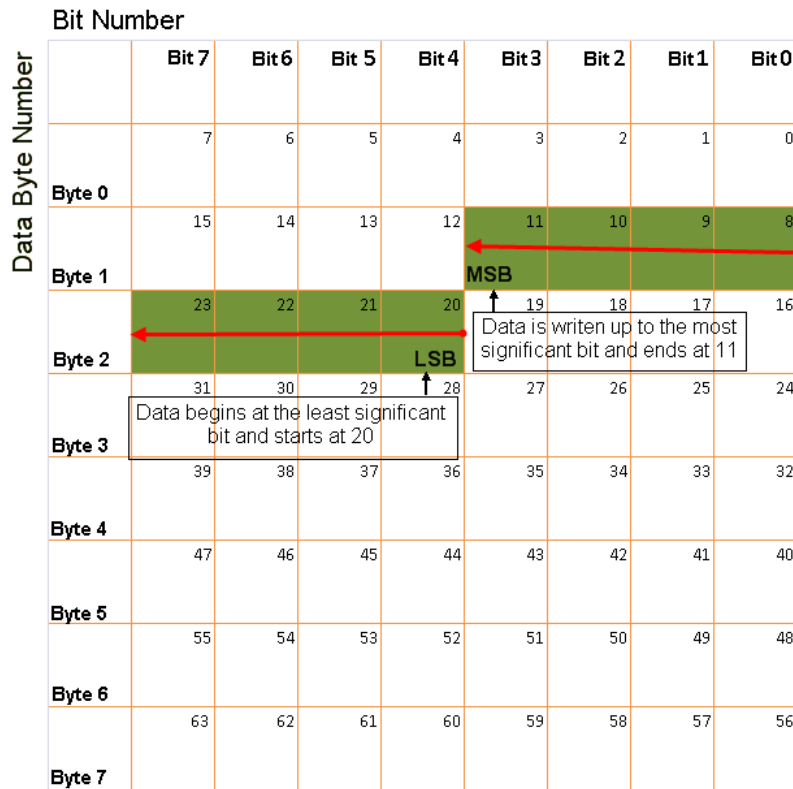
Select either of these options:

- **LE:** Where the byte order is in little-endian format (Intel). In this format you count bits from the least-significant bit to the most-significant bit. For example, if you pack one byte of data in little-endian format, with the start bit at 20, the data bit table resembles this figure.

		Bit Number							
		Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
Data Byte Number	Byte 0	7	6	5	4	3	2	1	0
	Byte 1	15	14	13	12	11	10	9	8
	Byte 2	23	22	21	20	19	18	17	16
	Byte 3	31	30	29	28	27	26	25	24
	Byte 4	39	38	37	36	35	34	33	32
	Byte 5	47	46	45	44	43	42	41	40
	Byte 6	55	54	53	52	51	50	49	48
	Byte 7	63	62	61	60	59	58	57	56

Little-Endian Byte Order Counted from the Least Significant Bit to the Highest Address

- BE: Where the byte order is in big-endian format (Motorola). In this format you count bits from the least-significant bit to the most-significant bit. For example, if you pack one byte of data in big-endian format, with the start bit at 20, the data bit table resembles this figure.



Big-Endian Byte Order Counted from the Least Significant Bit to the Lowest Address

Data type

Specify how the signal interprets the data in the allocated bits. Choose from:

- signed (default)
- unsigned
- single
- double

Multiplex type

Specify how the block unpacks the signals from the CAN message at each time step:

- Standard: The signal is unpacked at each time step.
- Multiplexor: The Multiplexor signal or the mode signal is unpacked. You can specify only one Multiplexor signal per message.
- Multiplexed: The signal is unpacked if the value of the Multiplexor signal (mode signal) at run time matches the configured **Multiplex value** of this signal.

For example, a message has four signals with these values.

Signal Name	Multiplex Type	Multiplex Value
Signal-A	Standard	Not applicable

Signal Name	Multiplex Type	Multiplex Value
Signal-B	Multiplexed	1
Signal-C	Multiplexed	0
Signal-D	Multiplexor	Not applicable

In this example:

- The block unpacks Signal-A (Standard signal) and Signal-D (Multiplexor signal) in every time step.
- If the value of Signal-D is 1 at a particular time step, then the block unpacks Signal-B along with Signal-A and Signal-D in that time step.
- If the value of Signal-D is 0 at a particular time step, then the block unpacks Signal-C along with Signal-A and Signal-D in that time step.
- If the value of Signal-D is not 1 or 0, the block does not unpack either of the Multiplexed signals in that time step.

Multiplex value

This option is available only if you have selected the **Multiplex type** to be **Multiplexed**. The value you provide must match the **Multiplexor** signal value at run time for the block to unpack the Multiplexed signal. The **Multiplex value** must be a positive integer or zero.

Factor

Specify the **Factor** value applied to convert the unpacked raw value to the physical value (signal value). For more information, see “Conversion Formula” on page 15-59.

Offset

Specify the **Offset** value applied to convert the physical value (signal value) to the unpacked raw value. For more information, see “Conversion Formula” on page 15-59.

Min, Max

Define a range of raw signal values. The default settings are **-Inf** (negative infinity) and **Inf**, respectively. For **CANdb specified signals**, these settings are read from the CAN database. For **manually specified signals**, you can specify the minimum and maximum physical value of the signal. By default, these settings do not clip signal values that exceed them.

Output Ports

Selecting an **Output ports** option adds an output port to your block.

Output identifier

Select this option to output a CAN message identifier. The data type of this port is **uint32**.

Output remote

Select this option to output the message remote frame status. This option adds a new output port to the block. The data type of this port is **uint8**.

Output timestamp

Select this option to output the message timestamp. This value indicates when the message was received, measured as the number of seconds elapsed since the model simulation began. This option adds a new output port to the block. The data type of this port is **double**.

Output length

Select this option to output the length of the message in bytes. This option adds a new output port to the block. The data type of this port is **uint8**.

Output error

Select this option to output the message error status. This option adds a new output port to the block. An output value of 1 on this port indicates that the incoming message is an error frame. If the output value is 0, there is no error. The data type of this port is **uint8**.

Output status

Select this option to output the message received status. The status is 1 if the block receives a new message and 0 if it does not. This option adds a new output port to the block. The data type of this port is **uint8**.

If you do not select an **Output ports** option, the number of output ports on your block depends on the number of signals that you specify.

Conversion Formula

The conversion formula is:

$$\text{physical_value} = \text{raw_value} * \text{Factor} + \text{Offset}$$

where `raw_value` is the unpacked signal value and `physical_value` is the scaled signal value.

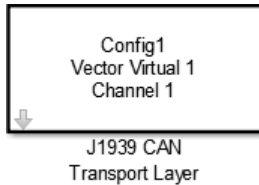
See Also**Blocks**

CAN Pack

Introduced in R2009a

J1939 CAN Transport Layer

Transport J1939 messages via CAN



Library

Vehicle Network Toolbox: J1939 Communication

Description

The J1939 CAN Transport Layer block allows J1939 communication via a CAN bus. This block associates a user-defined J1939 network configuration with a connected CAN device. Use one block for each J1939 Network Configuration block in your model.

Note You need a license for both Vehicle Network Toolbox and Simulink software to use this block.

Other Supported Features

The J1939 communication blocks support the use of Simulink Accelerator and Rapid Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information on this feature, see the Simulink documentation.

The J1939 communication blocks also support code generation with limited deployment capabilities. Code generation requires the Microsoft® C++ compiler.

Parameters

Config name

The name of the J1939 Network Configuration block to associate with.

Device

The CAN device, chosen from all connected CAN devices.

Bus speed

Speed of the CAN bus. The J1939 protocol specifies two rates of 250k and 500k. The default is 250000.

Sample time

Simulation refresh rate. Specify the sampling time of the block during simulation. This value defines the frequency at which the J1939 CAN Transport Layer block runs during simulation. For information about simulation sample timing, see “What Is Sample Time?” (Simulink) If the block is inside a triggered subsystem or inherits a sample time, specify a value of -1. You can also specify a MATLAB variable for sample time. The default value is 0.01 seconds.

See Also

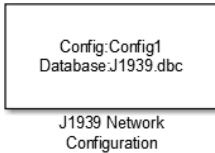
Blocks

Introduced in R2015b

J1939 Network Configuration

Define J1939 network configuration name and database file

Library: Simulink Real-Time / J1939 Communication
Vehicle Network Toolbox / J1939 Communication



Description

The J1939 Network Configuration block is where you define a configuration name and specify the associated user-supplied J1939 database. You can include more than one block per model, each corresponding to a unique configuration on the CAN bus.

To use this block, you must have a license for both Vehicle Network Toolbox and Simulink software.

The J1939 communication blocks support the use of Simulink accelerator and rapid accelerator modes. You can speed up the execution of Simulink models by using these modes. For more information on these modes, see the Simulink documentation.

The J1939 communication blocks also support code generation that have limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For the current list of supported compilers, see Supported and Compatible Compilers.

Parameters

Configuration name — Define a name for this J1939 network configuration

ConfigX (default) | character vector

The default value is ConfigX, where the number X increases from 1 based on the number of existing blocks.

Programmatic Use

ConfigName

Database File — Specify the J1939 database file name relative to the current folder

not set (default) | character vector

An example file name, enter J1939.dbc if the file is in the current folder; otherwise enter the full path with the file name, such as C:\work\J1939.dbc.

The database file defines the J1939 parameter groups and nodes. This file must be in the DBC file format defined by Vector Informatik GmbH.

Programmatic Use

DbFile

See Also

J1939 Node Configuration | J1939 Receive | J1939 Transmit | J1939 CAN Transport Layer

Topics

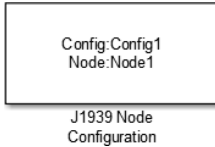
“Basic J1939 Communication over CAN” on page 16-94

Introduced in R2015b

J1939 Node Configuration

Configure J1939 node with address and network management attributes

Library: Simulink Real-Time / J1939 Communication
Vehicle Network Toolbox / J1939 Communication



Description

The J1939 Node Configuration block is where you define a node and associate it with a specific network configuration. Its Message information is read from the database for that configuration, unless you are creating and configuring a custom node.

To use this block, you must have a license for both Vehicle Network Toolbox and Simulink software.

The J1939 communication blocks support the use of Simulink accelerator and rapid accelerator modes. You can speed up the execution of Simulink models by using these modes. For more information on these modes, see “Design Your Model for Effective Acceleration” (Simulink).

The J1939 communication blocks also support code generation that have limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For the current list of supported compilers, see Supported and Compatible Compilers.

Ports

Output

Address — Returns the effective address of the node

int8

This optional output port exists when you select the **Output current node address** check box in the dialog box.

AC Status — Indicates the success (1) or failure (0) of the node’s address claim

0 | 1

This optional output port exists when you select the **Output address claim status** check box in the dialog box.

Parameters

Config name — ID of the J1939 network configuration to associate with this node

ConfigX (default) | character vector

To access the corresponding J1939 database, use this ID.

Programmatic Use

ConfigName

Node name — name of this J1939 node

NodeX (default) | character vector

The available list shows `none` if no J1939 network configuration is found or no node is defined in the associated database. If you are creating a custom node, the node name must be unique within its J1939 network configuration.

Programmatic Use

NodeID

Message — Nine network attributes as defined by the database file consistent with the J1939 protocol

vector array

Unless you are defining a custom node, these parameters are read-only:

- **Allow arbitrary address** — Allow/disallow the node to switch to an arbitrary address if the station address is not available. If this option is off and the node loses its address claim, the node goes silent.
- Node Address** — Station address, decimal, 8-bit.
- **Industry Group** — Decimal, 3-bit.
 - **Vehicle System** — Decimal, 7-bit.
 - **Vehicle System Instance** — Identifies one particular occurrence of a given vehicle system in a given network. If only one instance of a certain vehicle system exists in a network, then this field must be set to 0 to define it as the first instance. Decimal, 4-bit.
 - **Function ID** — Decimal, 8-bit.
 - **Function Instance** — Identifies the particular occurrence of a given function in a vehicle system and given network. If only one instance of a certain function exists in a network, then this field must be set to 0 to define it as the first instance. Decimal, 5-bit.
 - **ECU Instance** — This 3-bit field is used when multiple electronic control units (ECU) are involved in performing a single function. If only one ECU is used for a particular controller application (CA), then this field must be set to 0 to define it as the first instance.
 - **Manufacturer Code** — Decimal, 11-bit.
 - **Identity Number** — Decimal, 21-bit.

Programmatic Use

AllowACC
 NodeAddress
 IndustryGroup
 VehicleSystem
 VehicleSystemInstance
 FunctionID
 FunctionInstance
 ECUInstance
 ManufacturerCode
 IDNumber

Sample time — Simulation refresh rate

0.01 (default) | double

Specify the sampling time of the block during simulation. This value defines the frequency at which the J1939 Node Configuration updates its optional output ports. If the block is inside a triggered subsystem or inherits a sample time, specify a value of -1. You can also specify a MATLAB variable for sample time. The default value is 0.01 seconds. For information about simulation sample timing, see “What Is Sample Time?” (Simulink).

Programmatic Use

SampleTime

Output current node address — Enable or disable the Address port display

off (default) | on

Enable or disable the **Address** output port to show the effective address. The effective address is different from the predefined station address. If **Allow arbitrary address** is selected, a name conflict occurs, and the current node has lower priority. The output signal is a double value from 0 to 253. This port is disabled by default.

Programmatic Use

OutputAddress

Output address claim status — Enable or disable the address claim AC Status display

off (default) | on

Enable or disable the address claim **AC Status** output port to show the success of an address claim. The output value is binary, 1 for success or 0 for failure. This port is disabled by default.

Programmatic Use

OutputACStatus

See Also

J1939 Receive | J1939 Transmit | J1939 CAN Transport Layer | J1939 Network Configuration

Topics

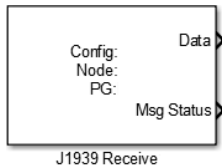
“Basic J1939 Communication over CAN” on page 16-94

Introduced in R2015b

J1939 Receive

Receive J1939 parameter group messages

Library: Simulink Real-Time / J1939 Communication
Vehicle Network Toolbox / J1939 Communication



Description

The J1939 Receive block receives a J1939 message from the configured CAN device. The J1939 database file defines the nodes and parameter groups. You specify the J1939 database by using the J1939 Network Configuration block.

To use this block, you must have a license for both Vehicle Network Toolbox and Simulink software.

The J1939 communication blocks support the use of Simulink accelerator and rapid accelerator modes. You can speed up the execution of Simulink models by using these modes. For more information on these modes, see “Design Your Model for Effective Acceleration” (Simulink).

The J1939 communication blocks also support code generation that have limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For the current list of supported compilers, see Supported and Compatible Compilers.

Ports

Output

Data — Data output

double

Depending on the J1939 parameter group defined in the J1939 database file, the block can have multiple data output signal ports. The block output data type is double.

Msg Status — Message received status

0 | 1

When you select the **Output New Message Received status** check box in the dialog box, this port outputs 1 when a new message is received from the CAN bus. Otherwise, this port outputs 0.

Parameters

Config name — Name of the J1939 network configuration to associate

ConfigX (default) | character vector

The name of the J1939 network configuration to associate. This value is used to access the corresponding J1939 database. Only the nodes defined in the model and associated with the specified

J1939 network configuration appear in the Node name list. The option shows none if no J1939 network configuration is found.

Programmatic Use

ConfigName

Node name — Name of the J1939 node

NodeX (default) | character vector

The name of the J1939 node. The drop-down list includes all the nodes in the model, both custom nodes and nodes from the database.

Programmatic Use

NodeName

Parameter Group — Parameter group number (PGN) and name from database

character vector

The parameter group number (PGN) and name from the database. The contents of this list vary depending on the parameter groups that the J1939 database file specifies. The default is the first parameter group for the selected node.

If you change any parameter group settings within your J1939 database file, open the J1939 Receive block dialog box and select the same **Parameter Group** and click **OK** or **Apply**.

Programmatic Use

PGList

Signals — Signals defined in the parameter group

array of character vectors

Signals that are defined in the parameter group. The **Min** and **Max** settings are read from the database, but by default the block does not clip signal values that exceed this range.

Programmatic Use

PGName
MsgLength
SignalInfo
NSignals
StartBits
SignalSizes
ByteOrders
DataTypes
MultiplexTypes
MultiplexValues
Factors
Offsets
Minimums
Maximums
Units
SPN
Comment

Source Address Filter — Filter messages based on source address

Allow all (default) | Allow only

Filter messages based on source address are:

- `Allow only` — Specify a single source address.
- `Allow all` — Accepts messages from any source address. This option is the default.

Programmatic Use

`SrcAddrFilter`
`SrcAddress`

Destination Address Filter — Filter out message based on destination address

`global and node specific (default) | global only | node specific only`

Filter out a message based on the destination address:

- `global only` — Receive only broadcast messages.
- `node specific only` — Receive only messages addressed to this node.
- `global and node specific` — Receive all broadcast and node-addressed messages. This option is the default.

Programmatic Use

`DestAddrFilter`

Sample time — Simulation refresh rate

`-1 (default) | double`

The simulation refresh rate. Specify the sampling time of the block during simulation. This value defines the frequency at which the J1939 Receive updates its output ports. If the block is inside a triggered subsystem or inherits a sample time, specify a value of `-1`. You can also specify a MATLAB variable for sample time. The default value is `0.01` seconds. For information about simulation sample timing, see “What Is Sample Time?” (Simulink).

Programmatic Use

`SampleTime`

Output New Message Received status — Create a Msg Status output

`0 (default) | 1`

Select this check box to create a Msg Status output **Msg Status** output port. Its output signal indicates a new incoming message, showing `1` for a new message received, or `0` when there is no new message.

Programmatic Use

`outputNew`

See Also

J1939 CAN Transport Layer | J1939 Network Configuration | J1939 Node Configuration | J1939 Transmit

Topics

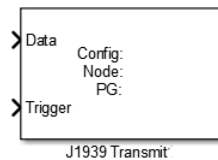
“Basic J1939 Communication over CAN” on page 16-94

Introduced in R2015b

J1939 Transmit

Transmit J1939 message

Library: Simulink Real-Time / J1939 Communication
Vehicle Network Toolbox / J1939 Communication



Description

The J1939 Transmit block transmits a J1939 message. The J1939 database file defines the nodes and parameter groups. You specify the J1939 database by using the J1939 Network Configuration block.

To use this block, you must have a license for both Vehicle Network Toolbox and Simulink software.

The J1939 communication blocks support the use of Simulink accelerator and rapid accelerator modes. You can speed up the execution of Simulink models by using these modes. For more information on these modes, see “Design Your Model for Effective Acceleration” (Simulink).

The J1939 communication blocks also support code generation that have limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For the current list of supported compilers, see Supported and Compatible Compilers.

Ports

Input

Data — Input data

signal

Depending on the J1939 parameter group and signals defined in the J1939 database file, the block can have multiple data input ports.

Trigger — Enables the transmission of message

0 | 1

Enables the transmission of the message for that sample. A value of 1 specifies to send, a value of 0 specifies not to send.

Parameters

Config name — Name of the J1939 network configuration to associate

ConfigX (default) | character vector

The name of the J1939 network configuration to associate with. This is used to access the corresponding J1939 database. Only the nodes defined in the model and associated with the specified J1939 network configuration appear in the Node name list. The option shows none if no J1939 network configuration is found.

Programmatic Use

ConfigName

Node name — Name of the J1939 node

NodeX (default) | character vector

The name of the J1939 node. The drop-down list includes all the nodes in the model, both custom nodes and nodes from the database.

Programmatic Use

NodeName

Parameter Group — Group number (PGN) and name

int8

The parameter group number (PGN) and name from the database. The contents of this list vary depending on the parameter groups that the J1939 database file specifies. The default is the first parameter group for the selected node.

If you change any parameter group settings within your J1939 database file, you must then open the J1939 Transmit block dialog box and select the same **Parameter Group**, then click **OK** or **Apply** to update the parameter group information in the block.

Programmatic Use

PGName

Signals — Signals defined in parameter group

array of character vectors

Signals defined in the parameter group. The **Min** and **Max** settings are read from the database, but by default the block does not clip signal values that exceed this range.

Programmatic Use

SignalInfo
 NSignals
 StartBits
 SignalSizes
 ByteOrders
 DataTypes
 MultiplexTypes
 MultiplexValuses
 Factors
 Offsets
 Minimums
 Maximums
 Units
 SPN
 Comment

PG Priority — Priority of the parameter group

int8

Priority of the parameter group, read from the database. This priority setting resolves clashes of multiple parameter groups transmitting on the same bus at the same time. If a conflict occurs, the

priority group with lower priority (higher value) will refrain from transmitting. The value can range from 0 (highest priority) to 7 (lowest).

Programmatic Use

PGPriority

Destination Address — Name of the destination node

int8

The name of the destination node. The default is the first node defined in the database, otherwise Custom.

For a custom destination address, you can specify 0-253 for the address of the destination node. For broadcasting to all nodes, use the Custom **Destination Address** setting with an address of 255.

Programmatic Use

DestAddrID

See Also

J1939 CAN Transport Layer | J1939 Network Configuration | J1939 Node Configuration | J1939 Receive

Topics

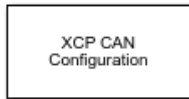
“Basic J1939 Communication over CAN” on page 16-94

Introduced in R2015b

XCP CAN Configuration

Configure XCP slave connection

Library: Simulink Real-Time / XCP / CAN
Vehicle Network Toolbox / XCP Communication / CAN



Description

The XCP CAN Configuration block uses the parameters specified in the A2L file and the ASAP2 database to establish an XCP slave connection.

Before you acquire or stimulate data, specify the A2L file to use in your XCP CAN Configuration. Use one XCP CAN Configuration to configure one slave connection for data acquisition or stimulation. If you add XCP CAN Data Acquisition and XCP CAN Data Stimulation blocks, your model checks to see if there is a corresponding XCP CAN Configuration block. If there is no corresponding XCP CAN Configuration block, the model prompts you to add one.

The XCP CAN communication blocks support Simulink accelerator mode and rapid accelerator mode. You can speed up the execution of Simulink models by using these modes. For more information about these simulation modes, see “Design Your Model for Effective Acceleration” (Simulink).

The XCP communication blocks support code generation with limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For more information, see Supported and Compatible Compilers.

Parameters

Config name — Specify XCP CAN session name

'CAN_Config1' (default)

Specify a unique name for your XCP CAN session.

Programmatic Use

SlaveName

A2L File — Select an A2L file

file name

Click **Browse** to select an A2L file for your XCP CAN session.

Programmatic Use

A2LFile

Enable seed/key security — Select that key required to establish connection

'off'

Select this option if your slave requires a secure key to establish connection. Select a file that contains the seed/key definition to enable security.

Programmatic Use

EnableSecurity

File (*.DLL) – Select file for seed and key security

file name

If you select **Enable seed/key security** (EnableSecurity), this field is enabled. Click **Browse** to select the file that contains the seed and key security algorithm that unlocks an XCP slave module. This parameter is available in Windows Desktop Simulation for Vehicle Network Toolbox.

Programmatic Use

SeedKeyLib

Output connection status – Display connection status

'off'

Select this option to display the status of the connection to the slave module. Selecting this option adds a new output port.

Programmatic Use

EnableStatus

See Also**Blocks**

XCP CAN Data Acquisition | XCP CAN Data Stimulation | XCP CAN Transport Layer

Introduced in R2013a

XCP CAN Data Acquisition

Acquire selected measurements from configured slave connection

Library: Simulink Real-Time / XCP / CAN
Vehicle Network Toolbox / XCP Communication / CAN



Description

The XCP CAN Data Acquisition block acquires data from the configured slave connection based on measurements that you select. The block uses the XCP CAN transport layer to obtain raw data for the selected measurements at the specified simulation time step. Configure your XCP connection and use the XCP CAN Data Acquisition block to select your event and measurements for the configured slave connection. The block displays the selected measurements as output ports.

The XCP communication blocks support the use of Simulink accelerator mode and rapid accelerator mode. You can speed up the execution of Simulink models by using these modes. For more information on these simulation modes, see “Design Your Model for Effective Acceleration” (Simulink).

The XCP communication blocks support code generation with limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For more information, see Supported and Compatible Compilers.

Parameters

Config name — Specify XCP CAN session name

select from list

Select the name of the XCP configuration that you want to use. This list displays all available names specified in the XCP CAN Configuration blocks in the model. Selecting a configuration displays events and measurements available in the A2L file of this configuration.

Note You can acquire measurements for only one event by using an XCP CAN Data Acquisition block. Use one block for each event whose measurements you want to acquire.

Programmatic Use

SlaveName

Event name — Select an event

select from list


Select an event from the available list of events. The XCP CAN Configuration block uses the specified A2L file to populate the events list.

Programmatic Use

EventName

All Measurements – List all measurements available for event

measurements list

This list displays all measurements available for the selected event. Select the measurement that you want to use and click the add button,  to add it to the selected measurements. On your keyboard, press the **Ctrl** key to select multiple measurements.

In the Block Parameters dialog box, type the name of the measurement you want to use in the **Search** box. The **All Measurements** list displays a list of all matching names. Click the x to clear your search.


Programmatic Use

AllMeasurements

Selected Measurements – List selected measurements

measurement names

This list displays selected measurements. To remove a measurement from this list, select the measurement and click the remove button, .

In the Block Parameters dialog box, use the toggle buttons  to reorder the selected measurements.

Programmatic Use

SelectedMeasurements

Force Datatypes and Allow Non-Scalar – Set the port data type according to the type definition in the A2L file

'off' (default) | 'on'

This parameter enables support for XCP data types and dimensions as defined in the ASAP2 standard. When the parameter value is set to 'on', the block:

- Sets the port data type according to the type definition in the A2L file
- Supports up to three-dimensional XCP measurements in Simulink

These ASAP2 data types are supported by corresponding Simulink port data types:

- SBYTE
- UWORD
- SWORD
- ULONG
- SLONG
- A_UINT64
- A_INT64

- FLOAT32_IEEE
- FLOAT64_IEEE

The dimension support in the block accommodates the different treatment of matrices by MATLAB and the ECU. The MATLAB default operation treats matrices as row-major matrices. An XCP measurement can have a LAYOUT as COLUMN_DIR or ROW_DIR . If a matrix measurement is COLUMN_DIR, the blocks rearrange the measurement in memory and ensure that the matrix (row X, col Y) in MATLAB refers to the same entry as (row X, col Y) on the ECU. The rearrangement causes matrix entries that are contiguous on the ECU to be noncontiguous in MATLAB and Simulink.

Programmatic Use

ForceDatatypes

DAQ List Priority — Specify a priority value for slave device driver

priority value

Specify a priority value as an integer from 0 to 255 for the slave device driver to prioritize transmission of data packets. The slave can accumulate XCP packets for lower priority DAQ lists before transmission to the master. A value of 255 has the highest priority. The SET_DAQ_LIST_MODE command communicates the **DAQ List Priority** value from master to slave. This communication method differs from the specification of the Event Channel Priority property, which comes from the A2L file.

Programmatic Use

DAQPriority

Sample time — Specify sampling time of block

0.01 (default)

Specify the sampling time of the block during simulation, which is the simulation time. This value defines the frequency at which the XCP CAN Data Acquisition block runs during simulation. If the block is inside a triggered subsystem or is to inherit sample time, you can specify -1 as your sample time. You can also specify a MATLAB variable for sample time. The default value is 0.01 (in seconds).

Programmatic Use

SampleTime

Enable Timestamp — Enable reading timestamp from incoming DTO packets

off (default) | on

When the Timestamp is enabled, the block reads the timestamp from incoming DTO packets and outputs the timestamp to Simulink. The **Enable Timestamp** check box appears in the block parameters dialog box when the parameter is supported in the A2L file.

Programmatic Use

EnableTimestamp

See Also

Blocks

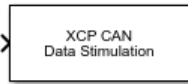
XCP CAN Configuration | XCP CAN Data Stimulation | XCP CAN Transport Layer

Introduced in R2013a

XCP CAN Data Stimulation

Perform data stimulation on selected measurements

Library: Simulink Real-Time / XCP / CAN
Vehicle Network Toolbox / XCP Communication / CAN



Description

The XCP CAN Data Stimulation block sends data to the selected slave connection for the selected event measurements. The block uses the XCP CAN transport layer to output raw data for the selected measurements at the specified stimulation time step. Configure your XCP session and use the XCP CAN Data Stimulation block to select your event and measurements on the configured slave connection. The block displays the selected measurements as input ports.

The XCP communication blocks support Simulink accelerator mode and rapid accelerator mode. You can speed up the execution of Simulink models by using these modes. For more information about these simulation modes, see “Design Your Model for Effective Acceleration” (Simulink).

The XCP communication blocks support code generation with limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For more information, see Supported and Compatible Compilers.

Parameters

Config name — Specify XCP CAN session name

select from list

Select the name of XCP configuration that you want to use. This list displays all available names specified in the available XCP CAN Configuration blocks in the model. Selecting a configuration displays events and measurements available in the A2L file of this configuration. You can stimulate measurements for only one event by using an XCP CAN Data Stimulation block. Use one block for each event whose measurements you want to stimulate.

Programmatic Use

SlaveName

Event name — Select an event

select from list

Select an event from the event list. The XCP CAN Configuration block uses the specified A2L file to populate the events list. The block is configured with the corresponding event number from the A2L.


The event time cycle does not control transmission of stimulation packets. The block stimulates each time it executes. For use in Simulink simulation, consider enabling simulation pacing to avoid free-running stimulation.

Programmatic Use

EventName

All Measurements — List all measurements available for event

measurements list

This list displays all measurements available for the selected event. Select the measurement that you want to use and click the add button,  to move it to the selected measurements. Hold the Ctrl key on your keyboard to select multiple measurements.


In the block parameters dialog box, type the name of the measurement you want to use in the **Search** box. The **All Measurements** lists displays a list of all matching names. Click the x to clear your search.


Programmatic Use

AllMeasurements

Selected Measurements — List selected measurements

measurement names

This list displays your selected measurements. To remove a measurement from this list, select the measurement and click the remove button, .

In the **Block Parameters** dialog box, use the toggle buttons  to reorder the selected measurements.

Programmatic Use

SelectedMeasurements

Force Datatypes and Allow Non-Scalar — Set the port data type according to the type definition in the A2L file

'off' (default) | 'on'

This parameter enables support for XCP data types and dimensions as defined in the ASAP2 standard. When the parameter value is set to 'on', the block:

- Sets the port data type according to the type definition in the A2L file
- Supports up to three-dimensional XCP measurements in Simulink

These ASAP2 data types are supported by corresponding Simulink port data types. SBYTE, UWORD, SWORD, ULONG, SLONG , A_UINT64, A_INT64, FLOAT32_IEEE, and FLOAT64_IEEE.

The dimension support in the block accommodates the different treatment of matrices by MATLAB and the ECU. MATLAB default operation treats matrices as row-major. An XCP measurement can have LAYOUT as COLUMN_DIR or ROW_DIR . If a matrix measurement is COLUMN_DIR, the blocks rearranges the measurement in memory and ensures that the matrix (row X, col Y) in MATLAB refers to the same entry as (row X, col Y) on the ECU. The rearrangement causes matrix entries that are contiguous on the ECU to be noncontiguous in MATLAB and Simulink.

Programmatic Use

ForceDatatypes

Enable Timestamp — Enable sending Simulink timestamp in STIM DTO packets

off (default) | on

When the Timestamp is enabled, the block inputs a timestamp from Simulink and sends the timestamp in the STIM DTO packets. The **Enable Timestamp** check box appears in the block parameters dialog box when the parameter is supported in the A2L file.

Programmatic Use

EnableTimestamp

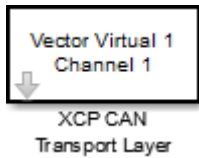
See Also**Blocks**

XCP CAN Configuration | XCP CAN Data Acquisition | XCP CAN Transport Layer

Introduced in R2013a

XCP CAN Transport Layer

Transport XCP messages via CAN



Library

Vehicle Network Toolbox: CAN Communication

Vehicle Network Toolbox: XCP Communication

Description

The XCP CAN Transport Layer subsystem uses the specified device to transport and receive XCP messages.

Use this block with an XCP Data Acquisition block to acquire and analyze specific XCP messages. Use this block with an XCP Data Stimulation block to send specific information to modules.

Other Supported Features

The XCP communication blocks support the use of Simulink Accelerator and Rapid Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information on this feature, see the Simulink documentation.

The XCP communication blocks support code generation with limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For more information, see Supported and Compatible Compilers.

Parameters

Device

+

Select a CAN device from the list of devices available to your system.

Bus speed

Set the bus speed property for the selected device. The default bus speed is the default assigned by the selected device.

Sample time

Specify the sampling time of the block during simulation, which is the simulation time as described by the Simulink documentation. This value defines the frequency at which the XCP CAN Transport Layer subsystem and the underlying blocks run during simulation. If the block is inside a triggered subsystem or to inherit sample time, you can specify -1 as your sample time. You can also specify a MATLAB variable for sample time. The default value is 0.01 (in seconds).

Extended Capabilities

C/C++ Code Generation

Generate C and C++ code using Simulink® Coder™.

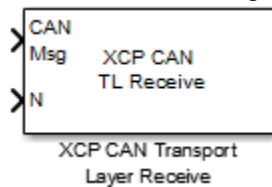
See Also

[XCP CAN Configuration](#) | [XCP CAN Data Acquisition](#) | [XCP CAN Data Stimulation](#)

Introduced in R2013a

XCP CAN Transport Layer Receive

Receive XCP messages via CAN device



Description

The XCP CAN Transport Layer Receive block receives XCP messages from a CAN Receive block.

Other Supported Features

The XCP communication blocks support the use of Simulink Accelerator and Rapid Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information on this feature, see the Simulink documentation.

The XCP communication blocks support code generation with limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For more information, see Supported and Compatible Compilers.

Parameters

Sample time

Specify the sampling time of the block during simulation, which is the simulation time as described by the Simulink documentation. This value defines the frequency at which the XCP CAN Transport Layer Receive block runs during simulation. If the block is inside a triggered subsystem or to inherit sample time, you can specify -1 as your sample time. You can also specify a MATLAB variable for sample time. The default value is -1 (in seconds).

See Also

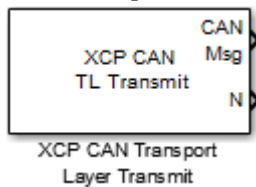
Blocks

CAN Receive | XCP CAN Transport Layer | XCP CAN Transport Layer Transmit

Introduced in R2013a

XCP CAN Transport Layer Transmit

Transmit queued XCP messages



Description

The XCP CAN Transport Layer Transmit block connects to a CAN Transmit block to transmit queued XCP messages.

Other Supported Features

The XCP communication blocks support the use of Simulink Accelerator and Rapid Accelerator mode. Using this feature, you can speed up the execution of Simulink models. For more information on this feature, see the Simulink documentation.

The XCP communication blocks support code generation with limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For more information, see Supported and Compatible Compilers.

Parameters

Maximum number of messages

Enter the maximum number of messages the block can transmit. Value must be a positive integer.

Sample time

Specify the sampling time of the block during simulation, which is the simulation time as described by the Simulink documentation. This value defines the frequency at which the XCP CAN Transport Layer block runs during simulation. If the block is inside a triggered subsystem or to inherit sample time, you can specify -1 as your sample time. You can also specify a MATLAB variable for sample time. The default value is 0.01 (in seconds).

See Also

Blocks

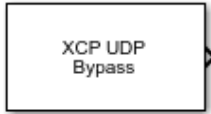
CAN Transmit | XCP CAN Transport Layer | XCP CAN Transport Layer Receive

Introduced in R2013a

XCP UDP Bypass

Connect the function-call output to a function-call subsystem

Library: Simulink Real-Time / XCP / UDP



Description

The XCP UDP Bypass block connects the function-call output to a function-call subsystem containing one data acquisition list. The block issues a function-call when the downstream data acquisition list has new data available.

Consider the downstream function-call subsystem as a bypass task:

In Simulink Real-Time, the bypass task is executed asynchronously with the assigned task priority.

In Simulink, the block checks for data acquisition data periodically at the assigned sample rate and executes the bypass task accordingly.

Ports

Output

Function-call — Function call for bypass

function call

Connects the function-call output to a function-call subsystem containing one data acquisition list.

Parameters

Task Priority — Task priority in QNX Neutrino scheduler

191 (default) | int

Select the task priority for the QNX Neutrino scheduler.

Programmatic Use

taskpri

Sample Time — Sample time

-1 (default) | double

Select the sample time.

Programmatic Use

sampletime

See Also

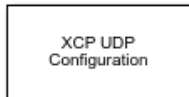
XCP UDP Configuration | XCP UDP Data Acquisition | XCP UDP Data Stimulation

Introduced in R2020b

XCP UDP Configuration

Configure XCP UDP slave connection

Library: Simulink Real-Time / XCP / UDP
Vehicle Network Toolbox / XCP Communication / UDP



Description

The XCP UDP Configuration block uses the parameters specified in the A2L file and the ASAP2 database to establish an XCP slave connection.

Before you acquire or stimulate data, specify the A2L file to use in your XCP UDP Configuration. Use one XCP UDP Configuration to configure one slave connection for data acquisition or stimulation. If you add XCP UDP Data Acquisition and XCP UDP Data Stimulation blocks, your model checks to see if there is a corresponding XCP UDP Configuration block. If there is no corresponding XCP CAN Configuration block, the model prompts you to add one.

The XCP UDP communication blocks support Simulink accelerator mode and rapid accelerator mode. You can speed up the execution of Simulink models by using these modes. For more information about these simulation modes, see “Design Your Model for Effective Acceleration” (Simulink).

The XCP communication blocks support code generation with limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For more information, see Supported and Compatible Compilers.

Parameters

Config name — Specify XCP UDP session name

'UDP_Config1' (default)

Specify a unique name for your XCP session.

Programmatic Use

SlaveName

A2L File — Select an A2L file

file name

Click **Browse** to select an A2L file for your XCP session.

Programmatic Use

A2LFile

Enable seed/key security — Select that key required to establish connection

'off'

Select this option if your slave requires a secure key to establish connection. Select a file that contains the seed/key definition to enable security.

Programmatic Use

EnableSecurity

File (*.DLL) – Select file for seed and key security

file name

If you select **Enable seed/key security**, this field is enabled. Click **Browse** to select the file that contains the seed and key security algorithm that unlocks an XCP slave module. This parameter is available in Windows Desktop Simulation for Vehicle Network Toolbox.

Programmatic Use

SeedKeyLib

Output connection status – Display connection status

'off'

Select this option to display the status of the connection to the slave module. Selecting this option adds a new output port.

Programmatic Use

EnableStatus

Disable CTR error detection – Disable CTR error detection scheme

'on' (default) | 'off'

To detect missing packets, the block can check the counter value in each XCP packet header. When 'on', counter error detection for packet headers is disabled. When 'off', the counter **Error detection scheme** is enabled.

Programmatic Use

HeaderErrDet

Error detection scheme – Select CTR error detection scheme

One counter for all CT0s and DT0s (default) | Separate counters for (RES,ERR,EV,SERV) and (DAQ) | Separate counters for (RES,ERR), (EV,SERV) and (DAQ)

To detect missing packets, the block can check the counter value in each XCP packet header and apply an error-detection scheme.

Programmatic Use

CTRScheme

Sample time – Sample time of block

-1 (default) | numeric

Enter the base sample time or a multiple of the base sample time. -1 means that sample time is inherited.

Programmatic Use**Block Parameter:** SampleTime**Local IP Address — Maser IP address**

X.X.X.X

Enter the IP address to which you want to connect.

Programmatic Use

LocalAddress

Local Port — Master IP port

1–65535

The combination of **Local IP address** and **Local port** must be unique.

Programmatic Use

LocalPort

See Also**Blocks**

XCP UDP Bypass | XCP UDP Data Acquisition | XCP UDP Data Stimulation

Introduced in R2019a

XCP UDP Data Acquisition

Acquire selected measurements from configured slave connection

Library: Simulink Real-Time / XCP / UDP
Vehicle Network Toolbox / XCP Communication / UDP



Description

The XCP UDP Data Acquisition block acquires data from the configured slave connection based on the measurements that you select. The block uses the XCP UDP transport layer to obtain raw data for the selected measurements at the specified simulation time step. Configure your XCP connection and use the XCP UDP Data Acquisition block to select your event and measurements for the configured slave connection. The block displays the selected measurements as output ports.

The XCP communication blocks support the use of Simulink accelerator mode and rapid accelerator mode. You can speed up the execution of Simulink models by using these modes. For more information on these simulation modes, see “Design Your Model for Effective Acceleration” (Simulink).

The XCP communication blocks support code generation with limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For more information, see Supported and Compatible Compilers.

Parameters

Config name — Specify XCP UDP session name

select from list

Select the name of XCP configuration that you want to use. This list displays all available names specified in the XCP UDP Configuration blocks in the model. Selecting a configuration displays events and measurements available in the A2L file of this configuration. You can acquire measurements for only one event by using an XCP UDP Data Acquisition block. Use one block for each event whose measurements you want to acquire.

Programmatic Use

SlaveName

Event name — Select an event

select from list


Select an event from the available list of events. The XCP UDP Configuration block uses the specified A2L file to populate the events list.

Programmatic Use

EventName

All Measurements – List all measurements available for event

measurements list

This list displays all measurements available for the selected event. Select the measurement that you want to use and click the add button,  to add it to the selected measurements. Hold the Ctrl key on your keyboard to select multiple measurements.

In the **Block Parameters** dialog box, type the name of the measurement you want to use in the **Search** box. The **All Measurements** lists displays a list of all matching names. Click the x to clear your search.



Programmatic Use

AllMeasurements

Selected Measurements – List selected measurements

measurement names

This list displays selected measurements. To remove a measurement from this list, select the measurement and click the remove button, .

In the **Block Parameters** dialog box, use the toggle buttons   to reorder the selected measurements.

Programmatic Use

SelectedMeasurements

Force Datatypes and Allow Non-Scalar – Set the port data type according to the type definition in the A2L file

'off' (default) | 'on'

This parameter enables support for XCP data types and dimensions as defined in the ASAP2 standard. When the parameter value is set to 'on', the block:

- Sets the port data type according to the type definition in the A2L file
- Supports up to three-dimensional XCP measurements in Simulink

These ASAP2 data types are supported by corresponding Simulink port data types. SBYTE, UWORD, SWORD, ULONG, SLONG , A_UINT64, A_INT64, FLOAT32_IEEE, and FLOAT64_IEEE.

The dimension support in the block accommodates the different treatment of matrices by MATLAB and the ECU. MATLAB default operation treats matrices as row-major. An XCP measurement can have LAYOUT as COLUMN_DIR or ROW_DIR . If a matrix measurement is COLUMN_DIR, the blocks rearranges the measurement in memory and ensures that the matrix (row X, col Y) in MATLAB refers to the same entry as (row X, col Y) on the ECU. The rearrangement causes matrix entries that are contiguous on the ECU to be noncontiguous in MATLAB and Simulink.

Programmatic Use

ForceDatatypes

DAQ List Priority – Specify a priority value for slave device driver

priority value

Specify a priority value as an integer from 0 to 255 for the slave device driver to prioritize transmission of data packets. The slave can accumulate XCP packets for lower priority DAQ lists before transmission to the master. A value of 255 has the highest priority. The SET_DAQ_LIST_MODE command communicates the **DAQ List Priority** value from master to slave. This communication method differs from the specification of the Event Channel Priority property, which comes from the A2L file.

Programmatic Use`DAQPriority`**Sample time — Specify sampling time of block**`0.01 (default)`

Specify the sampling time of the block during simulation, which is the simulation time. This value defines the frequency at which the XCP UDP Data Acquisition block runs during simulation. If the block is inside a triggered subsystem or is to inherit sample time, you can specify -1 as your sample time. You can also specify a MATLAB variable for sample time. The default value is 0.01 (in seconds).

Programmatic Use`SampleTime`**Enable Timestamp — Enable reading timestamp from incoming DTO packets**`off (default) | on`

When the Timestamp is enabled, the block reads the timestamp from incoming DTO packets and outputs the timestamp to Simulink. The **Enable Timestamp** check box appears in the block parameters dialog box when the parameter is supported in the A2L file.

Programmatic Use`EnableTimestamp`**See Also****Blocks**

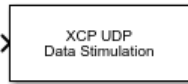
XCP UDP Configuration | XCP UDP Bypass | XCP UDP Data Stimulation

Introduced in R2019a

XCP UDP Data Stimulation

Perform data stimulation on selected measurements

Library: Simulink Real-Time / XCP / UDP
Vehicle Network Toolbox / XCP Communication / UDP



Description

The XCP UDP Data Stimulation block sends data to the selected slave connection for the event measurements that you select. The block uses the XCP UDP transport layer to output raw data for the selected measurements at the specified stimulation time step. Configure your XCP session and use the XCP UDP Data Stimulation block to select your event and measurements on the configured slave connection. The block displays the selected measurements as input ports.

The XCP communication blocks support Simulink accelerator mode and rapid accelerator mode. You can speed up the execution of Simulink models by using these modes. For more information about these simulation modes, see “Design Your Model for Effective Acceleration” (Simulink).

The XCP communication blocks support code generation with limited deployment capabilities. Code generation requires a C++ compiler that is compatible with the code generation target. For more information, see Supported and Compatible Compilers.

Parameters

Config name — Specify XCP UDP session name

select from list

Select the name of XCP configuration that you want to use. This list displays all available names specified in the available XCP UDP Configuration blocks in the model. Selecting a configuration displays events and measurements available in the A2L file of this configuration. You can stimulate measurements for only one event by using an XCP UDP Data Stimulation block. Use one block for each event whose measurements you want to stimulate.

Programmatic Use

SlaveName

Event name — Select an event

select from list

Select an event from the event list. The XCP UDP Configuration block uses the specified A2L file to populate the events list. The block is configured with the corresponding event number from the A2L.


The event time cycle does not control transmission of stimulation packets. The block stimulates each time it executes. For use in Simulink simulation, consider enabling simulation pacing to avoid free-running stimulation.

Programmatic Use

EventName

All Measurements — List all measurements available for event

measurements list

This list displays all measurements available for the selected event. Select the measurement that you want to use and click the add button,  to move it to the selected measurements. Hold the Ctrl key on your keyboard to select multiple measurements.


In the block parameters dialog box, type the name of the measurement you want to use. The **All Measurements** lists displays a list of all matching names. Click the x to clear your search.



Programmatic Use

AllMeasurements

Selected Measurements — List selected measurements

measurement names

This list displays your selected measurements. To remove a measurement from this list, select the measurement and click the remove button, .

In the **Block Parameters** dialog box, use the toggle buttons   to reorder the selected measurements.

Programmatic Use

SelectedMeasurements

Force Datatypes and Allow Non-Scalar — Set the port data type according to the type definition in the A2L file

'off' (default) | 'on'

This parameter enables support for XCP data types and dimensions as defined in the ASAP2 standard. When the parameter value is set to 'on', the block:

- Sets the port data type according to the type definition in the A2L file
- Supports up to three-dimensional XCP measurements in Simulink

These ASAP2 data types are supported by corresponding Simulink port data types. SBYTE, UWORD, SWORD, ULONG, SLONG , A_UINT64, A_INT64, FLOAT32_IEEE, and FLOAT64_IEEE.

The dimension support in the block accommodates the different treatment of matrices by MATLAB and the ECU. MATLAB default operation treats matrices as row-major. An XCP measurement can have LAYOUT as COLUMN_DIR or ROW_DIR . If a matrix measurement is COLUMN_DIR, the blocks rearranges the measurement in memory and ensures that the matrix (row X, col Y) in MATLAB refers to the same entry as (row X, col Y) on the ECU. The rearrangement causes matrix entries that are contiguous on the ECU to be noncontiguous in MATLAB and Simulink.

Programmatic Use

ForceDatatypes

Enable Timestamp — Enable sending Simulink timestamp in STIM DTO packets

off (default) | on

When the Timestamp is enabled, the block inputs a timestamp from Simulink and sends the timestamp in the STIM DTO packets. The **Enable Timestamp** check box appears in the block parameters dialog box when the parameter is supported in the A2L file.

Programmatic Use

EnableTimestamp

See Also**Blocks**[XCP UDP Configuration](#) | [XCP UDP Bypass](#) | [XCP UDP Data Acquisition](#)**Introduced in R2019a**

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- “CAN Message Reception Callback Functions” on page 16-11
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- “Create and Process Messages Using Database Definitions” on page 16-23
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Transmit and Receive CAN Messages

This example shows you how to use CAN channels to transmit and receive CAN messages. It uses MathWorks Virtual CAN channels connected in a loopback configuration.

Create a Receiving Channel

Create a CAN channel to receive messages by specifying the vendor name, device name, and device channel index.

```
rxCh = canChannel('MathWorks', 'Virtual 1', 2);
```

Inspect the Channel

Use the `get` command to obtain more detailed information on all of the channel's properties and their current values.

```
get(rxCh)

    ArbitrationBusSpeed: []
           DataBusSpeed: []
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
InitializationAccess: 1
    InitialTimestamp: [0x0 datetime]
           SilentMode: 0
    TransceiverState: 'N/A'
           BusSpeed: 500000
    NumOfSamples: []
           SJW: []
           TSEG1: []
           TSEG2: []
    BusStatus: 'N/A'
    TransceiverName: 'N/A'
           Database: []
    MessageReceivedFcn: []
MessageReceivedFcnCount: 1
           UserData: []
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'
    MessagesReceived: 0
    MessagesTransmitted: 0
           Running: 0
           Device: 'Virtual 1'
    DeviceChannelIndex: 2
    DeviceSerialNumber: 0
           DeviceVendor: 'MathWorks'
           ProtocolMode: 'CAN'
    MessagesAvailable: 0
```

Start the Channel

Use the `start` command to set the channel online.

```
start(rxCh);
```

Transmit Messages

The example function `generateMsgs` creates CAN messages and transmits them at various periodic rates. It creates traffic on the CAN bus for example purposes and is not part of the Vehicle Network Toolbox™.

```
type generateMsgs
```

```
function generateMsgs()
% generateMsgs Creates and transmits CAN messages for demo purposes.
%
% generateMsgs periodically transmits multiple CAN messages at various
% periodic rates with changing message data.
%
% Copyright 2008-2016 The MathWorks, Inc.

% Create the messages to send using the canMessage function. The
% identifier, an indication of standard or extended type, and the data
% length is given for each message.
msgTx100 = canMessage(100, false, 0);
msgTx200 = canMessage(200, false, 2);
msgTx400 = canMessage(400, false, 4);
msgTx600 = canMessage(600, false, 6);
msgTx800 = canMessage(800, false, 8);

% Create a CAN channel on which to transmit.
txCh = canChannel('MathWorks', 'Virtual 1', 1);

% Register each message on the channel at a specified periodic rate.
transmitPeriodic(txCh, msgTx100, 'On', 0.500);
transmitPeriodic(txCh, msgTx200, 'On', 0.250);
transmitPeriodic(txCh, msgTx400, 'On', 0.125);
transmitPeriodic(txCh, msgTx600, 'On', 0.050);
transmitPeriodic(txCh, msgTx800, 'On', 0.025);

% Start the CAN channel.
start(txCh);

% Run for several seconds incrementing the message data regularly.
for ii = 1:50
    % Increment the message data bytes.
    msgTx200.Data = msgTx200.Data + 1;
    msgTx400.Data = msgTx400.Data + 1;
    msgTx600.Data = msgTx600.Data + 1;
    msgTx800.Data = msgTx800.Data + 1;

    % Wait for a time period.
    pause(0.100);
end

% Stop the CAN channel.
stop(txCh);
end
```

Run the `generateMsgs` function to transmit messages for the example.

```
generateMsgs();
```

Receive Messages

Once `generateMsgs` completes, receive all of the available messages from the channel.

```
rxMsg = receive(rxCh, Inf, 'OutputFormat', 'timetable');
rxMsg(1:25, :)
```

```
ans =
```

```
25x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals	E
0.0059806 sec	100	false	{0x0 char}	{1x0 uint8}	0	{0x0 struct}	fa
0.0059971 sec	200	false	{0x0 char}	{1x2 uint8}	2	{0x0 struct}	fa
0.0060131 sec	400	false	{0x0 char}	{1x4 uint8}	4	{0x0 struct}	fa
0.0060312 sec	600	false	{0x0 char}	{1x6 uint8}	6	{0x0 struct}	fa
0.0060491 sec	800	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}	fa
0.03155 sec	800	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}	fa
0.0059829 sec	600	false	{0x0 char}	{1x6 uint8}	6	{0x0 struct}	fa
0.0060117 sec	800	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}	fa
0.031282 sec	800	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}	fa
0.056611 sec	600	false	{0x0 char}	{1x6 uint8}	6	{0x0 struct}	fa
0.056641 sec	800	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}	fa
0.081397 sec	400	false	{0x0 char}	{1x4 uint8}	4	{0x0 struct}	fa
0.08142 sec	800	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}	fa
0.10546 sec	600	false	{0x0 char}	{1x6 uint8}	6	{0x0 struct}	fa
0.10549 sec	800	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}	fa
0.12995 sec	800	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}	fa
0.15602 sec	600	false	{0x0 char}	{1x6 uint8}	6	{0x0 struct}	fa
0.15604 sec	800	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}	fa
0.18037 sec	800	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}	fa
0.20594 sec	200	false	{0x0 char}	{1x2 uint8}	2	{0x0 struct}	fa
0.20597 sec	400	false	{0x0 char}	{1x4 uint8}	4	{0x0 struct}	fa
0.20599 sec	600	false	{0x0 char}	{1x6 uint8}	6	{0x0 struct}	fa
0.20601 sec	800	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}	fa
0.23031 sec	800	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}	fa
0.25488 sec	600	false	{0x0 char}	{1x6 uint8}	6	{0x0 struct}	fa

Stop the Channel

Use the `stop` command to set the channel offline.

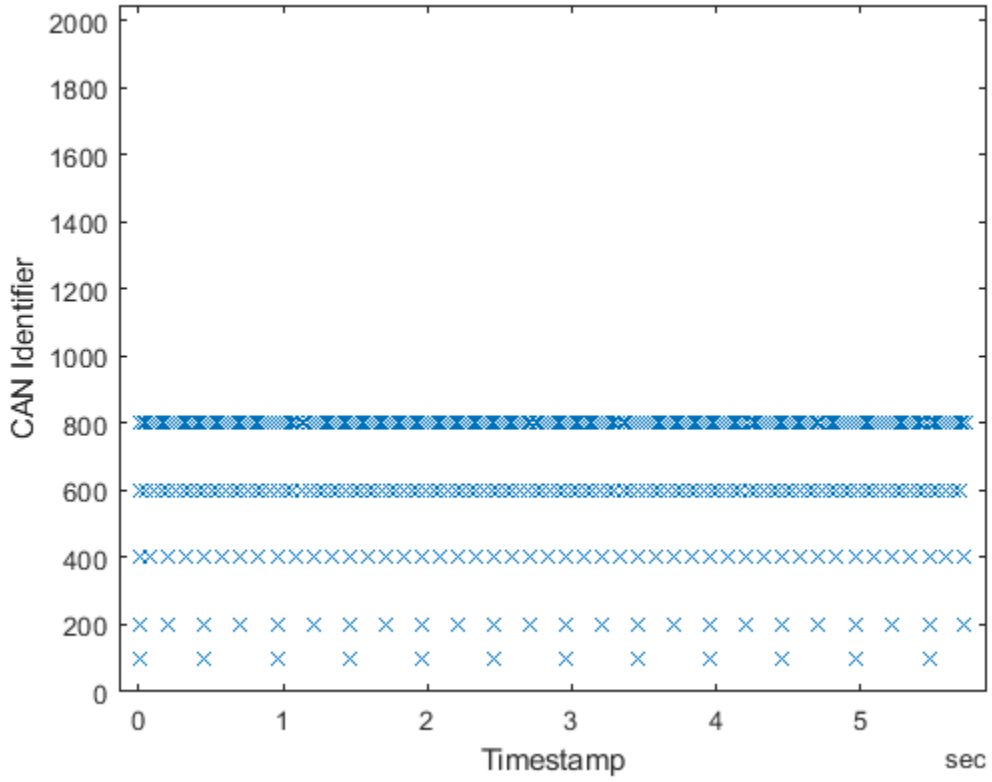
```
stop(rxCh);
```

Analyze Received Messages

MATLAB® provides a powerful environment for performing analysis on CAN messages. The `plot` command can create a scatter plot with message Timestamps and identifiers to provide an overview of when certain messages occurred on the network.

```
plot(rxMsg.Time, rxMsg.ID, 'x')
ylim([0 2047])
```

```
xlabel('Timestamp')  
ylabel('CAN Identifier')
```



Using CAN FD Channels and Messages

This example shows you how to use CAN FD channels to transmit and receive CAN FD messages. It uses MathWorks Virtual CAN channels connected in a loopback configuration.

View Available CAN FD Channels

Use `canFDChannelList` to see all available device channels supporting CAN FD.

```
canFDChannelList
```

```
ans =
```

```
2x6 table
```

Vendor	Device	Channel	DeviceModel	ProtocolMode	SerialNumber
"MathWorks"	"Virtual 1"	1	"Virtual"	"CAN, CAN FD"	"0"
"MathWorks"	"Virtual 1"	2	"Virtual"	"CAN, CAN FD"	"0"

Create Transmitting and Receiving Channels

Create CAN FD channels to send and receive messages by specifying the device details.

```
txCh = canFDChannel('MathWorks', 'Virtual 1', 1)
rxCh = canFDChannel('MathWorks', 'Virtual 1', 2);
```

```
txCh =
```

```
Channel with properties:
```

```
Device Information
```

```
    DeviceVendor: 'MathWorks'
      Device: 'Virtual 1'
DeviceChannelIndex: 1
DeviceSerialNumber: 0
    ProtocolMode: 'CAN FD'
```

```
Status Information
```

```
    Running: 0
MessagesAvailable: 0
MessagesReceived: 0
MessagesTransmitted: 0
InitializationAccess: 1
InitialTimestamp: [0x0 datetime]
FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'
```

```
Bit Timing Information
```

```
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
ReceiveErrorCount: 0
TransmitErrorCount: 0
```

```
ArbitrationBusSpeed: []
DataBusSpeed: []

Other Information
    Database: []
    UserData: []
```

Configure Bus Speed

CAN FD channels require setting of bus speed before going online. Both the arbitration and data phase speeds are configured.

```
configBusSpeed(txCh, 500000, 1000000);
configBusSpeed(rxCh, 500000, 1000000);
```

Open a CAN Database File

CAN database files specify CAN FD message.

```
db = canDatabase('CANFDExample.dbc')
rxCh.Database = db;
```

```
db =
```

```
Database with properties:
```

```
    Name: 'CANFDExample'
    Path: 'C:\TEMP\Bdoc20b_1465442_5924\ib8F4264\1\tp19378308\ex36915890\CANFDExample.dbc'
    Nodes: {}
    NodeInfo: [0x0 struct]
    Messages: {'CANFDMessage'}
    MessageInfo: [1x1 struct]
    Attributes: {2x1 cell}
    AttributeInfo: [2x1 struct]
    UserData: []
```

Start the Channels

Use the start command to set the channels online.

```
start(txCh);
start(rxCh);
```

Create CAN FD Messages

CAN FD messages are created also using canFDMessage.

```
msg1 = canFDMessage(500, false, 12)
msg2 = canFDMessage(1000, false, 24);
msg3 = canFDMessage(1500, false, 64);
```

```
% To engage the bit rate switch capability of CAN FD, set the |BRS| property of the messages.
```

```
msg1.BRS = true;
msg2.BRS = true;
msg3.BRS = true;
```

```
% CAN FD messages can also be created using a database file. The database defines if a message is  
msg4 = canFDMessage(db, 'CANFDMessage')
```

```
msg1 =
```

```
Message with properties:
```

```
Message Identification  
ProtocolMode: 'CAN FD'  
ID: 500  
Extended: 0  
Name: ''
```

```
Data Details  
Timestamp: 0  
Data: [0 0 0 0 0 0 0 0 0 0 0 0]  
Signals: []  
Length: 12  
DLC: 9
```

```
Protocol Flags  
BRS: 0  
ESI: 0  
Error: 0
```

```
Other Information  
Database: []  
UserData: []
```

```
msg4 =
```

```
Message with properties:
```

```
Message Identification  
ProtocolMode: 'CAN FD'  
ID: 1  
Extended: 0  
Name: 'CANFDMessage'
```

```
Data Details  
Timestamp: 0  
Data: [1x48 uint8]  
Signals: []  
Length: 48  
DLC: 14
```

```
Protocol Flags  
BRS: 1  
ESI: 0  
Error: 0
```

```
Other Information  
Database: [1x1 can.Database]  
UserData: []
```

Transmit Messages

Use the transmitting channel to send the messages.

```
transmit(txCh, [msg1 msg2 msg3 msg4])
```

Receive Messages

Receive the messages from the channel. Note that the return type for CAN FD channels is a timetable, containing information specific to CAN FD.

```
rxMsg = receive(rxCh, Inf)
```

```
rxMsg =
```

```
4x12 timetable
```

Time	ID	Extended	Name	ProtocolMode	Data	Length
0.25249 sec	500	false	{0x0 char }	{'CAN FD'}	{1x12 uint8}	12
0.25254 sec	1000	false	{0x0 char }	{'CAN FD'}	{1x24 uint8}	24
0.25257 sec	1500	false	{0x0 char }	{'CAN FD'}	{1x64 uint8}	64
0.25259 sec	1	false	{'CANFDMessage'}	{'CAN FD'}	{1x48 uint8}	48

Stop the Channels

Use the stop command to set the channels offline.

```
stop(txCh);
stop(rxCh);
```


CAN Message Reception Callback Functions

This example shows you how to configure and use a callback function to receive and process messages received from a CAN channel. It uses MathWorks Virtual CAN channels connected in a loopback configuration.

Create a Receiving Channel

Create a CAN channel to receive messages by specifying the vendor name, device name, and device channel index.

```
rxCh = canChannel('MathWorks', 'Virtual 1', 2)
```

```
rxCh =
```

```
Channel with properties:
```

```
Device Information
```

```
    DeviceVendor: 'MathWorks'
        Device: 'Virtual 1'
DeviceChannelIndex: 2
DeviceSerialNumber: 0
    ProtocolMode: 'CAN'
```

```
Status Information
```

```
    Running: 0
MessagesAvailable: 0
MessagesReceived: 0
MessagesTransmitted: 0
InitializationAccess: 1
    InitialTimestamp: [0x0 datetime]
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'
```

```
Channel Information
```

```
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
ReceiveErrorCount: 0
TransmitErrorCount: 0
    BusSpeed: 500000
        SJW: []
        TSEG1: []
        TSEG2: []
    NumOfSamples: []
```

```
Other Information
```

```
    Database: []
    UserData: []
```

Configure the Callback Function

Set a callback function on the channel to trigger via incoming messages.

```
rxCh.MessageReceivedFcn = @receivingFcn;
```

Configure the Message Received Count

Specify an available message threshold to control the quantity of messages required in the channel before the callback function is triggered.

```
rxCh.MessageReceivedFcnCount = 30;
```

Implement the Callback Function

The example callback function receives message from the channel on each execution and plots the CAN identifiers against their timestamps on each execution.

```
type receivingFcn

function receivingFcn(rxCh)
% RECEIVINGFCN A CAN channel message receive callback function.
%
% This is a callback function used to receive CAN message. It receives
% messages from the channel RXCH and plots the result.
%
% Copyright 2009-2016 The MathWorks, Inc.

    % Receive all available messages.
    rxMsg = receive(rxCh, Inf, 'OutputFormat', 'timetable');

    % Plot the signal values against their message timestamps.
    plot(rxMsg.Time, rxMsg.ID, 'x');
    ylim([0 2047])
    xlabel('Timestamp');
    ylabel('CAN Identifier');
    hold all;
end
```

Start the Channel

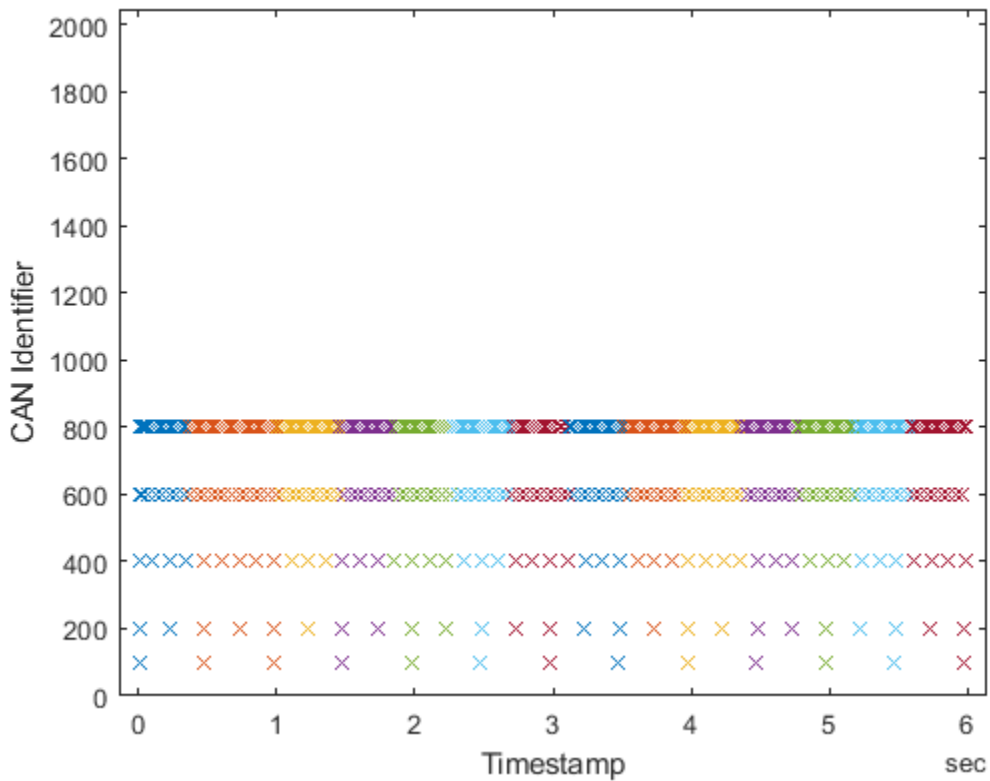
Use the `start` command to set the channel online.

```
start(rxCh);
```

Execute the Callback Function

The example function `generateMsgs` creates CAN messages and transmits them at various periodic rates. It creates traffic on the CAN bus for example purposes and is not part of the Vehicle Network Toolbox™. As the messages are transmitted, the callback function executes each time the message received function count threshold is met.

```
generateMsgs();
```



Inspect the Remaining Messages

Note the remaining messages in the channel. Since the available message count is below the threshold specified earlier, more messages are required to trigger the callback another time.

rxCh

rxCh =

Channel with properties:

Device Information

```

    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 2
    DeviceSerialNumber: 0
    ProtocolMode: 'CAN'

```

Status Information

```

    Running: 1
    MessagesAvailable: 5
    MessagesReceived: 446
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: 25-Aug-2020 13:53:41
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

```

```
Channel Information
  BusStatus: 'N/A'
  SilentMode: 0
  TransceiverName: 'N/A'
  TransceiverState: 'N/A'
  ReceiveErrorCount: 0
  TransmitErrorCount: 0
  BusSpeed: 500000
  SJW: []
  TSEG1: []
  TSEG2: []
  NumOfSamples: []
```

```
Other Information
  Database: []
  UserData: []
```

Stop the Channel

Use the `stop` command to set the channel offline.

```
stop(rxCh);
```

CAN Channel Message Filtering

This example shows you how to use CAN message filters to allow only messages that contain specified identifiers to pass through a channel. It uses MathWorks Virtual CAN channels connected in a loopback configuration.

Create Transmitting and Receiving Channels

One channel will transmit messages the other. Filters are set on the receiving channel.

```
txCh = canChannel('MathWorks', 'Virtual 1', 1);
rxCh = canChannel('MathWorks', 'Virtual 1', 2);
```

Create Messages

These messages are sent to the receiving channel multiple times throughout the example. Note that one of the messages has an extended identifier.

```
txMsgs(1) = canMessage(250, false, 8);
txMsgs(2) = canMessage(500, false, 8);
txMsgs(3) = canMessage(1000, false, 8);
txMsgs(4) = canMessage(1500, true, 8);
txMsgs(5) = canMessage(2000, false, 8);
```

Receive Messages on an Open Filter

Set the channels online, transmit the messages, and receive them. Note that all messages sent were received. The filter settings on a newly created channel are fully open for both standard and extended identifiers.

```
start(rxCh);
start(txCh);
transmit(txCh, txMsgs);
pause(0.5);
rxMsgs1 = receive(rxCh, Inf, 'OutputFormat', 'timetable');
stop(rxCh);
stop(txCh);
```

```
rxMsgs1 =
```

```
5x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
0.0043746 sec	250	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}
0.0044003 sec	500	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}
0.0044355 sec	1000	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}
0.0044592 sec	1500	true	{0x0 char}	{1x8 uint8}	8	{0x0 struct}
0.0044835 sec	2000	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}

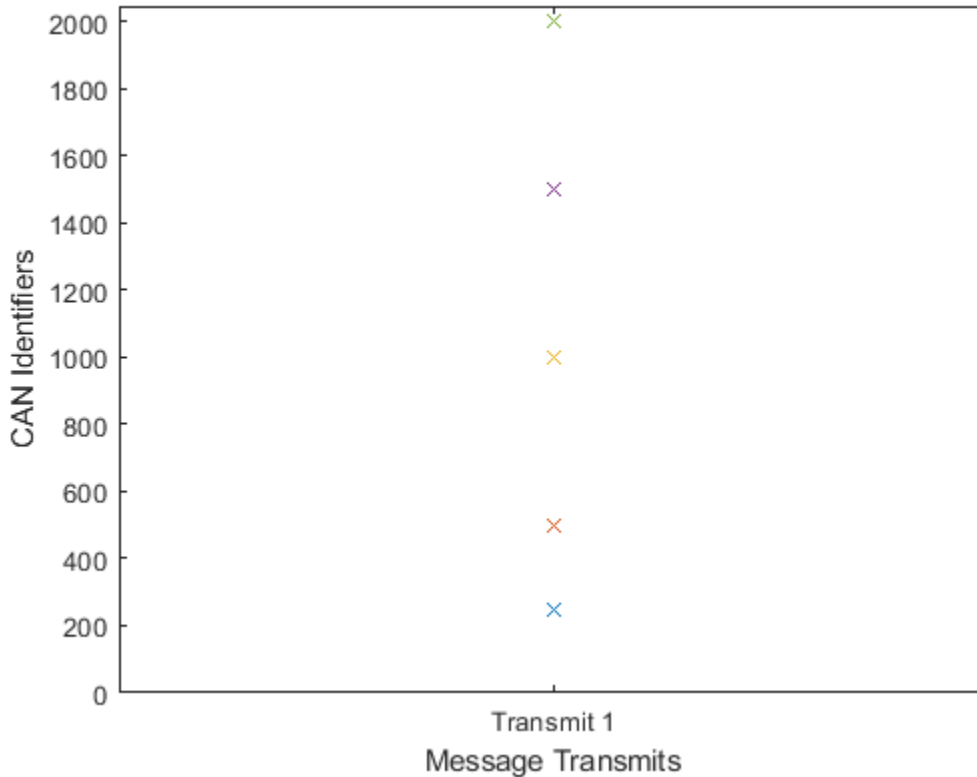
Plot the identifiers of the received messages to see that all messages sent were received by the channel.

```
plot(1, rxMsgs1.ID, 'x')
h_gca = gca;
```

```

h_gca.XTick = 0:1:2;
h_gca.XTickLabel = {'', 'Transmit 1', ''};
axis([0 2 0 2047])
xlabel('Message Transmits')
ylabel('CAN Identifiers')

```



Receive Messages on a Configured Filter

Use the `filterAllowOnly` command to specify messages to receive by CAN identifier and identifier type.

```
filterAllowOnly(rxCh, [500 2000], 'Standard');
```

Display the channel to view the configured state of the message filters.

```
rxCh
```

```
rxCh =
```

```
Channel with properties:
```

```

Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
DeviceChannelIndex: 2
DeviceSerialNumber: 0
ProtocolMode: 'CAN'

```

```

Status Information
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 5
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: 25-Aug-2020 13:54:09
    FilterHistory: 'Standard ID Filter: Allow Only | Extended ID Filter: Allow All'

Channel Information
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    BusSpeed: 500000
    SJW: []
    TSEG1: []
    TSEG2: []
    NumOfSamples: []

Other Information
    Database: []
    UserData: []

```

Transmit the messages again to the receiving channel. Note that fewer messages were received this time.

```

start(rxCh);
start(txCh);
transmit(txCh, txMsgs);
pause(0.5);
rxMsgs2 = receive(rxCh, Inf, 'OutputFormat', 'timetable')
stop(rxCh);
stop(txCh);

```

```
rxMsgs2 =
```

```
3x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
0.0067048 sec	500	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}
0.006743 sec	1500	true	{0x0 char}	{1x8 uint8}	8	{0x0 struct}
0.0067609 sec	2000	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}

Add the new receive data to the plot to see which messages are blocked by the filter. The message with the extended identifier was numerically supposed to be blocked, but it passed the filter because the filter was only configured for standard identifiers.

```

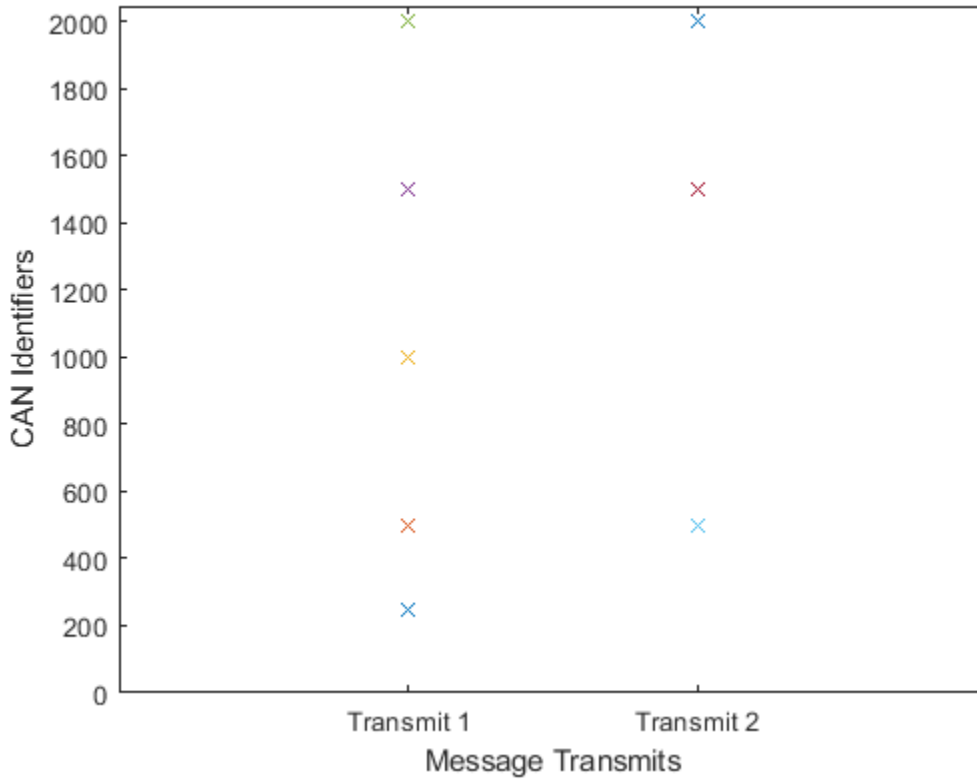
plot(1, rxMsgs1.ID, 'x', 2, rxMsgs2.ID, 'x');
h_gca = gca;

```

```

h_gca.XTick = 0:1:3;
h_gca.XTickLabel = {'', 'Transmit 1', 'Transmit 2', ''};
axis([0 3 0 2047])
xlabel('Message Transmits')
ylabel('CAN Identifiers')

```



Reset the Message Filter

You can reset the message filters to their default open state with the `filterAllowAll` command.

```
filterAllowAll(rxCh, 'Standard');
```

Display the channel to view the configured state of the message filters.

```
rxCh
```

```
rxCh =
```

```
Channel with properties:
```

```

Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
DeviceChannelIndex: 2
DeviceSerialNumber: 0
    ProtocolMode: 'CAN'

```



```

Status Information
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 3
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: 25-Aug-2020 13:54:12
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

Channel Information
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    BusSpeed: 500000
    SJW: []
    TSEG1: []
    TSEG2: []
    NumOfSamples: []

Other Information
    Database: []
    UserData: []

```

Transmit and receive a third time to see that all messages are once again passing through the filter and into the channel.

```

start(rxCh);
start(txCh);
transmit(txCh, txMsgs);
pause(0.5);
rxMsgs3 = receive(rxCh, Inf, 'OutputFormat', 'timetable')
stop(rxCh);
stop(txCh);

```

```
rxMsgs3 =
```

```
5x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
0.0022506 sec	250	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}
0.0022684 sec	500	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}
0.0022855 sec	1000	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}
0.0023053 sec	1500	true	{0x0 char}	{1x8 uint8}	8	{0x0 struct}
0.0023226 sec	2000	false	{0x0 char}	{1x8 uint8}	8	{0x0 struct}

With the new data added to the plot, observe that the first and third transmits are identical as the message filters were fully open in both cases.

```

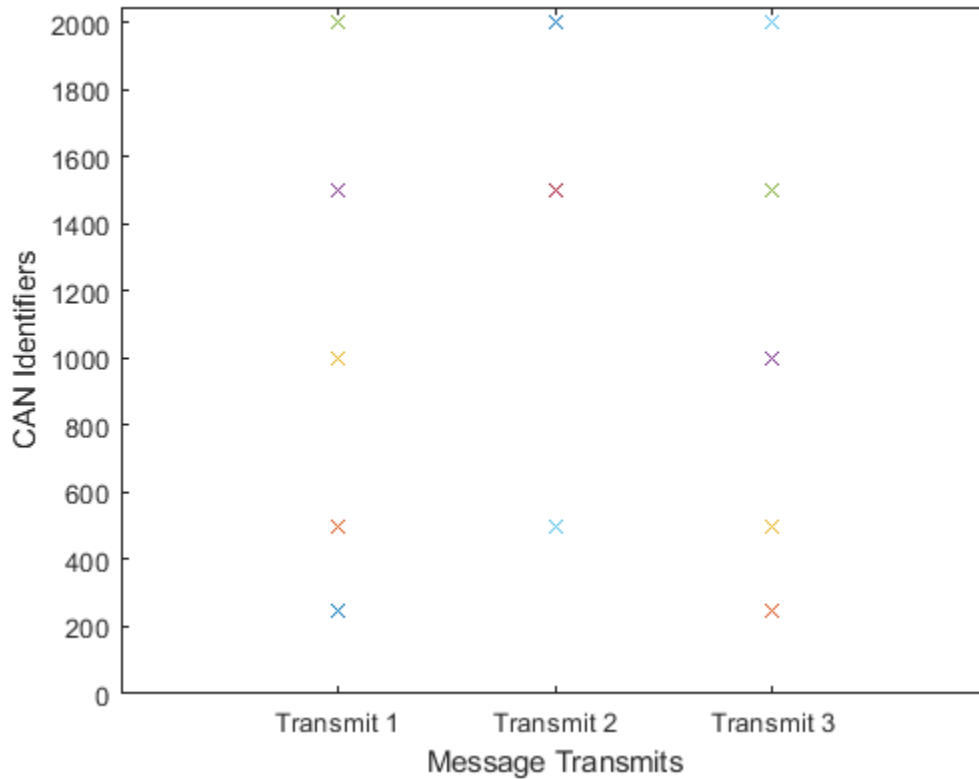
plot(1, rxMsgs1.ID, 'x', 2, rxMsgs2.ID, 'x', 3, rxMsgs3.ID, 'x')
h_gca = gca;

```

```

h_gca.XTick = 0:1:4;
h_gca.XTickLabel = {'', 'Transmit 1', 'Transmit 2', 'Transmit 3', ''};
axis([0 4 0 2047])
xlabel('Message Transmits')
ylabel('CAN Identifiers')

```



Filter Messages By Name

The `filterAllowOnly` command can also reference messages by name when using a CAN database file.

```

db = canDatabase('demoVNT_CANdbFiles.dbc');
rxCh.Database = db;
filterAllowOnly(rxCh, 'EngineMsg');
rxCh

```

```
rxCh =
```

```
Channel with properties:
```

```

Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
DeviceChannelIndex: 2
DeviceSerialNumber: 0
    ProtocolMode: 'CAN'

```

```

Status Information
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 5
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: 25-Aug-2020 13:54:13
    FilterHistory: 'Standard ID Filter: Allow Only | Extended ID Filter: Allow All'

Channel Information
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    BusSpeed: 500000
    SJW: []
    TSEG1: []
    TSEG2: []
    NumOfSamples: []

Other Information
    Database: [1x1 can.Database]
    UserData: []

```

Blocking All Messages of a Specific Type

The `filterBlockAll` command lets you quickly set the filter to block all messages of either standard or extended identifier type.

```
filterBlockAll(rxCh, 'Extended');
rxCh
```

```
rxCh =
```

```
Channel with properties:
```

```

Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 2
    DeviceSerialNumber: 0
    ProtocolMode: 'CAN'

Status Information
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 5
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: 25-Aug-2020 13:54:13
    FilterHistory: 'Standard ID Filter: Allow Only | Extended ID Filter: Block All'

Channel Information
    BusStatus: 'N/A'

```

```
SilentMode: 0
TransceiverName: 'N/A'
TransceiverState: 'N/A'
ReceiveErrorCount: 0
TransmitErrorCount: 0
    BusSpeed: 500000
        SJW: []
        TSEG1: []
        TSEG2: []
    NumOfSamples: []
```

Other Information

```
Database: [1x1 can.Database]
UserData: []
```

Create and Process Messages Using Database Definitions

This example shows you how to create, receive and process messages using information stored in CAN database files. This example uses the CAN database file, `demoVNT_CANdbFiles.dbc`.

Open the Database File

Open the database file and examine the `Messages` property to see the names of all message defined in this database.

```
db = canDatabase('demoVNT_CANdbFiles.dbc')
db.Messages
```

```
db =
```

```
Database with properties:
```

```

    Name: 'demoVNT_CANdbFiles'
    Path: 'C:\TEMP\Bdoc20b_1465442_5924\ib8F4264\1\tp19378308\ex80654288\demoVNT_CANdbFiles.dbc'
    Nodes: {}
    NodeInfo: [0x0 struct]
    Messages: {5x1 cell}
    MessageInfo: [5x1 struct]
    Attributes: {}
    AttributeInfo: [0x0 struct]
    UserData: []

```

```
ans =
```

```
5x1 cell array
```

```

{'DoorControlMsg' }
{'EngineMsg' }
{'SunroofControlMsg' }
{'TransmissionMsg' }
{'WindowControlMsg' }

```

View Message Information

Use `messageInfo` to view message information, including the identifier, data length, and a signal list.

```
messageInfo(db, 'EngineMsg')
```

```
ans =
```

```
struct with fields:
```

```

    Name: 'EngineMsg'
    ProtocolMode: 'CAN'
    Comment: ''
    ID: 100
    Extended: 0
    J1939: []

```

```
    Length: 8
      DLC: 8
      BRS: 0
    Signals: {2x1 cell}
  SignalInfo: [2x1 struct]
    TxNodes: {0x1 cell}
  Attributes: {}
  AttributeInfo: [0x0 struct]
```

You can also query for information on all messages at once.

```
messageInfo(db)
```

```
ans =
```

```
5x1 struct array with fields:
```

```
  Name
  ProtocolMode
  Comment
  ID
  Extended
  J1939
  Length
  DLC
  BRS
  Signals
  SignalInfo
  TxNodes
  Attributes
  AttributeInfo
```

View Signal Information

Use `signalInfo` to view signal definition information, including type, byte ordering, size, and scaling values that translate raw signals to physical values.

```
signalInfo(db, 'EngineMsg', 'EngineRPM')
```

```
ans =
```

```
struct with fields:
```

```
    Name: 'EngineRPM'
    Comment: ''
    StartBit: 0
  SignalSize: 32
  ByteOrder: 'LittleEndian'
    Signed: 0
  ValueType: 'Integer'
    Class: 'uint32'
    Factor: 0.1000
    Offset: 250
  Minimum: 250
  Maximum: 9500
```

```

        Units: 'rpm'
    ValueTable: [0x1 struct]
    Multiplexor: 0
    Multiplexed: 0
    MultiplexMode: 0
        RxNodes: {0x1 cell}
    Attributes: {}
    AttributeInfo: [0x0 struct]

```

You can also query for information on all signals in the message at once.

```
signalInfo(db, 'EngineMsg')
```

```
ans =
```

```
2x1 struct array with fields:
```

```

    Name
    Comment
    StartBit
    SignalSize
    ByteOrder
    Signed
    ValueType
    Class
    Factor
    Offset
    Minimum
    Maximum
    Units
    ValueTable
    Multiplexor
    Multiplexed
    MultiplexMode
    RxNodes
    Attributes
    AttributeInfo

```

Create a Message Using Database Definitions

Specify the name of the message when you create a new message to have the database definition applied. CAN signals in this messages are represented in engineering units in addition to the raw data bytes.

```
msgEngineInfo = canMessage(db, 'EngineMsg')
```

```
msgEngineInfo =
```

```
Message with properties:
```

```

    Message Identification
    ProtocolMode: 'CAN'
        ID: 100
    Extended: 0

```

```
        Name: 'EngineMsg'

Data Details
  Timestamp: 0
    Data: [0 0 0 0 0 0 0 0]
  Signals: [1x1 struct]
  Length: 8

Protocol Flags
  Error: 0
  Remote: 0

Other Information
  Database: [1x1 can.Database]
  UserData: []
```

View Signal Information

Use the `Signals` property to see signal values for this message. You can directly write to and read from these signals to pack or unpack data from the message.

```
msgEngineInfo.Signals
```

```
ans =
```

```
struct with fields:
  VehicleSpeed: 0
  EngineRPM: 250
```

Change Signal Information

Write directly to the signal to change a value and read its current value back.

```
msgEngineInfo.Signals.EngineRPM = 5500.25
msgEngineInfo.Signals
```

```
msgEngineInfo =
```

```
Message with properties:
  Message Identification
    ProtocolMode: 'CAN'
      ID: 100
    Extended: 0
    Name: 'EngineMsg'

Data Details
  Timestamp: 0
    Data: [23 205 0 0 0 0 0 0]
  Signals: [1x1 struct]
  Length: 8

Protocol Flags
  Error: 0
```



```

    Remote: 0

    Other Information
      Database: [1x1 can.Database]
      UserData: []

ans =

    struct with fields:

      VehicleSpeed: 0
      EngineRPM: 5.5003e+03

```

When you write directly to the signal, the value is translated, scaled, and packed into the message data using the database definition.

```

msgEngineInfo.Signals.VehicleSpeed = 70.81
msgEngineInfo.Signals

```

```

msgEngineInfo =

    Message with properties:

      Message Identification
        ProtocolMode: 'CAN'
          ID: 100
        Extended: 0
        Name: 'EngineMsg'

      Data Details
        Timestamp: 0
        Data: [23 205 0 0 71 0 0 0]
        Signals: [1x1 struct]
        Length: 8

      Protocol Flags
        Error: 0
        Remote: 0

      Other Information
        Database: [1x1 can.Database]
        UserData: []

```

```

ans =

    struct with fields:

      VehicleSpeed: 71
      EngineRPM: 5.5003e+03

```

Receive Messages with Database Information

Attach a database to a CAN channel that receives messages to apply database definitions to incoming messages automatically. The database decodes only messages that are defined. All other messages are received in their raw form.

```
rxCh = canChannel('MathWorks', 'Virtual 1', 2);  
rxCh.Database = db
```

```
rxCh =
```

```
Channel with properties:
```

```
Device Information
```

```
    DeviceVendor: 'MathWorks'  
    Device: 'Virtual 1'  
DeviceChannelIndex: 2  
DeviceSerialNumber: 0  
    ProtocolMode: 'CAN'
```

```
Status Information
```

```
    Running: 0  
MessagesAvailable: 0  
MessagesReceived: 0  
MessagesTransmitted: 0  
InitializationAccess: 1  
    InitialTimestamp: [0x0 datetime]  
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'
```

```
Channel Information
```

```
    BusStatus: 'N/A'  
    SilentMode: 0  
    TransceiverName: 'N/A'  
    TransceiverState: 'N/A'  
ReceiveErrorCount: 0  
TransmitErrorCount: 0  
    BusSpeed: 500000  
    SJW: []  
    TSEG1: []  
    TSEG2: []  
    NumOfSamples: []
```

```
Other Information
```

```
    Database: [1x1 can.Database]  
    UserData: []
```

Receive Messages

Start the channel, generate some message traffic and receive messages with physical message decoding.

```
start(rxCh);  
generateMsgsDb();  
rxMsg = receive(rxCh, Inf, 'OutputFormat', 'timetable');  
rxMsg(1:15, :)
```

```
ans =
```

```
15x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signal
0.00056739 sec	100	false	{'EngineMsg' }	{1x8 uint8}	8	{1x1 struct}
0.00058946 sec	200	false	{'TransmissionMsg' }	{1x8 uint8}	8	{1x1 struct}
0.00061013 sec	400	false	{'DoorControlMsg' }	{1x8 uint8}	8	{1x1 struct}
0.00062969 sec	600	false	{'WindowControlMsg' }	{1x4 uint8}	4	{1x1 struct}
0.00065036 sec	800	false	{'SunroofControlMsg' }	{1x2 uint8}	2	{1x1 struct}
0.025234 sec	100	false	{'EngineMsg' }	{1x8 uint8}	8	{1x1 struct}
0.050591 sec	100	false	{'EngineMsg' }	{1x8 uint8}	8	{1x1 struct}
0.05062 sec	200	false	{'TransmissionMsg' }	{1x8 uint8}	8	{1x1 struct}
0.074943 sec	100	false	{'EngineMsg' }	{1x8 uint8}	8	{1x1 struct}
0.099434 sec	100	false	{'EngineMsg' }	{1x8 uint8}	8	{1x1 struct}
0.099458 sec	200	false	{'TransmissionMsg' }	{1x8 uint8}	8	{1x1 struct}
0.12481 sec	100	false	{'EngineMsg' }	{1x8 uint8}	8	{1x1 struct}
0.12484 sec	400	false	{'DoorControlMsg' }	{1x8 uint8}	8	{1x1 struct}
0.15005 sec	100	false	{'EngineMsg' }	{1x8 uint8}	8	{1x1 struct}
0.15008 sec	200	false	{'TransmissionMsg' }	{1x8 uint8}	8	{1x1 struct}

Stop the channel and clear it from the workspace.

```
stop(rxCh);
clear rxCh
```

Examine a Received Message

Inspect a received message to see the applied database decoding.

```
rxMsg(10, :)
rxMsg.Signals{10}
```

```
ans =
```

```
1x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
0.099434 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}

```
ans =
```

```
struct with fields:
```

```
VehicleSpeed: 50
EngineRPM: 3.5696e+03
```

Extract All Instances of a Specified Message

Use MATLAB notation to extract all instances of a specified message by name.

```
allMsgEngine = rxMsg(strcmpi('EngineMsg', rxMsg.Name), :);
allMsgEngine(1:15, :)
```

```
ans =
```

```
15x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
0.00056739 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.025234 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.050591 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.074943 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.099434 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.12481 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.15005 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.17467 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.19996 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.22444 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.25107 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.27505 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.29974 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.32502 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
0.35023 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}

Plot Physical Signal Values

Plot the values of database decoded signals over time. Reference the message timestamps and the signal values in variables.

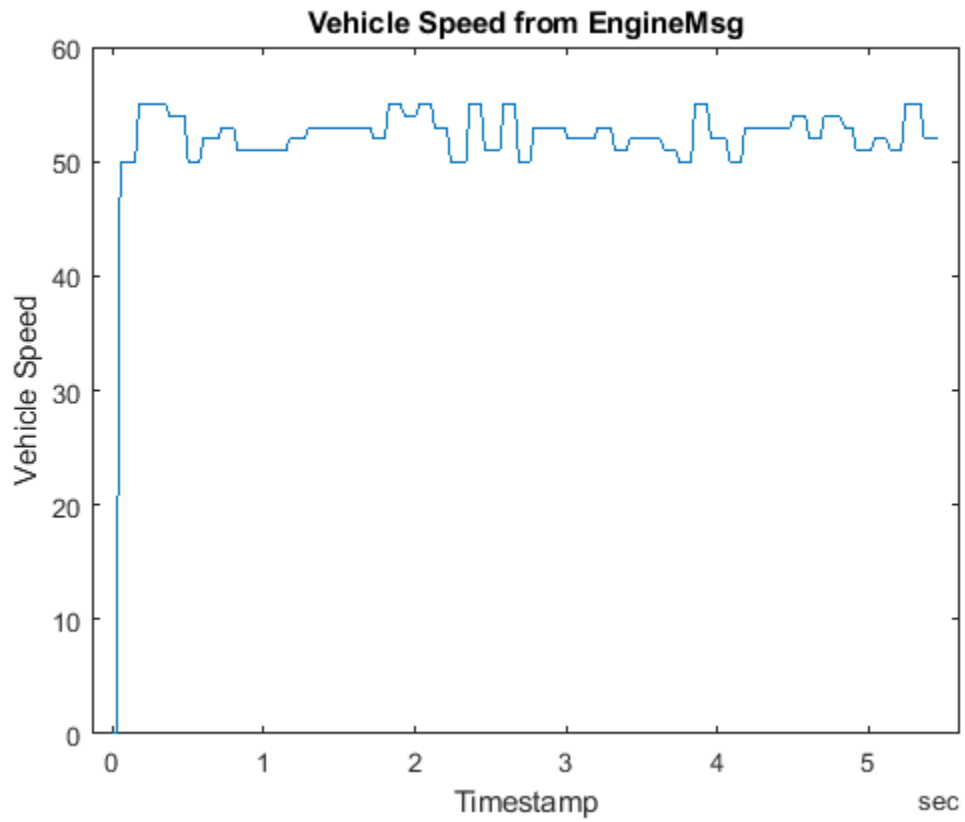
```
signalTimetable = canSignalTimetable(rxMsg, 'EngineMsg');
signalTimetable(1:15, :)
plot(signalTimetable.Time, signalTimetable.VehicleSpeed)
title('Vehicle Speed from EngineMsg', 'FontWeight', 'bold')
xlabel('Timestamp')
ylabel('Vehicle Speed')
```

```
ans =
```

```
15x2 timetable
```

Time	VehicleSpeed	EngineRPM
0.00056739 sec	0	250
0.025234 sec	0	250
0.050591 sec	50	3569.6
0.074943 sec	50	3569.6
0.099434 sec	50	3569.6
0.12481 sec	50	3569.6
0.15005 sec	50	3569.6
0.17467 sec	55	3621.3
0.19996 sec	55	3621.3
0.22444 sec	55	3621.3

0.25107 sec	55	3621.3
0.27505 sec	55	3663.9
0.29974 sec	55	3663.9
0.32502 sec	55	3663.9
0.35023 sec	55	3663.9



Periodic CAN Message Transmission

This example shows you how to use the automated CAN message transmit features of Vehicle Network Toolbox™ to send periodic messages. It uses MathWorks Virtual CAN channels connected in a loopback configuration. As this example is based on sending and receiving CAN messages on a virtual network, running Vehicle CAN Bus Monitor in conjunction may provide a more complete understanding of what the code is doing. To run Vehicle CAN Bus Monitor, open and configure it to use the same interface as the receiving channel of the example. Make sure to start Vehicle CAN Bus Monitor before beginning to run the example in order to see all of the messages as they occur.

Create the CAN Channels

Create CAN channels on which to use the automated message transmit commands.

```
txCh = canChannel('MathWorks', 'Virtual 1', 1);
rxCh = canChannel('MathWorks', 'Virtual 1', 2);
```

In this example, you will use a CAN database file to define and decode messages. Open the database and attach it to the CAN channels.

```
db = canDatabase('demoVNT_CANdbFiles.dbc');
txCh.Database = db;
rxCh.Database = db;
```

Create the CAN Messages

You can create CAN messages to register for periodic transmit using the database information.

```
msgFast = canMessage(db, 'EngineMsg')
msgSlow = canMessage(db, 'TransmissionMsg')
```

```
msgFast =
```

```
Message with properties:
```

```
Message Identification
```

```
ProtocolMode: 'CAN'
```

```
ID: 100
```

```
Extended: 0
```

```
Name: 'EngineMsg'
```

```
Data Details
```

```
Timestamp: 0
```

```
Data: [0 0 0 0 0 0 0 0]
```

```
Signals: [1x1 struct]
```

```
Length: 8
```

```
Protocol Flags
```

```
Error: 0
```

```
Remote: 0
```

```
Other Information
```

```
Database: [1x1 can.Database]
```

```
UserData: []
```

```

msgSlow =

  Message with properties:

    Message Identification
      ProtocolMode: 'CAN'
        ID: 200
      Extended: 0
      Name: 'TransmissionMsg'

    Data Details
      Timestamp: 0
      Data: [0 0 0 0 0 0 0 0]
      Signals: [1x1 struct]
      Length: 8

    Protocol Flags
      Error: 0
      Remote: 0

    Other Information
      Database: [1x1 can.Database]
      UserData: []

```

Configure Messages for Periodic Transmit

To configure a message for periodic transmit, use the `transmitPeriodic` command to specify the channel, the message to register on the channel, a mode value, and the periodic rate.

```

transmitPeriodic(txCh, msgFast, 'On', 0.100);
transmitPeriodic(txCh, msgSlow, 'On', 0.500);

```

Start the Periodic Message Transmit

When you start a channel which has periodic messages registered, transmit begins immediately. Allow the channels run for a short time.

```

start(rxCh);
start(txCh);
pause(2);

```

Modify Transmitted Data

To update the live message or signal data sent onto the CAN bus, write new values into the message you originally created using either the `Data` property or the `signals` interface.

```

msgFast.Signals.VehicleSpeed = 60;
pause(1);
msgFast.Signals.VehicleSpeed = 65;
pause(1);
msgFast.Signals.VehicleSpeed = 70;
pause(1);

```

Receive the Messages

Stop the CAN channels and receive all periodically transmitted messages for analysis.

```
stop(txCh);
stop(rxCh);
msgRx = receive(rxCh, Inf, 'OutputFormat', 'timetable');
msgRx(1:15, :)
```

```
ans =
```

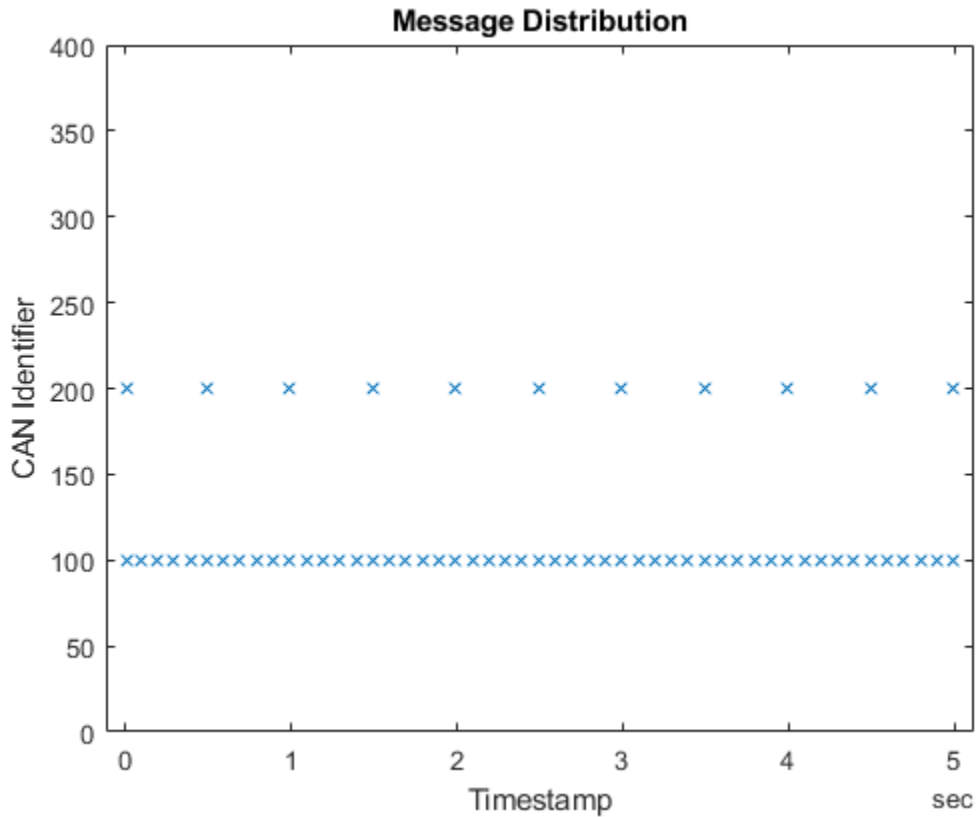
```
15x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
0.0074728 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.0074752 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]
0.092596 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.1926 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.29253 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.39159 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.49253 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.49253 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]
0.59084 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.69067 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.7907 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.89171 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.99207 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.99207 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]
1.0914 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]

Analyze the Periodic Transmit Behavior

You can analyze the distribution of messages by plotting the identifiers of each message against their timestamps. Notice the difference between how often the two messages appear according to their periodic rates.

```
plot(msgRx.Time, msgRx.ID, 'x')
ylim([0 400])
title('Message Distribution', 'FontWeight', 'bold')
xlabel('Timestamp')
ylabel('CAN Identifier')
```

For further analysis, separate the two messages into individual timetables.

```
msgRxFast = msgRx(strcmpi('EngineMsg', msgRx.Name), :);
msgRxFast(1:10, :)
msgRxSlow = msgRx(strcmpi('TransmissionMsg', msgRx.Name), :);
msgRxSlow(1:10, :)
```

ans =

10x8 timetable

Time	ID	Extended	Name	Data	Length	Signals
0.0074728 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.092596 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.1926 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.29253 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.39159 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.49253 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.59084 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.69067 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.7907 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]
0.89171 sec	100	false	'EngineMsg'	[1x8 uint8]	8	[1x1 struct]

ans =

```
10x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
0.0074752 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]
0.49253 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]
0.99207 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]
1.4918 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]
1.9909 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]
2.4909 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]
2.9934 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]
3.4918 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]
3.9914 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]
4.4918 sec	200	false	'TransmissionMsg'	[1x8 uint8]	8	[1x1 struct]

Analyze the timestamps of each set of messages to see how closely the average of the differences corresponds to the configured periodic rates.

```
avgPeriodFast = mean(diff(msgRxFast.Time))
avgPeriodSlow = mean(diff(msgRxSlow.Time))
```

```
avgPeriodFast =
```

```
duration
```

```
0.099686 sec
```

```
avgPeriodSlow =
```

```
duration
```

```
0.49843 sec
```

A plot of the received signal data reflects the updates in the message data sent on the CAN bus.

```
signalTimetable = canSignalTimetable(msgRx, 'EngineMsg');
signalTimetable(1:10, :)
plot(signalTimetable.Time, signalTimetable.VehicleSpeed)
title('Vehicle Speed from EngineMsg', 'FontWeight', 'bold')
xlabel('Timestamp')
ylabel('Vehicle Speed')
ylim([-5 75])
```

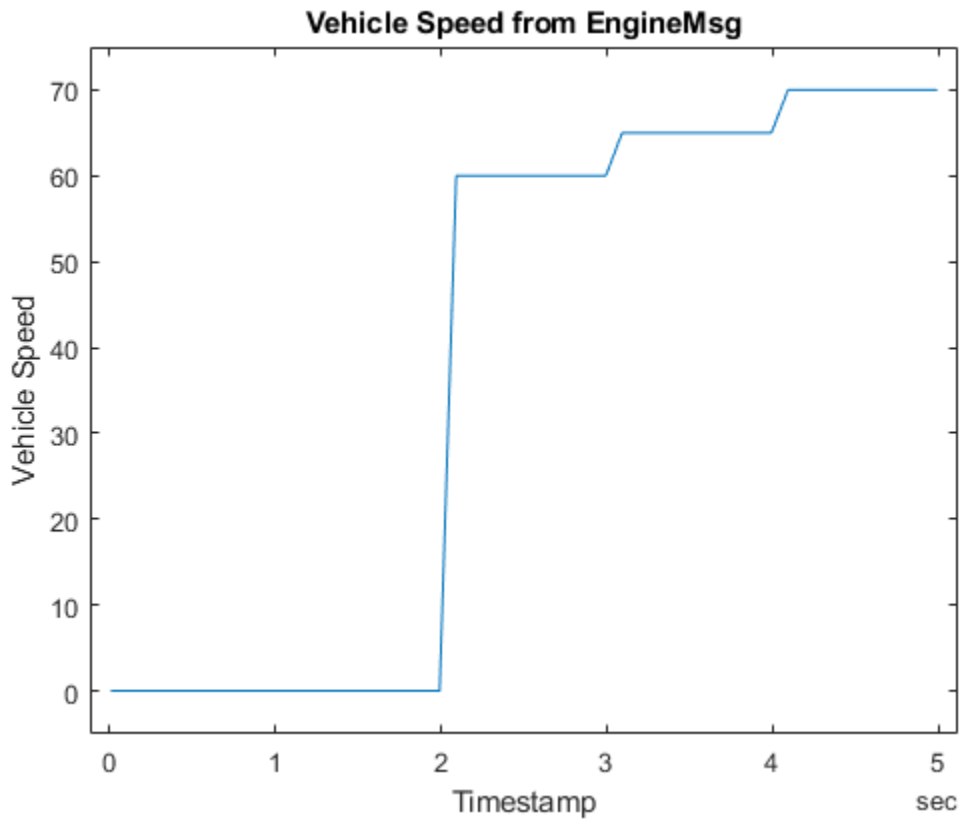
```
ans =
```

```
10x2 timetable
```

Time	VehicleSpeed	EngineRPM
0.0074728 sec	0	250

```

0.092596 sec      0      250
0.1926 sec       0      250
0.29253 sec      0      250
0.39159 sec      0      250
0.49253 sec      0      250
0.59084 sec      0      250
0.69067 sec      0      250
0.7907 sec       0      250
0.89171 sec      0      250
    
```



View Messages Configured for Periodic Transmit

To see messages configured on a channel for periodic transmit, use the `transmitConfiguration` command.

```
transmitConfiguration(txCh)
```

Periodic Messages

ID	Extended	Name	Data	Rate (seconds)
100	false	EngineMsg	0 0 0 0 70 0 0 0	0.100000
200	false	TransmissionMsg	0 0 0 0 0 0 0 0	0.500000

Event Messages

None

Event Triggered CAN Message Transmission

This example shows you how to use the automated CAN message transmit features of Vehicle Network Toolbox™ to send messages on event. It uses MathWorks Virtual CAN channels connected in a loopback configuration. As this example is based on sending and receiving CAN messages on a virtual network, running Vehicle CAN Bus Monitor in conjunction may provide a more complete understanding of what the code is doing. To run Vehicle CAN Bus Monitor, open and configure it to use the same interface as the receiving channel of the example. Make sure to start Vehicle CAN Bus Monitor before beginning to run the example in order to see all of the messages as they occur.

Create the CAN Channels

Create CAN channels on which to use the automated message transmit commands.

```
txCh = canChannel('MathWorks', 'Virtual 1', 1);
rxCh = canChannel('MathWorks', 'Virtual 1', 2);
```

In this example, you will use a CAN database file to define and decode messages. Open the database and attach it to the CAN channels.

```
db = canDatabase('demoVNT_CANdbFiles.dbc');
txCh.Database = db;
rxCh.Database = db;
```

Create the CAN Message

You can create a CAN message to register for event transmit using the database information.

```
msgEngineMsg = canMessage(db, 'EngineMsg')
```

```
msgEngineMsg =
```

```
Message with properties:
```

```
Message Identification
```

```
ProtocolMode: 'CAN'
```

```
ID: 100
```

```
Extended: 0
```

```
Name: 'EngineMsg'
```

```
Data Details
```

```
Timestamp: 0
```

```
Data: [0 0 0 0 0 0 0 0]
```

```
Signals: [1x1 struct]
```

```
Length: 8
```

```
Protocol Flags
```

```
Error: 0
```

```
Remote: 0
```

```
Other Information
```

```
Database: [1x1 can.Database]
```

```
UserData: []
```

Configure the Message for Event Transmit

To configure a message for event transmit, use the `transmitEvent` command to specify the channel, the message to register on the channel, and a mode value.

```
transmitEvent(txCh, msgEngineMsg, 'On');
```

Start the Event Message Transmit

Start the channels and write the new values to either the Data property or directly to the signals to trigger automatic event-based transmission of the message onto the CAN bus.

```
start(rxCh);
start(txCh);
msgEngineMsg.Data = [250 100 0 0 20 0 0 0];
pause(1);
msgEngineMsg.Signals.VehicleSpeed = 60;
pause(1);
stop(txCh);
stop(rxCh);
```

Analyze the Event Transmit Behavior

The receiving channel now has two messages available, corresponding to the two updates that resulted in two transmits.

```
rxCh
```

```
rxCh =
```

```
Channel with properties:
```

```
Device Information
```

```
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 2
    DeviceSerialNumber: 0
    ProtocolMode: 'CAN'
```

```
Status Information
```

```
    Running: 0
    MessagesAvailable: 2
    MessagesReceived: 0
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: 25-Aug-2020 13:54:04
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'
```

```
Channel Information
```

```
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    BusSpeed: 500000
    SJW: []
```

```
TSEG1: []
TSEG2: []
NumOfSamples: []
```

Other Information

```
Database: [1x1 can.Database]
UserData: []
```

Receive and inspect each message to see that each has the data values previously set.

```
msgRx = receive(rxCh, Inf, 'OutputFormat', 'timetable')
signals = canSignalTimetable(msgRx)
```

```
msgRx =
```

2x8 timetable

Time	ID	Extended	Name	Data	Length	Signals
0.0074577 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}
1.0488 sec	100	false	{'EngineMsg'}	{1x8 uint8}	8	{1x1 struct}

```
signals =
```

2x2 timetable

Time	VehicleSpeed	EngineRPM
0.0074577 sec	20	2835
1.0488 sec	60	2835

View Messages Configured for Event Transmit

To see messages configured on a channel for event transmit, use the `transmitConfiguration` command.

```
transmitConfiguration(txCh)
```

Periodic Messages

None

Event Messages

ID	Extended	Name	Data
100	false	EngineMsg	250 100 0 0 60 0 0 0

Using Timestamps

This example shows you how to use Vehicle Network Toolbox™ with the InitialTimestamp CAN channel property to work with relative and absolute timestamps for CAN messages. It also uses MathWorks Virtual CAN channels connected in a loopback configuration.

Open the Database File

Open the database file to access the definitions.

```
db = canDatabase('VehicleInfo.dbc')
```

```
db =
```

```
Database with properties:
```

```

    Name: 'VehicleInfo'
    Path: 'C:\TEMP\Bdoc20b_1465442_5924\ib8F4264\1\tp19378308\ex13648766\VehicleInfo.dbc'
    Nodes: {}
    NodeInfo: [0x0 struct]
    Messages: {'WheelSpeeds'}
    MessageInfo: [1x1 struct]
    Attributes: {'BusType'}
    AttributeInfo: [1x1 struct]
    UserData: []

```

Create the CAN Channels

Create CAN channels on which you can send and receive information.

```
txCh = canChannel('MathWorks','Virtual 1',1)
rxCh = canChannel('MathWorks','Virtual 1',2)
rxCh.Database = db;
```

```
txCh =
```

```
Channel with properties:
```

```

Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 1
    DeviceSerialNumber: 0
    ProtocolMode: 'CAN'

Status Information
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 0
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: [0x0 datetime]
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

```

```
Channel Information
```



```

        BusStatus: 'N/A'
        SilentMode: 0
        TransceiverName: 'N/A'
        TransceiverState: 'N/A'
        ReceiveErrorCount: 0
        TransmitErrorCount: 0
        BusSpeed: 500000
        SJW: []
        TSEG1: []
        TSEG2: []
        NumOfSamples: []

    Other Information
        Database: []
        UserData: []

rxCh =

Channel with properties:

    Device Information
        DeviceVendor: 'MathWorks'
        Device: 'Virtual 1'
        DeviceChannelIndex: 2
        DeviceSerialNumber: 0
        ProtocolMode: 'CAN'

    Status Information
        Running: 0
        MessagesAvailable: 0
        MessagesReceived: 0
        MessagesTransmitted: 0
        InitializationAccess: 1
        InitialTimestamp: [0x0 datetime]
        FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

    Channel Information
        BusStatus: 'N/A'
        SilentMode: 0
        TransceiverName: 'N/A'
        TransceiverState: 'N/A'
        ReceiveErrorCount: 0
        TransmitErrorCount: 0
        BusSpeed: 500000
        SJW: []
        TSEG1: []
        TSEG2: []
        NumOfSamples: []

    Other Information
        Database: []
        UserData: []

```

Create the CAN Message

You can create CAN messages to send on the network.

```
msg = canMessage(db, 'WheelSpeeds')

msg =

Message with properties:

    Message Identification
        ProtocolMode: 'CAN'
            ID: 1200
        Extended: 0
        Name: 'WheelSpeeds'

    Data Details
        Timestamp: 0
        Data: [0 0 0 0 0 0 0 0]
        Signals: [1x1 struct]
        Length: 8

    Protocol Flags
        Error: 0
        Remote: 0

    Other Information
        Database: [1x1 can.Database]
        UserData: []
```

Start the CAN Channels

To begin using channels for transmit and receive operations, place them online.

```
start(rxCh)
start(txCh)
```

Send CAN Messages

The `transmit` function sends messages onto the network. Use `pause` to delay the transmits. Update the signal data each transmit.

```
msg.Signals.LF_WSpeed = 10;
transmit(txCh,msg)
pause(1);
msg.Signals.LF_WSpeed = 20;
transmit(txCh,msg)
pause(2);
msg.Signals.LF_WSpeed = 30;
transmit(txCh,msg)
pause(3);
msg.Signals.LF_WSpeed = 40;
transmit(txCh,msg)
pause(1);
msg.Signals.LF_WSpeed = 50;
transmit(txCh,msg)
```

Receive the CAN Messages

The `receive` function retrieves information from the channel representing messaging that occurred on the network.

```
stop(rxCh)
stop(txCh)
msgRx = receive(rxCh,Inf,'OutputFormat','timetable')
```

```
msgRx =
```

```
5x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
0.013655 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
1.0197 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
3.0301 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
6.0605 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
7.0631 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}

Inspect Signal Data

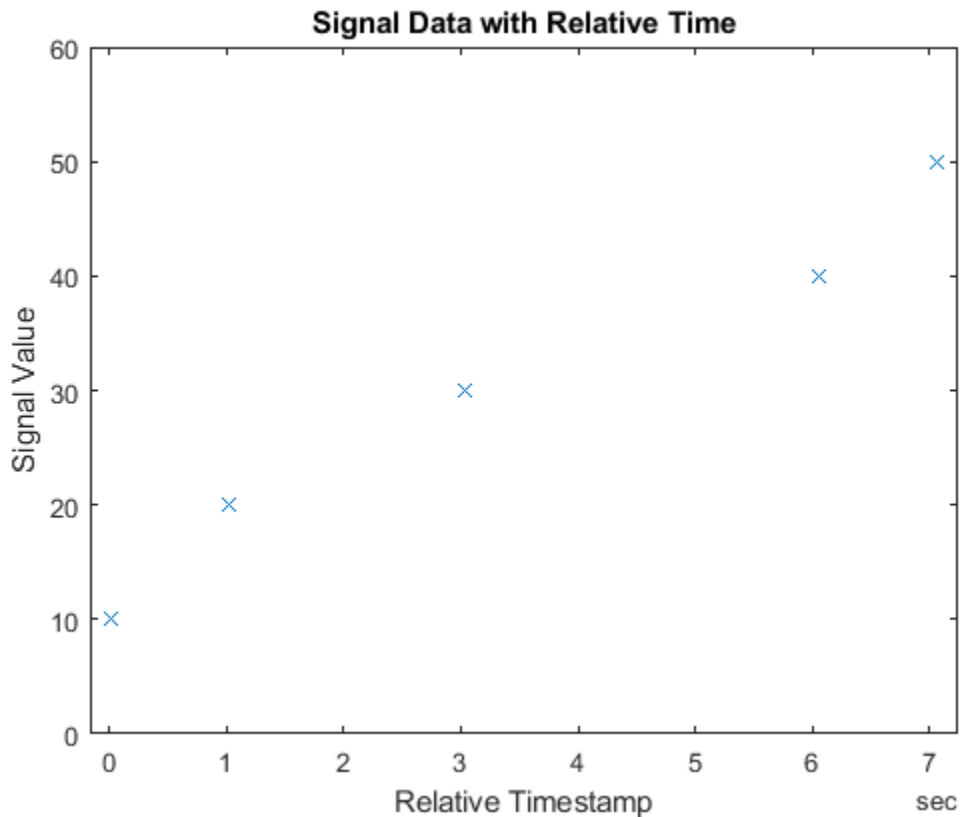
View details of the received messages, including the timestamps and the signal value. Note that timestamp values are relative from the start time of the CAN channel.

```
signalTimetable = canSignalTimetable(msgRx)
plot(signalTimetable.Time,signalTimetable.LF_WSpeed,'x')
title('Signal Data with Relative Time','FontWeight','bold')
xlabel('Relative Timestamp')
ylabel('Signal Value')
ylim([0 60])
```

```
signalTimetable =
```

```
5x4 timetable
```

Time	LR_WSpeed	RR_WSpeed	RF_WSpeed	LF_WSpeed
0.013655 sec	-100	-100	-100	10
1.0197 sec	-100	-100	-100	20
3.0301 sec	-100	-100	-100	30
6.0605 sec	-100	-100	-100	40
7.0631 sec	-100	-100	-100	50



Inspect InitialTimestamp Property

View the `InitialTimestamp` property of the receiving CAN channel. It is a datetime value that gives the absolute time of when the channel was started.

```
rxCh.InitialTimestamp
```

```
ans =
```

```
datetime
```

```
25-Aug-2020 13:54:18
```

Analyze Data with Absolute Timestamps

The relative timestamps of each message and the `InitialTimestamp` property combine to apply absolute time values to each message or signal contained within.

```
msgRx.Time = msgRx.Time + rxCh.InitialTimestamp
signalTimetable = canSignalTimetable(msgRx)
figure
plot(signalTimetable.Time, signalTimetable.LF_WSpeed, 'x')
title('Signal Data with Absolute Time', 'FontWeight', 'bold')
xlabel('Absolute Timestamp')
ylabel('Signal Value')
ylim([0 60])
```

```
msgRx =
```

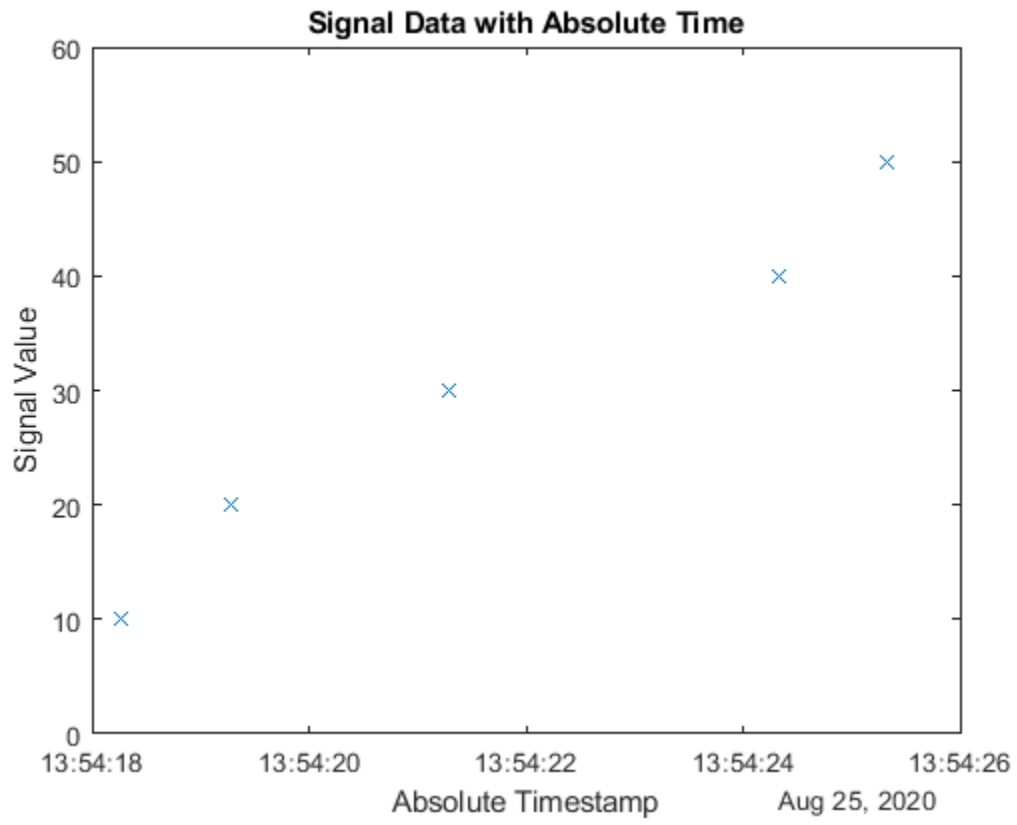
```
5x8 timetable
```

Time	ID	Extended	Name	Data	Length	Si
25-Aug-2020 13:54:18	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1
25-Aug-2020 13:54:19	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1
25-Aug-2020 13:54:21	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1
25-Aug-2020 13:54:24	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1
25-Aug-2020 13:54:25	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1

```
signalTimetable =
```

```
5x4 timetable
```

Time	LR_WSpeed	RR_WSpeed	RF_WSpeed	LF_WSpeed
25-Aug-2020 13:54:18	-100	-100	-100	10
25-Aug-2020 13:54:19	-100	-100	-100	20
25-Aug-2020 13:54:21	-100	-100	-100	30
25-Aug-2020 13:54:24	-100	-100	-100	40
25-Aug-2020 13:54:25	-100	-100	-100	50



Access XCP A2L Files

This example shows how to access information stored in A2L files for use with XCP connections. It uses a freely available XCP slave simulator from Vector.

Run a Slave Simulator

This example requires installing a free, third-party XCP implementation from Vector. The package includes an XCP slave simulator and A2L file. To install this driver, please follow these instructions:

- 1 Go to www.vector.com and navigate to the "DOWNLOADS" page.
- 2 Search for "Demos" under "Categories" and "XCP" under "Standards".
- 3 Download and install the available version of "XCP Sample Implementation".
- 4 In MATLAB, navigate to where you installed the sample package, and then go to `.\Samples\XCPSim\CANape`.
- 5 The MATLAB XCP examples will use the `XCPSIM.a2l` file and the `XCPSim.exe` slave simulator. Run `XCPSim.exe`.

Open an A2L File

Open an A2L file to parse and inspect the contents and make it usable for subsequent XCP activities.

```
a2lObj = xcpA2L('XCPSIM.a2l')
```

```
a2lObj =
```

```
  A2L with properties:
```

```

        FileName: 'XCPSIM.a2l'
        FilePath: '\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex15095408\XCPS
        SlaveName: 'CPP'
        ProtocolLayerInfo: [1x1 xcp.ProtocolLayerInfo]
        DAQInfo: [1x1 xcp.DAQInfo]
        TransportLayerCANInfo: [1x1 xcp.TransportLayerCANInfo]
        TransportLayerUDPInfo: [1x1 xcp.TransportLayerUDPInfo]
        TransportLayerTCPInfo: []
        Events: {1x6 cell}
        Measurements: {1x45 cell}
        Characteristics: {1x16 cell}
        EventInfo: [1x6 xcp.Event]
        MeasurementInfo: [45x1 containers.Map]
        CharacteristicInfo: [16x1 containers.Map]
        AxisInfo: [1x1 containers.Map]
        RecordLayouts: [41x1 containers.Map]
        CompuMethods: [16x1 containers.Map]
        CompuTabs: [0x1 containers.Map]
        CompuVtabs: [2x1 containers.Map]
```

Inspect A2L Information

The properties of the A2L file object allow you to inspect the many configuration parameters contained within the file. Of special note is the `Measurements` property which contains the names of all available measurements for use in DAQ/STIM lists.

```
a2l0bj.Measurements
```

```
ans =
```

```
1x45 cell array
```

```
Columns 1 through 4
```

```
 {'BitSlice'}    {'BitSlice0'}    {'BitSlice1'}    {'BitSlice2'}
```

```
Columns 5 through 8
```

```
 {'Counter_B4'}    {'Counter_B5'}    {'Counter_B6'}    {'Counter_B7'}
```

```
Columns 9 through 12
```

```
 {'DtChannel1'}    {'FW1'}    {'KL1Output'}    {'MaxChannel1'}
```

```
Columns 13 through 16
```

```
 {'MinChannel1'}    {'PWM'}    {'PWMFiltered'}    {'PWM_Level'}
```

```
Columns 17 through 20
```

```
 {'ShiftByte'}    {'Shifter_B0'}    {'Shifter_B1'}    {'Shifter_B2'}
```

```
Columns 21 through 24
```

```
 {'Shifter_B3'}    {'TestStatus'}    {'Triangle'}    {'ampl'}
```

```
Columns 25 through 29
```

```
 {'bit12Counter'}    {'byte1'}    {'byte2'}    {'byte3'}    {'byte4'}
```

```
Columns 30 through 33
```

```
 {'byteCounter'}    {'bytePWMFilter'}    {'channel1'}    {'channel2'}
```

```
Columns 34 through 37
```

```
 {'channel3'}    {'dwordCounter'}    {'limit'}    {'map1InputX'}
```

```
Columns 38 through 41
```

```
 {'map1InputY'}    {'map1Output'}    {'offset'}    {'period'}
```

```
Columns 42 through 45
```

```
 {'sbytePWMLLevel'}    {'v'}    {'vin'}    {'wordCounter'}
```

Query for Event Information

Use the `getEventInfo` command to retrieve detailed information about an event by name.

```
getEventInfo(a2l0bj, '10 ms')
```



```
ans =
```

```
Event with properties:
```

```
        Name: '10 ms'  
        Direction: 'DAQ_STIM'  
        MaxDAQList: 255  
        ChannelNumber: 1  
        ChannelTimeCycle: 10  
        ChannelTimeUnit: 6  
        ChannelPriority: 0  
        ChannelTimeCycleInSeconds: 0.0100
```

Query for Measurement Information

Use the `getMeasurementInfo` command to retrieve detailed information about a measurement by name.

```
getMeasurementInfo(a2lObj, 'Triangle')
```

```
ans =
```

```
Measurement with properties:
```

```
        Resolution: 0  
        Accuracy: 0  
        LocDataType: 'SBYTE'  
        Name: 'Triangle'  
        LongIdentifier: 'Triangle test signal used for PWM output PWM'  
        ECUAddress: 4951377  
        ECUAddressExtension: 0  
        Conversion: [1x1 xcp.CompuMethodRational]  
        Dimension: 1  
        LowerLimit: -50  
        UpperLimit: 50  
        BitMask: []
```

XCP Dynamic DAQ Lists

This example shows how to use XCP connections to create and use dynamic data acquisition lists. It uses a freely available XCP slave simulator from Vector and Vector virtual CAN channels. For access to virtual channels, Vector device drivers must be installed. It is also recommended to run Vehicle CAN Bus Monitor in conjunction with this example.

Run a Slave Simulator

This example requires installing a free, third-party XCP implementation from Vector. The package includes an XCP slave simulator and A2L file. To install this driver, please follow these instructions:

- 1 Go to www.vector.com and navigate to the "DOWNLOADS" page.
- 2 Search for "Demos" under "Categories" and "XCP" under "Standards".
- 3 Download and install the available version of "XCP Sample Implementation".
- 4 In MATLAB, navigate to where you installed the sample package, and then go to `.\Samples\XCPSim\CANape`.
- 5 The MATLAB XCP examples will use the `XCPSIM.a2l` file and the `XCPSim.exe` slave simulator. Run `XCPSim.exe`.

Open the A2L File

Establishing a connection to an XCP slave requires using the A2L file that describes the slave module.

```
a2lobj = xcpA2L('XCPSIM.a2l')
```

```
a2lobj =
```

```
A2L with properties:
```

```

    FileName: 'XCPSIM.a2l'
    FilePath: '\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex33137552\XCPS
    SlaveName: 'CPP'
    ProtocolLayerInfo: [1x1 xcp.ProtocolLayerInfo]
    DAQInfo: [1x1 xcp.DAQInfo]
    TransportLayerCANInfo: [1x1 xcp.TransportLayerCANInfo]
    TransportLayerUDPInfo: [1x1 xcp.TransportLayerUDPInfo]
    TransportLayerTCPInfo: []
    Events: {1x6 cell}
    Measurements: {1x45 cell}
    Characteristics: {1x16 cell}
    EventInfo: [1x6 xcp.Event]
    MeasurementInfo: [45x1 containers.Map]
    CharacteristicInfo: [16x1 containers.Map]
    AxisInfo: [1x1 containers.Map]
    RecordLayouts: [41x1 containers.Map]
    CompuMethods: [16x1 containers.Map]
    CompuTabs: [0x1 containers.Map]
    CompuVTabs: [2x1 containers.Map]

```

Create an XCP Channel

Create an XCP channel in order to prepare a connection to the slave.

```
xcpCh = xcpChannel(a2lObj, 'CAN', 'Vector', 'Virtual 1', 1)
```

```
xcpCh =
```

```
Channel with properties:
```

```
    SlaveName: 'CPP'  
    A2LFileName: 'XCPSIM.a2l'  
    TransportLayer: 'CAN'  
    TransportLayerDevice: [1x1 struct]  
    SeedKeyDLL: []
```

Connect to the Slave

To make communication with the slave active, connect to it.

```
connect(xcpCh)
```

Create a DAQ List

Create a DAQ list using one of the events specified in the A2L and assign to it some measurements defined in the A2L file.

```
createMeasurementList(xcpCh, 'DAQ', '10 ms', {'Triangle', 'PWM', 'channel3'})
```

Start Measurements

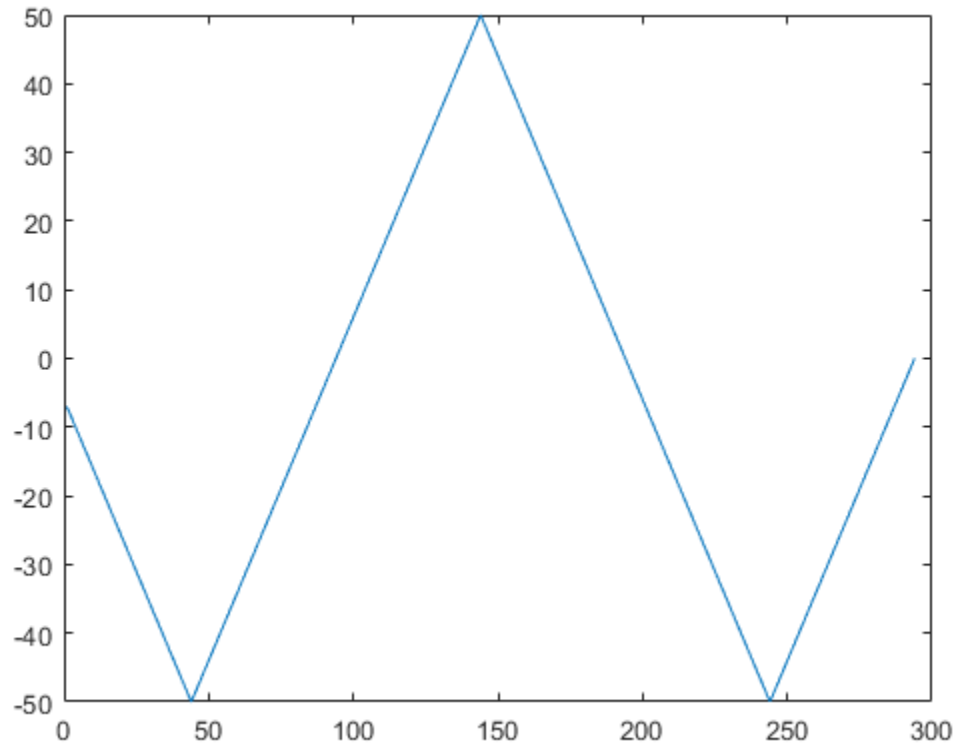
Starting measurements begins the transmission of DAQ messages from the slave. After running for a few seconds, stop measurements.

```
startMeasurement(xcpCh)  
pause(3);  
stopMeasurement(xcpCh)
```

Retrieve the Triangle Measurement Data

Receive the acquired data from the channel for each measurement.

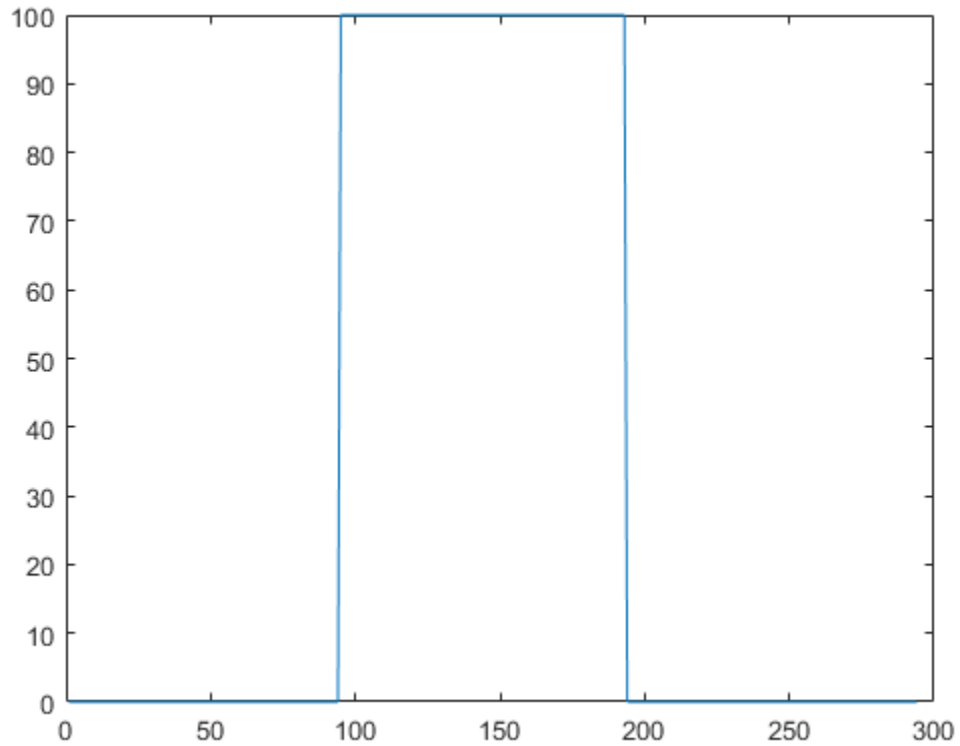
```
dataTriangle = readDAQListData(xcpCh, 'Triangle');  
plot(dataTriangle)
```



Retrieve the PWM Measurement Data

Receive the acquired data from the channel for each measurement.

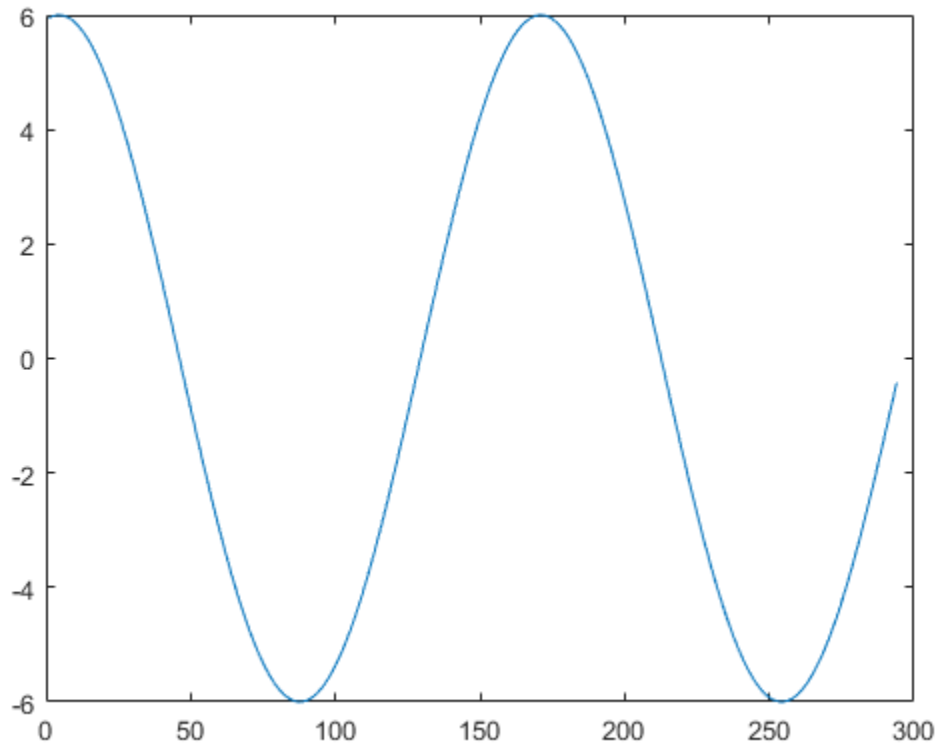
```
dataPWM = readDAQListData(xcpCh, 'PWM');  
plot(dataPWM)
```



Retrieve the channel3 Measurement Data

Receive the acquired data from the channel for each measurement.

```
datachannel3 = readDAQListData(xcpCh, 'channel3');  
plot(datachannel3)
```

**Disconnect from the Slave**

To make communication with the slave inactive, disconnect from it.

```
disconnect(xcpCh)
```

XCP Direct Data Acquisition

This example shows how to use XCP connections to directly acquire measurement values from a slave. It uses a freely available XCP slave simulator from Vector and Vector virtual CAN channels. For access to virtual channels, Vector device drivers must be installed. It is also recommended to run Vehicle CAN Bus Monitor in conjunction with this example.

Run a Slave Simulator

This example requires installing a free, third-party XCP implementation from Vector. The package includes an XCP slave simulator and A2L file. To install this driver, please follow these instructions:

- 1 Go to www.vector.com and navigate to the "DOWNLOADS" page.
- 2 Search for "Demos" under "Categories" and "XCP" under "Standards".
- 3 Download and install the available version of "XCP Sample Implementation".
- 4 In MATLAB, navigate to where you installed the sample package, and then go to `.\Samples\XCPSim\CANape`.
- 5 The MATLAB XCP examples will use the `XCPSIM.a2l` file and the `XCPSim.exe` slave simulator. Run `XCPSim.exe`.

Open the A2L File

Establishing a connection to an XCP slave requires using the A2L file that describes the slave module.

```
a2lObj = xcpA2L('XCPSIM.a2l')
```

```
a2lObj =
```

```
A2L with properties:
```

```

    FileName: 'XCPSIM.a2l'
    FilePath: '\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex81955136\XCPS
    SlaveName: 'CPP'
    ProtocolLayerInfo: [1x1 xcp.ProtocolLayerInfo]
    DAQInfo: [1x1 xcp.DAQInfo]
    TransportLayerCANInfo: [1x1 xcp.TransportLayerCANInfo]
    TransportLayerUDPInfo: [1x1 xcp.TransportLayerUDPInfo]
    TransportLayerTCPInfo: []
    Events: {1x6 cell}
    Measurements: {1x45 cell}
    Characteristics: {1x16 cell}
    EventInfo: [1x6 xcp.Event]
    MeasurementInfo: [45x1 containers.Map]
    CharacteristicInfo: [16x1 containers.Map]
    AxisInfo: [1x1 containers.Map]
    RecordLayouts: [41x1 containers.Map]
    CompuMethods: [16x1 containers.Map]
    CompuTabs: [0x1 containers.Map]
    CompuVTabs: [2x1 containers.Map]

```

Create an XCP Channel

Create an XCP channel to prepare a connection to the slave.

```
xcpCh = xcpChannel(a2lObj, 'CAN', 'Vector', 'Virtual 1', 1)
```

```
xcpCh =
```

```
Channel with properties:
```

```
    SlaveName: 'CPP'  
    A2LFileName: 'XCPSIM.a2l'  
    TransportLayer: 'CAN'  
    TransportLayerDevice: [1x1 struct]  
    SeedKeyDLL: []
```

Connect to the Slave

To make communication with the slave active, connect to it.

```
connect(xcpCh)
```

Directly Acquire Measurement Samples

Acquire some samples of a measurement from the slave.

```
readSingleValue(xcpCh, 'channel3')  
readSingleValue(xcpCh, 'channel3')  
readSingleValue(xcpCh, 'channel3')
```

```
ans =
```

```
single  
-3.0390
```

```
ans =
```

```
single  
-4.8650
```

```
ans =
```

```
single  
-5.5284
```

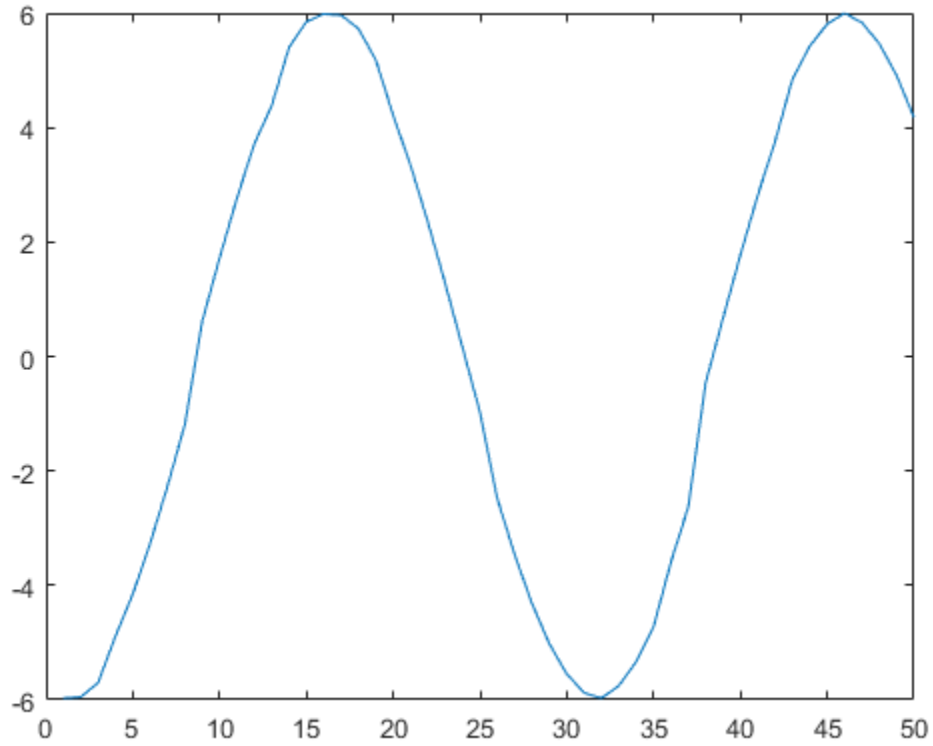
Directly Acquire a Series of Measurement Samples

Using a loop, acquire and plot many measurement samples from the slave.

```
allSamples = [];  
for ii = 1:50  
    newSample = readSingleValue(xcpCh, 'channel3');  
    allSamples = [allSamples newSample];  
end
```



```
end  
plot(allSamples)
```



Disconnect from the Slave

To make communication with the slave inactive, disconnect from it.

```
disconnect(xcpCh)
```

Create and Use J1939 Parameter Groups

This example shows you how to use Vehicle Network Toolbox™ with J1939 to create and manage J1939 parameter groups using information stored in CAN database files. This example uses the CAN database file, J1939.dbc.

Open the Database File

Open the database file to access the definitions.

```
db = canDatabase('J1939.dbc');
```

Create a Parameter Group

Use the `j1939ParameterGroup` function to create a parameter group using the information contained within the database.

```
pg = j1939ParameterGroup(db, 'VehicleDataSingle')
```

```
pg =
```

```
ParameterGroup with properties:
```

```
Protocol Data Unit Details:
```

```
-----
                Name: 'VehicleDataSingle'
                PGN: 40192
            Priority: 6
    PDUFormatType: 'Peer-to-Peer (Type 1)'
    SourceAddress: 254
    DestinationAddress: 254
```

```
Data Details:
```

```
-----
            Timestamp: 0
                Data: [255 255 255 255 255 255 255 255]
                Signals: [1x1 struct]
```

```
Other Information:
```

```
-----
            UserData: []
```

Set Source and Destination Addresses

To fully define the parameter group and determine the logistics of its transmission on a network, set the source and destination addresses.

```
pg.SourceAddress = 30
pg.DestinationAddress = 50
```

```
pg =
```

```
ParameterGroup with properties:
```

```
Protocol Data Unit Details:
```

```

-----
                Name: 'VehicleDataSingle'
                PGN: 40192
                Priority: 6
                PDUFormatType: 'Peer-to-Peer (Type 1)'
                SourceAddress: 30
                DestinationAddress: 254

Data Details:
-----
                Timestamp: 0
                Data: [255 255 255 255 255 255 255 255]
                Signals: [1x1 struct]

Other Information:
-----
                UserData: []

```

pg =

ParameterGroup with properties:

```

Protocol Data Unit Details:
-----
                Name: 'VehicleDataSingle'
                PGN: 40192
                Priority: 6
                PDUFormatType: 'Peer-to-Peer (Type 1)'
                SourceAddress: 30
                DestinationAddress: 50

Data Details:
-----
                Timestamp: 0
                Data: [255 255 255 255 255 255 255 255]
                Signals: [1x1 struct]

Other Information:
-----
                UserData: []

```

Set Priority

Set the `Priority` property to further customize the transmission.

```
pg.Priority = 5;
```

View Signal Information

Use the `Signals` property to see signal values for this parameter group. You can directly write to and read from these signals to pack or unpack data in the parameter group.

```
pg.Signals
```

ans =

```
struct with fields:

    VehicleSignal4: -1
    VehicleSignal3: -1
    VehicleSignal2: -1
    VehicleSignal1: -1
```

Change Signal Information

Write directly to a signal to change a value and read its current value back.

```
pg.Signals.VehicleSignal1 = 10
pg.Signals.VehicleSignal2 = 100
pg.Signals.VehicleSignal3 = 1000
pg.Signals.VehicleSignal4 = 10000
pg.Signals
```

```
pg =
```

```
ParameterGroup with properties:
```

```
Protocol Data Unit Details:
```

```
-----
                Name: 'VehicleDataSingle'
                PGN: 40192
                Priority: 5
                PDUFormatType: 'Peer-to-Peer (Type 1)'
                SourceAddress: 30
                DestinationAddress: 50
```

```
Data Details:
```

```
-----
                Timestamp: 0
                Data: [10 0 255 255 255 255 255 255]
                Signals: [1x1 struct]
```

```
Other Information:
```

```
-----
                UserData: []
```

```
pg =
```

```
ParameterGroup with properties:
```

```
Protocol Data Unit Details:
```

```
-----
                Name: 'VehicleDataSingle'
                PGN: 40192
                Priority: 5
                PDUFormatType: 'Peer-to-Peer (Type 1)'
                SourceAddress: 30
                DestinationAddress: 50
```

```
Data Details:
```

```
-----  
      Timestamp: 0  
      Data: [10 0 100 0 255 255 255 255]  
      Signals: [1x1 struct]  
  
Other Information:  
-----  
      UserData: []
```

pg =

ParameterGroup with properties:

Protocol Data Unit Details:

```
-----  
      Name: 'VehicleDataSingle'  
      PGN: 40192  
      Priority: 5  
      PDUFormatType: 'Peer-to-Peer (Type 1)'  
      SourceAddress: 30  
      DestinationAddress: 50
```

Data Details:

```
-----  
      Timestamp: 0  
      Data: [10 0 100 0 232 3 255 255]  
      Signals: [1x1 struct]
```

Other Information:

```
-----  
      UserData: []
```

pg =

ParameterGroup with properties:

Protocol Data Unit Details:

```
-----  
      Name: 'VehicleDataSingle'  
      PGN: 40192  
      Priority: 5  
      PDUFormatType: 'Peer-to-Peer (Type 1)'  
      SourceAddress: 30  
      DestinationAddress: 50
```

Data Details:

```
-----  
      Timestamp: 0  
      Data: [10 0 100 0 232 3 16 39]  
      Signals: [1x1 struct]
```

Other Information:

```
-----  
      UserData: []
```

```
ans =  
  
struct with fields:  
  
    VehicleSignal4: 10000  
    VehicleSignal3: 1000  
    VehicleSignal2: 100  
    VehicleSignal1: 10
```

Write New Direct Data

You can also write values directly into the `Data` property.

```
pg.Data(1:2) = [50 0]  
pg.Signals
```

```
pg =  
  
ParameterGroup with properties:  
  
Protocol Data Unit Details:  
-----  
                Name: 'VehicleDataSingle'  
                PGN: 40192  
                Priority: 5  
                PDUFormatType: 'Peer-to-Peer (Type 1)'  
                SourceAddress: 30  
                DestinationAddress: 50  
  
Data Details:  
-----  
                Timestamp: 0  
                Data: [50 0 100 0 232 3 16 39]  
                Signals: [1x1 struct]  
  
Other Information:  
-----  
                UserData: []
```

```
ans =  
  
struct with fields:  
  
    VehicleSignal4: 10000  
    VehicleSignal3: 1000  
    VehicleSignal2: 100  
    VehicleSignal1: 50
```

Create and Use J1939 Channels

This example shows you how to use Vehicle Network Toolbox™ with J1939 to create and use J1939 channels to transmit and receive parameter groups on a network. This example uses the CAN database file, J1939.dbc. It also uses MathWorks Virtual CAN channels connected in a loopback configuration

Open the Database File

Open the database file to access the definitions.

```
db = canDatabase('J1939.dbc');
```

Create the J1939 Channels

Create J1939 channels on which you can send and receive information.

```
txCh = j1939Channel(db, 'MathWorks', 'Virtual 1', 1)
rxCh = j1939Channel(db, 'MathWorks', 'Virtual 1', 2)
```

```
txCh =
```

```
Channel with properties:
```

```
Device Information:
```

```
-----
```

```
DeviceVendor: 'MathWorks'
Device: 'Virtual 1'
DeviceChannelIndex: 1
DeviceSerialNumber: 0
```

```
Data Details:
```

```
-----
```

```
ParameterGroupsAvailable: 0
ParameterGroupsReceived: 0
ParameterGroupsTransmitted: 0
FilterPassList: []
FilterBlockList: []
```

```
Channel Information:
```

```
-----
```

```
Running: 0
BusStatus: 'N/A'
InitializationAccess: 1
InitialTimestamp: [0x0 datetime]
SilentMode: 0
TransceiverName: 'N/A'
TransceiverState: 'N/A'
BusSpeed: 500000
SJW: []
TSEG1: []
TSEG2: []
NumOfSamples: []
```

```
Other Information:
```

```
-----
```

```

        UserData: []

rxCh =

Channel with properties:

Device Information:
-----
        DeviceVendor: 'MathWorks'
        Device: 'Virtual 1'
        DeviceChannelIndex: 2
        DeviceSerialNumber: 0

Data Details:
-----
        ParameterGroupsAvailable: 0
        ParameterGroupsReceived: 0
        ParameterGroupsTransmitted: 0
        FilterPassList: []
        FilterBlockList: []

Channel Information:
-----
        Running: 0
        BusStatus: 'N/A'
        InitializationAccess: 1
        InitialTimestamp: [0x0 datetime]
        SilentMode: 0
        TransceiverName: 'N/A'
        TransceiverState: 'N/A'
        BusSpeed: 500000
        SJW: []
        TSEG1: []
        TSEG2: []
        NumOfSamples: []

Other Information:
-----
        UserData: []

```

Create the J1939 Parameter Groups

You can create J1939 parameter groups to send on the network.

```

pgSingleFrame = j1939ParameterGroup(db, 'VehicleDataSingle')
pgSingleFrame.SourceAddress = 30;
pgSingleFrame.DestinationAddress = 50;
pgMultiFrame = j1939ParameterGroup(db, 'VehicleDataMulti')
pgMultiFrame.SourceAddress = 30;
pgMultiFrame.DestinationAddress = 255;

```

```

pgSingleFrame =

ParameterGroup with properties:

```



```

Protocol Data Unit Details:
-----
          Name: 'VehicleDataSingle'
          PGN: 40192
          Priority: 6
          PDUFormatType: 'Peer-to-Peer (Type 1)'
          SourceAddress: 254
          DestinationAddress: 254

Data Details:
-----
          Timestamp: 0
          Data: [255 255 255 255 255 255 255 255]
          Signals: [1x1 struct]

Other Information:
-----
          UserData: []

```

pgMultiFrame =

ParameterGroup with properties:

```

Protocol Data Unit Details:
-----
          Name: 'VehicleDataMulti'
          PGN: 51200
          Priority: 6
          PDUFormatType: 'Peer-to-Peer (Type 1)'
          SourceAddress: 254
          DestinationAddress: 254

Data Details:
-----
          Timestamp: 0
          Data: [255 255 255 255 255 255 255 255 255 255 255 255]
          Signals: [1x1 struct]

Other Information:
-----
          UserData: []

```

Start the J1939 Channels

To begin using channels for transmit and receive operations, place them online.

```

start(rxCh);
start(txCh);

```

Send J1939 Parameter Groups

The transmit function sends parameter groups onto the network. The J1939 channel automatically sends parameter groups requiring multiframe messaging via its transport protocol.

```

transmit(txCh, pgSingleFrame)
transmit(txCh, pgSingleFrame)

```

```
transmit(txCh, pgMultiFrame)
transmit(txCh, pgSingleFrame)
transmit(txCh, pgSingleFrame)
pause(1);
```

Receive the Parameter Groups

The `receive` function retrieves information from the channel which represents messaging that occurred on the network.

```
pgRx = receive(rxCh, Inf)
```

```
pgRx =
```

```
1x5 ParameterGroup array with properties:
```

```
Protocol Data Unit Details:
```

```
-----
```

```
Name
PGN
Priority
PDUFormatType
SourceAddress
DestinationAddress
```

```
Data Details:
```

```
-----
```

```
Timestamp
Data
Signals
```

```
Other Information:
```

```
-----
```

```
UserData
```

Inspect Received Parameter Groups

View details of the received information.

```
pgRx(1)
```

```
ans =
```

```
ParameterGroup with properties:
```

```
Protocol Data Unit Details:
```

```
-----
```

```
                Name: 'VehicleDataSingle'
                PGN: 40192
                Priority: 6
                PDUFormatType: 'Peer-to-Peer (Type 1)'
                SourceAddress: 30
                DestinationAddress: 50
```

```
Data Details:
```

```
-----
```

```

Timestamp: 0.0262
  Data: [255 255 255 255 255 255 255]
  Signals: [1x1 struct]

```

```
Other Information:
```

```
-----
      UserData: []
```

Note Multiframe Reception

Parameter groups sent using the transport protocol are reconstructed in full detail by the channel.

```
pgRx(3)
```

```
ans =
```

```
ParameterGroup with properties:
```

```
Protocol Data Unit Details:
```

```
-----
      Name: 'VehicleDataMulti'
      PGN: 51200
      Priority: 6
      PDUFormatType: 'Peer-to-Peer (Type 1)'
      SourceAddress: 30
      DestinationAddress: 255
```

```
Data Details:
```

```
-----
      Timestamp: 1.9336
      Data: [255 255 255 255 255 255 255 255 255 255 255 255]
      Signals: [1x1 struct]
```

```
Other Information:
```

```
-----
      UserData: []
```

Stop the J1939 Channels

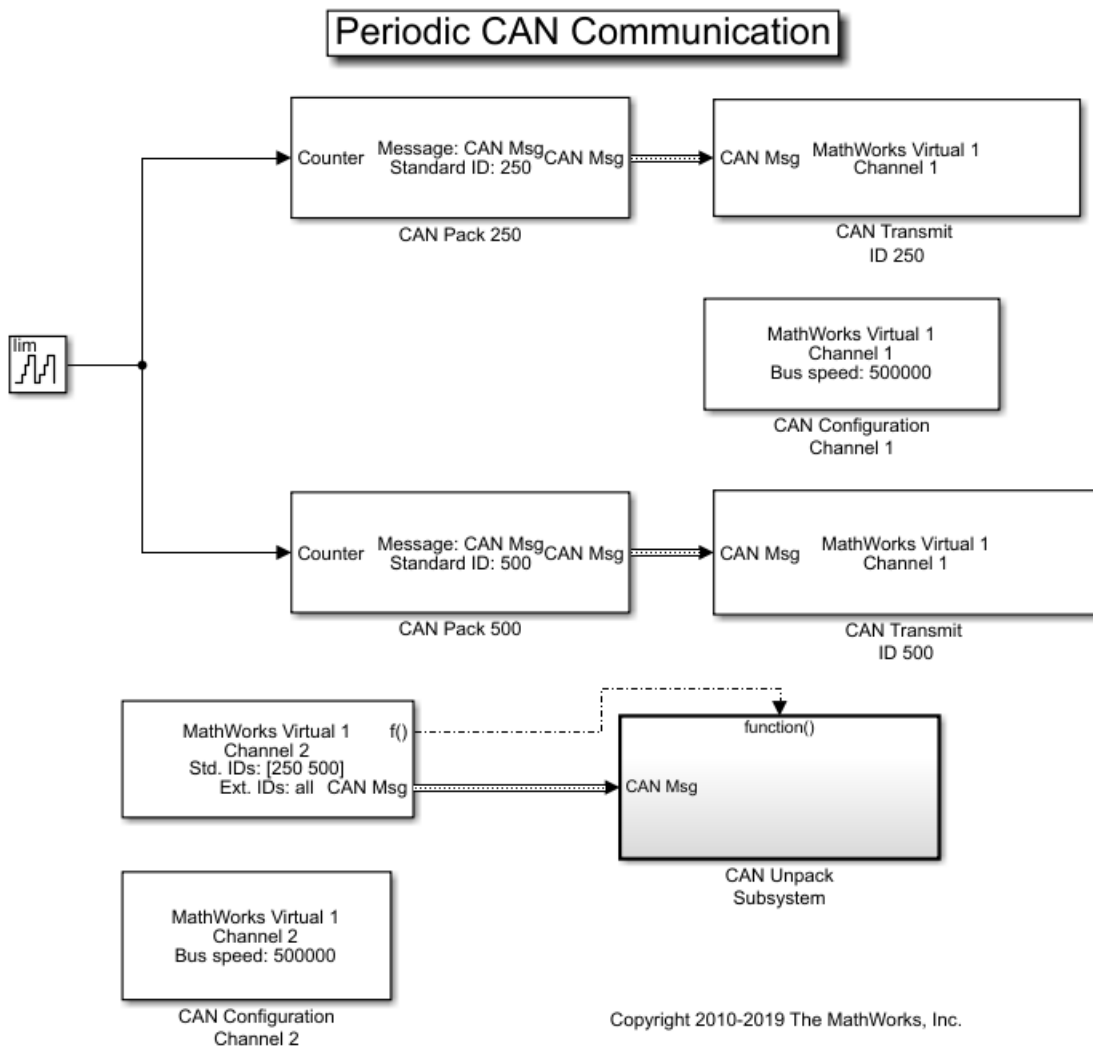
To stop receiving data from the network, stop the J1939 channels.

```
stop(rxCh);
stop(txCh);
```

Periodic CAN Communication

This example uses MathWorks Virtual CAN channels to set up periodic transmit and reception of CAN messages, using Simulink®. The Virtual channels are connected in a loopback configuration.

Vehicle Network Toolbox™ provides Simulink blocks for transmitting and receiving live messages via Simulink models over Controller Area Networks (CAN). This example uses the CAN Configuration, CAN Pack, CAN Transmit, CAN Receive and CAN Unpack blocks to perform data transfer over a CAN bus.



Transmit and Receive CAN Messages

Create a model to transmit two messages at different periods and receive only specified messages and unpack the message with a specified ID.

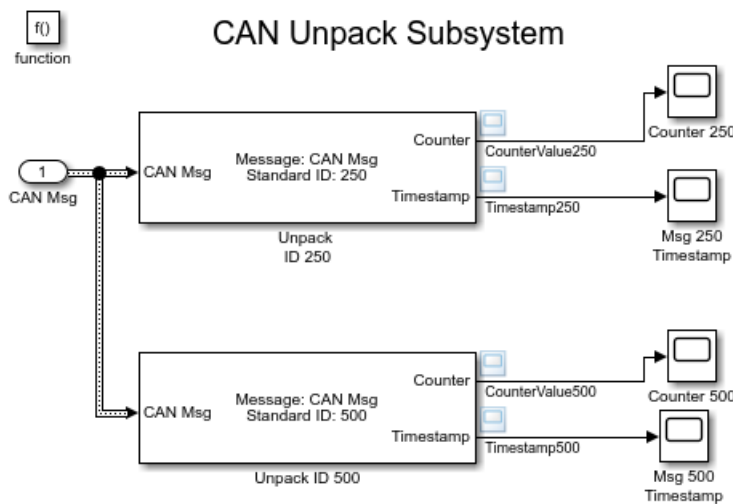
- Use a CAN Transmit block to transmit the CAN message with ID 250 to transmit messages every 1 second.

- Use another CAN Transmit block to transmit the CAN message with ID 500 to transmit messages every 0.5 seconds.
- Input a signal to both CAN Pack blocks to an auto-incrementing counter with a limit of 50.
- Both the CAN Transmit blocks are connected to MathWorks Virtual Channel 1.

Use a CAN Receive block to receive CAN messages from MathWorks Virtual Channel 2. Set the block to:

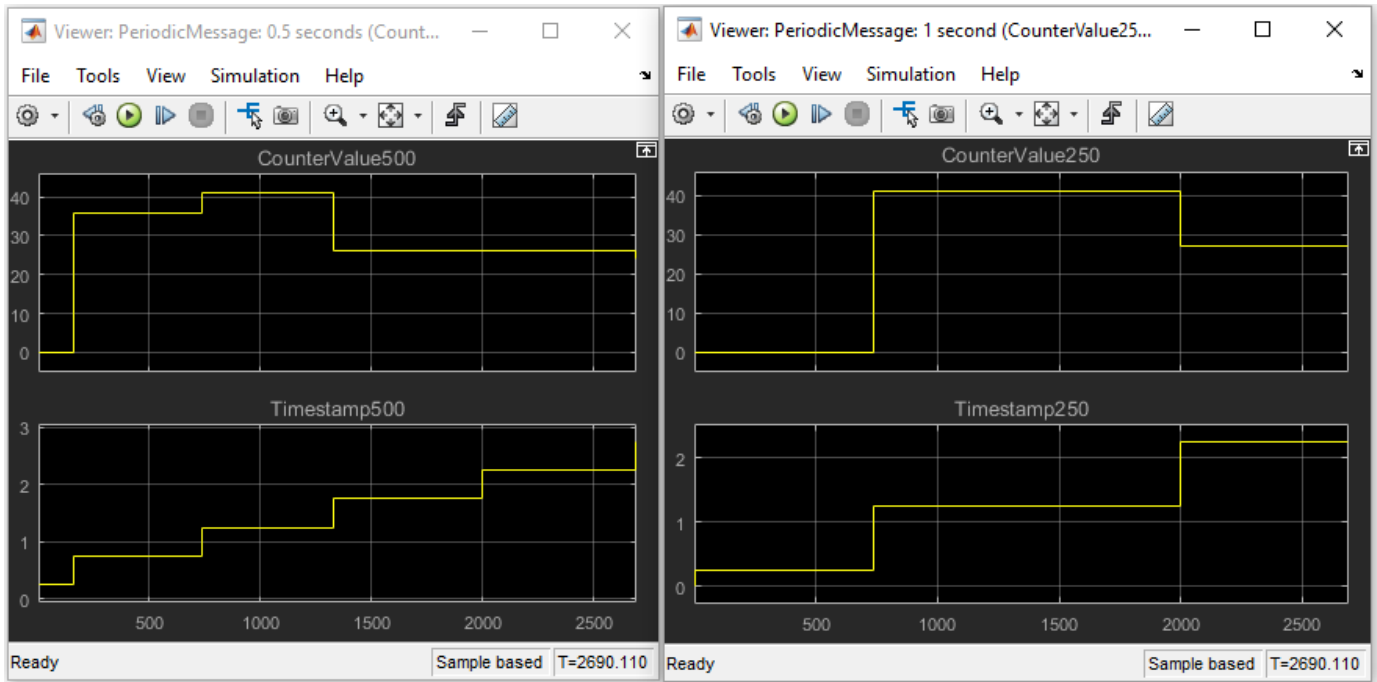
- Receive messages with ID 250 and 500 only.
- The Receive block generates a function call trigger if it receives a new message at any particular timestep.

The CAN Unpack subsystem is a function-call triggered subsystem and is executed only when a new message is received by the CAN Receive block at a particular timestep.



Visualize Messages at Different Timestamps

Plot the results to see the counter value and timestamp for each unpacked message. The X-axis on the plot corresponds to the simulation timestep. The timestamp plots show that the messages are sent at the specified times. It can also be seen that the number of messages transmitted for ID 250 is half as much transmitted for ID 500 due to the different periodic rates specified for them.



MathWorks CAN Virtual channels were used for this example. You can however connect your models to other supported hardware. You can also modify the model to transmit at different rates or transmit a combination of periodic and non-periodic messages.

Event-Based CAN Transmission in Simulink

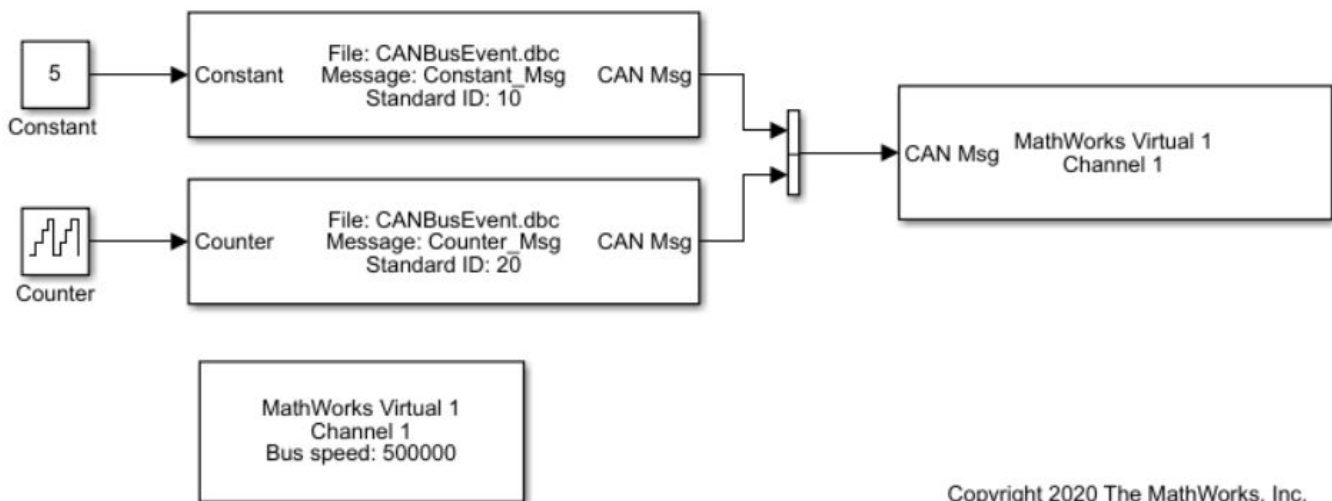
This example shows how to use event-based CAN message transmission in Simulink with Vehicle Network Toolbox. This feature allows for CAN and CAN FD message transmission when a change in data from one time step to the next is detected.

A configuration option available on the CAN and CAN FD Transmit blocks enables transmission on data change. When enabled, messages of particular CAN IDs transmit only when the data changes for that ID. Each message is independently processed in every time step based on its ID. When disabled, block operation and periodic transmit operation function normally. In addition, the event-based transmission can be enabled along with periodic transmission to have both work together simultaneously.

Prepare the Example Model

The included example model contains two CAN Pack blocks configured into a single CAN Transmit block. One message's data is a constant while the other is a counter that changes at every time step.

CAN Transmission Using Events



Copyright 2020 The MathWorks, Inc.

Open the example model.

open `EventTransmit`

Prepare the CAN Database File Access

You can access the contents of CAN DBC-files with the `canDatabase` function. Through this function, details about network nodes, messages, and signals are available. This DBC-file is used in the model and is used to decode information sent from the model.

```
db = canDatabase("CANBusEvent.dbc")
```

```
db =  
  Database with properties:  
  
      Name: 'CANBusEvent'  
      Path: '\\central-bgl\home$\aragarwa\Documents\MATLAB\Examples\vnt-ex59902587\CANBus'  
      Nodes: {'ECU'}  
      NodeInfo: [1x1 struct]  
      Messages: {2x1 cell}  
      MessageInfo: [2x1 struct]  
      Attributes: {}  
      AttributeInfo: [0x0 struct]  
      UserData: []
```

A test node is defined in the DBC-file.

```
node = nodeInfo(db, "ECU")  
  
node = struct with fields:  
      Name: 'ECU'  
      Comment: ''  
      Attributes: {}  
      AttributeInfo: [0x0 struct]
```

The node transmits two CAN messages.

```
messageInfo(db, "Constant_Msg")  
  
ans = struct with fields:  
      Name: 'Constant_Msg'  
      ProtocolMode: 'CAN'  
      Comment: ''  
      ID: 10  
      Extended: 0  
      J1939: []  
      Length: 4  
      DLC: 4  
      BRS: 0  
      Signals: {'Constant'}  
      SignalInfo: [1x1 struct]  
      TxNodes: {'ECU'}  
      Attributes: {}  
      AttributeInfo: [0x0 struct]
```

```
messageInfo(db, "Counter_Msg")  
  
ans = struct with fields:  
      Name: 'Counter_Msg'  
      ProtocolMode: 'CAN'  
      Comment: ''  
      ID: 20  
      Extended: 0  
      J1939: []  
      Length: 4  
      DLC: 4  
      BRS: 0  
      Signals: {'Counter'}
```



```

SignalInfo: [1x1 struct]
  TxNodes: {'ECU'}
  Attributes: {}
AttributeInfo: [0x0 struct]

```

Execute the Model with Event-Based Transmission

Enable Event-Based Transmission Only

Enable the event-based transmission in the CAN Transmit block programmatically. Also, disable periodic transmission.

```
db = canDatabase("CANBusEvent.dbc")
```

```
db =
```

```
Database with properties:
```

```

    Name: 'CANBusEvent'
    Path: '\\central-bgl\home$\aragarwa\Documents\MATLAB\Examples\vnt-ex59902587\CANBus
    Nodes: {'ECU'}
    NodeInfo: [1x1 struct]
    Messages: {2x1 cell}
    MessageInfo: [2x1 struct]
    Attributes: {}
    AttributeInfo: [0x0 struct]
    UserData: []

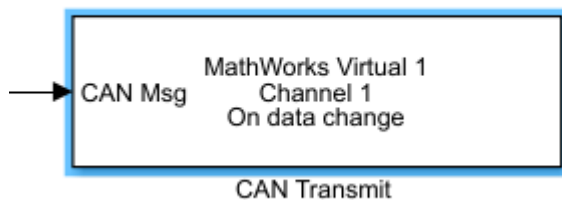
```

```

set_param('EventTransmit/CAN Transmit', 'EnableEventTransmit', 'on');
set_param('EventTransmit/CAN Transmit', 'EnablePeriodicTransmit', 'off');

```

Note that the block display changes after applying the settings.



Configure a CAN Channel in MATLAB for Communication with the Model

Create a CAN channel using virtual device communication to interface with the Simulink model. Also, attach the CAN database to it to automatically decode incoming messages.

```
canCh = canChannel("Mathworks", "Virtual 1", 2)
```

```
canCh =
```

```
Channel with properties:
```

```

Device Information
  DeviceVendor: 'MathWorks'
  Device: 'Virtual 1'

```

```
DeviceChannelIndex: 2
DeviceSerialNumber: 0
    ProtocolMode: 'CAN'

Status Information
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 0
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: [0x0 datetime]
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

Channel Information
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    BusSpeed: 500000
        SJW: []
        TSEG1: []
        TSEG2: []
    NumOfSamples: []

Other Information
    Database: []
    UserData: []
```

```
canCh.Database = db;
```

Start the CAN channel to go online.

```
start(canCh);
```

Run the Model

Assign a simulation run time and start the model.

```
t = "10";
set_param("EventTransmit", "StopTime", t)
set_param("EventTransmit", "SimulationCommand", "start");
```

Wait until the simulation starts.

```
while strcmp(get_param("EventTransmit", "SimulationStatus"), "stopped")
end
```

Wait until the simulation ends.

```
pause(2)
```

Receive Messages in MATLAB

Retrieve all messages from the bus generated by the model.

```
msg = receive(canCh, inf, "OutputFormat", "timetable")
```

msg=12x8 timetable							
Time	ID	Extended	Name	Data	Length	Signals	
0.26451 sec	10	false	{'Constant_Msg'}	{1x4 uint8}	4	{1x1 struct}	
0.26452 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}	
0.26839 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}	
0.26841 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}	
0.26842 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}	
0.26843 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}	
0.26844 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}	
0.26845 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}	
0.26846 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}	
0.26847 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}	
0.26848 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}	
0.26849 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}	

Stop the CAN channel in MATLAB.

```
stop(canCh);
```

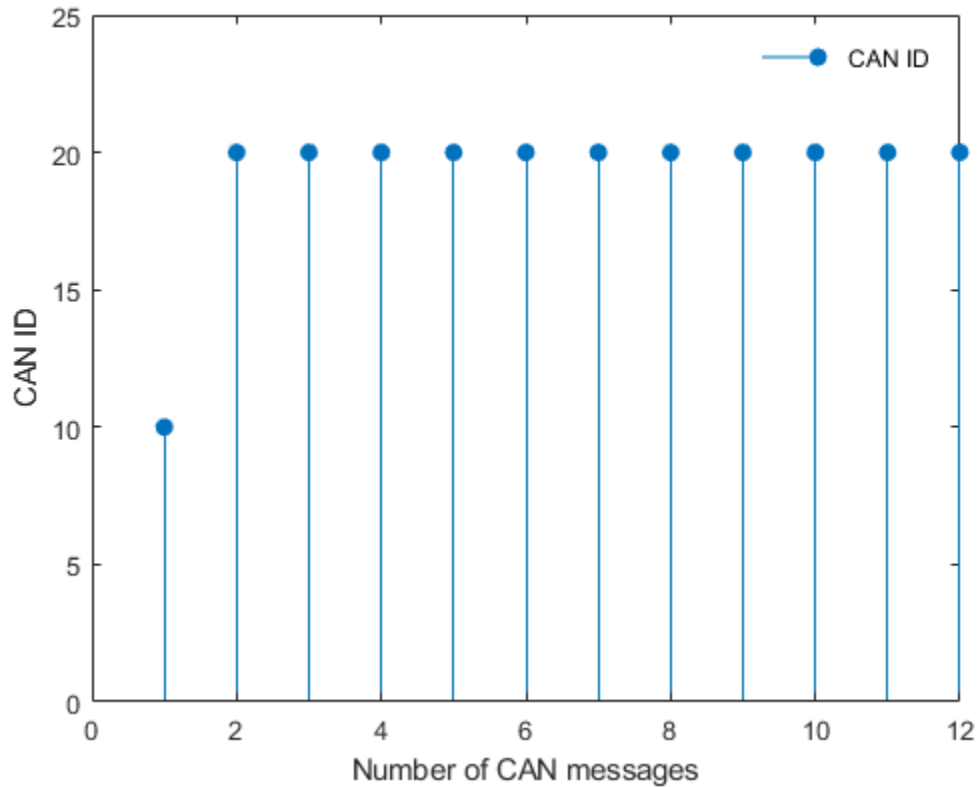
Explore the Message and Signal Data Received

The number of times a CAN ID has been received is plotted below. The message "Constant_Msg" (CAN ID 10) is received only once because its data does not change after its initial setting. The message "Counter_Msg" (CAN ID 20) is received from every time step because the data changed continuously in it as the model ran.

```
% Define X and Y axis.
x = 1:length(msg.ID);
y = msg.ID;

% Plot the graph for both the CAN IDs received.
stem(x,y,'filled')
hold on;
yMax = max(msg.ID)+5;
ylim([0 yMax])

% Label the graph.
xlabel("Number of CAN messages");
ylabel("CAN ID");
legend("CAN ID", "Location", "northeast");
legend("boxoff");
hold off;
```



Next, let's plot the signals received in each message over the same simulation run.

```
% Create a structure with signal details.
signalTimeTable = canSignalTimetable(msg);

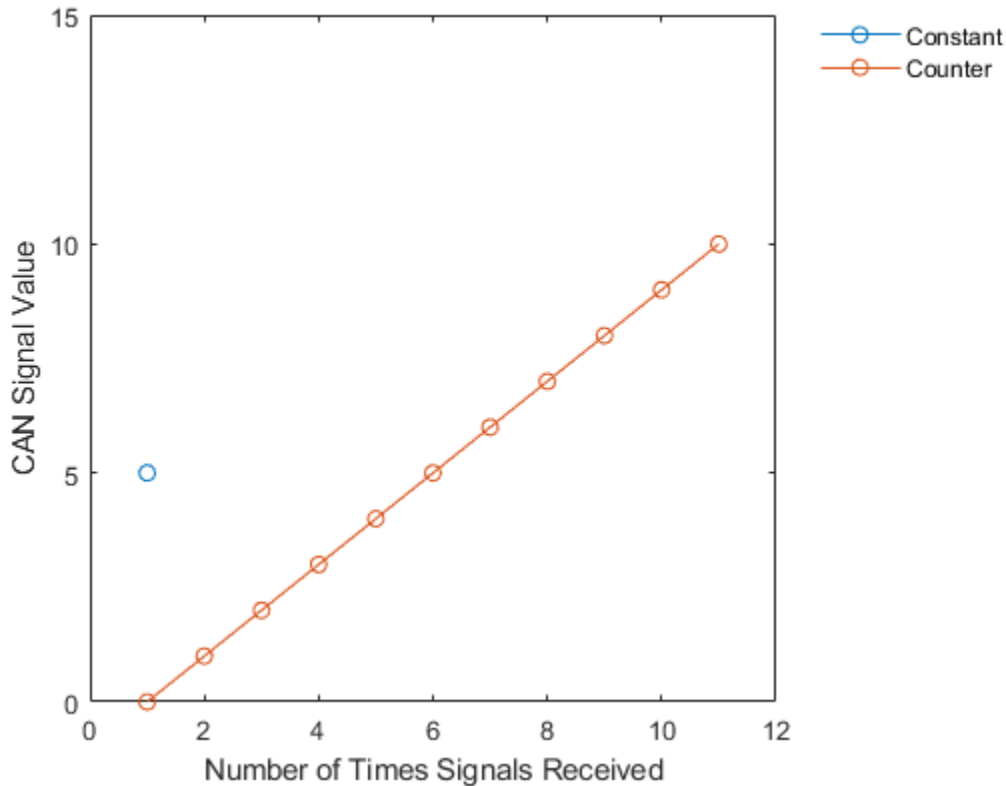
% Plot the signal values of "Constant_Msg".
x1 = 1:height(signalTimeTable.Constant_Msg);
y1 = signalTimeTable.Constant_Msg.Constant;
plot(x1, y1, "Marker", "o");
hold on

% Plot the signal values of "Counter_Msg".
x2 = 1:height(signalTimeTable.Counter_Msg);
y2 = signalTimeTable.Counter_Msg.Counter;
plot(x2, y2, "Marker", "o");

% Determine the maximum value for y-axis for scaling of graph.
y1Max = max(signalTimeTable.Constant_Msg.Constant);
y2Max = max(signalTimeTable.Counter_Msg.Counter);
yMax = max(y1Max, y2Max)+5;
ylim([0 yMax]);

% Label the graph.
xlabel("Number of Times Signals Received");
ylabel("CAN Signal Value");
legend("Constant", "Counter", "Location", "northeastoutside");
```

```
legend("boxoff");
hold off
```



The signal "Constant" (in message "Constant_Msg") is plotted only once, while the signal "Counter" (in message "Counter_Msg") is plotted for every time step. This is due to event-based transmission being enabled in the CAN Transmit block, which transmits a CAN message only if data has changed for that CAN ID compared with the previously received message.

As the signal in message "Counter_Msg" is a counter, which increments by 1 at every time step, a linear curve can be seen for it.

Each data points represents a transmission with event-based transmission enabled, hence signal "Counter" is received at every time step, but signal "Constant" is received only once.

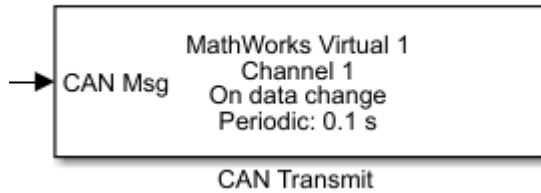
Execute the Model with Event-Based and Periodic Transmission

Enable Both Transmission Modes

Enable the event transmission in the CAN Transmit block programmatically. Also, enable the periodic transmission and set a message period.

```
set_param('EventTransmit/CAN Transmit', 'EnableEventTransmit', 'on');
set_param('EventTransmit/CAN Transmit', 'EnablePeriodicTransmit', 'on');
set_param('EventTransmit/CAN Transmit', 'MessagePeriod', '0.1');
```

Note that the block display changes after applying the settings.



Configure a CAN Channel in MATLAB for Communication with the Model

Create a CAN channel using virtual device communication to interface with the Simulink model. Also, attach the CAN database to it to automatically decode incoming messages.

```
canCh = canChannel("Mathworks", "Virtual 1", 2)
```

```
canCh =
```

```
Channel with properties:
```

```
Device Information
```

```
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 2
    DeviceSerialNumber: 0
    ProtocolMode: 'CAN'
```

```
Status Information
```

```
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 0
    MessagesTransmitted: 0
    InitializationAccess: 1
    InitialTimestamp: [0x0 datetime]
    FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'
```

```
Channel Information
```

```
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    BusSpeed: 500000
    SJW: []
    TSEG1: []
    TSEG2: []
    NumOfSamples: []
```

```
Other Information
```

```
    Database: []
    UserData: []
```

```
canCh.Database = db;
```

Start the CAN channel to go online.

```
start(canCh);
```

Run the Model

Assign a simulation run time and start the model.

```
t = "20";
set_param("EventTransmit", "StopTime", t)
set_param("EventTransmit", "SimulationCommand", "start");
```

Wait until the simulation starts.

```
while strcmp(get_param("EventTransmit", "SimulationStatus"), "stopped")
end
```

Wait until the simulation ends.

```
pause(5);
```

Receive Messages in MATLAB

Retrieve all messages from the bus generated by the model.

```
msg = receive(canCh, Inf, "OutputFormat", "timetable")
```

```
msg=28x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
0.29037 sec	10	false	{'Constant_Msg'}	{1x4 uint8}	4	{1x1 struct}
0.29037 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29192 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29194 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29196 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29197 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29198 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29199 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.292 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29201 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29202 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29203 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29204 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29204 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29205 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
0.29206 sec	20	false	{'Counter_Msg' }	{1x4 uint8}	4	{1x1 struct}
:						

Stop the CAN channel in MATLAB.

```
stop(canCh);
```

Explore the Data Received

Plot the data received in each message over the same period.

```
% Create a structure with signal details.
signalTimeTable = canSignalTimetable(msg);

% Plot the signal values of "Constant_Msg".
x3 = 1:height(signalTimeTable.Constant_Msg);
```

```

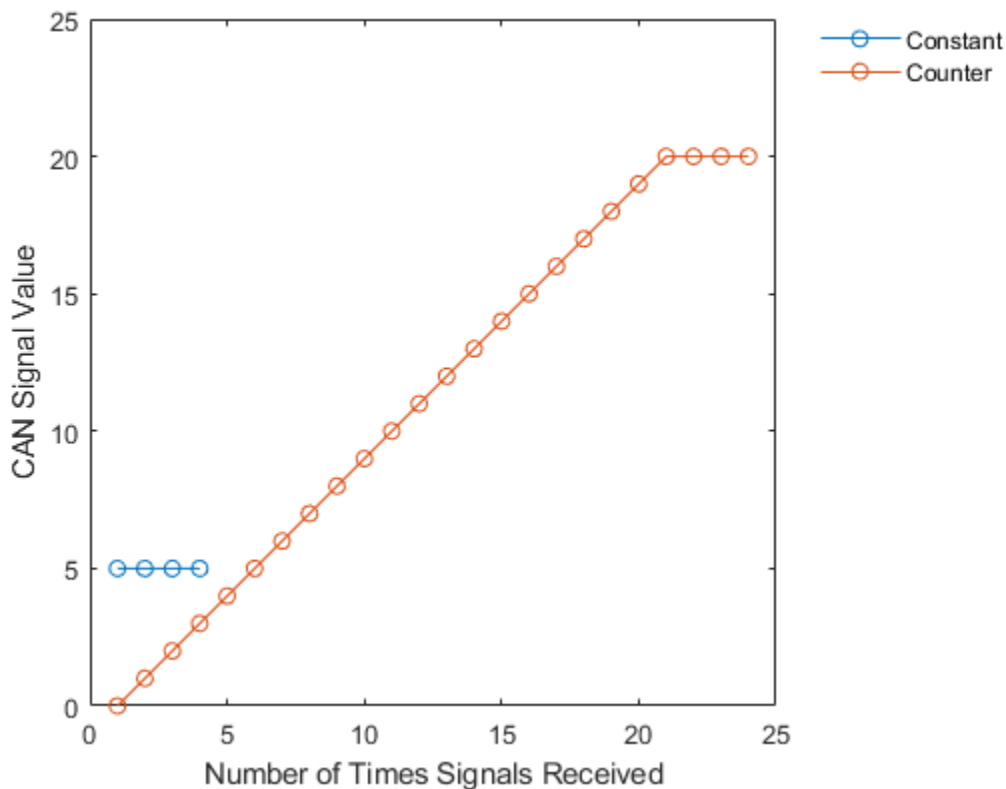
y3 = signalTimeTable.Constant_Msg.Constant;
plot(x3, y3, "Marker", "o");
hold on

% Plot the signal values of "Counter_Msg".
x4 = 1:height(signalTimeTable.Counter_Msg);
y4 = signalTimeTable.Counter_Msg.Counter;
plot(x4, y4, "Marker", "o");

% Determine the maximum value for y-axis for scaling of graph.
y3Max = max(signalTimeTable.Constant_Msg.Constant);
y4Max = max(signalTimeTable.Counter_Msg.Counter);
yMax = max(y3Max,y4Max)+5;
ylim([0 yMax]);

% Label the graph.
xlabel("Number of Times Signals Received");
ylabel("CAN Signal Value");
legend("Constant", "Counter", "Location", "northeastoutside");
legend("boxoff");
hold off

```



The plot shows that the signal "Constant" in message "Constant_Msg" is received only a few times; once at the start due to the event-based transmission, and later due to the periodic nature of the transmission. This is because the input value to the signal is kept constant.

While the value for signal "Counter" changes at every time step in the message "Counter_Msg", it is received continuously due to the event-based transmission, and later there are a few more transmissions because periodic transmission is enabled.

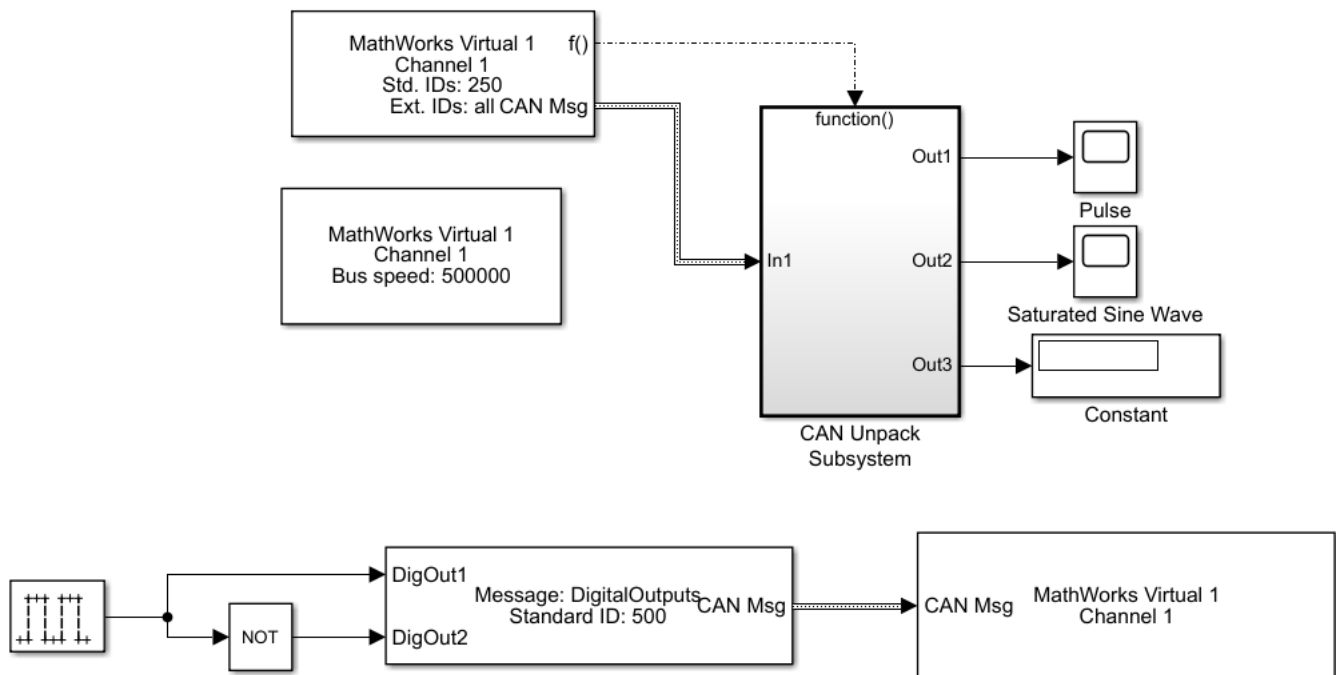
Set up Communication Between Host and Target Models

This example shows you how to set up CAN communication between host-side CAN Vector blocks and target models. This example uses:

- The Embedded Coder™ product with CANcaseXL hardware to open and run the model.
- The Spectrum Digital F28335 eZdsp™ board to run the target model.

Transmit and Receive Using a Host Model

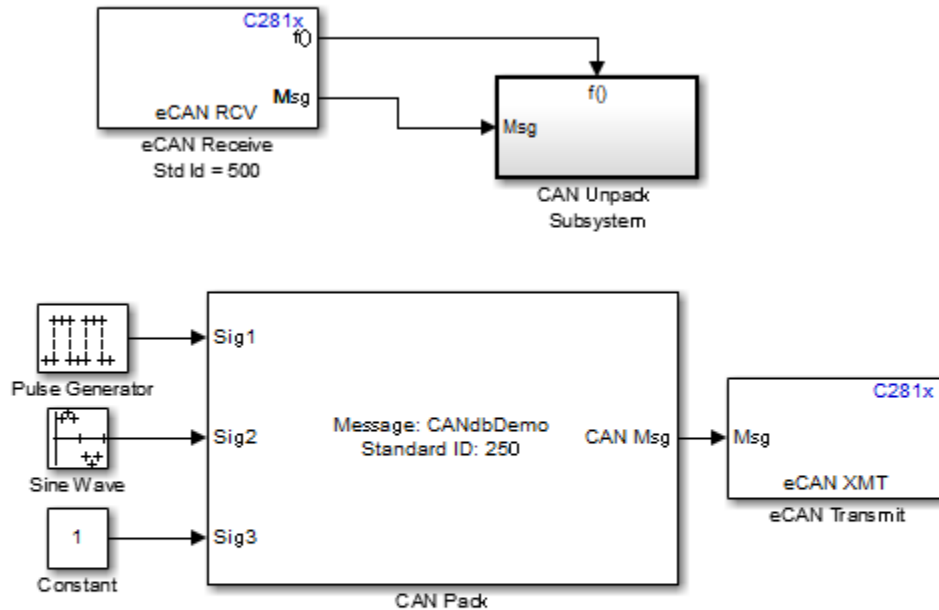
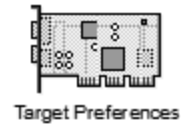
Host Model



The host model receives CAN messages through Channel 1 of Vector CANcaseXL hardware. The model transmits CAN messages using Channel 1 of Vector hardware over the CAN bus.

Transmit and Receive Using a Target Model

Target Model



This model illustrates how to use the CAN Pack and Unpack blocks to construct and inspect CAN messages. You can generate C281x specific code for this model.

If you have a CAN board and Vector CAN drivers installed, you can use the model `demoVNTSL_CANMessaging_Host` to exchange CAN messages with this model (running on C281x series hardware).

The target model contains the eCAN Receive and Transmit blocks that are packed and unpacked using the CAN Pack and Unpack blocks from Vehicle Network Toolbox™. To run this model successfully, the target model configuration settings done must match the host model configuration settings. The message that the target model receives controls the GPIO Digital outputs on the target DSP board.

Communication Between the Host and Target Models

Run the model `demoVNTSL_CANMessaging_Target.slx` on the target hardware.

Open the host side model `demoVNTSL_CANMessaging_Host.slx`.

Use the CAN Configuration block to configure a CAN channel on the Vector CAN hardware installed on your system.

Run the host communication model on your system.

CAN Messages are sent between the host model on your system and the target model running on your target hardware. The host receives, unpacks, and displays them using the display blocks and the scopes. The message transmitted by the host model controls the GPIO Digital outputs on the target hardware.

Vector CANcaseXL device was used for this example. You can however connect your models to other supported hardware.

Log and Replay CAN Messages

This example shows you how to log and replay CAN messages using MathWorks Virtual CAN channels in Simulink®. You can update this model to connect to supported hardware on your system.

Load the saved CAN message from `sourceMsgs.mat` file from the examples folder. The file contains CAN messages representing a 90 second drive cycle around a test track.

Convert these messages to a format compatible with the CAN Replay block and save it to a separate file.

Name	Size	Bytes	Class	Attributes
canMsgTimetable	100000x8	33510852	timetable	
canMsgs	1x1	2401176	struct	

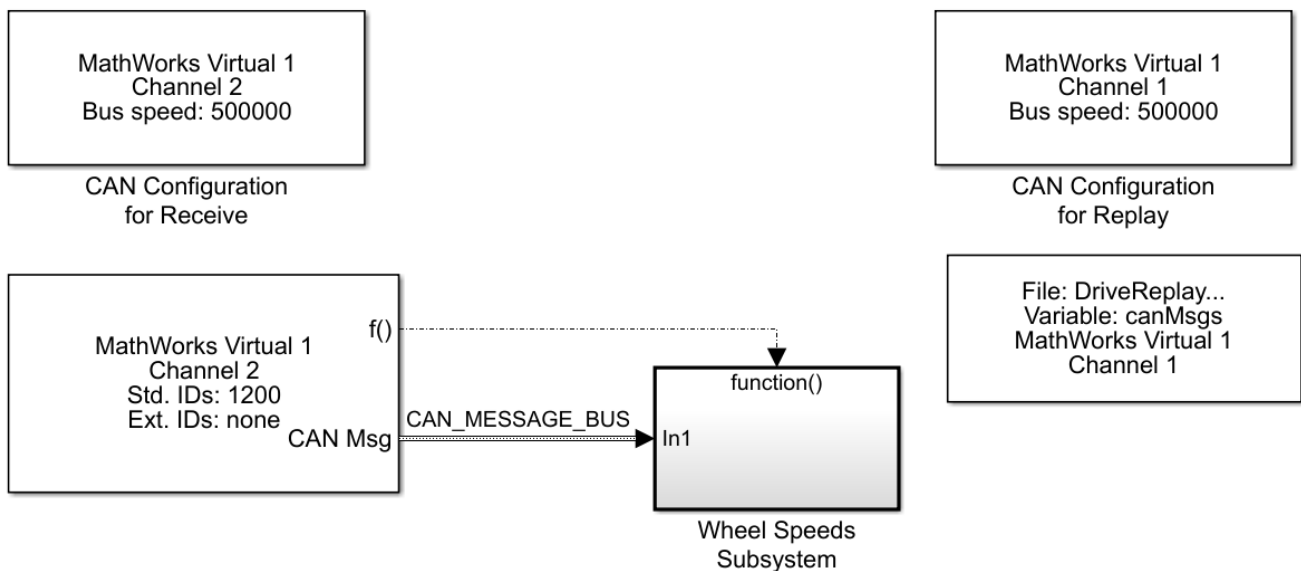
CAN Replay Model

This model contains:

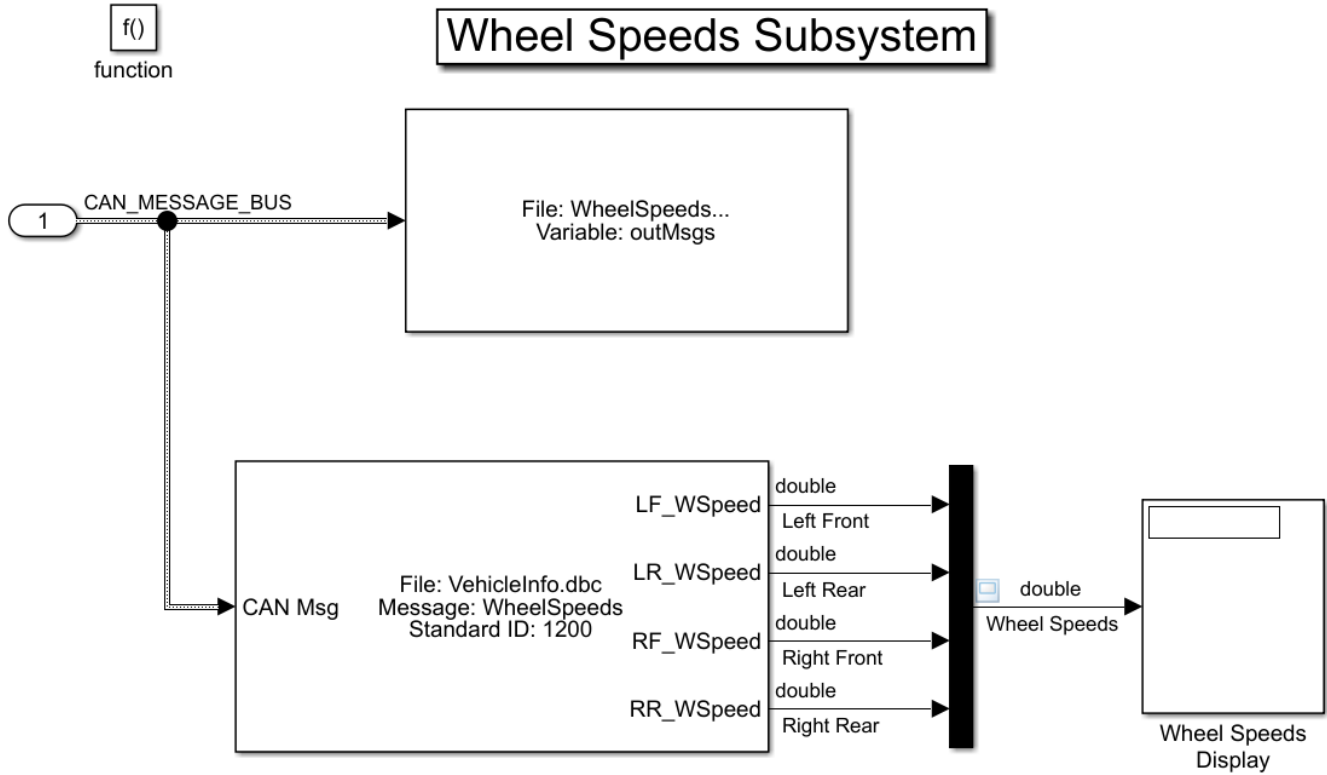
- A CAN Replay block that transmits to MathWorks Virtual Channel 1.
- A CAN Receive block that receives the messages on a CAN network, through MathWorks Virtual Channel 2.

The CAN Receive block is configured to block all extended IDs and allow only the `WheelSpeed` message with the standard ID 1200 to pass.

Log and Replay CAN Messages

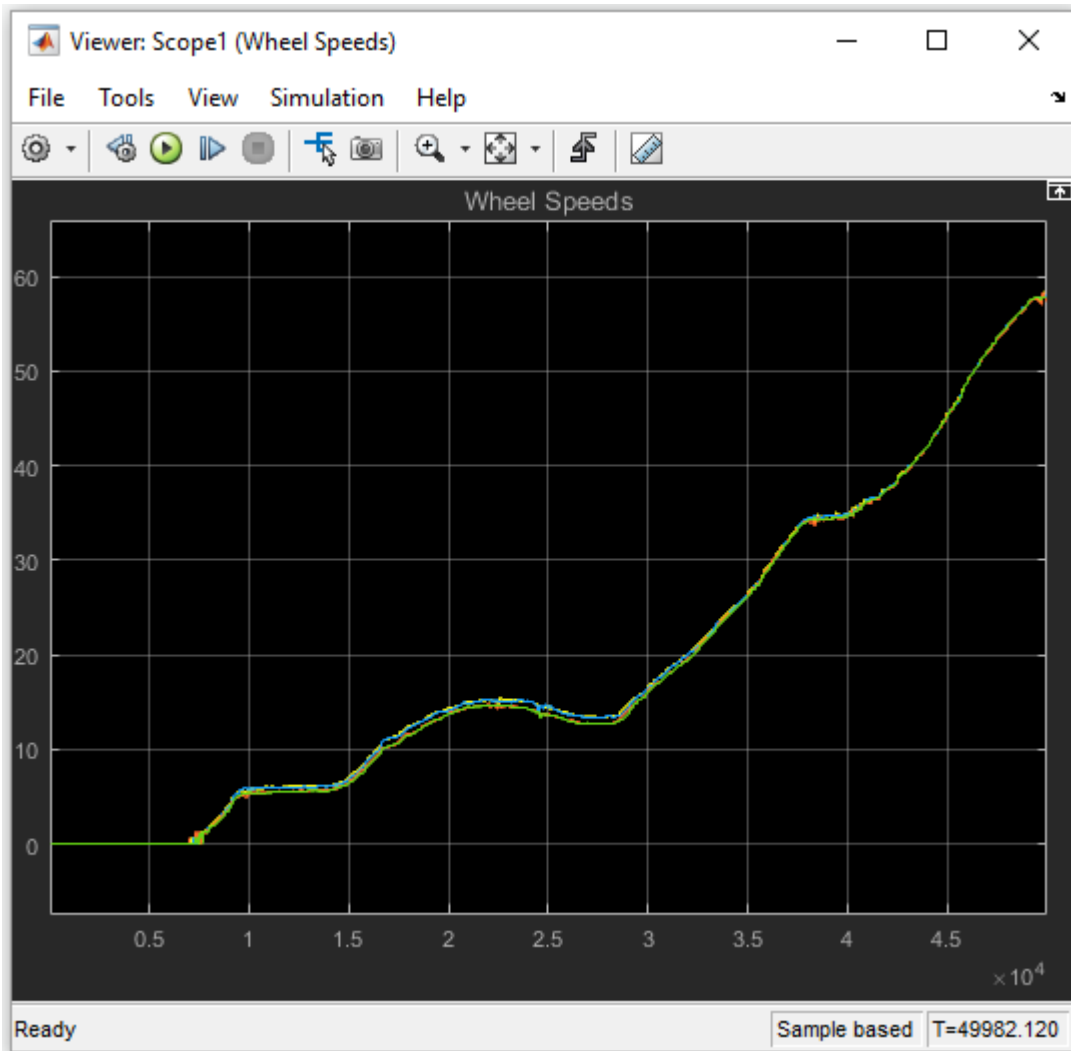


The Wheel Speeds subsystem unpacks the wheel speed information from the received CAN messages and plots them to a scope. The subsystem also logs the messages to a file.



Visualize Wheel Speed Information

The plot shows the wheel speed for all wheels for the duration of the test drive.



Load the Logged Message File

The CAN Log block creates a unique file each time you run the model. Use `dir` in the MATLAB Command Window to find the latest log file.

```
WheelSpeeds_2011-May-03_020634.mat
```

Name	Size	Bytes	Class	Attributes
canMsgTimetable	100000x8	33510852	timetable	
canMsgs	1x1	2401176	struct	
outMsgs	1x1	154320	struct	

Convert Logged Messages

Use `canMessageTimetable` to convert messages logged during the simulation to a timetable that you can use in the command window.

To access message signals directly, use the appropriate database file in the conversion along with `canSignalTimetable`.

ans =

15x8 timetable

Time	ID	Extended	Name	Data	Length	Signals
0.10701 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.1153 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.12349 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.13178 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.13998 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.14826 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.15647 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.16475 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.17338 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.18122 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.18941 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.19768 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.20591 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.2142 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}
0.2224 sec	1200	false	{'WheelSpeeds'}	{1x8 uint8}	8	{1x1 struct}

ans =

15x4 timetable

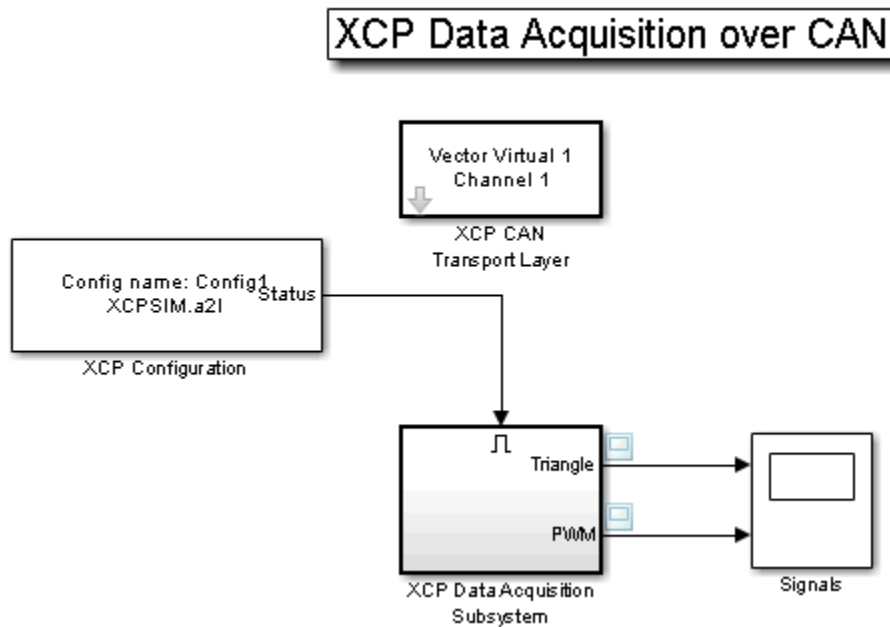
Time	LR_WSpeed	RR_WSpeed	RF_WSpeed	LF_WSpeed
0.10701 sec	0	0	0	0
0.1153 sec	0	0	0	0
0.12349 sec	0	0	0	0
0.13178 sec	0	0	0	0
0.13998 sec	0	0	0	0
0.14826 sec	0	0	0	0
0.15647 sec	0	0	0	0
0.16475 sec	0	0	0	0
0.17338 sec	0	0	0	0
0.18122 sec	0	0	0	0
0.18941 sec	0	0	0	0
0.19768 sec	0	0	0	0
0.20591 sec	0	0	0	0
0.2142 sec	0	0	0	0
0.2224 sec	0	0	0	0

MathWorks CAN Virtual channels were used for this example. You can however connect your models to other supported hardware.

XCP Data Acquisition over CAN

This example shows you how to use XCP blocks to directly acquire measurement values from a slave in Simulink®. It uses a freely available XCP slave simulator from Vector and Vector virtual CAN channels. For access to virtual channels, Vector device drivers must be installed.

Vehicle Network Toolbox™ provides Simulink blocks for acquiring measurement values from a slave via Simulink models over Controller Area Networks (CAN). This example uses the XCP Configuration, XCP Data Acquisition, and XCP CAN Transport Layer blocks to perform data transfer over a CAN bus.



Run a Slave Simulator

For this example, you must install a third party XCP Sample implementation from Vector. This includes a slave simulator and an A2L file. To install this free implementation:

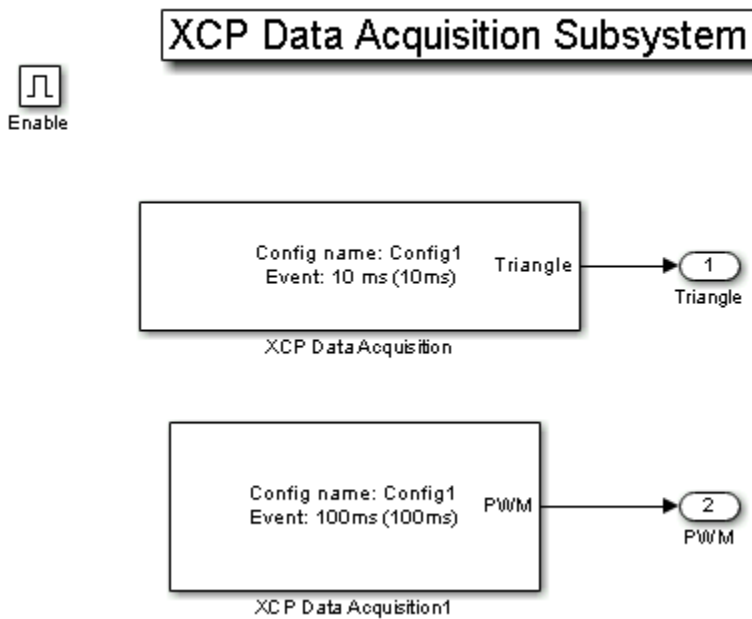
- 1 Go to www.vector.com and navigate to the "DOWNLOADS" page.
- 2 Search for "Demos" under "Categories" and "XCP" under "Standards".
- 3 Download and install the available version of "XCP Sample Implementation".
- 4 In MATLAB, navigate to where you installed the sample package, and then go to `.\Samples\XCPSim\CANape`.
- 5 The MATLAB XCP examples will use the `XCPSIM.a2l` file and the `XCPSim.exe` slave simulator. Run `XCPSim.exe`.

Setting up XCP Block Parameters

Create a model to set up XCP data acquisition for the measurements, Triangle and PWM, from the slave.

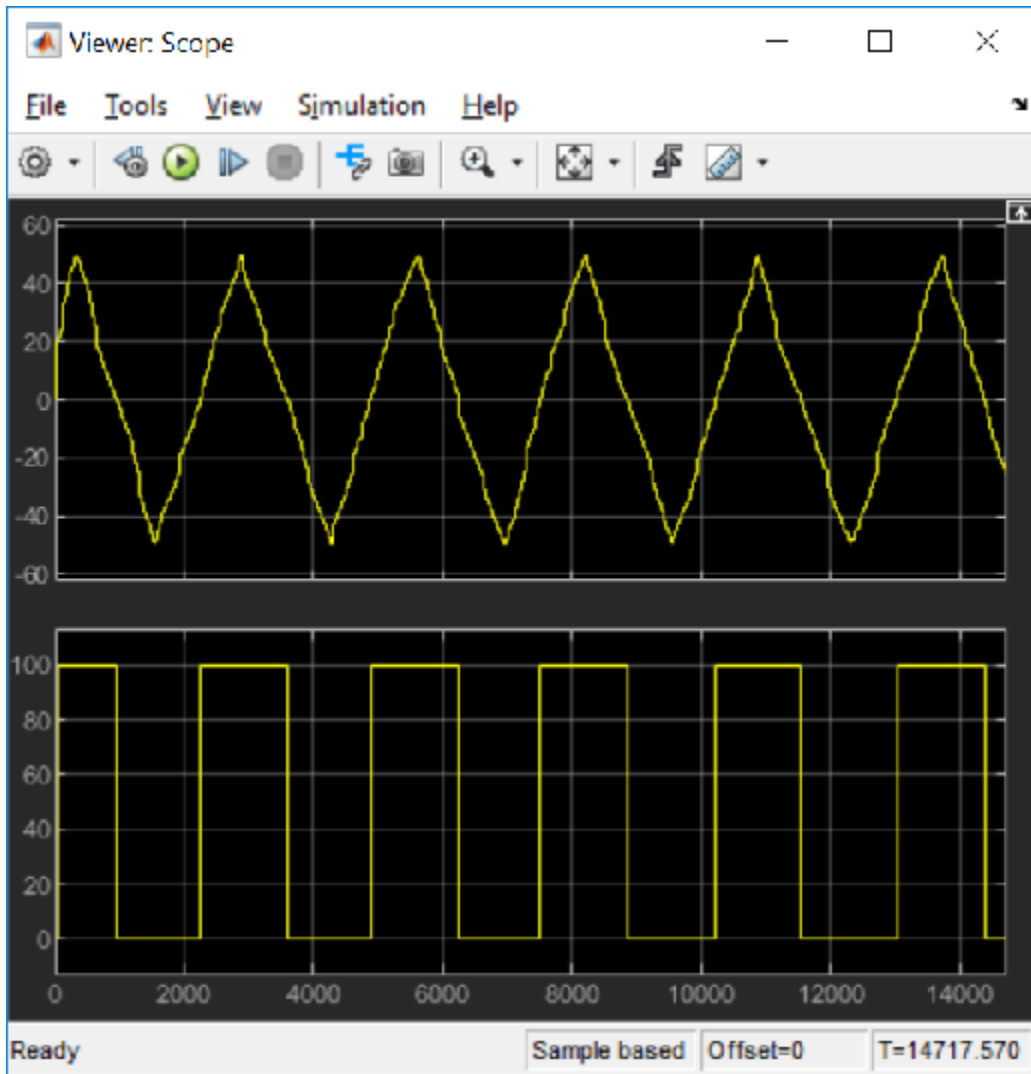
- Use an XCP Configuration block and select the A2L file, `XCPSim.a2l`

- Use an XCP CAN Transport Layer block and set the Device to Vector Virtual Channel 1. The transport layer is configured to transfer XCP messages over CAN via the specified virtual channel.
- Use XCP Data Acquisition blocks to receive selected measurements at specified events. For this example we have selected an XCP Data Acquisition block for each measurement of each selected event.



Visualize Measurement Values Received From Slave

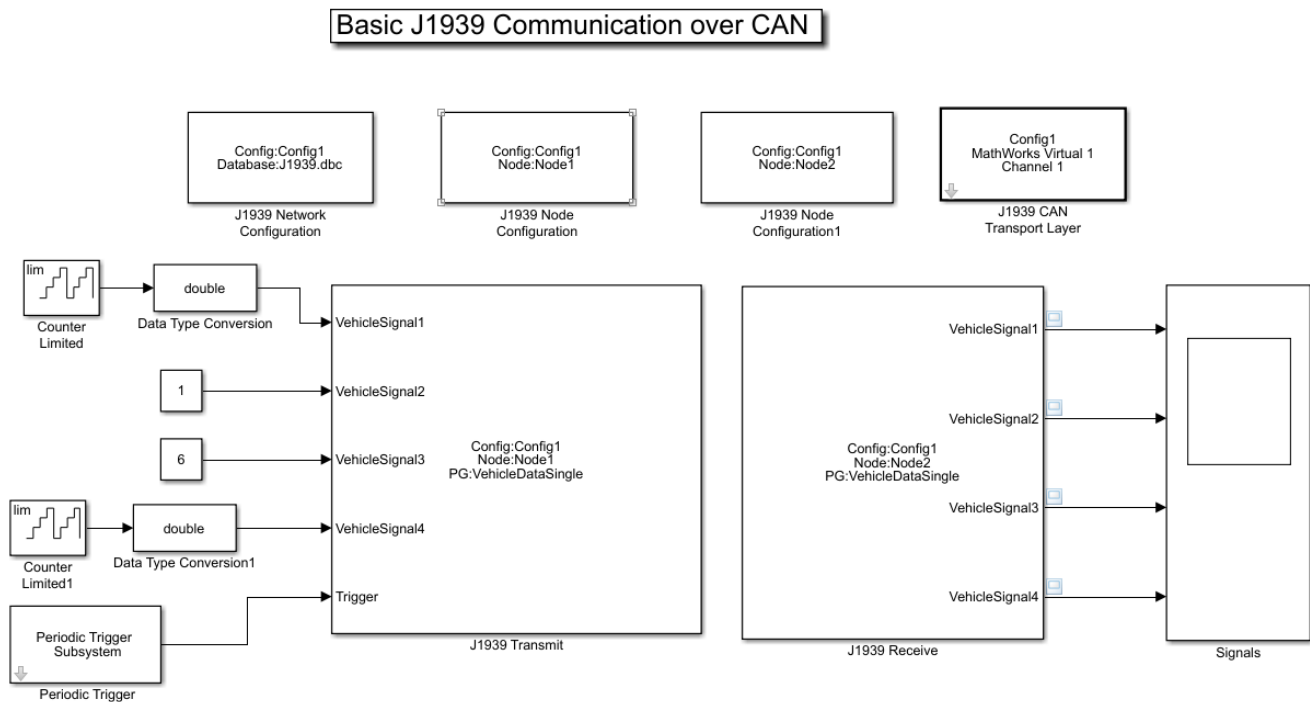
Plot the results to see the measurement values for Triangle and PWM from the slave. The X-axis corresponds to the simulation timestep.



Basic J1939 Communication over CAN

This example shows you how to use J1939 blocks to directly send and receive Parameter Group (PG) messages in Simulink®.

Vehicle Network Toolbox™ provides J1939 Simulink blocks for receiving and transmitting Parameter Groups via Simulink models over Controller Area Networks (CAN). This example performs data transfer over a CAN bus using the J1939 Network Configuration, J1939 Node Configuration, J1939 CAN Transport Layer, J1939 Receive and J1939 Transmit blocks. It also uses MathWorks Virtual CAN channels connected in a loopback configuration.



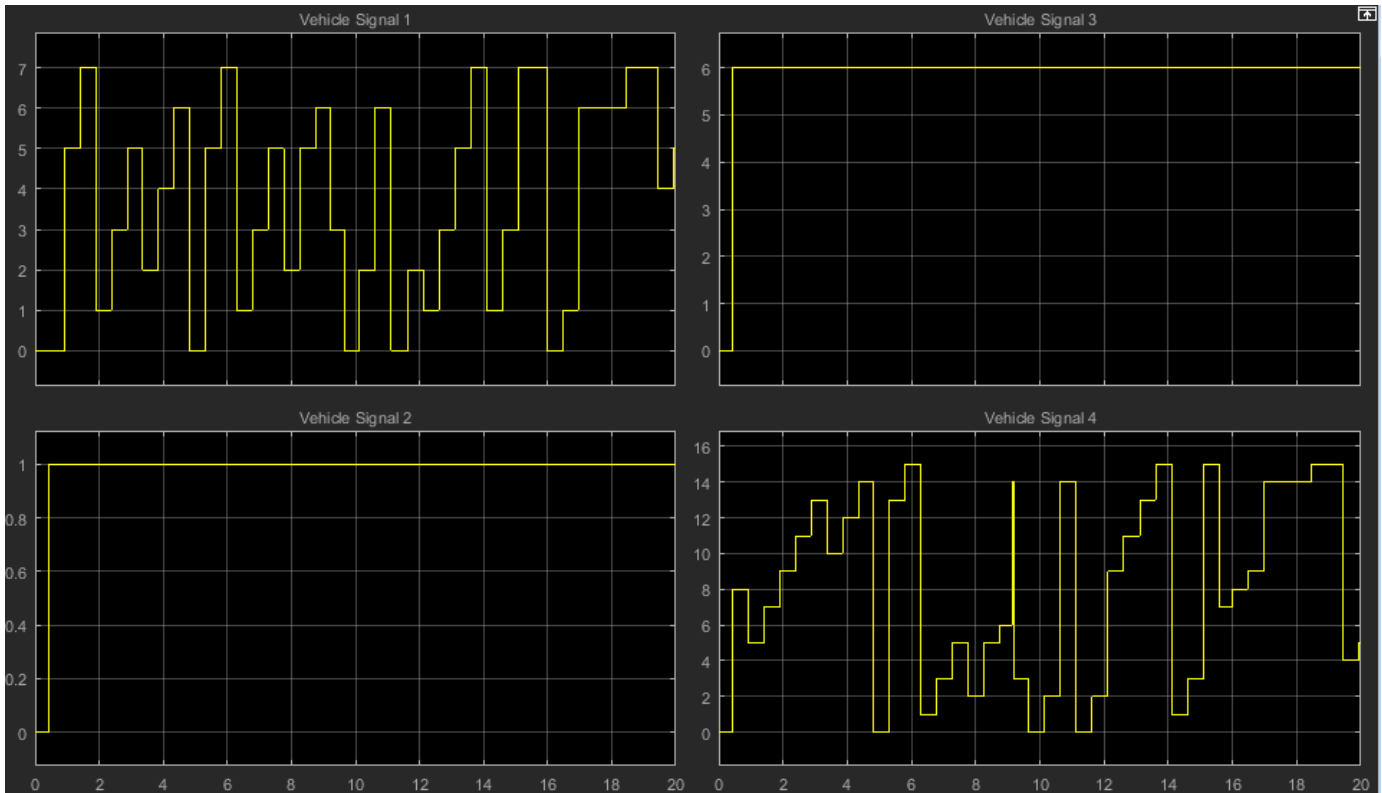
Set Up J1939 Block Parameters

Create a model to set up J1939 receive and transmit over the network. The model is configured to perform single frame transmission between two nodes defined in the J1939 database file.

- Use a J1939 Network Configuration block and select the CAN Database, J1939.dbc. This J1939 database file consists of two nodes and a couple of single-frame and multiframe messages.
- Use a J1939 CAN Transport Layer block and set the Device to MathWorks Virtual Channel 1. The transport layer is configured to transfer J1939 messages over CAN via the specified virtual channel.
- Use basic Simulink source blocks to connect to a J1939 Transmit block. The J1939 Transmit block is set to queue data for transmit at each timestep when the Trigger port is enabled. For this example, a periodic trigger subsystem sends a high pulse every 50 milliseconds.
- Use the J1939 Receive block to receive the messages transmitted over the network.

Visualize Signals Received on the Network

Plot the results to see the vehicle signal values received over the network. The X-axis corresponds to the simulation timestep.



Access MDF Files

This example shows you how to open MDF files and access information about the file and its contents.

Open an MDF File

Open an MDF file by specifying the name of the target file. Many basic details about the file are provided. This sample file was created using Vector CANape.

```
m = mdf("CANapeBasic.MF4")
```

```
m =
```

```
MDF with properties:
```

File Details

```
Name: 'CANapeBasic.MF4'
Path: '\\central-mi\home\michellw\Documents\MATLAB\Examples\vnt-ex51113426\CANapeBasic.MF4'
Author: 'Otmar Schneider'
Department: 'PMC @ Vector Informatik GmbH'
Project: 'Demo'
Subject: 'XCPSim'
Comment: 'Example file created with Vector CANape'
Version: '4.10'
DataSize: 176545
InitialTimestamp: 2016-04-21 14:27:17.000010630
```

Creator Details

```
ProgramIdentifier: 'MCD14.02'
Creator: [1x1 struct]
```

File Contents

```
Attachment: [0x1 struct]
ChannelNames: {2x1 cell}
ChannelGroup: [1x2 struct]
```

View File Creation Details

Information about the originating tool of the MDF file is found in the Creator property.

```
m.Creator
```

```
ans =
```

```
struct with fields:
```

```
VendorName: 'Vector Informatik GmbH'
ToolName: 'CANape'
ToolVersion: '14.0.20.2386'
UserName: 'visosr'
Comment: 'created'
```

View Channel Group Details

Data in an MDF file is stored in channels contained within channel groups. This sample file contains two channel groups.

```
m.ChannelGroup(1)
m.ChannelGroup(2)
```

```
ans =
```

```
struct with fields:
    AcquisitionName: '10 ms'
    Comment: '10 ms'
    NumSamples: 1993
    DataSize: 153461
    Sorted: 1
    Channel: [74x1 struct]
```

```
ans =
```

```
struct with fields:
    AcquisitionName: '100ms'
    Comment: '100ms'
    NumSamples: 199
    DataSize: 23084
    Sorted: 1
    Channel: [46x1 struct]
```

View Channel Details

Within a channel group, details about each channel are stored.

```
m.ChannelGroup(1).Channel(1)
```

```
ans =
```

```
struct with fields:
    Name: 'Counter_B4'
    DisplayName: ''
    ExtendedNamePrefix: 'XCPsim'
    Description: 'Single bit demo signal (bit from a byte shifting)'
    Comment: 'Single bit demo signal (bit from a byte shifting)'
    Unit: ''
    Type: FixedLength
    DataType: IntegerUnsignedLittleEndian
    NumBits: 1
    ComponentType: None
    CompositionType: None
```

Quickly Access Channels Names

The ChannelNames property allows quick access to find specific channels within the various channel groups.

```
m.ChannelNames
m.ChannelNames{1}
```

```
ans =
```

```
2×1 cell array
```

```
{74×1 cell}
{46×1 cell}
```

```
ans =
```

```
74×1 cell array
```

```
{'Counter_B4'           }
{'Counter_B5'           }
{'Counter_B6'           }
{'Counter_B7'           }
{'PWM'                   }
{'PWM_Level'            }
{'PWMFiltered'          }
{'Triangle'             }
{'map1_8_8_uc_measure[0][0]'}
{'map1_8_8_uc_measure[0][1]'}
{'map1_8_8_uc_measure[0][2]'}
{'map1_8_8_uc_measure[0][3]'}
{'map1_8_8_uc_measure[0][4]'}
{'map1_8_8_uc_measure[0][5]'}
{'map1_8_8_uc_measure[0][6]'}
{'map1_8_8_uc_measure[0][7]'}
{'map1_8_8_uc_measure[1][0]'}
{'map1_8_8_uc_measure[1][1]'}
{'map1_8_8_uc_measure[1][2]'}
{'map1_8_8_uc_measure[1][3]'}
{'map1_8_8_uc_measure[1][4]'}
{'map1_8_8_uc_measure[1][5]'}
{'map1_8_8_uc_measure[1][6]'}
{'map1_8_8_uc_measure[1][7]'}
{'map1_8_8_uc_measure[2][0]'}
{'map1_8_8_uc_measure[2][1]'}
{'map1_8_8_uc_measure[2][2]'}
{'map1_8_8_uc_measure[2][3]'}
{'map1_8_8_uc_measure[2][4]'}
{'map1_8_8_uc_measure[2][5]'}
{'map1_8_8_uc_measure[2][6]'}
{'map1_8_8_uc_measure[2][7]'}
{'map1_8_8_uc_measure[3][0]'}
{'map1_8_8_uc_measure[3][1]'}
{'map1_8_8_uc_measure[3][2]'}
{'map1_8_8_uc_measure[3][3]'}
{'map1_8_8_uc_measure[3][4]'}

```



```

{'map1_8_8_uc_measure[3][5]'}
{'map1_8_8_uc_measure[3][6]'}
{'map1_8_8_uc_measure[3][7]'}
{'map1_8_8_uc_measure[4][0]'}
{'map1_8_8_uc_measure[4][1]'}
{'map1_8_8_uc_measure[4][2]'}
{'map1_8_8_uc_measure[4][3]'}
{'map1_8_8_uc_measure[4][4]'}
{'map1_8_8_uc_measure[4][5]'}
{'map1_8_8_uc_measure[4][6]'}
{'map1_8_8_uc_measure[4][7]'}
{'map1_8_8_uc_measure[5][0]'}
{'map1_8_8_uc_measure[5][1]'}
{'map1_8_8_uc_measure[5][2]'}
{'map1_8_8_uc_measure[5][3]'}
{'map1_8_8_uc_measure[5][4]'}
{'map1_8_8_uc_measure[5][5]'}
{'map1_8_8_uc_measure[5][6]'}
{'map1_8_8_uc_measure[5][7]'}
{'map1_8_8_uc_measure[6][0]'}
{'map1_8_8_uc_measure[6][1]'}
{'map1_8_8_uc_measure[6][2]'}
{'map1_8_8_uc_measure[6][3]'}
{'map1_8_8_uc_measure[6][4]'}
{'map1_8_8_uc_measure[6][5]'}
{'map1_8_8_uc_measure[6][6]'}
{'map1_8_8_uc_measure[6][7]'}
{'map1_8_8_uc_measure[7][0]'}
{'map1_8_8_uc_measure[7][1]'}
{'map1_8_8_uc_measure[7][2]'}
{'map1_8_8_uc_measure[7][3]'}
{'map1_8_8_uc_measure[7][4]'}
{'map1_8_8_uc_measure[7][5]'}
{'map1_8_8_uc_measure[7][6]'}
{'map1_8_8_uc_measure[7][7]'}
{'map1_8_8_uc_measure'      }
{'t'                        }

```

Find Channels in an MDF File

The `channelList` function is available to quickly and easily query for channel details within an MDF file. It returns a case-insensitive, partial match to the provided input by default, but an exact match can also be used.

```

channelList(m, "PWM")
channelList(m, "PWM", "ExactMatch", true)

```

ans =

3×9 table

ChannelName	ChannelGroupNumber	ChannelGroupNumSamples	ChannelGroupAcquisitionName
"PWM"	1	1993	10 ms
"PWM_Level"	1	1993	10 ms

```
"PWMFiltered"      1      1993      10 ms
```

```
ans =
```

```
1×9 table
```

<u>ChannelName</u>	<u>ChannelGroupNumber</u>	<u>ChannelGroupNumSamples</u>	<u>ChannelGroupAcquisitionName</u>
"PWM"	1	1993	10 ms

Reading Data from MDF Files

This example shows you how to read channel data from an MDF file.

Open the MDF file

Before reading channel data from an MDF file, open access to the file with the `mdf` command.

```
m = mdf('CANape.MF4')
```

```
m =
```

```
MDF with properties:
```

File Details

```
Name: 'CANape.MF4'
Path: '\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex94427230\CANape.MF4'
Author: 'Otmar Schneider'
Department: 'PMC @ Vector Informatik GmbH'
Project: 'Demo'
Subject: 'XCPSim'
Comment: 'Example file created with Vector CANape'
Version: '4.10'
DataSize: 176545
InitialTimestamp: 2016-04-21 14:27:17.000010629
```

Creator Details

```
ProgramIdentifier: 'MCD14.02'
Creator: [1x1 struct]
```

File Contents

```
Attachment: [0x0 struct]
ChannelNames: {2x1 cell}
ChannelGroup: [1x2 struct]
```

Specifying Data to Read

The `read` command is used to retrieve data from the MDF file with several variations. It requires two primary arguments. One is the numeric index of the channel group from which to read. Second is the name(s) of the channels in the channel group to read. Information about these items is available from the MDF file.

```
m.ChannelGroup(1)
m.ChannelNames{1}
```

```
ans =
```

```
struct with fields:
```

```
AcquisitionName: '10 ms'
Comment: '10 ms'
NumSamples: 1993
DataSize: 153461
Sorted: 1
Channel: [1x74 struct]
```

ans =

74×1 cell array

```
{'Counter_B4'           }
{'Counter_B5'           }
{'Counter_B6'           }
{'Counter_B7'           }
{'PWM'                   }
{'PWM_Level'            }
{'PWMFiltered'          }
{'Triangle'             }
{'map1_8_8_uc_measure[0][0]'}
{'map1_8_8_uc_measure[0][1]'}
{'map1_8_8_uc_measure[0][2]'}
{'map1_8_8_uc_measure[0][3]'}
{'map1_8_8_uc_measure[0][4]'}
{'map1_8_8_uc_measure[0][5]'}
{'map1_8_8_uc_measure[0][6]'}
{'map1_8_8_uc_measure[0][7]'}
{'map1_8_8_uc_measure[1][0]'}
{'map1_8_8_uc_measure[1][1]'}
{'map1_8_8_uc_measure[1][2]'}
{'map1_8_8_uc_measure[1][3]'}
{'map1_8_8_uc_measure[1][4]'}
{'map1_8_8_uc_measure[1][5]'}
{'map1_8_8_uc_measure[1][6]'}
{'map1_8_8_uc_measure[1][7]'}
{'map1_8_8_uc_measure[2][0]'}
{'map1_8_8_uc_measure[2][1]'}
{'map1_8_8_uc_measure[2][2]'}
{'map1_8_8_uc_measure[2][3]'}
{'map1_8_8_uc_measure[2][4]'}
{'map1_8_8_uc_measure[2][5]'}
{'map1_8_8_uc_measure[2][6]'}
{'map1_8_8_uc_measure[2][7]'}
{'map1_8_8_uc_measure[3][0]'}
{'map1_8_8_uc_measure[3][1]'}
{'map1_8_8_uc_measure[3][2]'}
{'map1_8_8_uc_measure[3][3]'}
{'map1_8_8_uc_measure[3][4]'}
{'map1_8_8_uc_measure[3][5]'}
{'map1_8_8_uc_measure[3][6]'}
{'map1_8_8_uc_measure[3][7]'}
{'map1_8_8_uc_measure[4][0]'}
{'map1_8_8_uc_measure[4][1]'}
{'map1_8_8_uc_measure[4][2]'}
{'map1_8_8_uc_measure[4][3]'}
{'map1_8_8_uc_measure[4][4]'}
{'map1_8_8_uc_measure[4][5]'}
{'map1_8_8_uc_measure[4][6]'}
{'map1_8_8_uc_measure[4][7]'}
{'map1_8_8_uc_measure[5][0]'}
{'map1_8_8_uc_measure[5][1]'}
{'map1_8_8_uc_measure[5][2]'}
{'map1_8_8_uc_measure[5][3]'}

```

```

{'map1_8_8_uc_measure[5][4]'}
{'map1_8_8_uc_measure[5][5]'}
{'map1_8_8_uc_measure[5][6]'}
{'map1_8_8_uc_measure[5][7]'}
{'map1_8_8_uc_measure[6][0]'}
{'map1_8_8_uc_measure[6][1]'}
{'map1_8_8_uc_measure[6][2]'}
{'map1_8_8_uc_measure[6][3]'}
{'map1_8_8_uc_measure[6][4]'}
{'map1_8_8_uc_measure[6][5]'}
{'map1_8_8_uc_measure[6][6]'}
{'map1_8_8_uc_measure[6][7]'}
{'map1_8_8_uc_measure[7][0]'}
{'map1_8_8_uc_measure[7][1]'}
{'map1_8_8_uc_measure[7][2]'}
{'map1_8_8_uc_measure[7][3]'}
{'map1_8_8_uc_measure[7][4]'}
{'map1_8_8_uc_measure[7][5]'}
{'map1_8_8_uc_measure[7][6]'}
{'map1_8_8_uc_measure[7][7]'}
{'map1_8_8_uc_measure'      }
{'t'                        }

```

Read a Subset of Data by Index

To read just a subset of data by index, the index range is provided as input to the read command.

```
data = read(m, 1, m.ChannelNames{1}, 1, 10)
```

```
data =
```

```
10×74 timetable
```

Time	Counter_B4	Counter_B5	Counter_B6	Counter_B7	PWM	PWM_Level
0.00082554 sec	0	0	1	0	100	0
0.010826 sec	0	0	1	0	100	0
0.020826 sec	0	0	1	0	100	0
0.030826 sec	0	0	1	0	100	0
0.040826 sec	0	0	1	0	100	0
0.050826 sec	0	0	1	0	100	0
0.060826 sec	0	0	1	0	100	0
0.070826 sec	0	0	1	0	100	0
0.080826 sec	0	0	1	0	100	0
0.090826 sec	0	0	1	0	100	0

Read a Specific Data Value by Index

Providing a single numeric index argument will retrieve the data values at that index.

```
data = read(m, 1, m.ChannelNames{1}, 5)
```

```
data =
```

```
1x74 timetable
```

Time	Counter_B4	Counter_B5	Counter_B6	Counter_B7	PWM	PWM_Level
0.040826 sec	0	0	1	0	100	0

Read a Subset of Data by Time

To read a subset of data by time, duration arguments are provided as input to the read command.

```
data = read(m, 1, m.ChannelNames{1}, seconds(0.50), seconds(0.60))
```

```
data =
```

```
10x74 timetable
```

Time	Counter_B4	Counter_B5	Counter_B6	Counter_B7	PWM	PWM_Level
0.50083 sec	1	1	1	0	0	0
0.51083 sec	1	1	1	0	0	0
0.52083 sec	1	1	1	0	0	0
0.53083 sec	1	1	1	0	0	0
0.54083 sec	1	1	1	0	0	0
0.55083 sec	1	1	1	0	0	0
0.56083 sec	1	1	1	0	0	0
0.57083 sec	1	1	1	0	0	0
0.58083 sec	1	1	1	0	0	0
0.59083 sec	1	1	1	0	0	0

Read a Specific Data Value by Time

Providing a single duration will retrieve the data values at or closest to that timestamp.

```
data = read(m, 1, m.ChannelNames{1}, seconds(0.55))
```

```
data =
```

```
1x74 timetable
```

Time	Counter_B4	Counter_B5	Counter_B6	Counter_B7	PWM	PWM_Level
0.55083 sec	1	1	1	0	0	0

Output Format Defaults to Timetable

The default output format of the read command is a timetable. This option can also be controlled with the OutputFormat argument.

```
data = read(m, 1, 'Triangle', 1, 10, 'OutputFormat', 'timetable')
```

```
data =
```

```
10x1 timetable
```

Time	Triangle
0.00082554 sec	18
0.010826 sec	17
0.020826 sec	16
0.030826 sec	15
0.040826 sec	14
0.050826 sec	13
0.060826 sec	12
0.070826 sec	11
0.080826 sec	10
0.090826 sec	9

Output Data as Timeseries

If a timeseries is desired as output, the `OutputFormat` can be specified to the `read` command. When outputting data as a timeseries, only a single channel may be read at a time.

```
data = read(m, 1, 'Triangle', 1, 10, 'OutputFormat', 'timeseries')
```

```
timeseries
```

```
Common Properties:
```

```
    Name: 'Triangle'
    Time: [10x1 double]
    TimeInfo: tsdata.timemetadata
    Data: [10x1 double]
    DataInfo: tsdata.datametadata
```

Output Data as Vectors

Output from the `read` command can also be specified as vectors. When outputting data as a vector, only a single channel may be read at a time.

```
[data, time] = read(m, 1, 'Triangle', 1, 10, 'OutputFormat', 'vector')
```

```
data =
```

```
18
17
16
15
14
13
12
11
10
9
```

```
time =
```

```
0.0008  
0.0108  
0.0208  
0.0308  
0.0408  
0.0508  
0.0608  
0.0708  
0.0808  
0.0908
```

Read an Entire Channel Group

To quickly read the data from an entire channel group in a single call, no additional arguments are specified to the `read` command.

```
data = read(m, 1, m.ChannelNames{1});
```


Using MDF Files Via MDF Datastore

This example shows you how to use the MDF Datastore feature of Vehicle Network Toolbox to quickly and efficiently process a data set spread across a collection of multiple MDF files. This workflow is also valuable when there is too much data to fit into available memory.

Access MDF Files in a Datastore

Find the collection of MDF files representing logged information from multiple test sequences. Note that MDF files to be used by MDF datastore as a set must have the same channel group and channel content structure.

```
dir('File*.mf4')
```

```
File01.mf4 File02.mf4 File03.mf4 File04.mf4 File05.mf4
```

Create an MDF Datastore

You create an MDF datastore by selecting a folder location containing a collection of MDF files. In this case, target all files in the current working directory.

```
mds = mdfDatastore(pwd)
```

```
mds =
```

```
MDFDatastore with properties:
```

```

Files: {
    '...\home\jpyle\documents\MATLAB\examples\vnt-ex10761765\File01
    '...\home\jpyle\documents\MATLAB\examples\vnt-ex10761765\File02
    '...\home\jpyle\documents\MATLAB\examples\vnt-ex10761765\File03
    ... and 2 more
}
ChannelGroups:
ChannelGroupNumber  AcquisitionName  Comment  ...
-----
1                    ''             'Integer Types'
2                    ''             'Float Types'

Channels:
ChannelGroupNumber  ChannelName  Di
-----
1                    'Sigend_Int16_LE_Offset_32'
1                    'Unsigend_UInt32_LE_Master_Offset_0'
2                    'Float_32_LE_Offset_64'
... and 1 more rows
SelectedChannelNames: {
    'Sigend_Int16_LE_Offset_32';
    'Unsigend_UInt32_LE_Master_Offset_0'
}

```

```
SelectedChannelGroupNumber: 1
ReadSize: 'file'
```

Configure the MDF Datastore

Multiple options allow control of what data is read from the MDF files and how the reads are performed. In this case, the first channel group is used by default. Note that only one channel group may be selected by the datastore at a time. You can also specify certain channels within the selected channel group to read. In this case, all channels are read by default.

```
mds.SelectedChannelGroupNumber
mds.SelectedChannelNames
```

```
ans =
```

```
1
```

```
ans =
```

```
2×1 string array
```

```
"Sigend_Int16_LE_Offset_32"
"Unsigend_UInt32_LE_Master_Offset_0"
```

MDF Datastore preview

Using the `preview` function, you can obtain a quick view of the data available in the file set. `Preview` always returns up to eight data points from the first file in the datastore.

```
preview(mds)
```

```
ans =
```

```
8×2 timetable
```

Time	Sigend_Int16_LE_Offset_32	Unsigend_UInt32_LE_Master_Offset_0
0 sec	0	0
1 sec	1	1
2 sec	2	2
3 sec	3	3
4 sec	4	4
5 sec	5	5
6 sec	6	6
7 sec	7	7

Using MDF Datastore readall

You can use the `readall` function to read the entire contents of data in a single call. This is an efficient way to read from many files when the data set fits into available memory. After running `readall`, the datastore resets to the beginning of the data set.

```
data = readall(mds);
data(1:5,:)
```

```
ans =
```

```
5×2 timetable
```

Time	Sigend_Int16_LE_Offset_32	Unsigend_UInt32_LE_Master_Offset_0
0 sec	0	0
1 sec	1	1
2 sec	2	2
3 sec	3	3
4 sec	4	4

Using MDF Datastore read

You can use the `read` function to obtain data from the file set. By default, reads from the MDF datastore will read an entire file's worth of data per call. The power of a datastore comes from reading through multiple files sequentially within the file set. As you read, the datastore automatically bridges from one file to the next until all data from all files is read.

```
for ii = 1:3
    data = read(mds);
    whos('data')
    data(1:5,:)
end
```

Name	Size	Bytes	Class	Attributes
data	10000x2	241767	timetable	

```
ans =
```

```
5×2 timetable
```

Time	Sigend_Int16_LE_Offset_32	Unsigend_UInt32_LE_Master_Offset_0
0 sec	0	0
1 sec	1	1
2 sec	2	2
3 sec	3	3
4 sec	4	4

Name	Size	Bytes	Class	Attributes
data	10000x2	241767	timetable	

```
ans =
```

```
5×2 timetable
```

Time	Sigend_Int16_LE_Offset_32	Unsigend_UInt32_LE_Master_Offset_0
0 sec	0	0
1 sec	1	1
2 sec	2	2
3 sec	3	3
4 sec	4	4

Name	Size	Bytes	Class	Attributes
data	10000x2	241767	timetable	

```
ans =
```

```
5x2 timetable
```

Time	Sigend_Int16_LE_Offset_32	Unsigend_UInt32_LE_Master_Offset_0
0 sec	0	0
1 sec	1	1
2 sec	2	2
3 sec	3	3
4 sec	4	4

MDF Datastore reset

At any time, you can call the `reset` function to start over again at the beginning of the data set.

```
reset(mds)
```

Configure MDF Datastore read By Data Record

You can use the `ReadSize` property to specify how much data to read on each call. `ReadSize` can be specified as a numeric value to read a fixed number of data points. `ReadSize` lets you control how much data is loaded into memory when you have a data set larger than available memory. We recommend using custom read sizes that are small enough to fit in memory, but still as large as possible to reduce processing overhead and improve performance.

```
mds.ReadSize = 5
for ii = 1:3
    data = read(mds)
end
```

```
mds =
```

```
MDFDatastore with properties:
```

```
Files: {
    ' ...\home\jpyle\documents\MATLAB\examples\vnt-ex10761765\File01
    ' ...\home\jpyle\documents\MATLAB\examples\vnt-ex10761765\File02
    ' ...\home\jpyle\documents\MATLAB\examples\vnt-ex10761765\File03
    ... and 2 more
}
```

```

ChannelGroups:
  ChannelGroupNumber  AcquisitionName  Comment  ...
  -----
  1                    ''           'Integer Types'
  2                    ''           'Float Types'

Channels:
  ChannelGroupNumber  ChannelName  Dis
  -----
  1                    'Sigend_Int16_LE_Offset_32'
  1                    'Unsigend_UInt32_LE_Master_Offset_0'
  2                    'Float_32_LE_Offset_64'
  ... and 1 more rows
SelectedChannelNames: {
  'Sigend_Int16_LE_Offset_32';
  'Unsigend_UInt32_LE_Master_Offset_0'
}
SelectedChannelGroupNumber: 1
ReadSize: 5

```

```
data =
```

```
5x2 timetable
```

Time	Sigend_Int16_LE_Offset_32	Unsigend_UInt32_LE_Master_Offset_0
0 sec	0	0
1 sec	1	1
2 sec	2	2
3 sec	3	3
4 sec	4	4

```
data =
```

```
5x2 timetable
```

Time	Sigend_Int16_LE_Offset_32	Unsigend_UInt32_LE_Master_Offset_0
5 sec	5	5
6 sec	6	6
7 sec	7	7
8 sec	8	8
9 sec	9	9

```
data =
```

```
5x2 timetable
```

Time	Sigend_Int16_LE_Offset_32	Unsigend_UInt32_LE_Master_Offset_0
------	---------------------------	------------------------------------

10 sec	10	10
11 sec	11	11
12 sec	12	12
13 sec	13	13
14 sec	14	14

Configure MDF Datastore read By Data Timestamp

You can also specify `ReadSize` as a duration to read data points by elapsed time. Note that when the read type is changed, the datastore resets to the beginning of the data set.

```
mds.ReadSize = seconds(5)
for ii = 1:3
    data = read(mds)
end
```

```
mds =
```

```
MDFDatastore with properties:
```

```

Files: {
    '...\home\jpyle\documents\MATLAB\examples\vnt-ex10761765\File01'
    '...\home\jpyle\documents\MATLAB\examples\vnt-ex10761765\File02'
    '...\home\jpyle\documents\MATLAB\examples\vnt-ex10761765\File03'
    ... and 2 more
}
ChannelGroups:


| ChannelGroupNumber | AcquisitionName | Comment         | ... |
|--------------------|-----------------|-----------------|-----|
| 1                  | ''              | 'Integer Types' |     |
| 2                  | ''              | 'Float Types'   |     |


Channels:


| ChannelGroupNumber | ChannelName                          | Dis... |
|--------------------|--------------------------------------|--------|
| 1                  | 'Sigend_Int16_LE_Offset_32'          |        |
| 1                  | 'Unsigend_UInt32_LE_Master_Offset_0' |        |
| 2                  | 'Float_32_LE_Offset_64'              |        |


... and 1 more rows
SelectedChannelNames: {
    'Sigend_Int16_LE_Offset_32';
    'Unsigend_UInt32_LE_Master_Offset_0'
}
SelectedChannelGroupNumber: 1
ReadSize: 5 sec

```

```
data =
```

```
5x2 timetable
```

<u>Time</u>	<u>Sigend_Int16_LE_Offset_32</u>	<u>Unsigend_UInt32_LE_Master_Offset_0</u>
0 sec	0	0
1 sec	1	1
2 sec	2	2
3 sec	3	3
4 sec	4	4

data =

5×2 timetable

<u>Time</u>	<u>Sigend_Int16_LE_Offset_32</u>	<u>Unsigend_UInt32_LE_Master_Offset_0</u>
5 sec	5	5
6 sec	6	6
7 sec	7	7
8 sec	8	8
9 sec	9	9

data =

5×2 timetable

<u>Time</u>	<u>Sigend_Int16_LE_Offset_32</u>	<u>Unsigend_UInt32_LE_Master_Offset_0</u>
10 sec	10	10
11 sec	11	11
12 sec	12	12
13 sec	13	13
14 sec	14	14

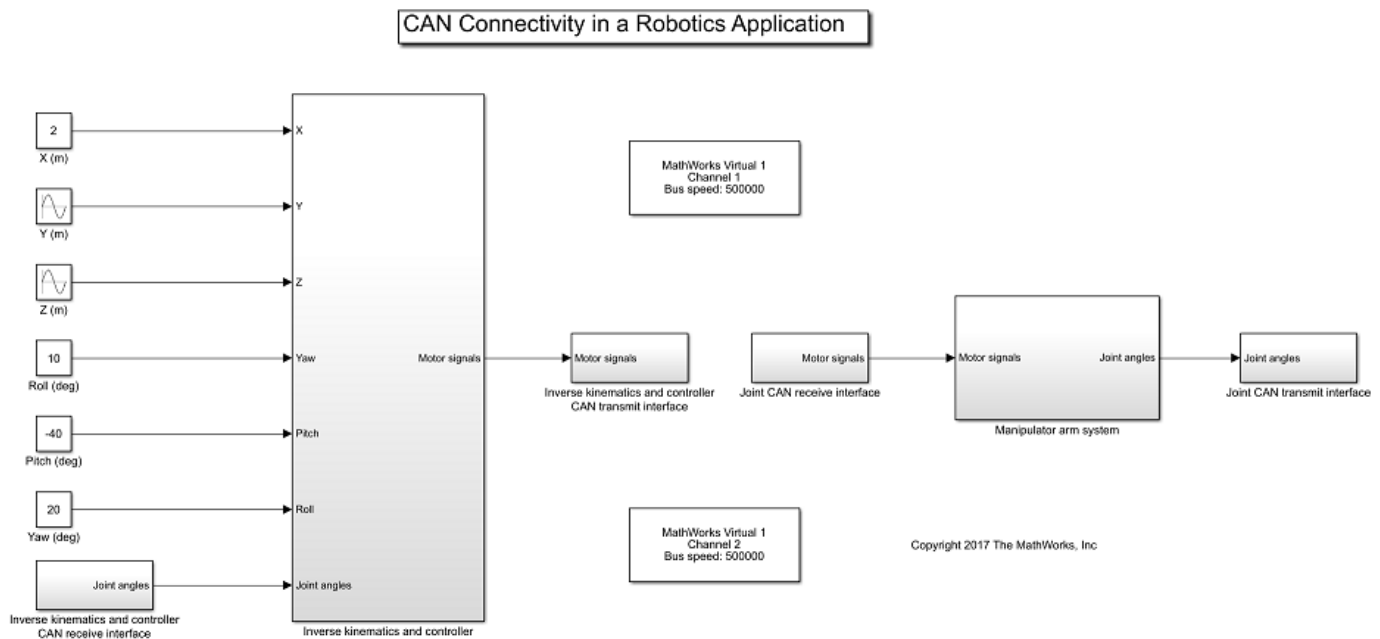
CAN Connectivity in a Robotics Application

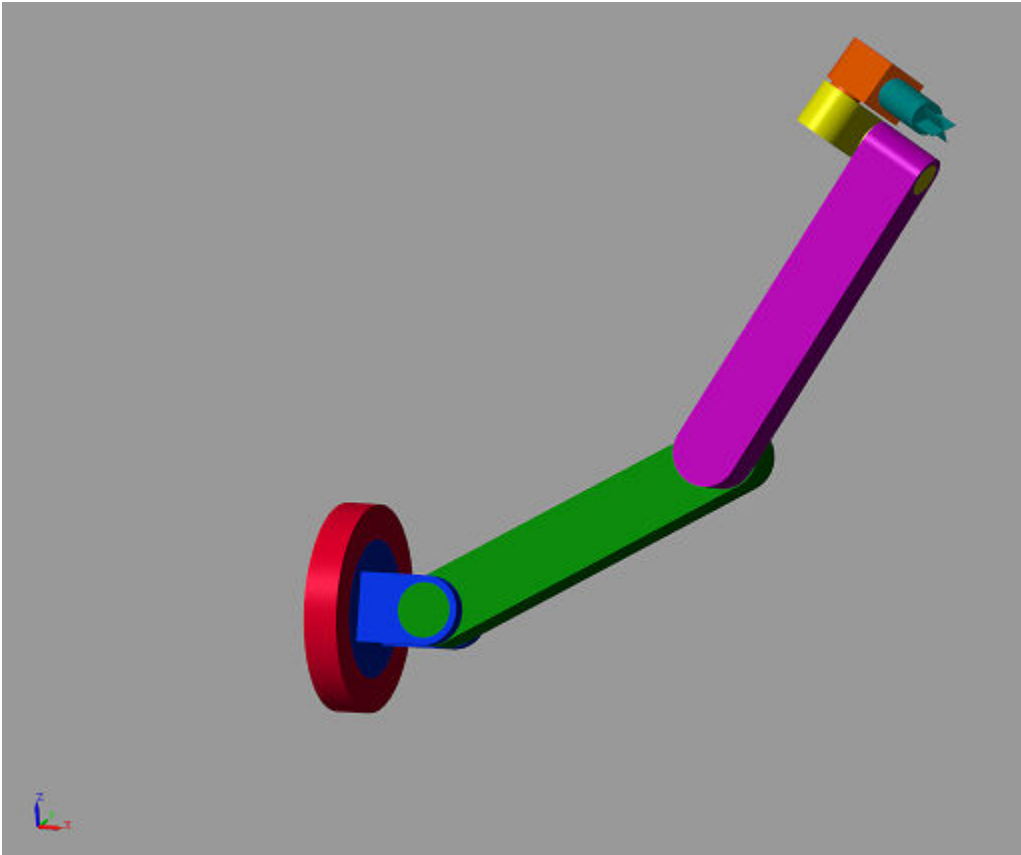
This example shows you how to use Vehicle Network Toolbox™ to implement a Controller Area Network (CAN) in a remote manipulator arm using Simulink®. The CAN messages used are defined in the CAN database file, `canDatabaseFor6DofRoboticArm.dbc`.

Vehicle Network Toolbox provides Simulink blocks for transmitting and receiving live messages via Simulink models over Controller Area Networks (CAN). This example uses the CAN Configuration, CAN Pack, CAN Transmit, CAN Receive, and CAN Unpack blocks to perform data transfer over a CAN bus.

MathWorks virtual CAN channels are used for this example. Alternatively, you can connect your models to other supported hardware.

Model Description





The model consists of the following subsystems: Manipulator arm system, Inverse kinematics and controller, Joint CAN transmit interface, Joint CAN receive interface, Inverse kinematics and controller CAN transmit interface, and Inverse kinematics and controller CAN receive interface. Each joint and the inverse kinematics and controller subsystem constitute a node in the CAN bus.

The user inputs the position coordinates (X, Y and Z in metres) and the orientation (roll, pitch and yaw angles in degrees, in body-3 2-3-1 sequence) of the end effector. The inverse kinematics and controller subsystem receives feedback from the joint angle sensors that are sent via the CAN bus, and sends appropriate commands to each joint motor via the CAN bus to drive the position and the orientation of the end effector to the user-input values.

The remote manipulator arm is assumed to be attached to a spacecraft in orbit. As a result, gravity is neglected.

Manipulator Arm System

This subsystem consists of the rigid-body model of the remote manipulator arm, modeled using Simscape Multibody 2G. The arm has six joints. Each joint is actuated by a DC motor with a gearbox, and are modeled using Simscape Foundational Library. Each joint also has a joint angle sensor. The sensor data is sent into the CAN bus. Each motor is powered by a controlled voltage source. The voltage sources receive messages from the CAN bus and apply the DC voltage across their terminals corresponding to the information in the messages.

Inverse Kinematics and Controller

The Inverse kinematics and controller subsystem further implements the inverse kinematics and the control algorithm. The inverse kinematics computes the desired joint angles from the desired position (X, Y and Z) and orientation (roll, pitch and yaw angles) that are input by the user. The discrete PID controllers utilize the joint angle sensor values that are read from the CAN bus to determine the DC voltage that should be applied to each motor to drive the joint angles to the desired values. The DC voltage values are sent as messages in the CAN bus.

Joint CAN Transmit Interface

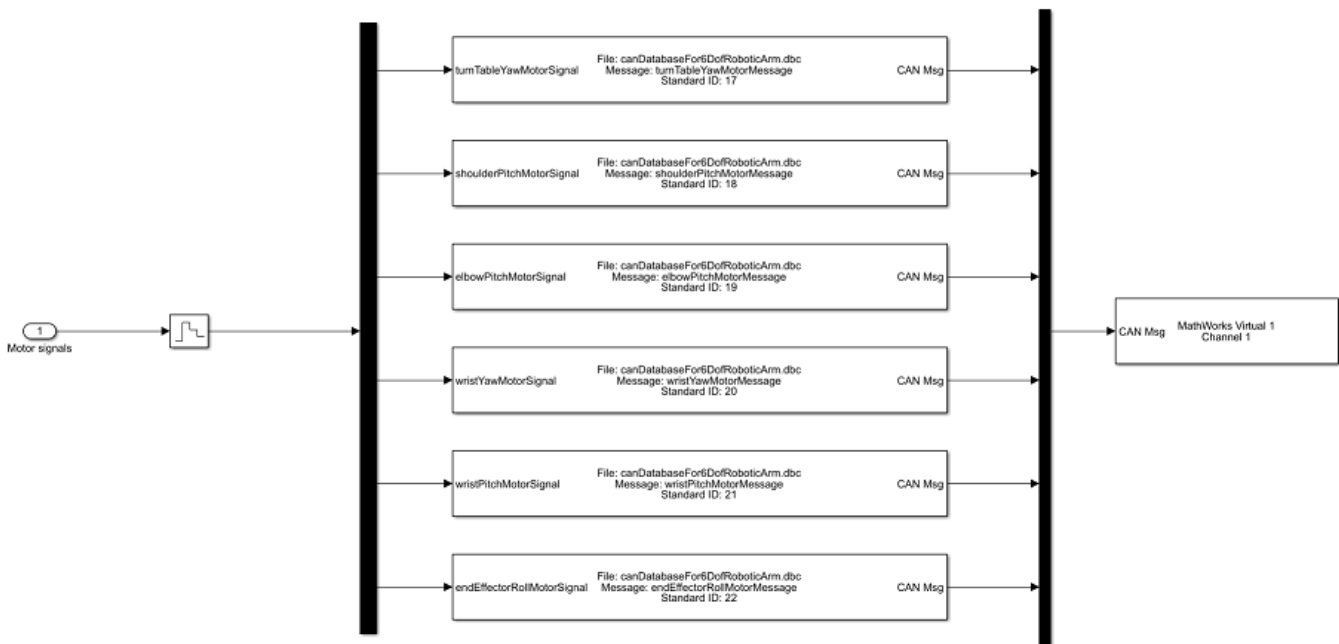
This subsystem consists of the VNT blocks that are necessary to transmit the joint angle values from the corresponding sensors into the CAN bus.

Joint CAN Receive Interface

This subsystem consists of the VNT blocks that are necessary to receive and unpack the messages from the CAN bus that contain information about the DC voltages that need to be applied to the controlled voltage sources corresponding to each motor.

Inverse Kinematics and Controller CAN Transmit Interface

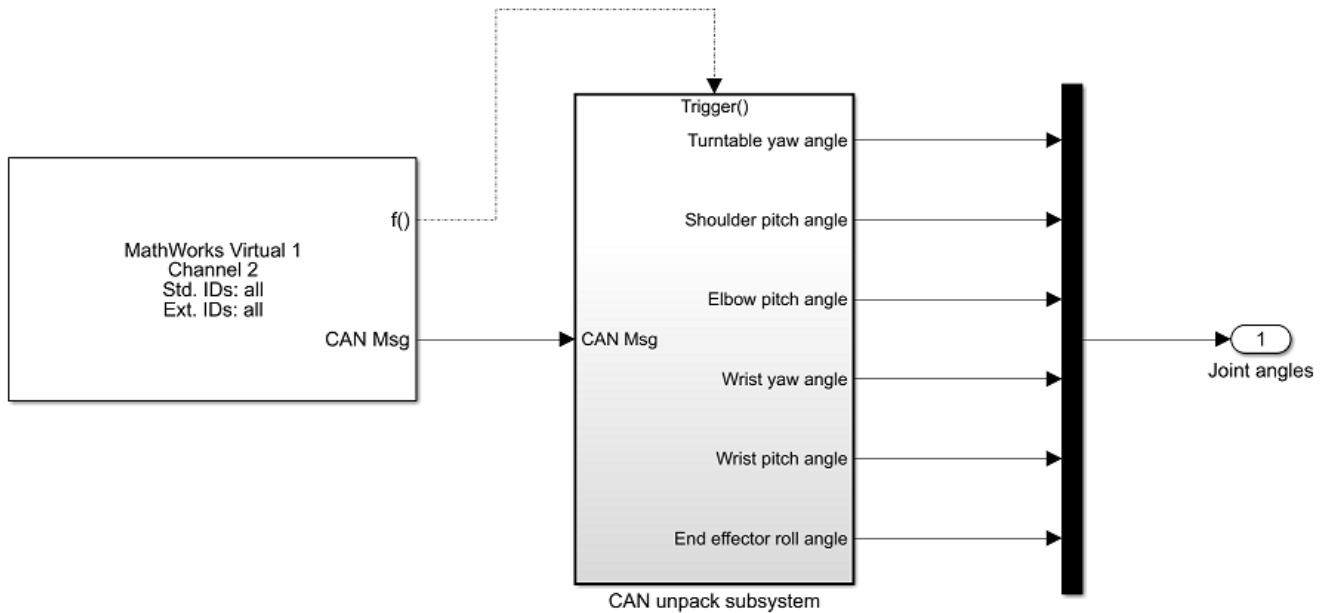
Inverse kinematics and controller CAN transmit interface



This subsystem consists of the VNT blocks that are necessary to transmit the motor signals (DC voltages that need to be applied across the controlled voltage sources) calculated by the Inverse Kinematics and Controller subsystem into the CAN bus.

Inverse Kinematics and Controller CAN Receive Interface

Inverse kinematics and controller CAN receive interface



This subsystem consists of the VNT blocks that are necessary to receive the messages from the CAN bus that contain information about the joint angles that are sent by the joint angle sensors.

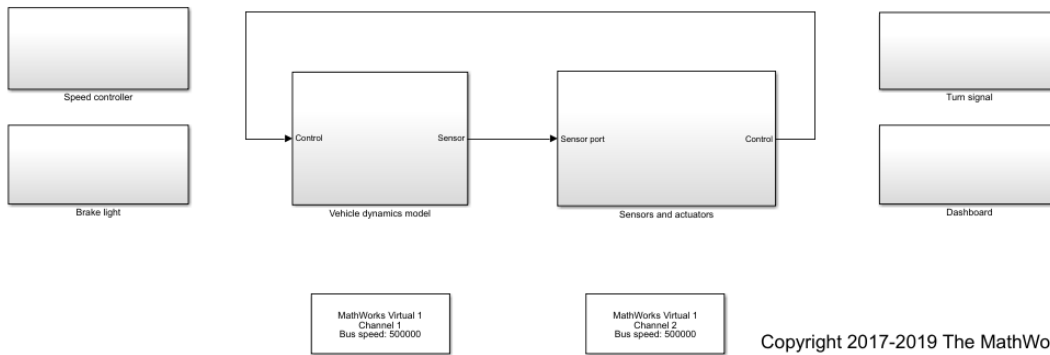
CAN Connectivity in an Automotive Application

This example uses Vehicle Network Toolbox to implement a distributed Electronic Control Unit (ECU) network on CAN for an automobile using Simulink®. The CAN messages used are defined in the CAN database file, `canConnectivityForVehicle.dbc`.

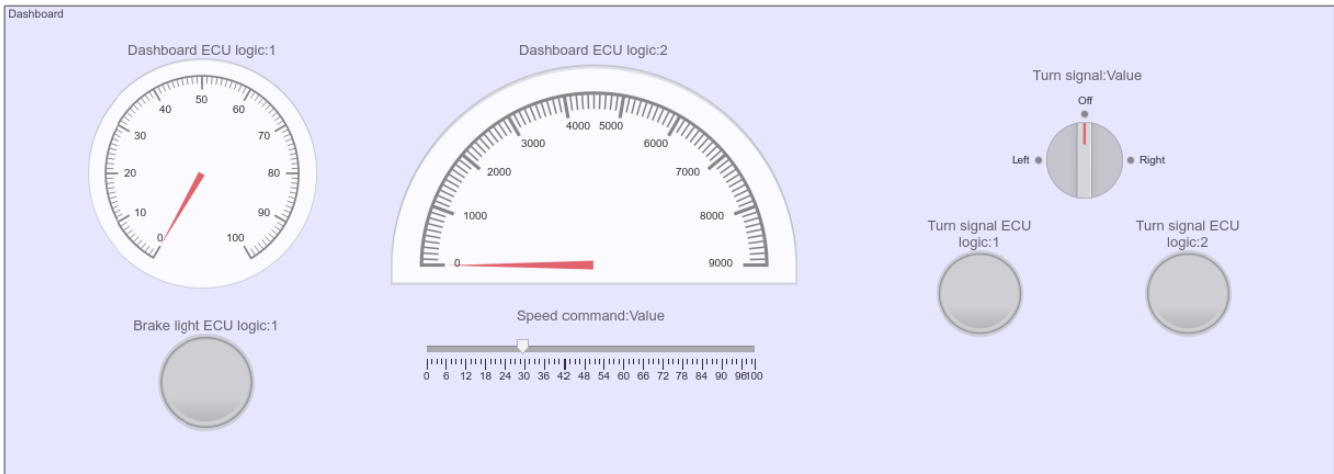
Vehicle Network Toolbox™ provides Simulink blocks for transmitting and receiving live messages via Simulink models over Controller Area Networks (CAN). This example uses the CAN Configuration, CAN Pack, CAN Transmit, CAN Receive and CAN Unpack blocks to perform data transfer over a CAN bus.

MathWorks virtual CAN channels were used for this example. You can however connect your models to other supported hardware.

Model Description



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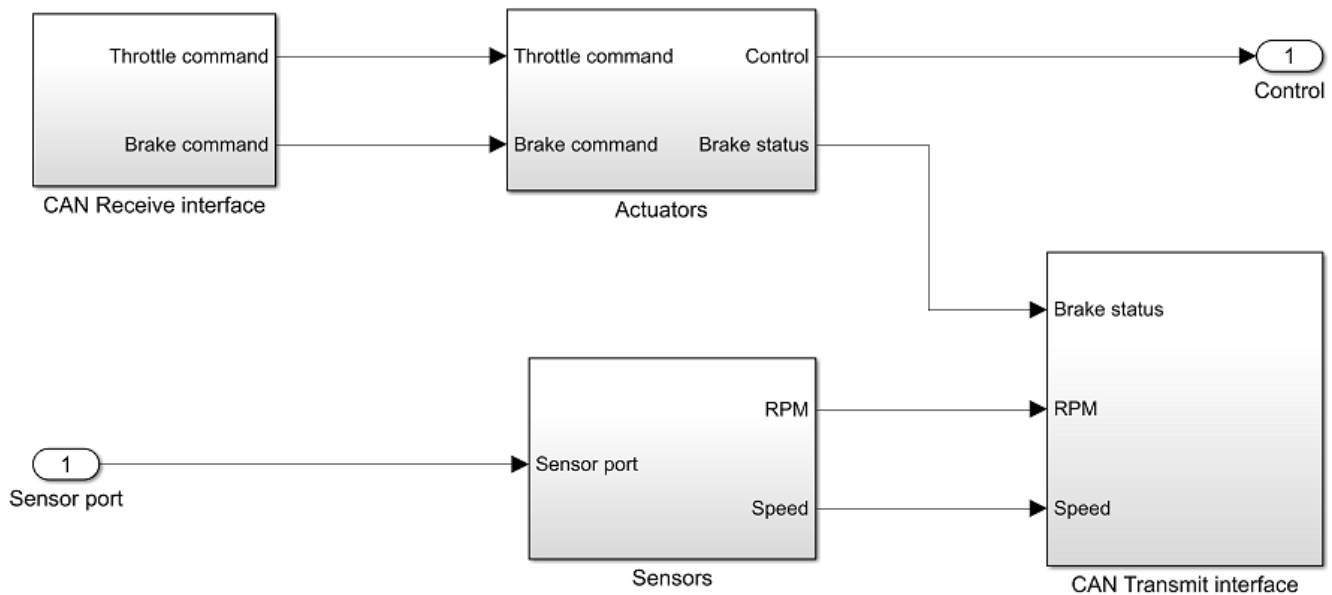
The model consists of the following subsystems: Vehicle dynamics model, Sensors and actuators, Turn signal, Dashboard, brake light and Speed controller. The Vehicle dynamics model represents the automobile (the environment), and the other subsystems represent the various nodes on the CAN bus.

Vehicle Dynamics Model

This subsystem defines the equations of motion of the automobile. The inputs are the throttle and brake actuator positions. The outputs are the engine RPM and vehicle speed, that are multiplexed into a single signal.

Sensors and Actuators

Sensors and actuators



This subsystem consists of the throttle and brake actuators, and the RPM and vehicle speed sensors. The actuators receive the throttle and the brake commands via the CAN bus. The actuator outputs (control) are fed to the vehicle dynamics model.

The brake actuator also sends a signal that informs whether or not the brakes are actuated. This signal is sampled at 100 Hz and transmitted into the CAN bus. The engine RPM and vehicle speed signals from the vehicle dynamics model that are input to this subsystem and are also sampled at 100 Hz and transmitted into the CAN bus.

Dashboard

The dashboard is the interface between the vehicle and the driver. The commanded speed can be set by the user using the slider (Speed command:Value). The turn signal can be operated using the rotary switch (Turn signal:Value).

The speed command and turn signal status signals are transmitted into the CAN bus. The sampled vehicle speed and engine RPM are read from the CAN bus and displayed on the speedometer and the tachometer respectively.

Speed Controller

The speed controller sends commands to the actuators to drive the vehicle speed to the commanded value. The vehicle speed and the commanded speed are read from the CAN bus. The throttle and

brake commands are calculated by the corresponding discrete Proportional - Integral controllers. The actuator commands are transmitted into the CAN bus.

Brake Light

The Brake light subsystem receives the brake actuator status signal from the CAN bus and appropriately operates the brake lights. Whenever the brakes are actuated, the brake lights are turned on.

Turn Signal

The turn signal subsystem receives the turn signal status message from the CAN bus and appropriately activates the turn signals. The left turn signal light blinks periodically when the rotary switch is set to the "Left" position, and the right turn signal light blinks periodically when the rotary switch is set to the "Right" position.

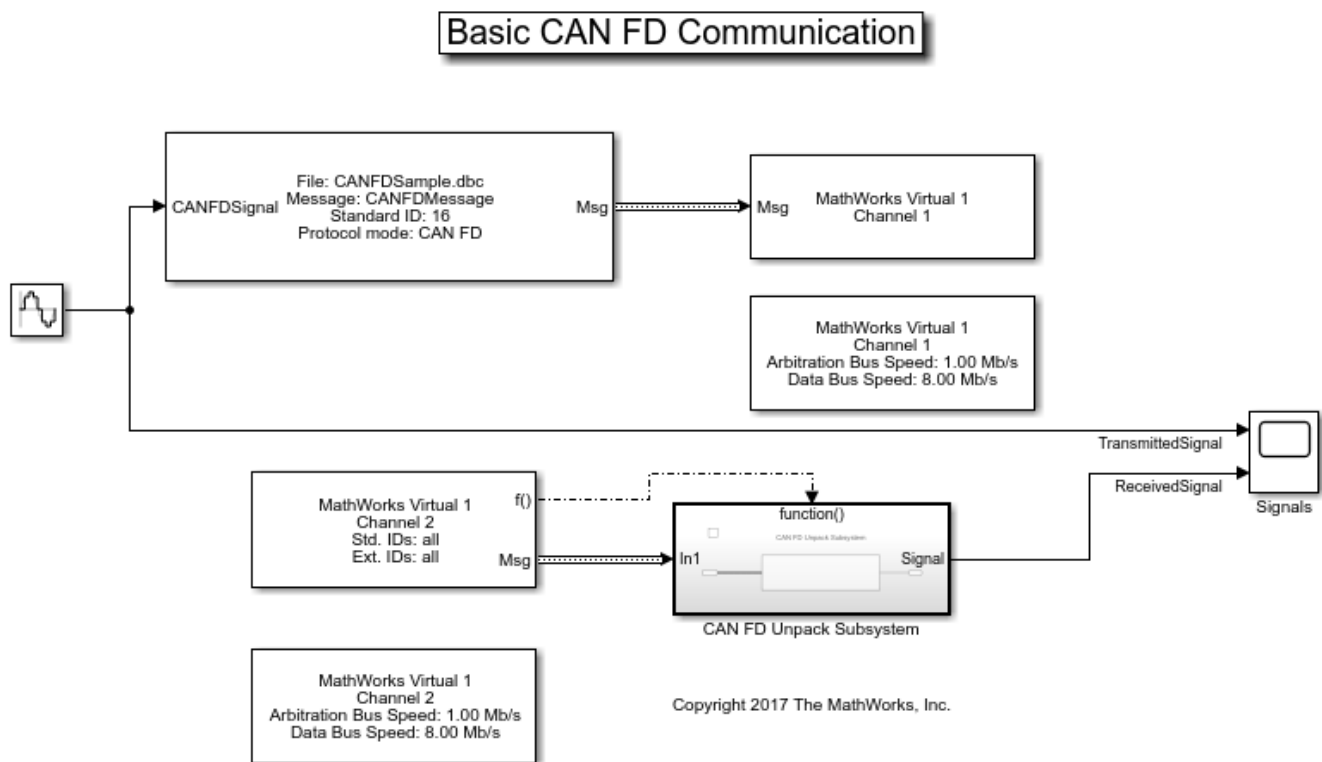
Basic CAN FD Communication

This example uses MathWorks Virtual CAN FD channels to set up transmission and reception of CAN FD messages, using Simulink®. The Virtual channels are connected in a loopback configuration.

Vehicle Network Toolbox™ provides Simulink blocks for transmitting and receiving live messages via Simulink models over networks utilizing the Controller Area Network Flexible Data (CAN FD) format. This example uses the CAN FD Configuration, CAN FD Pack, CAN FD Transmit, CAN FD Receive and CAN FD Unpack blocks to perform data transfer over a CAN FD bus. These blocks operate similarly to the existing CAN blocks, but are intended for use only on networks or devices that support the CAN FD protocol.

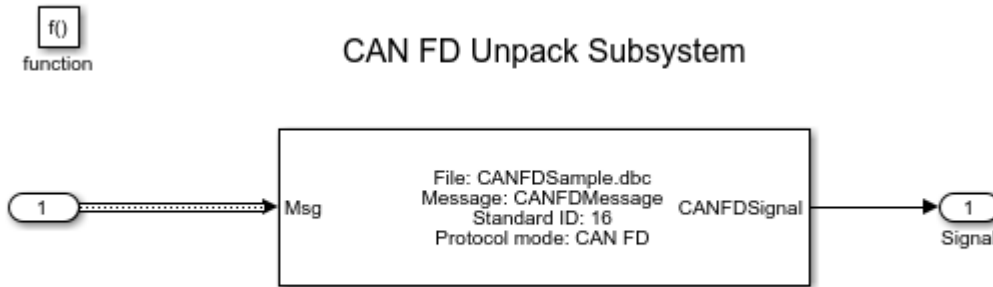
Transmit and Receive CAN FD Messages

Create a model to transmit and receive a CAN FD message carrying a sine wave data signal. The model transmits a single message per timestep. A CAN database file (.dbc) defines the message and signal used in the model.



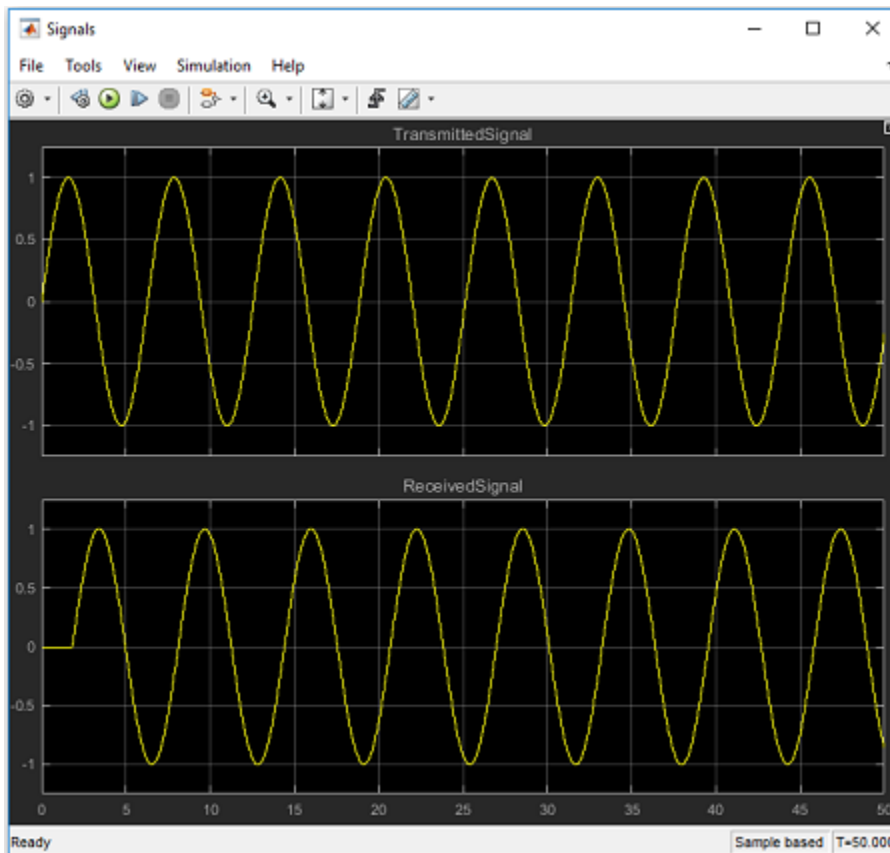
Process CAN FD Messages

The CAN FD Receive block generates a function-call trigger if it receives a new message at any particular timestep. This indicates to other blocks in the model that a message is available for decoding activities. Signal decoding and processing is performed inside the function-triggered subsystem.



Visualize Signal Data

Plot the sine wave values before and after transmission. The X-axis corresponds to the simulation timestep and the Y-axis corresponds to the value of the signal. Note that the phase shift in the two plots. This represents the propagation delay as the signal travels across the network.



Extend the Example

MathWorks CAN FD Virtual channels were used for this example. You can however connect your models to other supported hardware. You can also modify the model to transmit at periodic rates.

Forward Collision Warning Application with CAN FD and TCP/IP

This example shows you how to execute a forward collision warning (FCW) application with sensor and vision data replayed live via CAN FD and TCP/IP protocols. Recorded data from a sensor suite mounted on a test vehicle are replayed live as if they were coming through the network interfaces of the vehicle. The Vehicle Network Toolbox™ and Instrument Control Toolbox™ provide these interfaces. This setup is used to test an FCW system developed using features from the Automated Driving Toolbox™. For assistance with the design and development of actual FCW algorithms, refer to the Forward Collision Warning Using Sensor Fusion example.

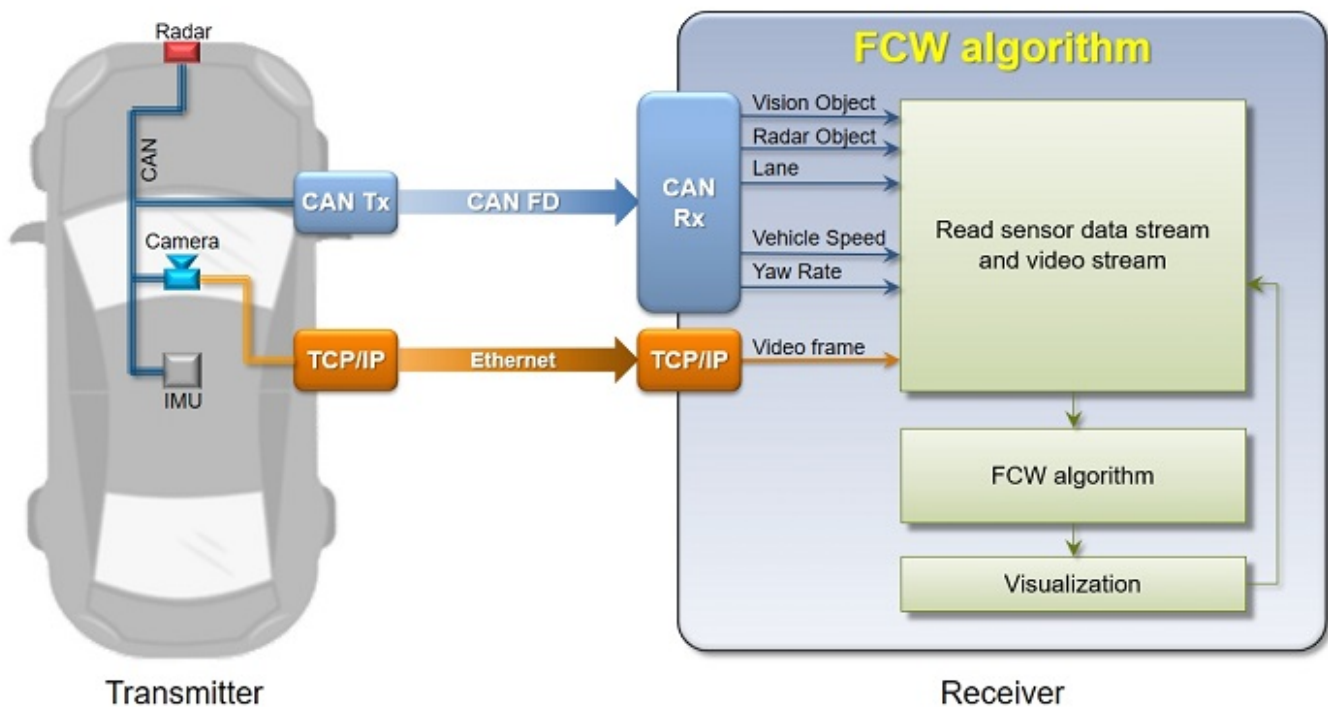
System Configuration

This example uses virtual CAN FD channels from Vector. These virtual device channels are available with the installation of the Vector Driver Setup package from www.vector.com.

This example has two primary components:

- 1 Transmitter: Sends the sensor and vision data via CAN FD and TCP/IP. This portion represents a sample vehicle environment. It replays prerecorded data as if it were a live vehicle.
- 2 Receiver: Collects all the data and executes the FCW algorithm and visualizations. This portion represents the application component.

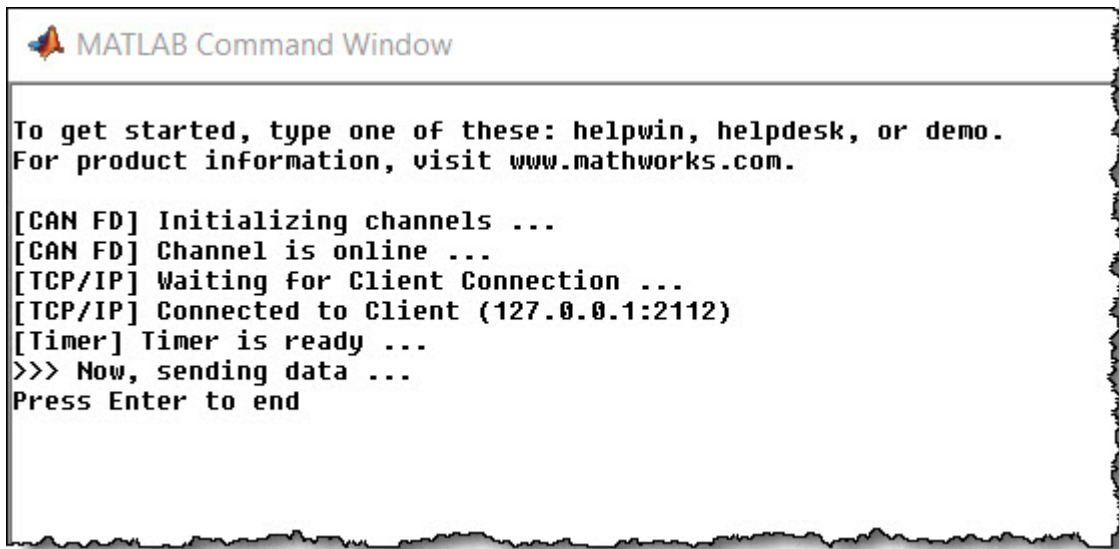
To execute the example, the transmitter and receiver portions run from separate sessions of MATLAB. This replicates the data source existing outside the MATLAB session serving as the development tool. Furthermore, this example allows you to run the FCW application in multiple execution modes (interpreted and MEX) with different performance characteristics.



Generate Data

The transmitting application executes via the `helperStartTransmitter` function. It launches a separate MATLAB process to run outside of the current MATLAB session. The transmitter initializes itself and begins sending sensor and vision data automatically. To run the transmitter, use the `system` command.

```
system('matlab -nodesktop -nosplash -r helperStartTransmitter &')
```

A screenshot of a MATLAB Command Window titled "MATLAB Command Window". The window contains the following text:

```
To get started, type one of these: helpwin, helpdesk, or demo.  
For product information, visit www.mathworks.com.  
  
[CAN FD] Initializing channels ...  
[CAN FD] Channel is online ...  
[TCP/IP] Waiting for Client Connection ...  
[TCP/IP] Connected to Client (127.0.0.1:2112)  
[Timer] Timer is ready ...  
>>> Now, sending data ...  
Press Enter to end
```

Execute Forward Collision Warning System (Interpreted Mode)

To open the receiving FCW application, execute the `helperStartReceiver` function. You can click **START** to begin data reception, processing, and visualization. You can explore the `helperStartReceiver` function to see how the Vehicle Network Toolbox CAN FD functions, Instrument Control Toolbox TCP/IP functions, and Automated Driving Toolbox capabilities are used in concert with one another.

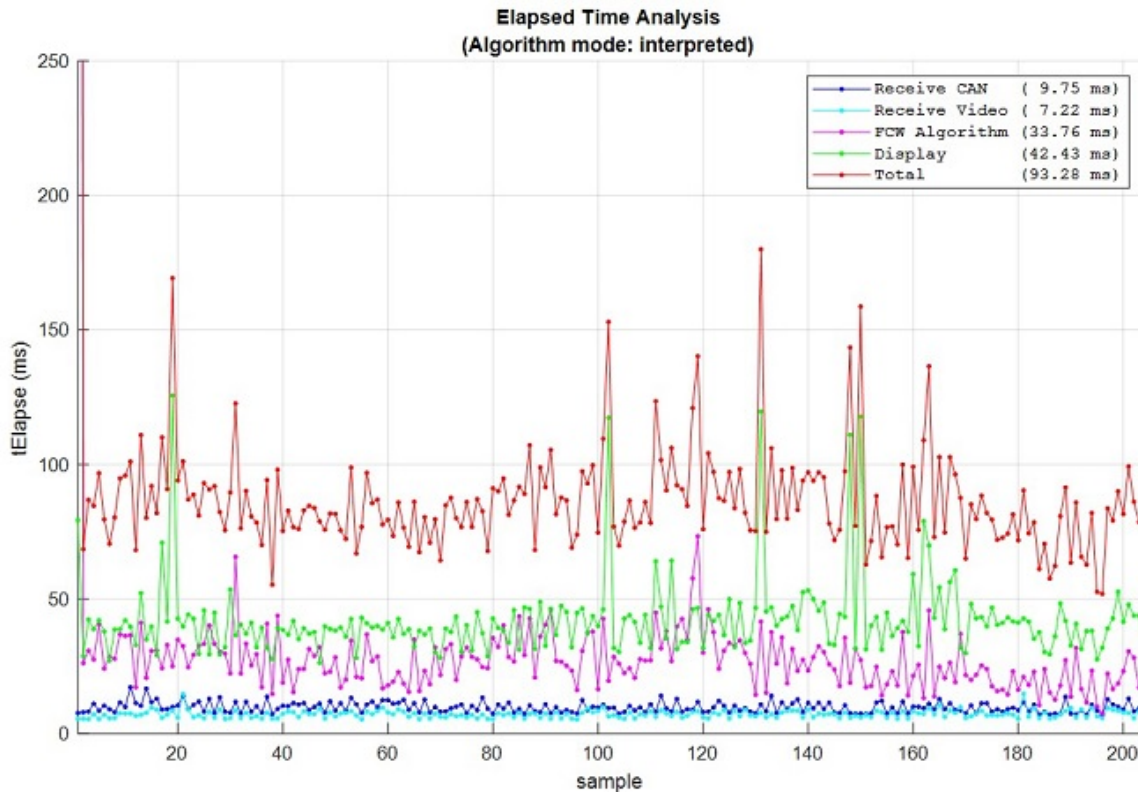
```
helperStartReceiver('interpreted')
```



Review Results

When ready, stop the transmitter application using the close window button on its command window. Click **STOP** on the receiving FCW application, and then close its window as well.

When the receiving FCW application is stopped, a plot appears detailing performance characteristics of the application. It shows time spent receiving data, processing the FCW algorithm, and performing visualizations. Benchmarking is useful to show parts of the setup that need performance improvement. It is clear that a significant portion of time is spent executing the FCW algorithm. In the next section, explore code generation as a strategy to improve performance.



Execute Forward Collision Warning System (MEX Mode)

If faster performance is a requirement in your workflow, you can use MATLAB Coder™ to generate and compile MATLAB code as MEX code. To build this example as MEX code, use the `helperGenerateCode` function. The build will compile the FCW application into a MEX function directly callable within MATLAB.

```
helperGenerateCode('mex')
```

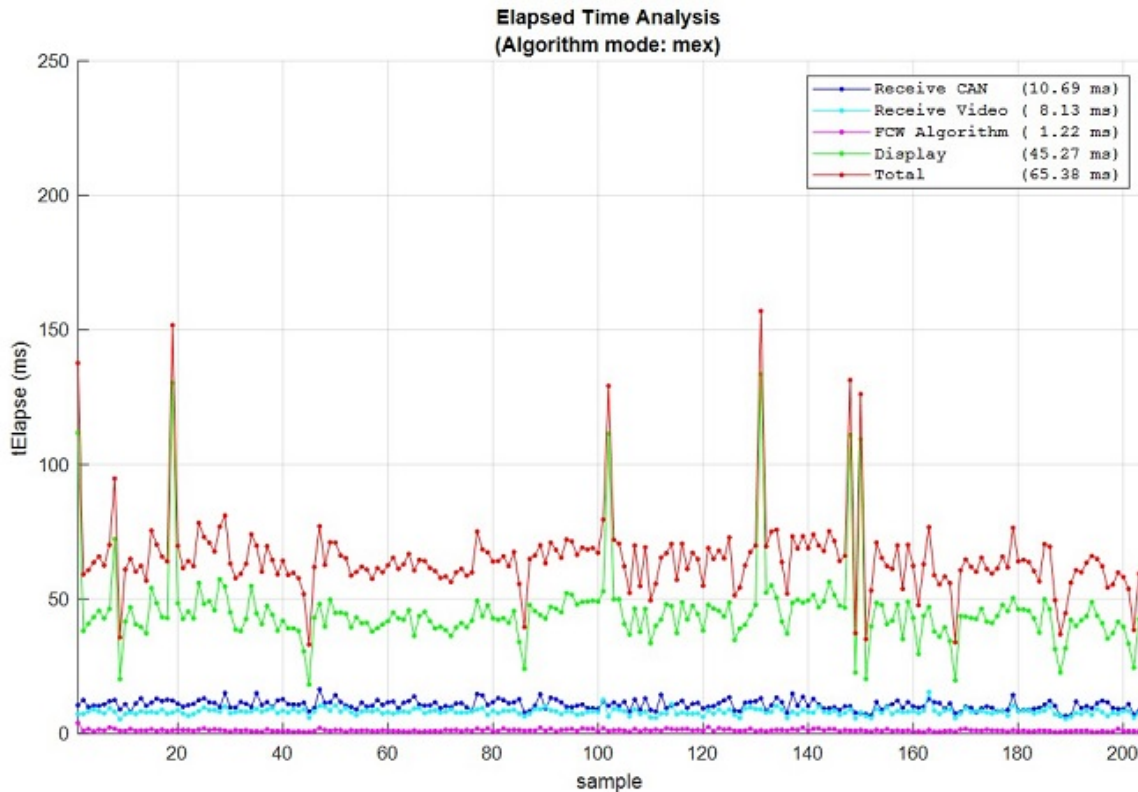
Restart the transmitter application.

```
system('matlab -nodesktop -nosplash -r helperStartTransmitter &')
```

The receiving FCW application can also be restarted. This time with an input argument to use the MEX compiled code built in the prior step.

```
helperStartReceiver('mex')
```

When ready, stop and close the transmitter and receiving FCW application. Comparing the time plot for MEX execution to the interpreted mode plot, you can see the performance improvement for the FCW algorithm.



Use Physical Hardware and Multiple Computers

The example uses a single computer to simulate the entire system with virtual connectivity. As such, its performance is meant as an approximation. You can also execute this example using two computers (one as transmitter, one as receiver). This would represent more of a real live data scenario. To achieve this, you can make simple modifications to the example code.

Changing the CAN FD communication from virtual to physical devices requires editing the transmission and reception code to invoke `canChannel` using a hardware device instead of the virtual channels. You may also need to modify the call to `configBusSpeed` depending on the capabilities of the hardware. These calls are found in the `helperStartReceiver` and `dataTransmitter` functions of the example.

Changing TCP/IP communication for multiple computers requires adjusting the TCP/IP address of the transmitter from local host (127.0.0.1) to a static value (192.168.1.2 recommended). This address is set first on the host transmitting computer. After, modify the `tcpipAddr` variable in the `helperStartReceiver` function to match.

Once configured and connected physically, you can run the transmitter application on one computer and the FCW application on the other.

Data Analytics Application with Many MDF Files

This example shows you how to investigate vehicle battery power during discharge mode across various drive cycles. The data for this analysis are contained in a set of vehicle log files in MDF format. For this example, we need to build up a mechanism that can "detect" when the vehicle battery is in a given mode. What we are really doing is building a detector to determine when a signal of interest (battery power in this case) meets specific criteria. When the criteria is met, we will call that an "event". Each event will be subsequently "qualified" by imposing time bounds. That is to say an event is "qualified" if it persists for at least 5 seconds (such a qualification step can help limit noise and remove transients). The thresholds shown in this example are illustrative only.

Set Data Source Location

Define the location of the file set to analyze.

```
dataDir = '*.dat';
```

Obtain File Set Information

Get the names of all the MDF files to analyze into a single cell array.

```
fileList = dir(dataDir);
fileName = {fileList(:).name}';
fileDir = {fileList(:).folder}';
fullFilePath = fullfile(fileDir, fileName)

fullFilePath = 10x1 cell array
    {'\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex86857001\ADAC.dat' }
    {'\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex86857001\ECE.dat' }
    {'\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex86857001\FTP75.dat' }
    {'\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex86857001\HUDDS.dat' }
    {'\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex86857001\HWFET.dat' }
    {'\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex86857001\JC08.dat' }
    {'\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex86857001\LA92.dat' }
    {'\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex86857001\NEDC.dat' }
    {'\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex86857001\SC03.dat' }
    {'\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex86857001\US06.dat' }
```

Pre-allocate the Output Data Cell Array

Use a cell array to capture a collection of mini-tables which represent the event data of interest for each individual MDF file.

```
numFiles = size(fullFilePath, 1);
eventSet = cell(numFiles, 1)
```

```
eventSet = 10x1 cell array
    {0x0 double}
    {0x0 double}
    {0x0 double}
    {0x0 double}
    {0x0 double}
    {0x0 double}
    {0x0 double}
    {0x0 double}
    {0x0 double}
    {0x0 double}
```

```
{0x0 double}
```

Define Event Detection and Channel Information Criteria

```
chName = 'Power';           % Name of the signal of interest in the MDF files
thdValue = [5, 55];        % Threshold in KW
thdDuration = seconds(5); % Threshold for event qualification
```

Loop Through Each MDF File and Apply the Event Detector Function

eventSet is a cell array which contains a summary table for each file that was analyzed. You can think of this cell array of tables as a set of mini-tables, all with the same format but the contents of each mini-table correspond to the individual MDF files.

In this example, the event detector not only reports the event start and end times but also some descriptive statistics about the event itself. This kind of aggregation and reporting can be useful for discovery and troubleshooting activities. To understand the MDF file interfacing and data handling in more detail, open and explore the processMDF function from this example.

Note that the data processing is written such that each MDF file is parsed atomically and returns into its own index of the resulting cell array. This allows the processing function to leverage parallel computing capability with parfor. parfor and standard for are interchangeable in terms of outputs, but result in varying processing time needed to complete the analysis. To experiment with parallel computing, simply change the for call below to parfor and run this example.

```
for i = 1:numFiles
    eventSet{i} = processMDF(fullFilePath{i}, chName, thdValue, thdDuration);
end
eventSet{1}
```

```
ans=20x8 table
```

FileName	EventNumber	EventDuration	EventStart	EventStop	MeanPower_KW	MaxPower_KW
ADAC.dat	2	00:01:22	19.345 sec	101.79 sec	28.456	54.37
ADAC.dat	3	00:00:08	107.82 sec	116.36 sec	21.295	37.5
ADAC.dat	5	00:00:55	123.8 sec	179.67 sec	28.642	54.37
ADAC.dat	6	00:00:10	189.83 sec	200.36 sec	11.192	54.37
ADAC.dat	8	00:00:40	212.4 sec	252.79 sec	28.539	37.5
ADAC.dat	9	00:00:08	258.76 sec	267.37 sec	21.289	54.37
ADAC.dat	11	00:00:44	274.81 sec	319.79 sec	28.554	37.5
ADAC.dat	12	00:00:08	325.75 sec	334.37 sec	21.279	54.37
ADAC.dat	14	00:00:44	341.81 sec	386.79 sec	28.554	37.5
ADAC.dat	15	00:00:08	392.75 sec	401.37 sec	21.278	54.37
ADAC.dat	17	00:00:44	408.81 sec	453.67 sec	28.579	37.5
ADAC.dat	18	00:00:07	463.77 sec	471.37 sec	11.895	54.37
ADAC.dat	20	00:00:40	483.44 sec	523.79 sec	28.544	37.5
ADAC.dat	21	00:00:08	529.75 sec	538.37 sec	21.279	54.37
ADAC.dat	23	00:00:44	545.81 sec	590.79 sec	28.553	37.5
ADAC.dat	24	00:00:08	596.75 sec	605.37 sec	21.279	54.37
:						

Concatenate Results

Combine the contents of the cell array `eventSet` into a single table. We can now use the table `eventSummary` for subsequent analysis. The `head` function is used to display the first 5 rows of the table `eventSummary`.

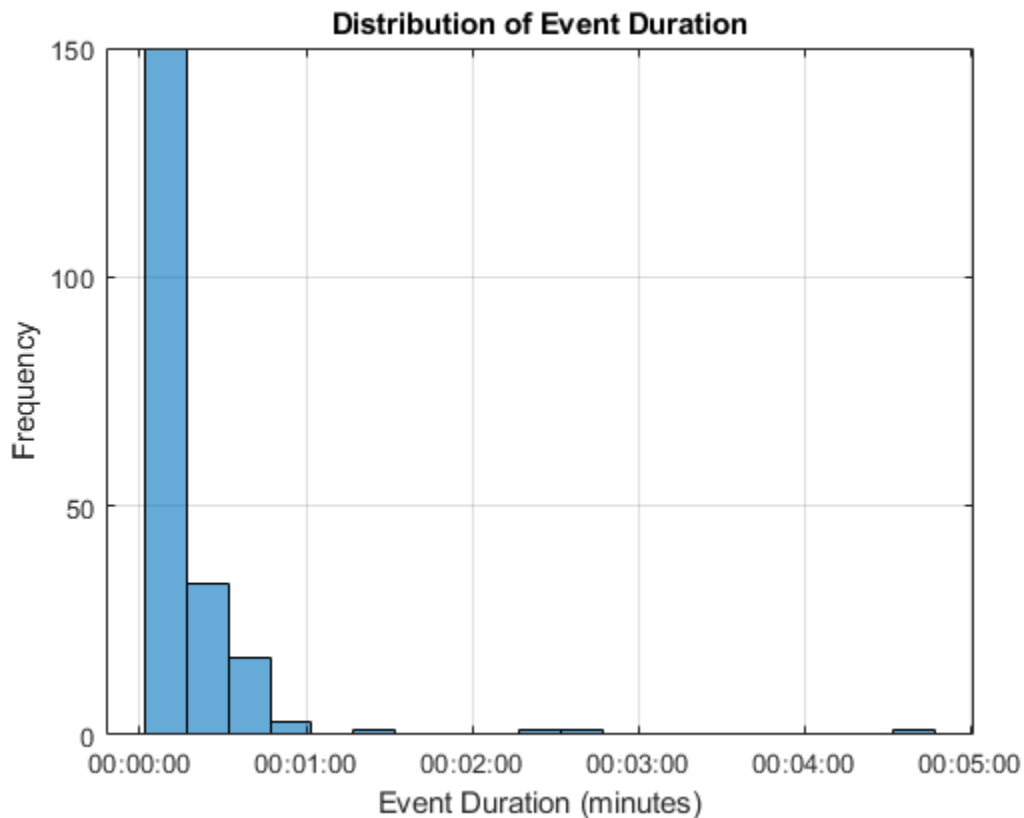
```
eventSummary = vertcat(eventSet{:});
disp(head(eventSummary, 5))
```

FileName	EventNumber	EventDuration	EventStart	EventStop	MeanPower_KW	MaxP
ADAC.dat	2	00:01:22	19.345 sec	101.79 sec	28.456	53
ADAC.dat	3	00:00:08	107.82 sec	116.36 sec	21.295	53
ADAC.dat	5	00:00:55	123.8 sec	179.67 sec	28.642	3
ADAC.dat	6	00:00:10	189.83 sec	200.36 sec	11.192	54
ADAC.dat	8	00:00:40	212.4 sec	252.79 sec	28.539	3

Visualize Summary Results to Determine Next Steps

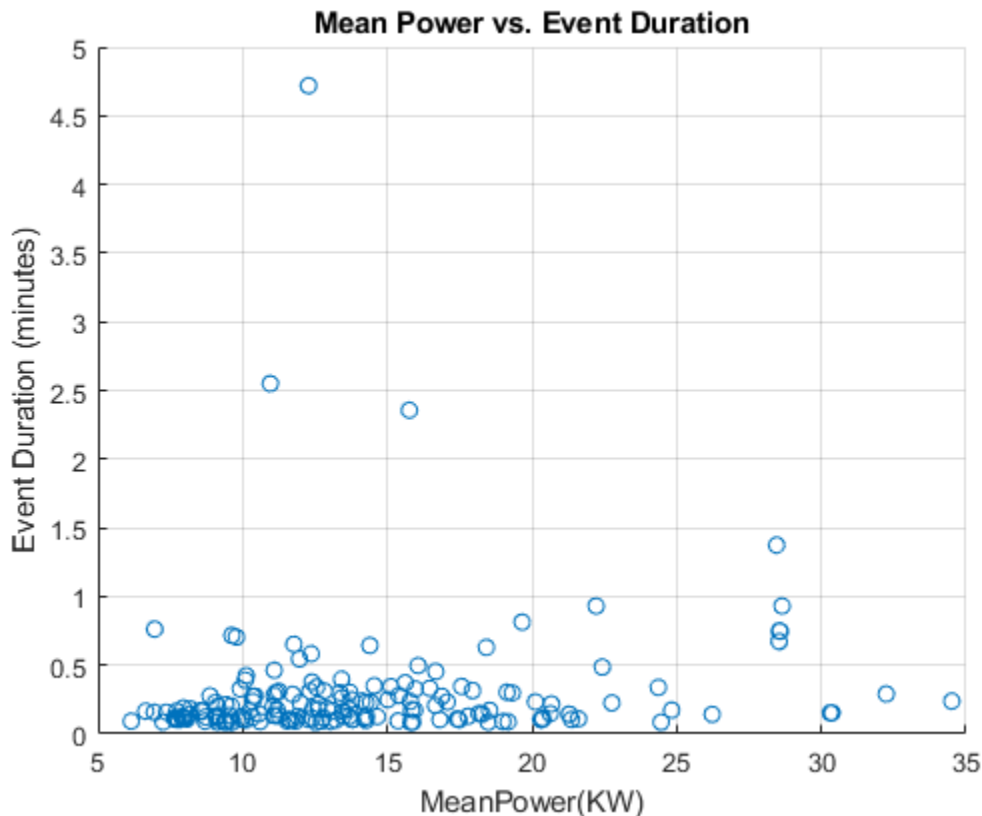
Look at an overview of the event durations.

```
histogram(eventSummary.EventDuration)
grid on
title 'Distribution of Event Duration'
xlabel 'Event Duration (minutes)'
ylabel 'Frequency'
```



Now look at Mean Power vs. Event Duration.

```
scatter(eventSummary.MeanPower_KW, minutes(eventSummary.EventDuration))
grid on
xlabel 'MeanPower(KW)'
ylabel 'Event Duration (minutes)'
title 'Mean Power vs. Event Duration'
```



Deep Dive an Event of Interest

Inspect the event that lasted for more than 4 minutes. First, create a mask to find the case of interest. `msk` is a logical index that shows which rows of the table `eventSummary` meet the specified criteria.

```
msk = eventSummary.EventDuration > minutes(4);
```

Pull out the rows of the table `eventSummary` that meet the criteria specified and display the results.

```
eventOfInterest = eventSummary(msk, :);
disp(eventOfInterest)
```

FileName	EventNumber	EventDuration	EventStart	EventStop	MeanPower_KW	MaxPower_KW
HWFET.dat	18	00:04:43	297.22 sec	580.37 sec	12.275	30.000

Visualize This Event in the Context of the Entire Drive Cycle

We need the full file path and file name to read the data from the MDF file. The table `eventOfInterest` has the filename because we kept track of that. It does not have the full file path

to that file. To get this information we will apply a bit of set theory to our original list of filenames and paths. First, find the full file path of the file of interest.

```
fileMsk = find(ismember(fileName, eventOfInterest.FileName))
```

```
fileMsk = 5
```

Create an MDF object to read data from the MDF file.

```
mdfObj = mdf(fullFilePath{fileMsk})
```

```
mdfObj =
```

```
MDF with properties:
```

```
File Details
```

```

    Name: 'HWFET.dat'
    Path: '\\central-mi\home\jpyle\documents\MATLAB\examples\vnt-ex86857001\HWFET.d
    Author: ''
    Department: ''
    Project: ''
    Subject: ''
    Comment: ''
    Version: '3.00'
    DataSize: 3167040
    InitialTimestamp: 2017-08-09 12:20:03.000000000
```

```
Creator Details
```

```

    ProgramIdentifier: 'MDA v7.1'
    Creator: [0x0 struct]
```

```
File Contents
```

```

    Attachment: [0x0 struct]
    ChannelNames: {{5x1 cell}}
    ChannelGroup: [1x1 struct]
```

Identify the channel with `channelList` and read all the data from this file.

```
chInfo = channelList(mdfObj, chName)
```

```
chInfo=1x9 table
```

ChannelName	ChannelGroupNumber	ChannelGroupNumSamples	ChannelGroupAcquisitionName
"Power"	1	79176	<undefined>

```
data = read(mdfObj, chInfo)
```

```

data = 1x1 cell array
    {79176x1 timetable}
```

Note that reading with the output of `channelList` returns a cell array of results.

```
data{1}(1:10,:)
```

```

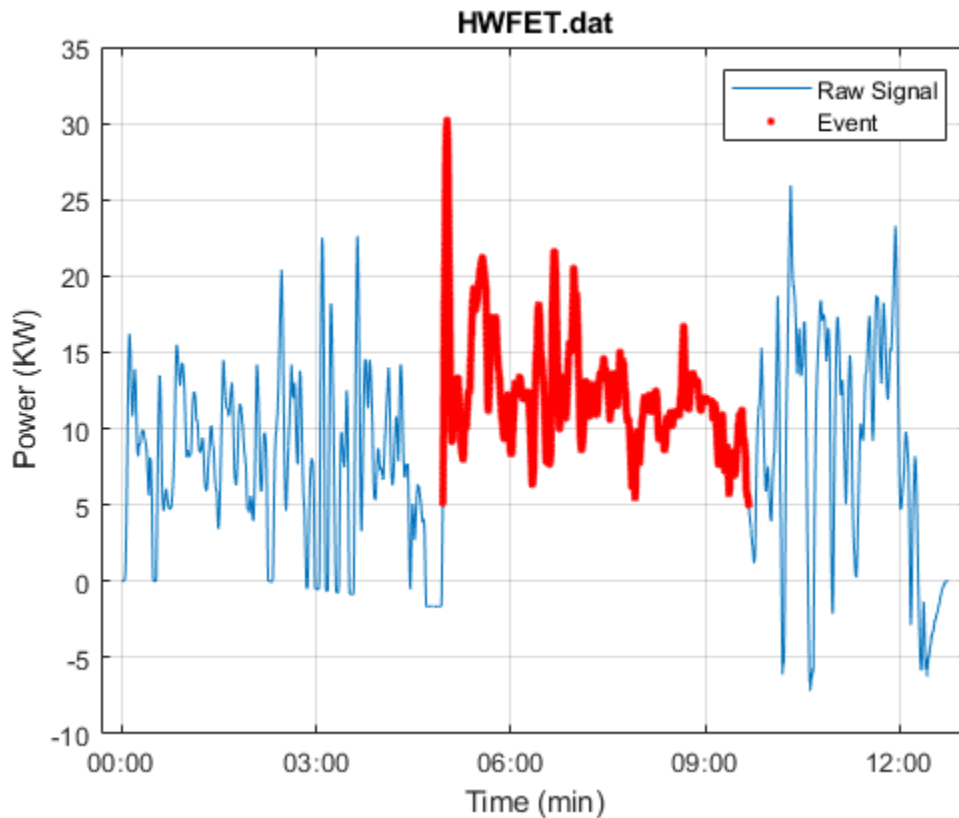
ans=10x1 timetable
    Time          Power
```

0.0048987 sec	0
0.0088729 sec	0
0.01 sec	0
0.013223 sec	0
0.016446 sec	0
0.019668 sec	0
0.02 sec	0
0.021658 sec	-2.4e-28
0.023878 sec	-3.42e-15
0.026098 sec	-1.04e-14

Visualize Using a Custom Plotting Function

Custom plotting functions are useful for encapsulation and reuse. Visualize the event in the context of the entire drive cycle. To understand how the visualization was created, open and explore the `eventPlotter` function from this example.

```
eventPlotter(data{1}, eventOfInterest)
```



Log and Replay CAN FD Messages

This example shows you how to log and replay CAN FD messages using MathWorks Virtual CAN FD channels in Simulink®. You can update this model to connect to supported hardware on your system.

Load the saved CAN FD message from `sourceFDMsgs.mat` file from the examples folder. The file contains CAN FD messages representing a 90 second drive cycle around a test track.

Convert these messages to a format compatible with the CAN FD Replay block and save it to a separate file.

Name	Size	Bytes	Class	Attributes
canFDMsgTimetable	100000x12	45411726	timetable	
canFDMsgs	1x1	8401848	struct	

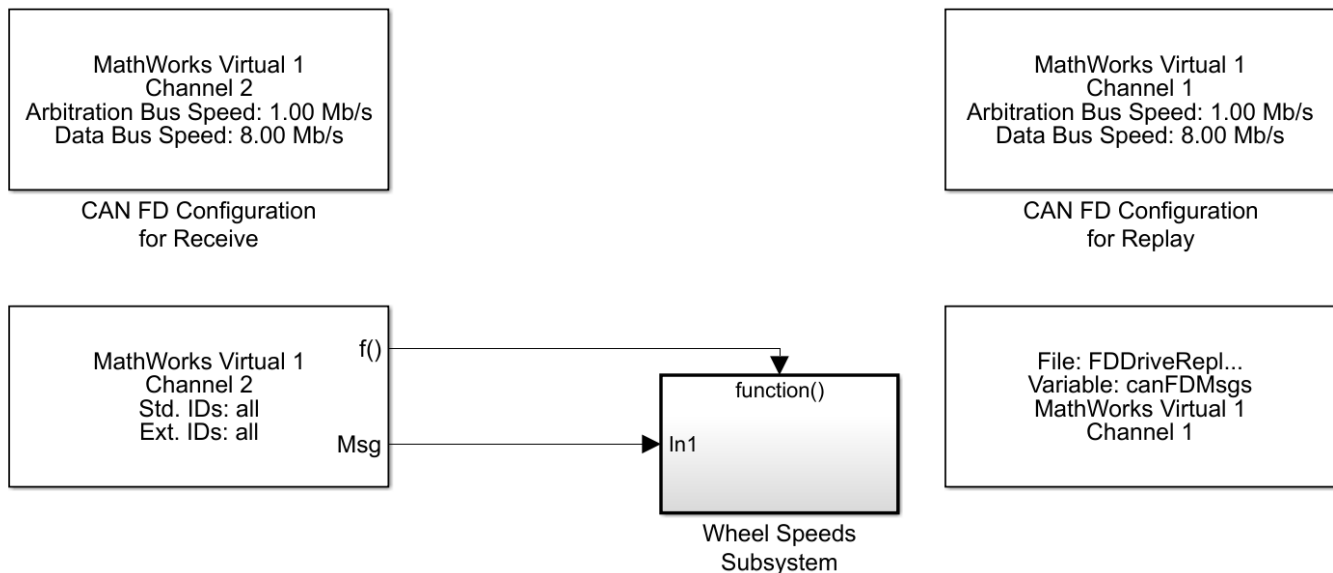
CAN FD Replay Model

This model contains:

- A CAN FD Replay block that transmits to MathWorks Virtual Channel 1.
- A CAN FD Receive block that receives the messages on a CAN FD network, through MathWorks Virtual Channel 2.

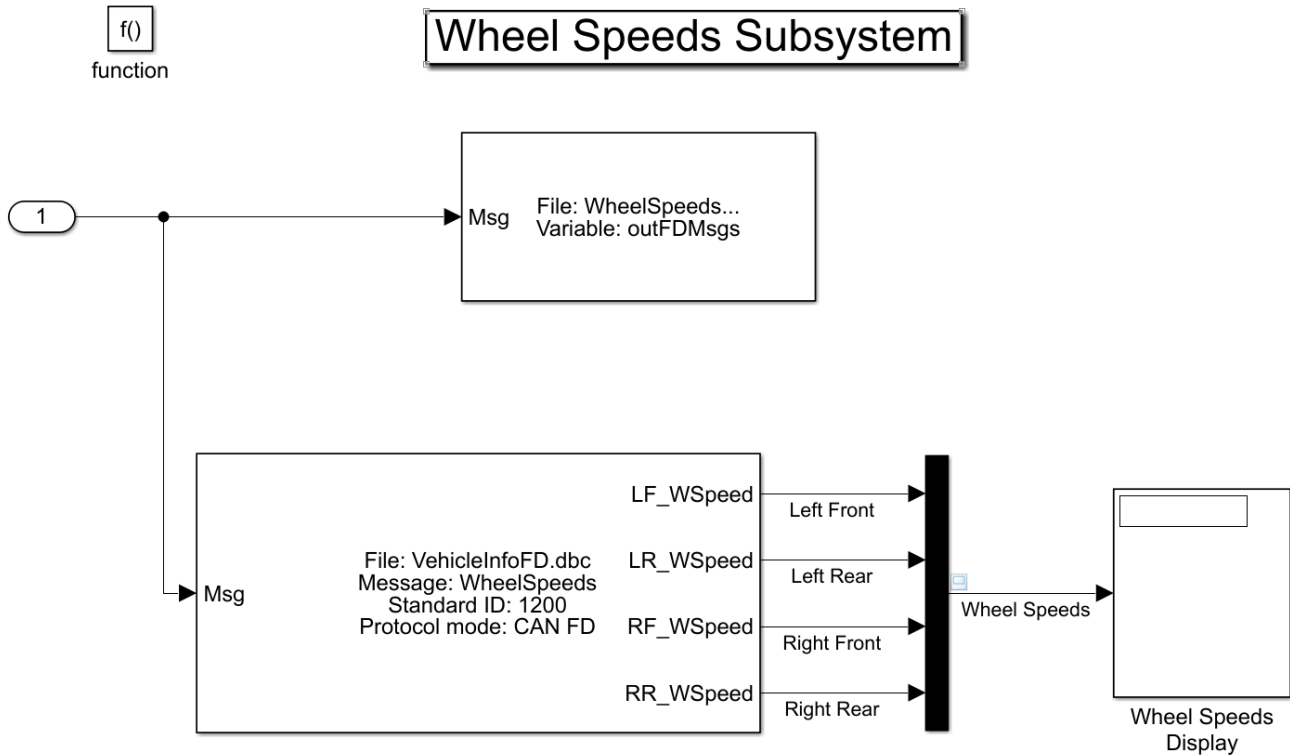
The CAN FD Receive block is configured to block all extended IDs and allow only the `WheelSpeed` message with the standard ID 1200 to pass.

Log and Replay CAN FD Messages



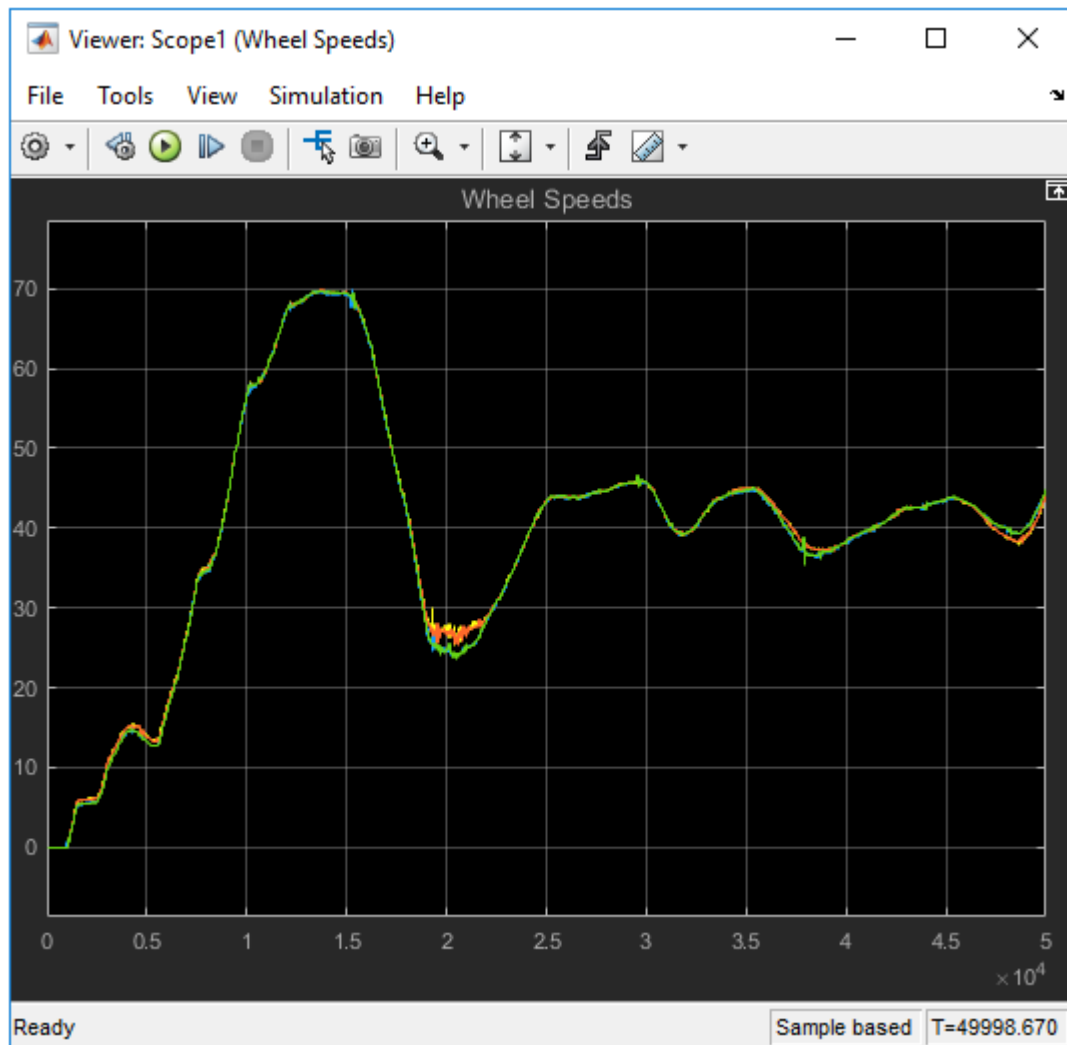
Copyright 2018 The MathWorks, Inc.

The Wheel Speeds subsystem unpacks the wheel speed information from the received CAN FD messages and plots them to a scope. The subsystem also logs the messages to a file.



Visualize Wheel Speed Information

The plot shows the wheel speed for all wheels for the duration of the test drive.



Load the Logged Message File

The CAN FD Log block creates a unique file each time you run the model. Use `dir` in the MATLAB Command Window to find the latest log file.

```
WheelSpeeds_2018-Apr-30_132033.mat
```

Name	Size	Bytes	Class	Attributes
canFDMsgTimetable	100000x12	45411726	timetable	
canFDMsgs	1x1	8401848	struct	
outFDMsgs	1x1	841848	struct	

Convert Logged Messages

Use `canFDMessageTimetable` to convert messages logged during the simulation to a timetable that you can use in the command window.

To access message signals directly, use the appropriate database file in the conversion along with `canSignalTimetable`.

ans =

15x12 timetable

Time	ID	Extended	Name	ProtocolMode	Data	Length
75.393 sec	576	false	{0x0 char }	{'CAN FD'}	{1x4 uint8}	4
75.397 sec	1200	false	{'WheelSpeeds'}	{'CAN FD'}	{1x8 uint8}	8
75.398 sec	128	false	{0x0 char }	{'CAN FD'}	{1x7 uint8}	7
75.398 sec	133	false	{0x0 char }	{'CAN FD'}	{1x8 uint8}	8
75.398 sec	144	false	{0x0 char }	{'CAN FD'}	{1x8 uint8}	8
75.398 sec	528	false	{0x0 char }	{'CAN FD'}	{1x7 uint8}	7
75.399 sec	529	false	{0x0 char }	{'CAN FD'}	{1x8 uint8}	8
75.399 sec	1201	false	{0x0 char }	{'CAN FD'}	{1x8 uint8}	8
75.399 sec	512	false	{0x0 char }	{'CAN FD'}	{1x8 uint8}	8
75.399 sec	513	false	{0x0 char }	{'CAN FD'}	{1x8 uint8}	8
75.399 sec	533	false	{0x0 char }	{'CAN FD'}	{1x8 uint8}	8
75.4 sec	1312	false	{0x0 char }	{'CAN FD'}	{1x5 uint8}	5
75.405 sec	1200	false	{'WheelSpeeds'}	{'CAN FD'}	{1x8 uint8}	8
75.406 sec	1201	false	{0x0 char }	{'CAN FD'}	{1x8 uint8}	8
75.408 sec	1296	false	{0x0 char }	{'CAN FD'}	{1x3 uint8}	3

ans =

15x4 timetable

Time	RR_WSpeed	RF_WSpeed	LR_WSpeed	LF_WSpeed
75.397 sec	41.19	40.04	41.19	39.95
75.405 sec	41.2	40.04	41.21	39.97
75.414 sec	41.22	40.05	41.26	40.03
75.424 sec	41.25	40.13	41.3	40.05
75.433 sec	41.19	40.14	41.28	40.08
75.441 sec	41.17	40.18	41.31	40.14
75.45 sec	41.31	40.27	41.31	40.17
75.458 sec	41.37	40.25	41.31	40.19
75.466 sec	41.39	40.22	41.3	40.19
75.475 sec	41.39	40.25	41.3	40.2
75.483 sec	41.37	40.26	41.33	40.21
75.492 sec	41.44	40.35	41.33	40.19
75.501 sec	41.51	40.44	41.36	40.22
75.509 sec	41.58	40.47	41.44	40.29
75.517 sec	41.63	40.45	41.44	40.31

MathWorks CAN FD Virtual channels were used for this example. You can however connect your models to other supported hardware.

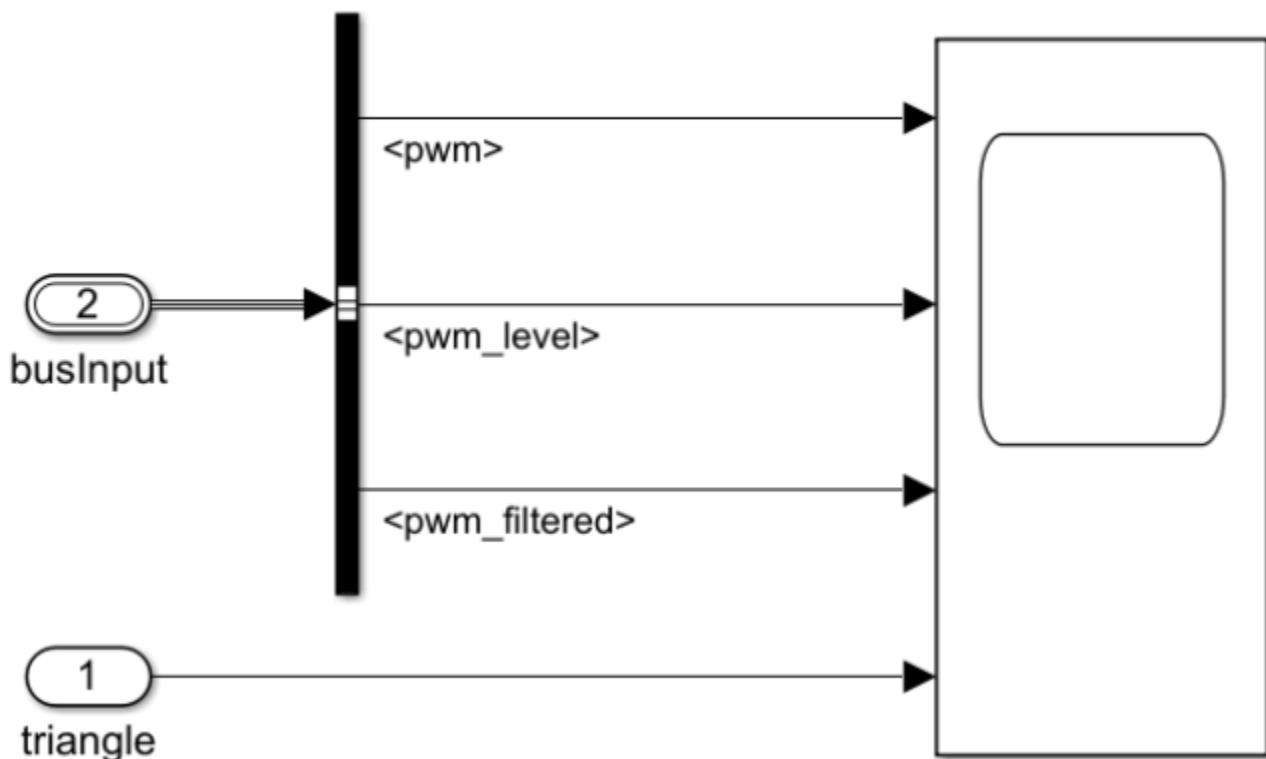
Mapping MDF Channels to Simulink Model Input Ports

This example shows you how to programmatically map MDF channels and consume their data via input ports of a Simulink model. It performs the gathering of input port names of a Simulink model and correlates them to the contents of a given MDF file. A linkage between them is then created which consumes channel data sourced from the MDF file when the model runs.

Acquire Model Details

Define the example model name and open it.

```
mdlName = 'ModelForMDFInput';
open_system(mdlName);
```



Use the `createInputDataset` function to obtain overall information about the model and its inputs.

```
dsObj = createInputDataset(mdlName)

dsObj =
Simulink.SimulationData.Dataset '' with 2 elements
```

		Name	BlockPath
1	[1x1 timeseries]	triangle	''
2	[1x1 struct]	busInput	''

- Use braces { } to access, modify, or add elements using index.

Obtain Model Input Port Names

This model has both a bus and an individual input port. The `helperGetMdlInputNames` function demonstrates how to get the name of all the model inputs regardless of how they are defined in the model.

```
mdlInputNames = helperGetMdlInputNames(mdlName)

mdlInputNames = 4x1 string array
    "triangle"
    "pwm"
    "pwm_level"
    "pwm_filtered"
```

Investigate the MDF File

Now that you have the input port names of the model, you can see what channels exist in the MDF file so you can attempt to match them. The `channelList` function of the MDF feature allows quick access to the available channels present in an MDF file.

```
mdfName = 'CANape.MF4';
mdfObj = mdf(mdfName);
mdfChannelInfo = channelList(mdfObj)
```

```
mdfChannelInfo=120x9 table
    ChannelName      ChannelGroupNumber  ChannelGroupNumSamples  ChannelGroupA
```

ChannelName	ChannelGroupNumber	ChannelGroupNumSamples	ChannelGroupA
"ampl"	2	199	10
"channel1"	2	199	10
"Counter_B4"	1	1993	10
"Counter_B5"	1	1993	10
"Counter_B6"	1	1993	10
"Counter_B7"	1	1993	10
"map1_8_8_uc_measure"	1	1993	10
"map1_8_8_uc_measure[0][0]"	1	1993	10
"map1_8_8_uc_measure[0][1]"	1	1993	10
"map1_8_8_uc_measure[0][2]"	1	1993	10
"map1_8_8_uc_measure[0][3]"	1	1993	10
"map1_8_8_uc_measure[0][4]"	1	1993	10
"map1_8_8_uc_measure[0][5]"	1	1993	10
"map1_8_8_uc_measure[0][6]"	1	1993	10
"map1_8_8_uc_measure[0][7]"	1	1993	10
"map1_8_8_uc_measure[1][0]"	1	1993	10
⋮			

Construct a Table to Manage Items of Interest

Use a table to map the model input ports to MDF channels.

```
channelTable = table();
channelTable.PortNames = mdlInputNames;
n = size(channelTable.PortNames,1);
channelTable.ChGrpNum = NaN(n,1);
channelTable.ChNameActual = strings(n,1);
channelTable
```

```
channelTable=4x3 table
    PortNames      ChGrpNum      ChNameActual
    _____      _____      _____
    "triangle"      NaN           ""
    "pwm"           NaN           ""
    "pwm_level"    NaN           ""
    "pwm_filtered" NaN           ""
```

Perform Input Port to Channel Matching

The `helperReportChannelInfo` function searches the MDF file for channel names that match the model input port names. When found, the details of the channel are recorded in the table. Specifically, the channel group number where the given channel is in the file and its actual defined name. Note that the actual channel names are not exact matches to the model port names. In this example, the channel name matching is performed case-insensitive and ignores the underscore characters. This algorithm can be adapted as needed based on application-specific matching criteria.

```
channelTable = helperReportChannelInfo(channelTable, mdfChannelInfo)
```

```
channelTable=4x3 table
    PortNames      ChGrpNum      ChNameActual
    _____      _____      _____
    "triangle"      1             "Triangle"
    "pwm"           1             "PWM"
    "pwm_level"    1             "PWM_Level"
    "pwm_filtered" 1             "PWMFiltered"
```

Populate the Simulink Dataset Object with MDF Channel Data

The dataset object created earlier contains both a single timeseries object and a structure of timeseries objects. This makes assigning data back to them somewhat challenging. Things to keep in mind include:

- When specifying 'TimeSeries' as the return type from the MDF read function, you must call `read` separately for each channel.
- Because the dataset object has dissimilar elements (a scalar timeseries and a scalar structure of timeseries objects), you need to manually manage the collection and make sure you are writing to the correct location.

```
for ii = 1:dsObj.numElements
    switch ii
        case {1} % [1x1 timeseries], triangle
            % Read the input port data from the MDF file one channel at a time.
            mdfData = read(mdfObj, channelTable.ChGrpNum(ii), channelTable.ChNameActual(ii), 'Output');
            % Populate the dataset object.
            dsObj{ii} = mdfData;

        case {2} % [1x1 struct], busInput
            for jj = 1:numel(fieldnames(dsObj.getElement(ii)))
                % Read the input port data from the MDF file one channel at a time.
                mdfData = read(mdfObj, channelTable.ChGrpNum(jj+1), channelTable.ChNameActual(jj+1), 'Output');
                % Populate the dataset object.
                dsObj{ii}.(channelTable.PortNames{jj+1}) = mdfData;
            end
    end
end
```

```
        end
    end
end
dsObj

dsObj =
Simulink.SimulationData.Dataset '' with 2 elements
```

		Name	BlockPath
1	[1x1 timeseries]	Triangle	''
2	[1x1 struct]	busInput	''

- Use braces { } to access, modify, or add elements using index.

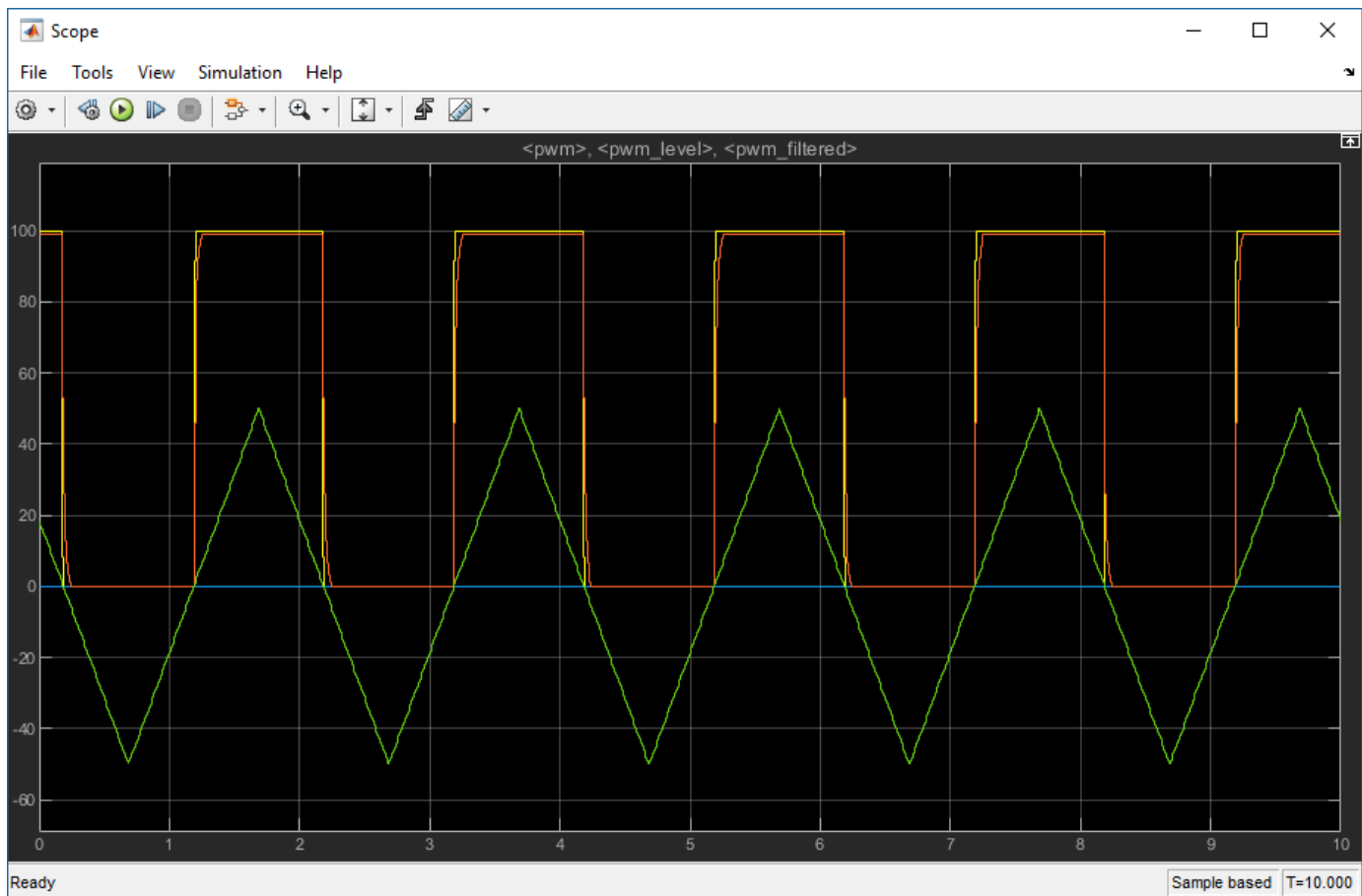
Enable the Dataset as Input to the Simulink Model

```
set_param mdlName, 'LoadExternalInput', 'on');
set_param mdlName, 'ExternalInput', 'dsObj');
```

Run the Model

Upon executing the model, note that the MDF channel data properly maps to the designated input ports and plots through Simulink as expected.

```
open_system(mdlName);
bp = find_system(mdlName, 'BlockType', 'Scope');
open_system(bp);
pause(1)
set_param(mdlName, 'SimulationCommand', 'start');
```



Helper Functions

```
function mdlInputNames = helperGetMdlInputNames mdlName)
% helperGetMdlInputNames Find input port names of a Simulink model.
%
% This function takes in the name of a Simulink model and returns the names of each model input.
% both a bus and a stand-alone input port going into it. To drive an input port that expects a bus
% the signals as timeseries objects in a struct that matches the structure of the bus object attached
%
% Test to see if the model is currently loaded in memory.
isLoading = bdIsLoaded(matlab.lang.makeValidName(mdlName));

% If the model is not open then load it.
if ~isLoading
    load_system(mdlName);
end

dsObj = createInputDataset(mdlName);
numElements = dsObj.numElements;
isStruct = zeros(1:numElements);

% Check to see if any of the elements in the returned dataset object are
% structs. If they are, assume they are for an input port that accepts a bus.
for elementIdx = 1:numElements
    isStruct(elementIdx) = isa(dsObj.getElement(elementIdx), 'struct');
```

```
end

% For a port that accepts a bus, the data to be loaded must be arranged in a struct
% that matches the structure of the bus object attached to the input port.
busInportIdx = 1;
for idx = 1:numElements
    if isStruct(idx)
        % Get names of signals from a bus input port.
        inPortsBus(busInportIdx, :) = string(fieldnames(dsObj.getElement(idx)));
    else
        % Get signal name from a non-bus input port.
        inPorts(idx) = string(dsObj.getElement(idx).Name);
    end
end

mdlInputNames = [inPorts, inPortsBus]';
end

function channelTableOut = helperReportChannelInfo(channelTableIn, mdfChannelInfo)
% channelTableOut Reports if a channel is present in a set of channel names.

% Assign the output data.
channelTableOut = channelTableIn;

% Remove underscores and make everything lowercase for matching.
inPortChannelNames = lower(erase(channelTableIn.PortNames, '_'));
mdfChannelNames = lower(erase(mdfChannelInfo.ChannelName, '_'));

% Match the input channel names to the channel names in the MDF file.
[~, inPortidx] = ismember(inPortChannelNames, mdfChannelNames);

% Assign the relevant information back to the channel table.
channelTableOut.ChGrpNum = mdfChannelInfo{(inPortidx), {'ChannelGroupNumber'}};
channelTableOut.ChNameActual = mdfChannelInfo{(inPortidx), {'ChannelName'}};
end
```

Working With ASAM CDFX Files in MATLAB

This example shows how to import a calibration data file into MATLAB, examine and modify its contents, and export the changes back to a file on disk.

Importing a CDFX file

Import data from a CDFX file using the `cdfx` function.

```
cdfxObj = cdfx("CDFXExampleFile.cdfx")
```

```
cdfxObj =
```

```
  CDFX with properties:
```

```
    Name: "CDFXExampleFile.cdfx"
```

```
    Path: "C:\TEMP\Bdoc20b_1465442_5924\ib8F4264\25\tpb4bb48cc\vnt-ex38787800\CDFXExampleFile"
```

```
    Version: "CDF20"
```

Visualizing Calibration Data

CDFX files contain information about vehicle ECUs (systems), and their parameters (instances). Use `instanceList` and `systemList` to visualize the calibration data in table form. These functions also allow filtering based on instance or system short names.

```
iList = instanceList(cdxfObj)
```

```
iList=4x6 table
```

ShortName	System	Category	Value	Units	FeatureRef
"ASAM.C.SCALAR.GAIN"	"ExampleSystem"	"VALUE"	{[3]}	"gain"	"Function"
"ASAM.C.SCALAR.BITMASK_0001"	"ExampleSystem"	"BOOLEAN"	{[1]}	""	"Function"
"ASAM.C.MAP"	"ExampleSystem"	"MAP"	{1x1 struct}	""	"Function"
"ASAM.C.COM_AXIS"	"ExampleSystem"	"COM_AXIS"	{5x1 double}	"hours"	"Function"

If you want to filter the table based on a desired short name, pass a string as a second argument.

```
iListArray = instanceList(cdxfObj, "ASAM.C.SCALAR")
```

```
iListArray=2x6 table
```

ShortName	System	Category	Value	Units	FeatureRef
"ASAM.C.SCALAR.GAIN"	"ExampleSystem"	"VALUE"	{[3]}	"gain"	"Function"
"ASAM.C.SCALAR.BITMASK_0001"	"ExampleSystem"	"BOOLEAN"	{[1]}	""	"Function"

The default querying behavior will return a table for all instances whose short names partially match the search string. To filter for an exact instance name match, use the `ExactMatch` name-value pair.

```
iListArrayExact = instanceList(cdxfObj, "ASAM.C.SCALAR.BITMASK_0001", "ExampleSystem", 'ExactMatch')
```

```
iListArrayExact=1x6 table
```

ShortName	System	Category	Value	Units	FeatureRef
"ASAM.C.SCALAR.BITMASK_0001"	"ExampleSystem"	"BOOLEAN"	{[1]}	""	"Function"

```
"ASAM.C.SCALAR.BITMASK_0001" "ExampleSystem" "BOOLEAN" {[1]} "" "FunctionS
```

For CDFX files that contain calibration data for more than one ECU system, `systemList` can be useful to view the contents of each system at a high level.

```
sList = systemList(cdfxObj)
```

```
sList=1x3 table
      ShortName      Instances      Metadata
      _____      _____      _____
      "ExampleSystem" {1x4 string} "NO_VCD"
```

Examining and Modifying Simple Calibration Parameters

Use `getValue` to extract the value of an instance from the CDFX object. Use `setValue` to modify the value of the instance.

```
iValueScalar = getValue(cdfxObj, "ASAM.C.SCALAR.GAIN")
iValueScalar = 3
iValueScalarNew = iValueScalar + 20;
setValue(cdfxObj, "ASAM.C.SCALAR.GAIN", iValueScalarNew);
iValueScalarNew = getValue(cdfxObj, "ASAM.C.SCALAR.GAIN")
iValueScalarNew = 23
```

Working With More Complex Parameter Types

Certain instance categories contain more than just a physical value. These instances are often multi-dimensional arrays that are scaled according to an axis. Calling `getValue` on these instances returns a structure that contains each axis as a separate field, distinct from the `PhysicalValue`.

To inspect the CUBOID instance, first call `getValue`, then examine the properties of the returned structure. Notice that there is additional data associated with each axis, including the type of axis, its physical values, and whether the axis values are referenced from another instance on the CDFX object.

```
iValueMap = getValue(cdfxObj, "ASAM.C.MAP")
iValueMap = struct with fields:
    PhysicalValue: [5x5 double]
    Axis1: [1x1 struct]
    Axis2: [1x1 struct]

disp(iValueMap.PhysicalValue)

     2     5     7    10    12
    15    17    20    22    25
    27    30    32    35    37
    40    42    47    50    52
    55    57    60    62    65

disp(iValueMap.Axis1)
```



```

ReferenceName: ""
  Category: "STD_AXIS"
PhysicalValue: [5x1 double]
IsReferenced: 0

```

```
disp(iValueMap.Axis2)
```

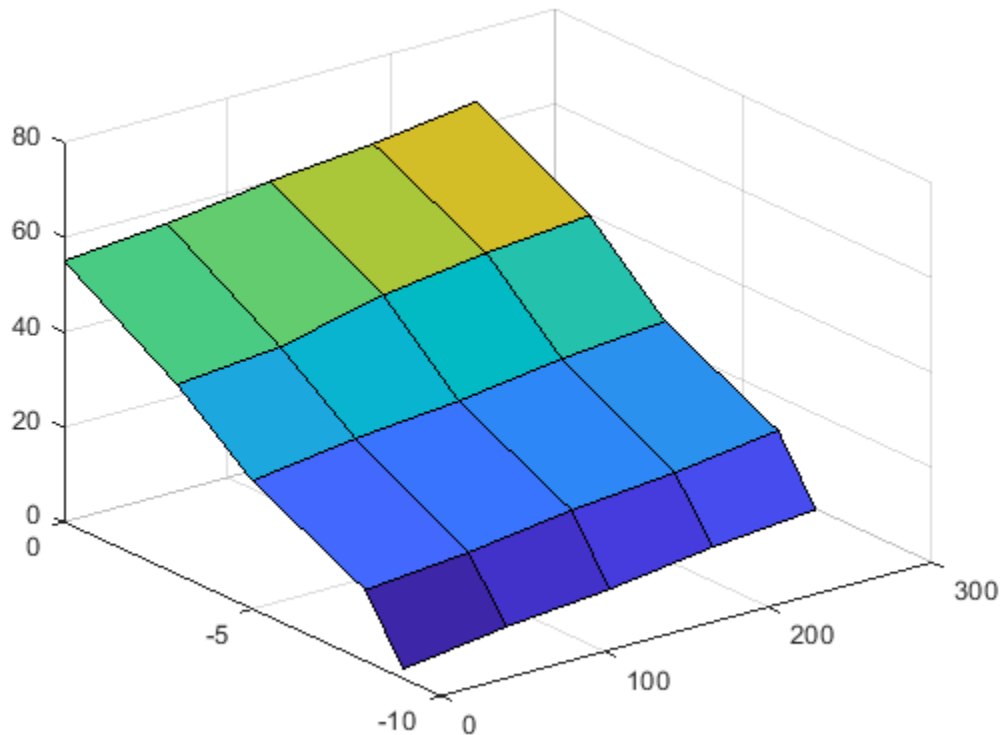
```

ReferenceName: "ASAM.C.COM_AXIS"
  Category: "COM_AXIS"
PhysicalValue: [5x1 double]
IsReferenced: 1

```

We can also visualize the instance values using MATLAB plotting functions. For multidimensional arrays, use the physical values of the axes structures to define the axes on the plot.

```
surf('ZDataSource', 'iValueMap.PhysicalValue', 'XDataSource', 'iValueMap.Axis1.PhysicalValue', 'YDataSource', 'iValueMap.Axis2.PhysicalValue', 'refreshdata');
```



Modifying the physical value of this instance works the same as for scalars. Update the physical value field of the structure and pass it back to `setValue`.

```
iValueMap.PhysicalValue(:, 1) = iValueMap.PhysicalValue(:, 1)*2;
setValue(cdfxObj, "ASAM.C.MAP", iValueMap);
```

Now we can observe that the changes have been committed to the CDFX object in the workspace.

```
iValueMapNew = getValue(cdfxObj, "ASAM.C.MAP")
```

```
iValueMapNew = struct with fields:
  PhysicalValue: [5x5 double]
  Axis1: [1x1 struct]
  Axis2: [1x1 struct]
```

```
disp(iValueMapNew.PhysicalValue)
```

```

  4    5    7   10   12
 30   17   20   22   25
 54   30   32   35   37
 80   42   47   50   52
110   57   60   62   65
```

To modify the axis values of this instance, we first need to know if the axis we want to modify is referenced or not. This can be determined by examining the `IsReferenced` field of each axis structure. If the axis is not referenced, we simply modify the `PhysicalValue` field of the axis structure and pass the top-level structure back to `setValue`.

```
disp(iValueMapNew.Axis1.PhysicalValue)
```

```

  0
 63
126
189
252
```

```
iValueMapNew.Axis1.PhysicalValue = iValueMapNew.Axis1.PhysicalValue*10;
setValue(cdfxObj, "ASAM.C.MAP", iValueMapNew);
iValueMapNewAxis = getValue(cdfxObj, "ASAM.C.MAP");
disp(iValueMapNewAxis.Axis1.PhysicalValue)
```

```

  0
 630
1260
1890
2520
```

However, some axes are not defined on the instance itself, and are instead referenced from another instance. There are specific instance categories for representing referenced axis values (`COM_AXIS`, `RES_AXIS`, and `CURVE_AXIS`). Attempting to modify a referenced axis from a referencing instance will result in an error. The solution is to update the values directly on the axis instance itself. Information on whether an axis is using referenced values, including the short name of the instance being referenced can be found on the axis fields of the top-level structure.

```
iValueCommonAxis = getValue(cdfxObj, iValueMapNewAxis.Axis2.ReferenceName)
```

```
iValueCommonAxis = 5x1
```

```

 -9
 -8
 -5
 -3
  0
```

```
iValueCommonAxis(:) = 1:5;
setValue(cdfxObj, iValueMapNewAxis.Axis2.ReferenceName, iValueCommonAxis);
```

Now that we have modified the original instance, we can observe that the changes are reflected in the referencing instance.

```
iValueMapNew = getValue(cdfx0bj, "ASAM.C.MAP")
```

```
iValueMapNew = struct with fields:  
    PhysicalValue: [5x5 double]  
        Axis1: [1x1 struct]  
        Axis2: [1x1 struct]
```

```
iValueMapNew.Axis2.PhysicalValue
```

```
ans = 5x1
```

```
1  
2  
3  
4  
5
```

Exporting Calibration Data to a File

You can write back to the same file, or to a new file by specifying a filepath.

```
write(cdfx0bj, "NewExampleFile.cdfx");
```

Using ASAM CDFX Data With Simulink

This example shows how to use calibration data from a CDF file as inputs to a Simulink model.

Import Data

Import the calibration data using the `cdfx` function.

```
cdfxObj = cdfx("CDFXExampleFile.cdfx")

cdfxObj =
  CDFX with properties:

      Name: "CDFXExampleFile.cdfx"
      Path: "C:\TEMP\Bdoc20b_1465442_5924\ib8F4264\25\tpb4bb48cc\vnt-ex88524458\CDFXExampleFile"
      Version: "CDF20"
```

Instantiate Local Variables

Use `getValue` to extract the desired parameters into the MATLAB workspace.

```
gainParam = getValue(cdfxObj, "ASAM.C.SCALAR.GAIN")

gainParam = 3

mapParam = getValue(cdfxObj, "ASAM.C.MAP")

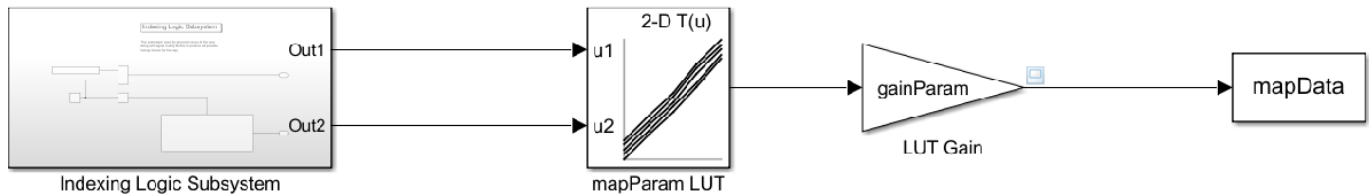
mapParam = struct with fields:
    PhysicalValue: [5x5 double]
    Axis1: [1x1 struct]
    Axis2: [1x1 struct]
```

Lookup-Gain Model

```
open_system("CDFXSimulinkModel.slx");
cdfxMdl = gcs

cdfxMdl =
  'CDFXSimulinkModel'
```

Using CDFX Data With Simulink



The top-level model uses the generated indices to index into the mapParam lookup table. The output is then scaled using the value of gainParam.

This model contains:

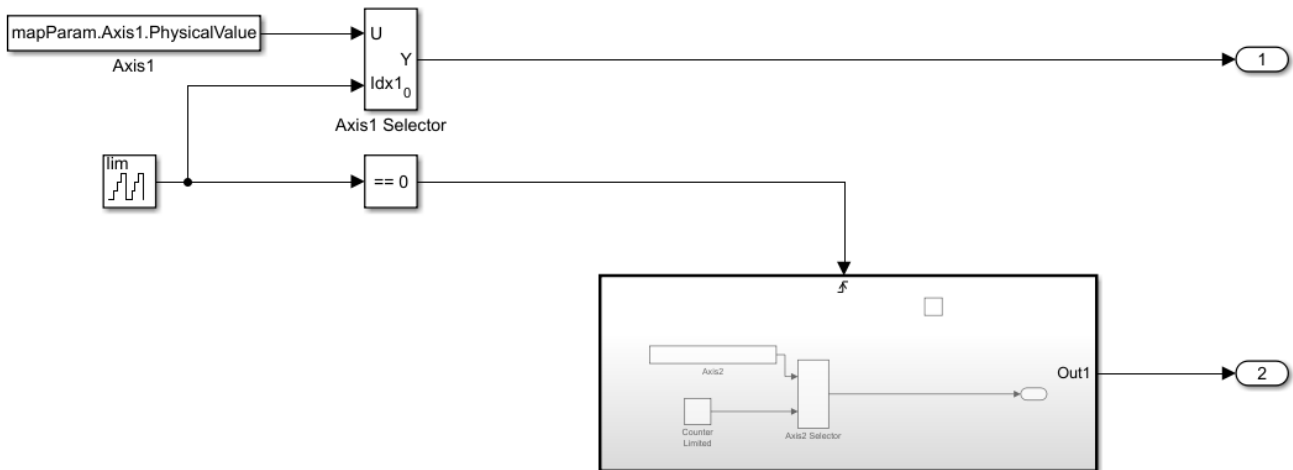
- 2-D Lookup Table block to represent the ASAM.C.MAP parameter from the CDFX file. The "Table data" field represents the physical value of the instance, and the "Breakpoint" fields represent the physical values of the axes.
- Gain block to represent the ASAM.C.SCALAR.GAIN parameter from the CDFX file.
- To Workspace block to log the simulation data.

Indexing Logic Subsystem

The Indexing Logic subsystem uses the physical values of the axes of the ASAM.C.MAP parameter, along with signal routing blocks and a triggered subsystem, to produce all valid combinations of lookup indices. This configuration can be useful if you need to test across the full range of possible input values of a calibration parameter.

Indexing Logic Subsystem

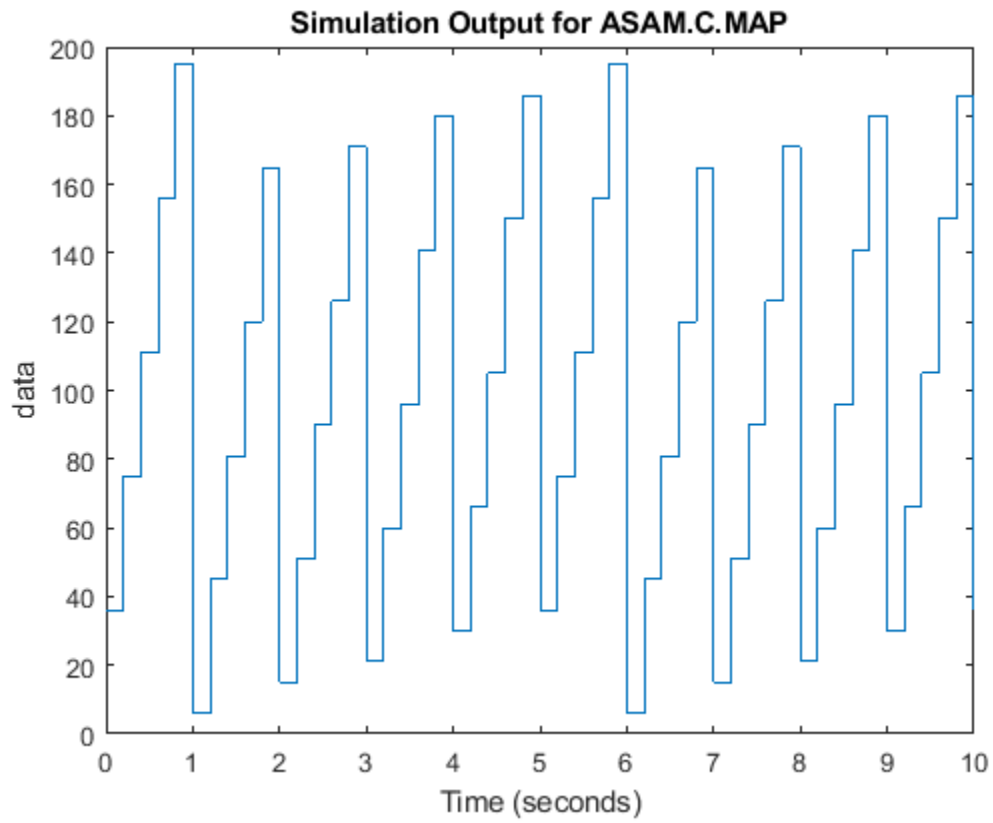
This subsystem uses the physical values of the axes along with signal routing blocks to produce all possible lookup indices for the map.



Log Output Data in MATLAB

The output of the simulation is sent to MATLAB by the To Workspace block, where it is stored as a timeseries object called `mapData`. This data can now be inspected and visualized in the MATLAB workspace.

```
sim(cdfxMdl);
plot(mapData)
title("Simulation Output for ASAM.C.MAP")
```



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Using ASAM CDFX Data With Simulink Data Dictionary

This example shows how to store calibration data from an ASAM CDFX file in a data dictionary and use these values as parameters to a Simulink model.

Import Data

Import the calibration data using the `cdfx` function.

```
cdfxObj = cdfx("CDFXExampleFile.cdfx")

cdfxObj =
  CDFX with properties:

      Name: "CDFXExampleFile.cdfx"
      Path: "/mathworks/home/rollinb/Documents/MATLAB/Examples/vnt-ex73237310-20190405222527/CDFXExampleFile.cdfx"
      Version: "CDF20"
```

Create and Populate Data Dictionary with Calibration Data

Use `getValue` to extract the desired parameters into the MATLAB workspace.

```
dictName = "CDFXExampleDD.sldd"

dictName =
  "CDFXExampleDD.sldd"

% Check if dictionary is already in the working folder.
if isfile(dictName)
    % If data dictionary exists, open it.
    dDict = Simulink.data.dictionary.open(dictName)
else
    % If dictionary does not exist, create it and populate with CDFX data.
    dDict = Simulink.data.dictionary.create(dictName)
    ddSection = getSection(dDict, "Design Data")

    addEntry(ddSection, "gainParam", getValue(cdfxObj, "ASAM.C.SCALAR.GAIN"))
    addEntry(ddSection, "mapParam", getValue(cdfxObj, "ASAM.C.MAP"))
end

dDict =
  Dictionary with properties:

      DataSources: {0x1 cell}
      HasAccessToBaseWorkspace: 0
      EnableAccessToBaseWorkspace: 0
      HasUnsavedChanges: 0
      NumberOfEntries: 2

% Display contents of the data dictionary.
listEntry(dDict)
```

Section	Name	Status	DataSource	LastModified	LastModifiedBy	CL
---------	------	--------	------------	--------------	----------------	----

Design Data	gainParam	CDFXExampleDD.sldd	2019-04-05 22:33	rollinb	do
Design Data	mapParam	CDFXExampleDD.sldd	2019-04-05 22:33	rollinb	st

Link Data Dictionary to Simulink Model

Open the Simulink model, then use set param to link the existing data dictionary to your model. This will allow the model to access the values defined within the dictionary.

```
open_system("CDFXSLDDModel.slx");
cdfxMdl = gcs

cdfxMdl =
'CDFXSLDDModel'

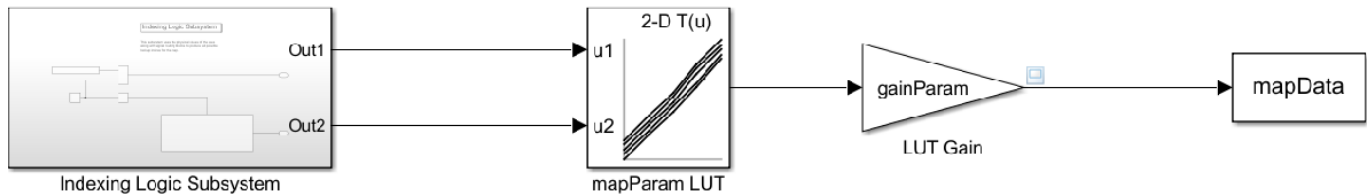
set_param(gcs, 'DataDictionary', dictName)
```

We can now close the connection to the data dictionary.

```
close(dDict)
```

Lookup-Gain Model

Using CDFX Data With Simulink



The top-level model uses the generated indices to index into the mapParam lookup table. The output is then scaled using the value of gainParam.

This model contains:

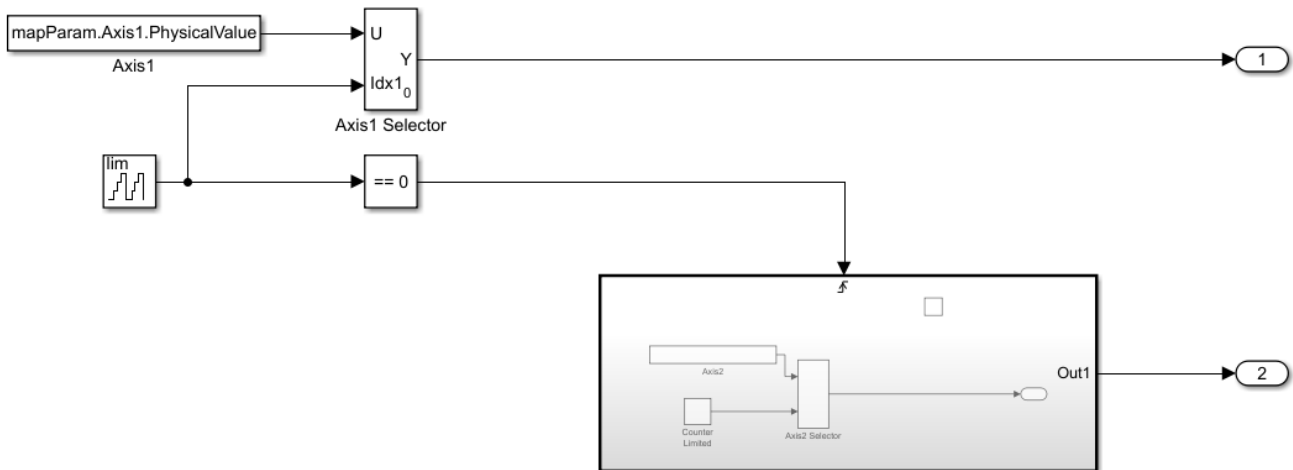
- 2-D Lookup Table block to represent the ASAM.C.MAP parameter from the CDFX file. The "Table data" field represents the physical value of the instance, and the "Breakpoint" fields represent the physical values of the axes.
- Gain block to represent the ASAM.C.SCALAR.GAIN parameter from the CDFX file.
- To Workspace block to log the simulation data.

Indexing Logic Subsystem

The Indexing Logic subsystem uses the physical values of the axes of the ASAM.C.MAP parameter, along with signal routing blocks and a triggered subsystem, to produce all valid combinations of lookup indices. This configuration can be useful if you need to test across the full range of possible input values of a calibration parameter.

Indexing Logic Subsystem

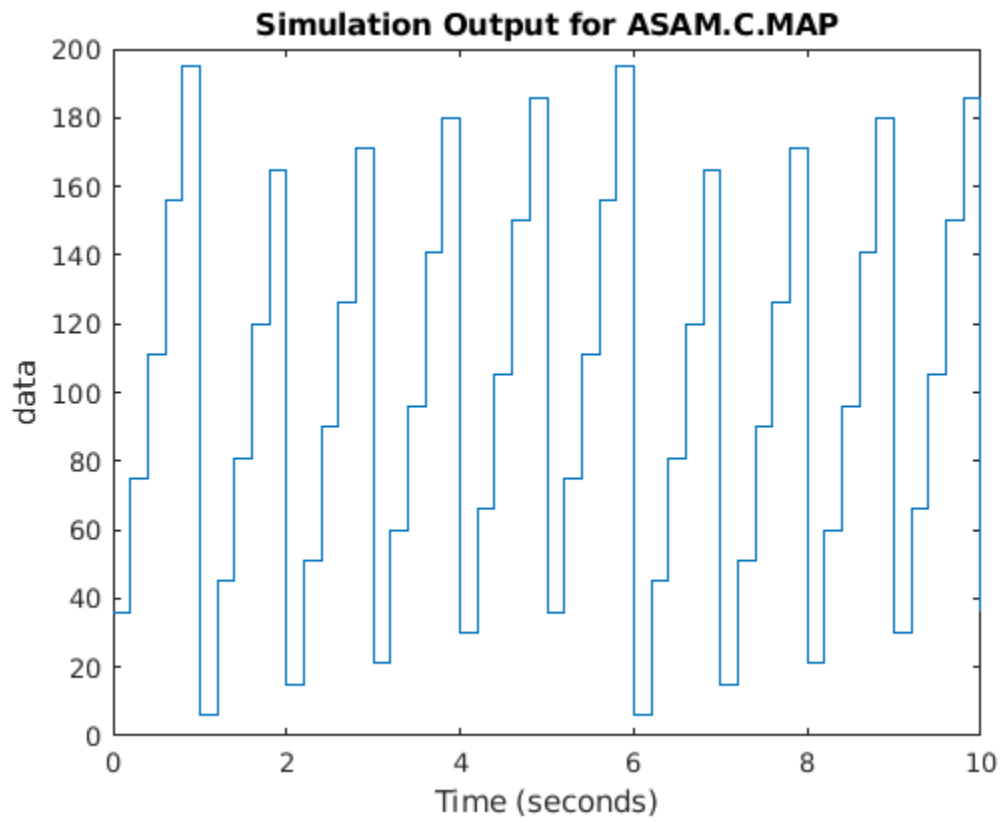
This subsystem uses the physical values of the axes along with signal routing blocks to produce all possible lookup indices for the map.



Log Output Data in MATLAB

The output of the simulation is sent to MATLAB by the To Workspace block, where it is stored as a timeseries object called `mapData`. This data can now be inspected and visualized in the MATLAB workspace.

```
sim(cdfxMdl);
plot(mapData)
title("Simulation Output for ASAM.C.MAP")
```

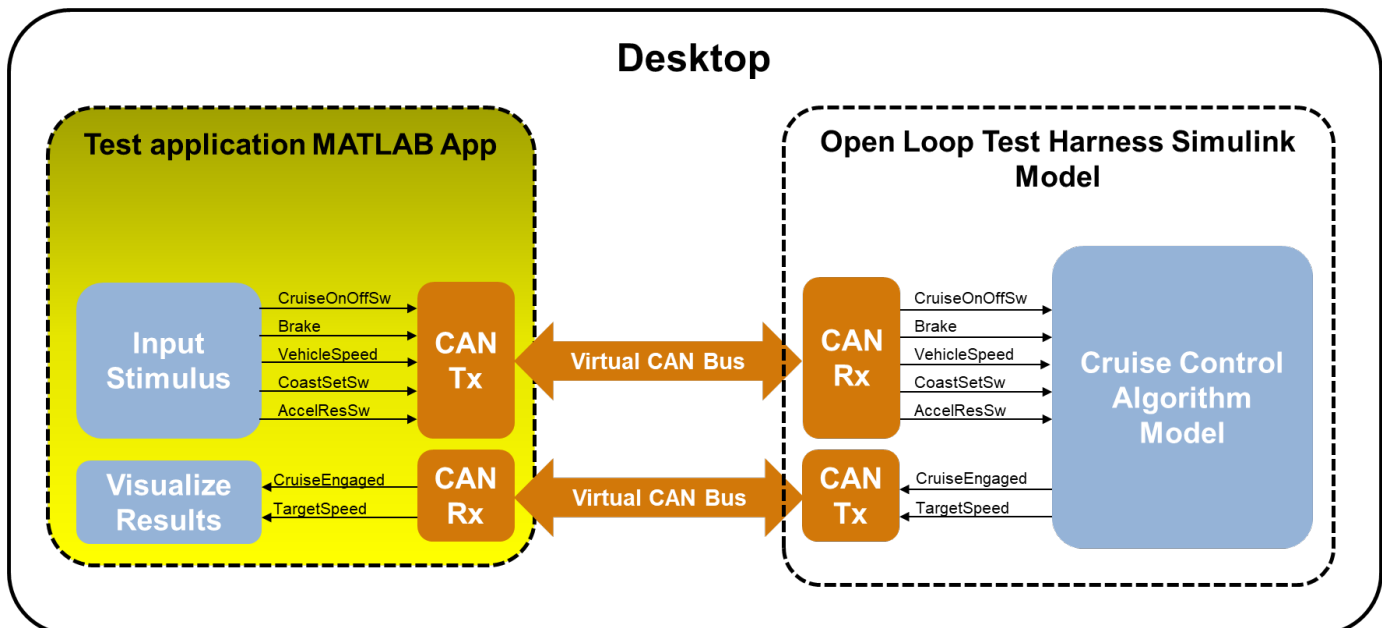


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Developing an App Designer App for a Simulink Model using CAN

This example shows how to construct a test application user interface (UI) and connect it to a Simulink model using virtual CAN channels. The test application UI is constructed using MATLAB App Designer™ along with several Vehicle Network Toolbox™ (VNT) functions to provide a virtual CAN bus interface to a Simulink model of an automotive cruise control application. The test application UI allows a user to provide input stimulus to the cruise control algorithm model, observe results fed back from the model, log CAN messages to capture test stimuli, and replay logged CAN messages to debug and correct issues with the algorithm model. The example shows the key Vehicle Network Toolbox functions and blocks used to implement CAN communication in the following areas:

- The test application UI supporting communication with the Simulink algorithm model for testing via CAN
- The test application UI supporting logging and replaying of CAN data
- The Simulink algorithm model



Adding Virtual CAN Channel Communication to the UI

In this section, we describe the key Vehicle Network Toolbox functions used to add a CAN channel interface to the Simulink Cruise Control algorithm test application model. This covers the following topics:

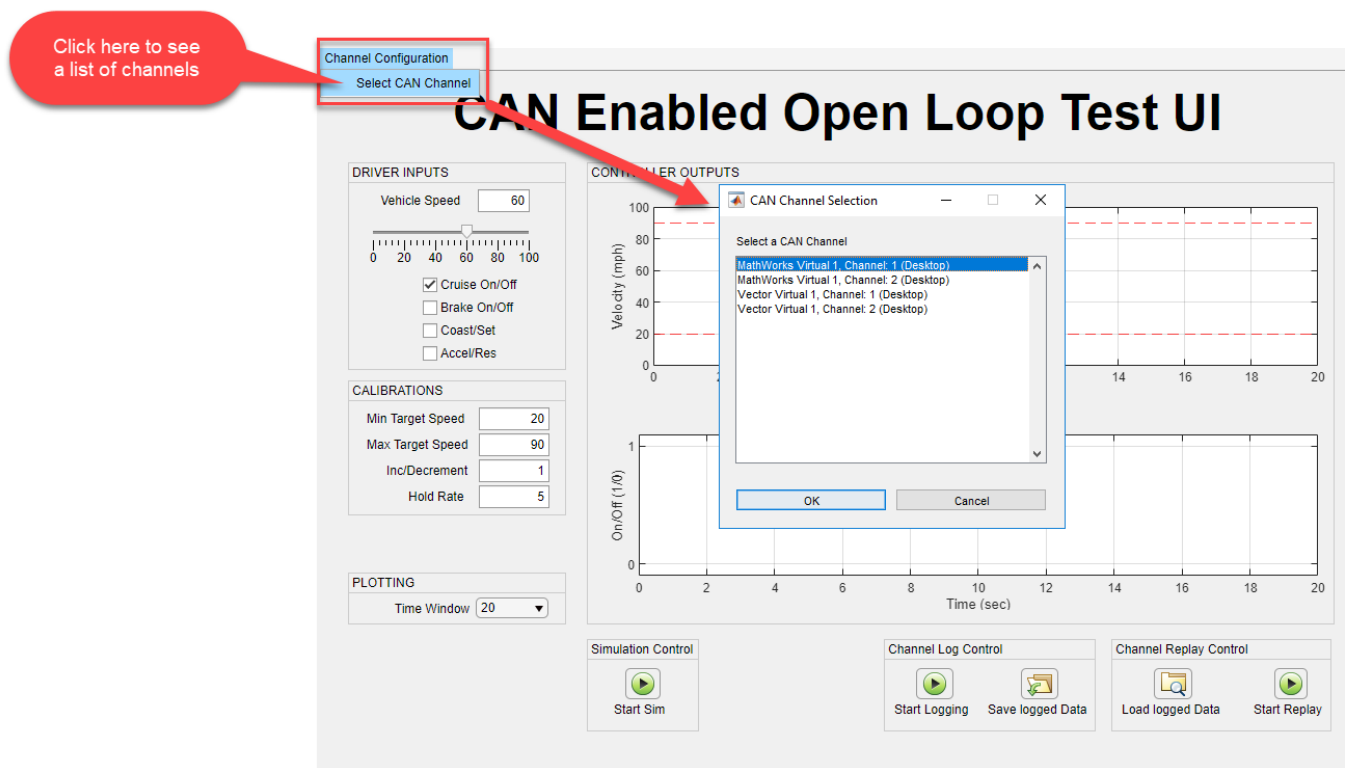
- Getting a list of available CAN channels
- Formatting the channel information for channel creation
- Creating the channel in the UI
- Configure the UI to transmit and receive CAN messages
- Starting and stopping the channel
- Extracting selected messages

Open App Designer

Open the test application UI in App Designer. With the test application UI open in App Designer you can alternate between the "Design" and "Code" views to follow along as you explore the controls and corresponding MATLAB code to communicate with the Simulink Cruise Control algorithm model via virtual CAN channels. Use the following command to open the example UI: `appdesigner('CruiseControlTestUI.mlapp')`.

List Available CAN Channels

First, implement a mechanism to find and present a list of the available CAN channels for a user to select. For this, we added a "Channel Configuration" menu item at the top left corner of the test application UI. It has a "Select CAN Channel" sub-menu.



When the user clicks on the "Select CAN Channel" sub-menu, the helper function `getAvailableCANChannelInfo(app)` is called via the sub-menu callback. `getAvailableCANChannelInfo()` uses the Vehicle Network Toolbox function `canChannelList` to detect the available CAN channels, as shown in the code fragment below:

```
function getAvailableCANChannelInfo(app)
    % Get a table containing all available CAN channels and devices.
    app.canChannelInfo = canChannelList;

    % Format CAN channel information for display on the UI.
    app.availableCANChannelsForDisplay = formatCANChannelEntryForDisplay(app);

    % Save the number of available constructors.
    app.numConstructors = numel(app.canChannelInfo.Vendor);
end
```

Run `canChannelList` to see how the available CAN channel information is stored.

```
canChannels = canChannelList
```

```
canChannels=12x6 table
```

Vendor	Device	Channel	DeviceModel	ProtocolMode	SerialNumber
"MathWorks"	"Virtual 1"	1	"Virtual"	"CAN, CAN FD"	"0"
"MathWorks"	"Virtual 1"	2	"Virtual"	"CAN, CAN FD"	"0"
"Vector"	"VN1610 1"	1	"VN1610"	"CAN, CAN FD"	"46457"
"Vector"	"VN1610 1"	2	"VN1610"	"CAN, CAN FD"	"46457"
"Vector"	"VN1610 3"	1	"VN1610"	"CAN, CAN FD"	"46456"
"Vector"	"VN1610 3"	2	"VN1610"	"CAN, CAN FD"	"46456"
"Vector"	"VN1610 2"	1	"VN1610"	"CAN, CAN FD"	"48599"
"Vector"	"VN1610 2"	2	"VN1610"	"CAN, CAN FD"	"48599"
"Vector"	"Virtual 1"	1	"Virtual"	"CAN, CAN FD"	"0"
"Vector"	"Virtual 1"	2	"Virtual"	"CAN, CAN FD"	"0"
"Kvaser"	"Virtual 1"	1	"Virtual"	"CAN, CAN FD"	"0"
"Kvaser"	"Virtual 1"	2	"Virtual"	"CAN, CAN FD"	"0"

The list of channels returned from `canChannelList` is stored in the UI property `app.canChannelInfo` and then displayed to the user in a "CAN Channel Selection" listdlg as shown in the screen shot above.

Format Channel List for Channel Configuration

The user selects a CAN channel from the "CAN Channel Selection" listdlg. The listdlg returns an index corresponding to the user's selection. This index is passed to the helper function `formatCANChannelConstructor`.

```
function canChannelConstructor = formatCANChannelConstructor(app, index)
    canChannelConstructor = "canChannel(" + "" + app.canChannelInfo.Vendor(index) + "" + ", " + "
end
```

As shown in the code fragment above, `formatCANChannelConstructor` uses the strings stored in the table of CAN channels, `app.canChannelInfo`, to assemble the channel object constructor string corresponding to the channel the user selected from the channel selector list dialog box. To see an example of a CAN channel constructor string, execute the code shown below.

```
index = 1;
canChannelConstructor = "canChannel(" + "" + canChannels.Vendor(index) + "" + ", " + "" + canChannels.Device(index) + "" + ", " + "" + canChannels.Channel(index) + "" + ", " + "" + canChannels.DeviceModel(index) + "" + ", " + "" + canChannels.ProtocolMode(index) + "" + ", " + "" + canChannels.SerialNumber(index) + "" + ")"

canChannelConstructor =
"canChannel('MathWorks', 'Virtual 1', 1)"
```

The CAN channel constructor string is stored in the app UI property `app.canChannelConstructorSelected` and will be used later to create the selected CAN channel object in the application UI as well as to update the Vehicle Network Toolbox Simulink blocks that implement the CAN channel interface in the Simulink Cruise Control algorithm model.

Create the CAN Channel in the UI

When the UI is first opened and initialized, the formatted CAN channel constructor string stored in `app.canChannelConstructorSelected` is used by the helper function `setupCANChannel` to create an instance of a CAN channel object, connect a network configuration database (.DBC) file, and set the

bus speed as shown in the code fragment below. The resulting channel object is stored in the UI property `app.canChannelObj`.

```
function setupCANChannel(app)
    % Open CAN database file.
    db = canDatabase('CruiseControl.dbc');

    % Create a CAN channel for sending and receiving messages.
    app.canChannelObj = eval(app.canChannelConstructorSelected);

    % Attach CAN database to channel for received message decoding.
    app.canChannelObj.Database = db;

    % Set the baud rate (can only do this if the UI has channel initialization access).
    if app.canChannelObj.InitializationAccess
        configBusSpeed(app.canChannelObj, 500000);
    end
end
```

To see an example CAN database object, execute the following:

```
db = canDatabase('CruiseControl.dbc')
```

```
db =
```

```
Database with properties:
```

```
    Name: 'CruiseControl'
    Path: '\\fs-01-mi\shome$\rollinb\Documents\MATLAB\Examples\vnt-ex00964061\CruiseCon
    Nodes: {2x1 cell}
    NodeInfo: [2x1 struct]
    Messages: {2x1 cell}
    MessageInfo: [2x1 struct]
    Attributes: {'BusType'}
    AttributeInfo: [1x1 struct]
    UserData: []
```

To see an example CAN channel object, execute the following:

```
% Instantiate the CAN channel object using the channel constructor string.
canChannelObj = eval(canChannelConstructor);
```

```
% Attach the CAN database to the channel object.
```

```
canChannelObj.Database = db
```

```
canChannelObj =
```

```
Channel with properties:
```

```
Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 1
    DeviceSerialNumber: 0
    ProtocolMode: 'CAN'
```

```
Status Information
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 0
```

```

MessagesTransmitted: 0
InitializationAccess: 1
  InitialTimestamp: [0x0 datetime]
  FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

Channel Information
  BusStatus: 'N/A'
  SilentMode: 0
  TransceiverName: 'N/A'
  TransceiverState: 'N/A'
  ReceiveErrorCount: 0
  TransmitErrorCount: 0
  BusSpeed: 500000
  SJW: []
  TSEG1: []
  TSEG2: []
  NumOfSamples: []

Other Information
  Database: [1x1 can.Database]
  UserData: []

```

`setupCANChannel` uses the following Vehicle Network Toolbox functions:

- `canChannel` to instantiate the channel object using the `eval` command and the CAN channel constructor string stored in the app UI property `app.canChannelConstructorSelected`. The resultant channel object is stored in the app UI property `app.canChannelObj`.
- `canDatabase` to create a CAN database (.DBC) object representing the .DBC file. This object is stored in the "Database" property of the channel object.

Setup to Transmit CAN Messages

After setting up the selected CAN channel object and storing it in the UI property `app.canChannelObj`, the next step is to call the helper function `setupCANTransmitMessages`, shown in the code fragment below. `setupCANTransmitMessages` defines the CAN message to transmit from the UI, populates the message payload with signals, assigns each signal a value, and queues the message to transmit periodically once the CAN channel is started.

```

function setupCANTransmitMessages(app)
    % Create a CAN message container.
    app.cruiseControlCmdMessage = canMessage(app.canChannelObj.Database, 'CruiseCtrlCmd');

    % Fill the message container with signals and assign values to each signal.
    app.cruiseControlCmdMessage.Signals.S01_CruiseOnOff = logical2Numeric(app, app.cruisePowerCh
    app.cruiseControlCmdMessage.Signals.S02_Brake = logical2Numeric(app, app.brakeOnOffCheckBox
    app.cruiseControlCmdMessage.Signals.S03_VehicleSpeed = app.vehicleSpeedSlider.Value;
    app.cruiseControlCmdMessage.Signals.S04_CoastSetSw = logical2Numeric(app, app.cruiseCoastSe
    app.cruiseControlCmdMessage.Signals.S05_AccelResSw = logical2Numeric(app, app.cruiseAccelRes

    % Set up periodic transmission of this CAN message. Actual transmission starts/stops with C
    transmitPeriodic(app.canChannelObj, app.cruiseControlCmdMessage, 'On', 0.1);
end

```

To see what the CAN message object looks like, execute the following:

```
cruiseControlCmdMessage = canMessage(canChannelObj.Database, 'CruiseCtrlCmd')
```



```

cruiseControlCmdMessage =
  Message with properties:

  Message Identification
    ProtocolMode: 'CAN'
        ID: 256
    Extended: 0
        Name: 'CruiseCtrlCmd'

  Data Details
    Timestamp: 0
        Data: [0 0]
    Signals: [1x1 struct]
    Length: 2

  Protocol Flags
    Error: 0
    Remote: 0

  Other Information
    Database: [1x1 can.Database]
    UserData: []

```

```
cruiseControlCmdMessage.Signals
```

```

ans = struct with fields:
  S03_VehicleSpeed: 0
  S05_AccelResSw: 0
  S04_CoastSetSw: 0
  S02_Brake: 0
  S01_CruiseOnOff: 0

```

`setupCANTransmitMessages` uses the following Vehicle Network Toolbox functions:

- `canMessage` to build a CAN message based defined in the CAN database object.
- `transmitPeriodic` to queue the message stored in the UI property `app.cruiseControlCmdMessage` for periodic transmission on the channel defined by the channel object stored in the UI property `app.canChannelObj`, at the rate specified by the last argument, in this case every 0.1 seconds.

Setup to Receive CAN Messages

The UI needs to receive CAN messages on a periodic basis to update the plots with feedback from the Cruise Control algorithm within the Simulink model. To achieve this, we first create a MATLAB timer object as shown in the code fragment below.

```

% create a timer to receive CAN msgs
app.receiveCANmsgsTimer = timer('Period', 0.5,...
    'ExecutionMode', 'fixedSpacing', ...
    'TimerFcn', @(~,~)receiveCANmsgsTimerCallback(app));

```

The timer object will call the timer callback function `receiveCANmsgsTimerCallback` every 0.5 seconds. `receiveCANmsgsTimerCallback`, shown in the code fragment below, retrieves all the CAN messages from the bus, uses the helper function `getCruiseCtrlFBCANmessage` to extract the CAN messages fed back from the Cruise Control Algorithm model, and updates the UI plots with the extracted CAN message data.

```

% receiveCANmsgsTimerCallback Timer callback function for GUI updating
function receiveCANmsgsTimerCallback(app)
    try
        % Receive available CAN messages.
        msg = receive(app.canChannelObj, Inf, 'OutputFormat', 'timetable');

        % Update Cruise Control Feedback CAN message data.
        newFbData = getCruiseCtrlFBCANmessage(app, msg);

        if ~newFbData
            return;
        end

        % Update target speed and engaged plots with latest data from CAN bus.
        updatePlots(app);
    catch err
        disp(err.message)
    end
end

```

To see what the messages returned from the receive command look like, run the following code:

```

% Queue periodic transmission of a CAN message to generate some message data once the channel
% starts.
transmitPeriodic(canChannelObj, cruiseControlCmdMessage, 'On', 0.1);

% Start the channel.
start(canChannelObj);

% Wait 1 second to allow time for some messages to be generated on the bus.
pause(1);

% Retrieve all messages from the bus and output the results as a timetable.
msg = receive(canChannelObj, Inf, 'OutputFormat', 'timetable')

```

msg=31x8 timetable

Time	ID	Extended	Name	Data	Length	Signals
0.0066113 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.059438 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.16047 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.26045 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.36045 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.46046 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.56046 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.66046 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.75945 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.86044 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.95945 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
1.0594 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
1.1594 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
1.2594 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
1.3595 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
1.4605 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
⋮						

```
% Stop the channel.
stop(canChannelObj)
```

receiveCANmsgsTimerCallback uses the following Vehicle Network Toolbox functions:

- receive to retrieve CAN messages from the CAN bus. In this case, the function is configured to retrieve all messages since the previous invocation and output the results as a MATLAB timetable.

Extracting Select CAN Messages

The helper function `getCruiseCtrlFBCANmessage` filters out the "CruiseCtrlFB" messages from all the retrieved CAN messages, extracts the *tspeedFb* and *engagedFb* signals from these messages, and concatenates these to MATLAB timeseries objects for the *tspeedFb* and *engagedFb* signals. These timeseries objects are stored in the UI properties *app.tspeedFb* and *app.engagedFb*, respectively. The stored timeseries signals are used to update the plots for each signal on the UI. Note the use of the `seconds` method to convert the time data stored in the timetable from a duration array into the equivalent numeric array in units of seconds in the timeseries objects for each signal.

```
function newFbData = getCruiseCtrlFBCANmessage(app, msg)
    % Exit if no messages were received as there is nothing to update.
    if isempty(msg)
        newFbData = false;
        return;
    end

    % Extract signals from all CruiseCtrlFB messages.
    cruiseCtrlFBsignals = canSignalTimetable(msg, "CruiseCtrlFB");

    % if no messages then just return as there is nothing to do
    if isempty(cruiseCtrlFBsignals)
        newFbData = false;
        return;
    end

    if ~isempty(cruiseCtrlFBsignals)
        % Received new Cruise Control Feedback messages, so create time series from CAN signal data.
        % save the Target Speed feedback signal.
        if isempty(app.tspeedFb) % Check if target speed feedback property has been initialized.
            app.tspeedFb = cell(2,1);

            % It appears Simulink.SimulationData.Dataset class is not
            % compatible with MATLAB Compiler, so change the way we store data
            % from a Dataset format to cell array.

            % Save target speed actual data.
            app.tspeedFb = timeseries(cruiseCtrlFBsignals.F02_TargetSpeed, seconds(cruiseCtrlFBsignals.Time),
                'Name', 'CruiseControlTargetSpeed');
        else % Add to existing data.
            % Save target speed actual data.
            app.tspeedFb = timeseries([app.tspeedFb.Data; cruiseCtrlFBsignals.F02_TargetSpeed],
                [app.tspeedFb.Time; seconds(cruiseCtrlFBsignals.Time)], 'Name', 'CruiseControlTargetSpeed');
        end

        % Save the Cruise Control Engaged actual signal.
        % Check if Cruise engaged property has been initialized.
        if isempty(app.engagedFb)
            app.engagedFb = cell(2,1);
        end
    end
end
```

```

        % It appears Simulink.SimulationData.Dataset class is not
        % compatible with MATLAB Compiler, so change the way we store data
        % from a Dataset format to cell array.

        % Save cruise engaged command data.
        app.engagedFb = timeseries(cruiseCtrlFBSignals.F01_Engaged,seconds(cruiseCtrlFBSigna
            'Name','CruiseControlEngaged');
    else % Add to existing logouts.
        % Save cruise engaged command data.
        app.engagedFb = timeseries([app.engagedFb.Data; cruiseCtrlFBSignals.F01_Engaged], ..
            [app.engagedFb.Time; seconds(cruiseCtrlFBSignals.Time)], 'Name', 'CruiseControlEng
    end

    newFbData = true;
end
end

```

The helper function `getCruiseCtrlFBCANmessage` uses the following Vehicle Network Toolbox functions:

- `canSignalTimetable` to return a MATLAB timetable containing the signals from the CAN message *CruiseCtrlFB*.

Start the CAN Channel

Once the CAN channel object `app.canChannelObj` has been instantiated and messages have been set up to be transmitted and received, we can now start the channel. When the user clicks the start sim button on the UI, we want the channel to start just before we start running the Simulink model. To achieve this, the helper function `startSimApplication` is called. `startSimApplication`, shown in the code fragment below, checks to make sure we are using a virtual CAN channel, because this is the only type that makes sense if you are using only desktop simulation. Next, it checks to make sure the Simulink model we want to connect to is loaded in memory using the `bdIsLoaded` command. If the model is loaded and is not already running, the UI plots are cleared to accept new signal data, the CAN channel is started using the helper function `startCANChannel`, and the model is started.

```

function startSimApplication(app, index)
    % Start the model running on the desktop.

    % Check to see if hardware or virtual CAN channel is selected, otherwise do nothing.
    if app.canChannelInfo.DeviceModel(index) == "Virtual"
        % Check to see if the model is loaded before trying to run.
        if bdIsLoaded(app.mdl)
            % Model is loaded, now check to see if it is already running.
            if ~strcmp('running',get_param(app.mdl,'SimulationStatus'))
                % Model is not already running, so start it
                % flush the CAN Receive message buffers.
                app.tspeedFb = [];
                app.engagedFb = [];

                % Clear figure window.
                cla(app.tspeedPlot)
                cla(app.engagedPlot)

                % Start the CAN channels and update timer if it isn't already running.
                startCANChannel(app);
            end
        end
    end
end

```

```

        % Start the model.
        set_param(app.mdl, 'SimulationCommand', 'start');

        % Set the sim start/stop button icon to the stop icon indicating the model has
        % been successfully started and is ready to be stopped at the next button press.
        app.SimStartStopButton.Icon = "IconEnd.png";
        app.StartSimLabel.Text = "Stop Sim";
    else
        % Model is already running, inform the user.
        warnStr = sprintf('Warning: Model %s is already running', app.mdl);
        warndlg(warnStr, 'Warning');
    end
else
    % Model is not yet loaded, so warn the user.
    warnStr = sprintf('Warning: Model %s is not loaded\nPlease load the model and try again');
    warndlg(warnStr, 'Warning');
end
end
end
end

```

The helper function `startCANChannel` is shown in the code fragment below. This function checks to make sure the channel is not already running before it starts it. Next, it starts the MATLAB timer object so that the timer callback function `receiveCANmsgsTimerCallback`, described in the previous section, is called every 0.5 seconds to retrieve CAN message data from the bus.

```

function startCANChannel(app)
    % Start the CAN channel if it isn't already running.
    try
        if ~app.canChannelObj.Running
            start(app.canChannelObj);
        end
    catch
        % do nothing.
    end

    % Start the CAN receive processing timer - check to see if it is already running. This allows
    % with or without starting and stopping the model running on the real time target.
    if strcmpi(app.receiveCANmsgsTimer.Running, 'off')
        start(app.receiveCANmsgsTimer);
    end
end

```

`startCANChannel` uses the following Vehicle Network Toolbox function:

- `start` to start the CAN channel running. The channel will remain on-line until a `stop` command is issued.

Stop the CAN Channel

When the user clicks the stop sim button on the UI, we want to stop the Simulink model just before stopping the CAN channel. To achieve this, the helper function `stopSimApplication` is called. `stopSimApplication`, shown in the code fragment below, checks to make sure we are using a virtual CAN channel, because this is the only type that makes sense if you are using only desktop simulation. Next, it stops the Simulink model and calls the helper function `stopCANChannel` to stop the CAN channel.

```

function stopSimApplication(app, index)
    % Stop the model running on the desktop.

```

```

try
    % Check to see if hardware or virtual CAN channel is selected.
    if app.canChannelInfo.DeviceModel(index) == "Virtual"
        % Virtual channel selected, so issue a stop command to the
        % the simulation, even if it is already stopped.
        set_param(app.mdl, 'SimulationCommand', 'stop')

        % Stop the CAN channels and update timer.
        stopCANChannel(app);
    end

    % Set the sim start/stop button text to Start indicating the model has
    % been successfully stopped and is ready to start again at the next
    % button press.
    app.SimStartStopButton.Icon = "IconPlay.png";
    app.StartSimLabel.Text = "Start Sim";
catch
    % Do nothing at the moment.
end
end
end

```

The helper function `stopCANChannel` is shown in the code fragment below. This function stops the CAN channel, then stops the MATLAB timer object so that the timer callback function `receiveCANmsgsTimerCallback`, described previously, is no longer called to retrieve messages from the bus.

```

function stopCANChannel(app)
    % Stop the CAN channel.
    stop(app.canChannelObj);

    % Stop the CAN message processing timer.
    stop(app.receiveCANmsgsTimer);
end

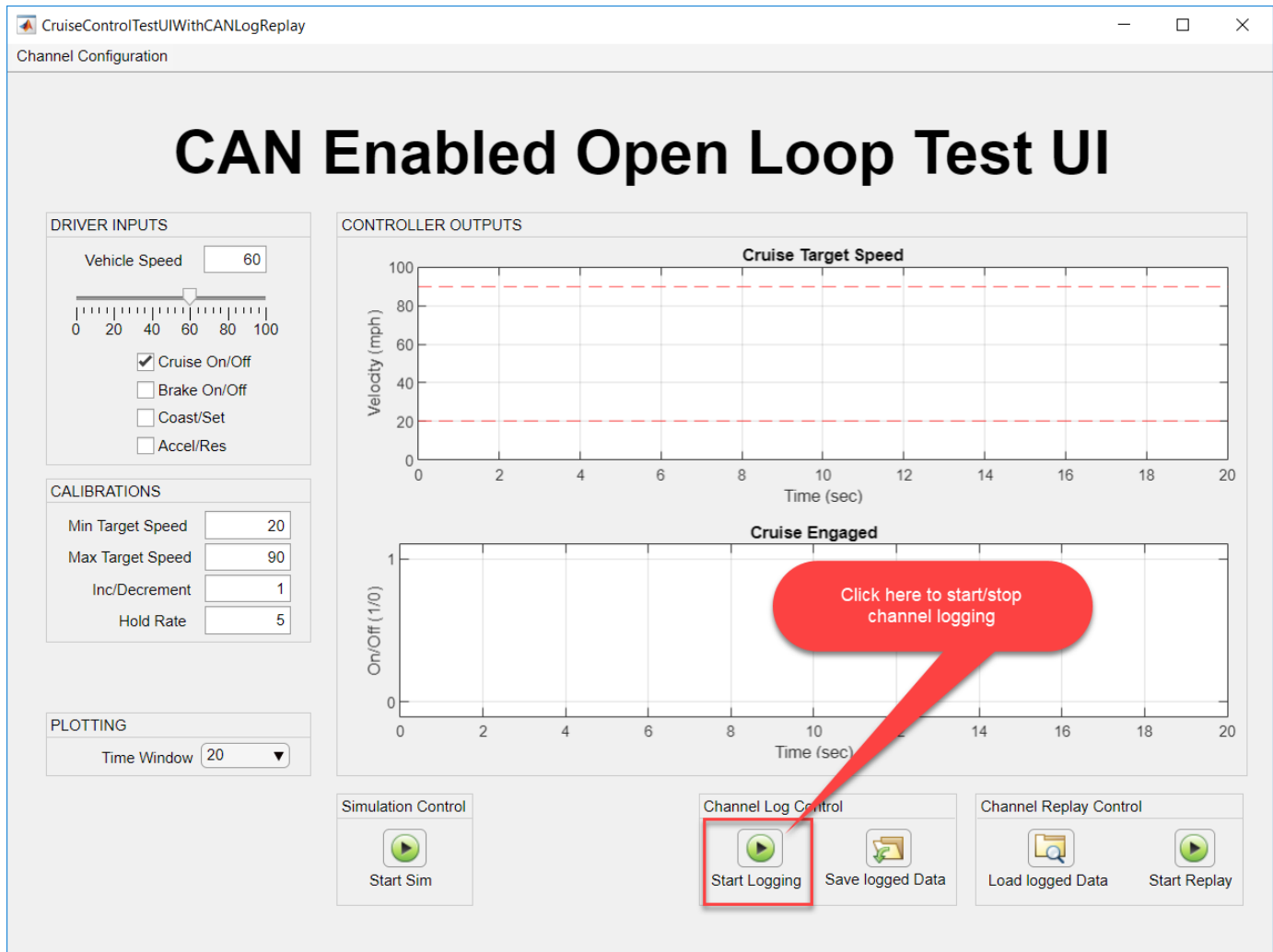
```

`stopCANchannel` uses the following Vehicle Network Toolbox function:

- `stop` to stop the CAN channel. The channel will remain offline until another *start* command is issued.

Adding CAN Log and Replay Capability

In this step, we will describe the key Vehicle Network Toolbox functions used to add the ability to log, save, and replay CAN messages. To implement this functionality, we instantiate a second CAN channel, identical to the first one created. Because the second CAN channel object is identical to the first one, it will see and collect the same messages as the first CAN channel object. The second CAN channel will be started when the user clicks the start logging button on the UI as shown in the UI screen shot below. The channel continues to run and collect messages until the user clicks the stop logging button on the UI. Once the user stops logging CAN messages, we will retrieve all the messages that have accumulated in the message buffer for the second CAN channel object, extract the messages we are interested in replaying, and save them to a .MAT file. Once the messages have been saved, we can replay them using the first CAN channel to provide an input stimulus to the Simulink Cruise Control algorithm model for debugging and algorithm verification purposes.



This description will cover the following topics:

- Setup a channel to log CAN messages
- Starting and Stopping the channel
- Retrieving and extracting logged CAN messages
- Saving the extracted messages to a file
- Loading saved messages from a file
- Start playback of logged CAN messages
- Stop playback of logged CAN messages

Setup a CAN Channel Object in the UI to Log CAN messages

In a manner directly analogous to how the first CAN channel was instantiated, the formatted CAN channel constructor string stored in `app.canChannelConstructorSelected` is used by a new helper function `setupCANLogChannel` to create a second instance of a CAN channel object, connect the same network configuration database (.DBC) file as was used for the first channel, and set the bus speed as shown in the code fragment below. The resulting channel object is stored in the UI property `app.canLogChannelObj`.

```

function setupCANLogChannel(app)
    % Open CAN database file.
    db = canDatabase('CruiseControl.dbc');

    % Create a CAN channel for sending and receiving messages.
    app.canLogChannelObj = eval(app.canChannelConstructorSelected);

    % Attach CAN database to channel for received message decoding.
    app.canLogChannelObj.Database = db;

    % Set the baud rate (can only do this if the UI has channel initialization access).
    if app.canLogChannelObj.InitializationAccess
        configBusSpeed(app.canLogChannelObj, 500000);
    end
end

```

To see an example CAN database object, execute the following code:

```
db = canDatabase('CruiseControl.dbc')
```

```
db =
```

```
Database with properties:
```

```

    Name: 'CruiseControl'
    Path: '\\fs-01-mi\shome$\rollin\Documents\MATLAB\Examples\vnt-ex00964061\CruiseControl.dbc'
    Nodes: {2x1 cell}
    NodeInfo: [2x1 struct]
    Messages: {2x1 cell}
    MessageInfo: [2x1 struct]
    Attributes: {'BusType'}
    AttributeInfo: [1x1 struct]
    UserData: []

```

To see an example CAN channel object, execute the following code:

```
% Instantiate the CAN channel object using the channel constructor string.
canLogChannelObj = eval(canChannelConstructor);
```

```
% Attach the CAN database to the channel object.
canLogChannelObj.Database = db
```

```
canLogChannelObj =
```

```
Channel with properties:
```

```

Device Information
    DeviceVendor: 'MathWorks'
    Device: 'Virtual 1'
    DeviceChannelIndex: 1
    DeviceSerialNumber: 0
    ProtocolMode: 'CAN'

```

```

Status Information
    Running: 0
    MessagesAvailable: 0
    MessagesReceived: 0
    MessagesTransmitted: 0
    InitializationAccess: 0
    InitialTimestamp: [0x0 datetime]

```



```

FilterHistory: 'Standard ID Filter: Allow All | Extended ID Filter: Allow All'

Channel Information
    BusStatus: 'N/A'
    SilentMode: 0
    TransceiverName: 'N/A'
    TransceiverState: 'N/A'
    ReceiveErrorCount: 0
    TransmitErrorCount: 0
    BusSpeed: 500000
    SJW: []
    TSEG1: []
    TSEG2: []
    NumOfSamples: []

Other Information
    Database: [1x1 can.Database]
    UserData: []

```

`setupCANLogChannel` uses the following Vehicle Network Toolbox functions:

- `canChannel` to instantiate the channel object using the `eval` command and the CAN channel constructor string stored in the app UI property `app.canChannelConstructorSelected`. The resultant channel object is stored in the app UI property `app.canLogChannelObj`.
- `canDatabase` to create a CAN database (.DBC) object representing the .DBC file. This object is stored in the "Database" property of the channel object.

Starting the CAN Log Channel

As with the first CAN channel, the CAN channel object `app.canLogChannelObj`, was instantiated when the test application UI is opened. When the user clicks the start Logging button on the UI as shown on the screen shot above, we call the helper function `startCANLogChannel`, shown in the code fragment below. This function checks to see if the second CAN channel is already running and starts it if isn't.

```

function startCANLogChannel(app)
    % Start the CAN Log channel if it isn't already running.
    try
        if ~app.canLogChannelObj.Running
            start(app.canLogChannelObj);
        end
    catch
        % Do nothing.
    end
end

```

`startCANLogChannel` uses the following Vehicle Network Toolbox function:

- `start` to start the CAN channel running. The channel will remain online until a `stop` command is issued.

Stopping the CAN Log Channel

When the user clicks the "Stop logging" button on the UI, the button callback calls the helper function `stopCANLogging`, shown in the code fragment below. `stopCANLogging` stops the CAN

channel and retrieves all the messages accumulated in the second channel buffer since the second CAN channel was started by the user clicking the "Start Logging" button.

```
function stopCANLogging(app)
    % Stop the CAN Log channel.
    stop(app.canLogChannelObj);

    % Get the messages from the CAN log message queue.
    retrieveLoggedCANMessages(app);

    % Update the button icon and label.
    app.canLoggingStartStopButton.Icon = 'IconPlay.png';
    app.StartLoggingLabel.Text = "Start Logging";
end
```

stopCANLogging uses the following Vehicle Network Toolbox function:

- stop to stop the CAN channel. The channel will remain offline until another *start* command is issued.

Retrieving and Extracting Logged Messages

Once the logging CAN channel has been stopped, the helper function `retrieveLoggedCANMessages`, shown in the code fragment below, is called to retrieve all the CAN messages from the second channel bus. The CAN messages are acquired from the second channel bus using the `receive` command and logical indexing is used to extract the "CruiseCtrlCmd" messages from all the message timetable returned by the `receive` command.

```
function retrieveLoggedCANMessages(app)
    try
        % Receive available CAN message
        % initialize buffer to make sure it is empty.
        app.canLogMsgBuffer = [];

        % Receive available CAN messages.
        msg = receive(app.canLogChannelObj, Inf, 'OutputFormat', 'timetable');

        % Fill the buffer with the logged Cruise Control Command CAN message data.
        app.canLogMsgBuffer = msg(msg.Name == "CruiseCtrlCmd", :);
    catch err
        disp(err.message)
    end
end
```

To see what the messages returned from the `receive` command look like in the timetable format, run the following code:

```
% Queue periodic transmission of CAN messages to generate sample message data once the channel s
cruiseControlFbMessage = canMessage(db, 'CruiseCtrlFB');
transmitPeriodic(canChannelObj, cruiseControlFbMessage, 'On', 0.1);
transmitPeriodic(canChannelObj, cruiseControlCmdMessage, 'On', 0.1);

% Start the first channel.
start(canChannelObj);

% Start the second (logging) channel.
start(canLogChannelObj);
```

```
% Wait 1 second to allow time for some messages to be generated on the bus.
pause(1);

% Stop the channels.
stop(canChannelObj)
stop(canLogChannelObj)

% Retrieve all messages from the logged message bus and output the results as a timetable.
msg = receive(canLogChannelObj, Inf, 'OutputFormat','timetable')
```

msg=20x8 timetable

Time	ID	Extended	Name	Data	Length	Signals
0.077716 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.07772 sec	512	false	'CruiseCtrlFB'	{1x2 uint8}	2	{1x1 struct}
0.1777 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.17771 sec	512	false	'CruiseCtrlFB'	{1x2 uint8}	2	{1x1 struct}
0.27673 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.27674 sec	512	false	'CruiseCtrlFB'	{1x2 uint8}	2	{1x1 struct}
0.37673 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.37674 sec	512	false	'CruiseCtrlFB'	{1x2 uint8}	2	{1x1 struct}
0.47773 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.47773 sec	512	false	'CruiseCtrlFB'	{1x2 uint8}	2	{1x1 struct}
0.57674 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.57674 sec	512	false	'CruiseCtrlFB'	{1x2 uint8}	2	{1x1 struct}
0.67673 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.67673 sec	512	false	'CruiseCtrlFB'	{1x2 uint8}	2	{1x1 struct}
0.77771 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.77771 sec	512	false	'CruiseCtrlFB'	{1x2 uint8}	2	{1x1 struct}
:						

```
% Extract only the Cruise Control Command CAN messages.
msgCmd = msg(msg.Name == "CruiseCtrlCmd", :)
```

msgCmd=10x8 timetable

Time	ID	Extended	Name	Data	Length	Signals
0.077716 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.1777 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.27673 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.37673 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.47773 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.57674 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.67673 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.77771 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.87776 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}
0.97769 sec	256	false	'CruiseCtrlCmd'	{1x2 uint8}	2	{1x1 struct}

retrieveLoggedCANMessages uses the following Vehicle Network Toolbox functions:

- receive to retrieve CAN messages from the CAN bus. In this case, the function is configured to retrieve all messages since the previous invocation and output the results as a MATLAB timetable.

Saving Messages to a File

When the user clicks the "Save Logged Data" button on the UI, the helper function `saveLoggedCANDataToFile` is called. This function opens a file browser window using the `uinputfile` function. `uinputfile` returns the filename and path selected by the user to store the logged CAN message data. The Vehicle Network Toolbox function `canMessageReplayBlockStruct` is used to convert the CAN messages from a MATLAB timetable into a form that the CAN Replay block can use. Once the logged CAN message data has been converted and saved to a file it can be recalled and replayed later using the Vehicle Network Toolbox "Replay" Simulink block. To replay messages in MATLAB with Vehicle Network Toolbox with the `replay` command, the timetable itself is passed as input to the function.

```
function saveLoggedCANDataToFile(app)
    % Raise dialog box to prompt user for a CAN log file to store the logged data.
    [FileName,PathName] = uinputfile('*.mat','Select a .MAT file to store logged CAN data');

    if FileName ~= 0
        % User did not cancel the file selection operation, so OK to save
        % convert the CAN log data from Timetable to struct of arrays so the data is compatible
        % with the VNT Simulink Replay block.
        canLogStructOfArrays = canMessageReplayBlockStruct(app.canLogMsgBuffer);
        save(fullfile(PathName, FileName), 'canLogStructOfArrays');

        % Clear the buffer after saving it.
        app.canLogMsgBuffer = [];
    end
end
```

`saveLoggedCANDataToFile` uses the following Vehicle Network Toolbox function:

- `canMessageReplayBlockStruct` to convert the CAN messages stored in the MATLAB timetable into a form that can be used by the CAN Message Replay Block.

Loading Messages From a File

When the user clicks the "Load Logged Data" button on the UI the helper function `loadLoggedCANDataFromFile` is called. This function opens a file browser window using the `uigetfile` function, which returns the logged message filename selected by the user. The logged CAN message data is loaded from the file and converted back into a timetable representation for use with the Vehicle Network Toolbox `replay` command. Note that the same data file could be used directly with the Vehicle Network Toolbox "Replay" Simulink block if the user desired to replay the data from the Simulink model. You might choose to replay the data using the "Replay" block instead of from the UI using the `replay` command because the "Replay" block works with the Simulink debugger, pausing playback when the simulation halts on a breakpoint. The `replay` command, in contrast, does not recognize when the Simulink model halts on a breakpoint and would simply keep playing the stored message data from the file. For the purposes of the example, we will replay the data using the `replay` command.

```
function loadLoggedCANDataFromFile(app)
    % Raise dialog box to prompt user for a CAN log file to load.
    [FileName,PathName] = uigetfile('*.mat','Select a CAN log file to load');

    % Return focus to main UI after dlg closes.
    figure(app.UIFigure)

    if FileName ~= 0
```

```

% User did not cancel the file selection operation, so OK to load
% make sure the message buffer is empty before loading in the logged CAN data.
app.canLogMsgBuffer = [];

% Upload the saved message data from the selected file.
canLogMsgStructOfArrays = load(fullfile(PathName, FileName), 'canLogStructOfArrays');

% Convert the saved message data into timetables for the replay command.
app.canLogMsgBuffer = canMessageTimetable(canLogMsgStructOfArrays.canLogStructOfArrays);
end
end

```

`loadLoggedCANDataFromFile` uses the following Vehicle Network Toolbox function:

- `canMessageTimetable` to convert the CAN messages stored in a form compatible with the CAN message "Replay" Simulink block back into a MATLAB timetable for use with the `replay` function.

Start Playback of Logged Messages

After the logged CAN message data has been loaded into the UI and reformatted it is ready for playback using the Vehicle Network Toolbox `replay` command. When the user clicks "Start Replay" button on the UI the helper function `startPlaybackOfLoggedCANData` is called. In order to replay the logged CAN message data over the first CAN channel, all activity associated with this channel must be halted and any buffered message data cleared. As shown in the code fragment below, `startPlaybackOfLoggedCANData` turns off periodic transmission of CAN messages, stops the CAN channel, clears any CAN message data buffered in the UI, and clears the plots displaying the signal data fed back from the Cruise Control algorithm model. The CAN channel is then restarted, and the logged CAN message data is replayed.

```

function startPlaybackOfLoggedCANData(app)
% Turn off periodic transmission of CruiseCtrlCmd CAN message from UI controls.
transmitPeriodic(app.canChannelObj, app.cruiseControlCmdMessage, 'Off');

% Stop the UI CAN channel so we can instead use it for playback.
stopCANChannel(app)

% Flush the existing CAN messages stored for plotting.
flushCANFbMsgQueue(app)

% Clear the existing plots.
cla(app.tspeedPlot)
cla(app.engagedPlot)

% Start the CAN Channel and replay the logged CAN message data.
startCANChannel(app)

% Replay the logged CAN data on the UI CAN Channel.
replay(app.canChannelObj, app.canLogMsgBuffer);
end

```

`startPlaybackOfLoggedCANData` uses the following Vehicle Network Toolbox functions:

- `transmitPeriodic` to disable periodic transmission of the command signals sent to the Cruise Control algorithm model in the "CruiseCtrlCmd" message.
- `replay` to replay logged CAN message data on the first CAN channel.

Stop Playback of Logged Messages

When the user presses the "Stop Replay" button on the UI the helper function `stopPlaybackOfLoggedCANData` is called. In order to halt the playback of logged CAN message data the CAN channel where the data is being replayed must be stopped. Once that is done the periodic transmission of the "CruiseCtrlCmd" message can be re-enabled and the channel restarted so that the user will once again be able to inject test stimulus signals to the Cruise Control algorithm model interactively from the UI. As shown in the code fragment below, `stopPlaybackOfLoggedCANData` first stops the channel, which halts the replay of the logged message data. Logged message data is cleared from local buffers on the UI as well as the plots displaying the signal data fed back from the Cruise Control algorithm model. Periodic transmission of the "CruiseCtrlCmd" message is re-enabled, and the CAN channel restarted.

```
function stopPlaybackOfLoggedCANData(app)
    % Stop the playback CAN channel.
    stopCANChannel(app)

    % Flush the existing CAN messages stored for plotting.
    flushCANFbMsgQueue(app)

    % Clear the existing plots.
    cla(app.tspeedPlot)
    cla(app.engagedPlot)

    % Re-enable periodic transmission of CruiseCtrlCmd CAN message from UI controls.
    transmitPeriodic(app.canChannelObj, app.cruiseControlCmdMessage, 'On', 0.1);

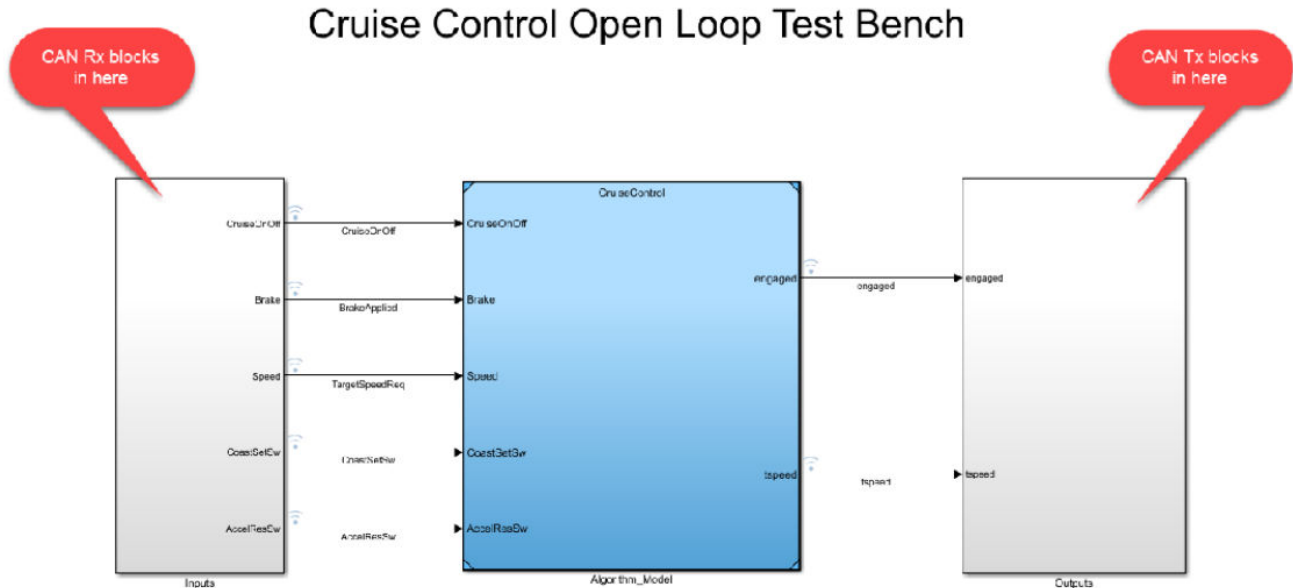
    % Restart the CAN Channel from/To UI.
    startCANChannel(app)
end
```

`stopPlaybackOfLoggedCANData` uses the following Vehicle Network Toolbox functions:

- `stop` to stop the CAN channel to halt replay of the logged CAN message data.
- `transmitPeriodic` to re-enable periodic transmission of the command signals sent to the Cruise Control algorithm model in the "CruiseCtrlCmd" message.
- `start` to re-start the CAN channel so the user can once again inject test stimulus signals to the Cruise Control algorithm model interactively from the UI.

Adding Virtual CAN Channel Communication to the Simulink Cruise Control Algorithm Model

In this step, we describe how Vehicle Network Toolbox Simulink blocks were used to add virtual CAN communication capability to the Simulink Cruise Control algorithm model.



This description will cover the following topics:

- Adding CAN message receive capability
- Adding CAN message transmit capability
- Pushing CAN channel configuration information from the UI to the Simulink model

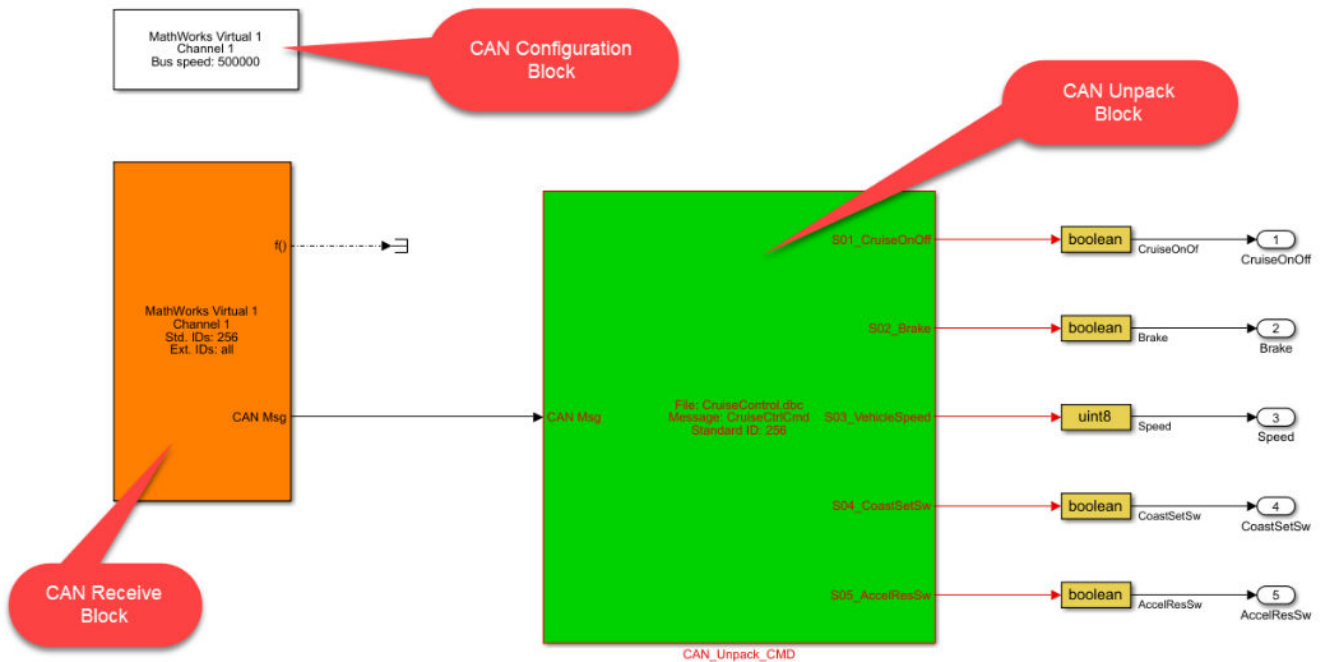
Open the Cruise Control Algorithm Simulink Model

Run the helper functions to configure the workspace with needed data parameters and then open the Cruise Control algorithm test harness model. With the Simulink model open, you can explore the portions of the model explained in the sections below. Execute `helperPrepareTestBenchParameterData` followed by `helperConfigureAndOpenTestBench`.

Adding CAN Message Receive Capability

For the Cruise Control algorithm Simulink model to receive CAN data from the test UI requires a block to connect the Simulink model to a specific CAN device, a block to receive CAN messages from the selected device, and a block to unpack the data payload of the messages received into individual signals. To accomplish this, an "Inputs" subsystem is added to the Cruise Control algorithm Simulink model. The "Inputs" subsystem uses Vehicle Network Toolbox CAN Configuration, CAN Receive, and CAN Unpack blocks interconnected as shown in the screen shot below.

The CAN Configuration Block allows the user to determine which of the available CAN devices and channels to connect with the Simulink model. The CAN Receive block receives CAN messages from the CAN device and channel selected in the CAN Configuration block. It also allows the user to receive all messages on the bus or apply a filter to receive only select message(s). The CAN Unpack block has been configured to read a user defined network database (.DBC) file. This allows the user to determine the message name, message ID, and data payload to unpack signals with this block. Simulink input ports are automatically added to the block for each signal defined in the message in the network database file.



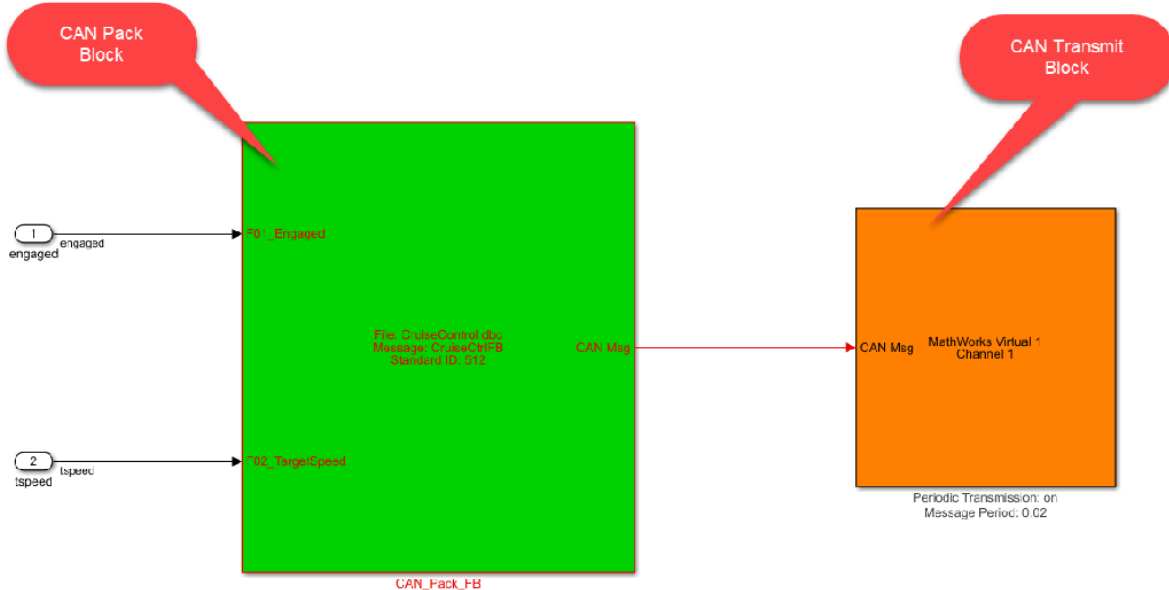
The "Inputs" subsystem of the Cruise Control algorithm Simulink model uses the following Vehicle Network Toolbox Simulink blocks to receive CAN messages:

- CAN Configuration Block to select which CAN channel device to connect to the Simulink model.
- CAN Receive Block to receive the CAN messages from the CAN device selected in the CAN Configuration block.
- CAN Unpack Block to unpack the payload of the received CAN message(s) into individual signals, one for each data item defined in the message.

Adding CAN Message Transmit Capability

For the Cruise Control algorithm Simulink model to transmit CAN data to the test UI requires a block to connect the Simulink model to a specific CAN device, a block to pack Simulink signals into the data payload of one or more CAN messages, and a block to transmit the CAN messages from the selected device. To accomplish this, an "Outputs" subsystem is added to the Cruise Control algorithm Simulink model. The "Outputs" subsystem uses Vehicle Network Toolbox CAN pack and CAN Transmit blocks interconnected as shown in the screen shot below.

The CAN Pack block has been configured to read a user defined network database (.DBC) file. This allows the user to determine the message name, message ID, and data payload to pack signal with this block. Simulink output ports are automatically added to the block for each signal defined in the message in the network database file. The CAN Transmit block will transmit the message assembled by the Pack Block on the CAN channel and CAN device selected by the user with the Configuration block. Note that a second CAN Configuration block is not required since the "Outputs" subsystem is transmitting CAN messages on the same CAN channel and device used to receive CAN messages.



The "Outputs" subsystem of the Cruise Control algorithm Simulink model uses the following Vehicle Network Toolbox Simulink blocks to transmit CAN messages:

- CAN Pack Block to unpack the payload of the received CAN message(s) into individual signals, one for each data item defined in the message.
- CAN Transmit Block to receive the CAN messages from the CAN device selected in the CAN Configuration block.

Pushing CAN Channel Configuration from the UI to the Simulink Model

Because the user selects which of the available CAN devices and channels to use from the UI, this information needs to be sent to the Cruise Control algorithm Simulink model to keep the CAN device and channel configurations between the UI and the Simulink model in sync. In order to accomplish this, the CAN device and channel information used by the Vehicle Network Toolbox "CAN Configuration", "CAN Transmit" and "CAN Receive" blocks need to be configured programmatically from the UI. Every time a user selects a CAN device and CAN channel from the UI "Channel Configuration/Select CAN Channel" menu, the helper function `updateModelWithSelectedCANChannel` is called. As shown in the code fragment below, `updateModelWithSelectedCANChannel` finds the block path for the "CAN Configuration", "CAN Transmit", and "CAN Receive" blocks within the Cruise Control algorithm Simulink model. Using `set_param` commands, the "Device", "DeviceMenu", and "ObjConstructor" block properties for each of these three blocks are set to the corresponding properties from the CAN device and CAN channel selected by the user.

```
function updateModelWithSelectedCANChannel(app, index)
    % Check to see if we are using a virtual CAN channel and whether the model is loaded.
    if app.canChannelInfo.DeviceModel(index) == "Virtual" && bdIsLoaded(app.mdl)
        % Using a virtual channel.

        % Find path to CAN configuration block.
        canConfigPath = find_system(app.mdl, 'Variants', 'AllVariants', 'LookUnderMasks', 'all', 'FollowLinks', 'on', 'Name', 'CAN Configuration');
```

```

% Find path to CAN transmit block.
canTransmitPath = find_system(app.mdl, 'Variants', 'AllVariants', 'LookUnderMasks', 'all',
    'FollowLinks', 'on', 'Name', 'CAN Transmit');

% Find path to CAN receive block.
canReceivePath = find_system(app.mdl, 'Variants', 'AllVariants', 'LookUnderMasks', 'all',
    'FollowLinks', 'on', 'Name', 'CAN Receive');

% Push the selected CAN channel into the simulation model CAN Configuration block.
set_param(canConfigPath{1}, 'Device', app.canChannelDeviceSelected);
set_param(canConfigPath{1}, 'DeviceMenu', app.canChannelDeviceSelected);
set_param(canConfigPath{1}, 'ObjConstructor', app.canChannelConstructorSelected);

% Push the selected CAN channel into the simulation model CAN Receive block.
set_param(canReceivePath{1}, 'Device', app.canChannelDeviceSelected);
set_param(canReceivePath{1}, 'DeviceMenu', app.canChannelDeviceSelected);
set_param(canReceivePath{1}, 'ObjConstructor', app.canChannelConstructorSelected);

% Push the selected CAN channel into the simulation model CAN Transmit block.
set_param(canTransmitPath{1}, 'Device', app.canChannelDeviceSelected);
set_param(canTransmitPath{1}, 'DeviceMenu', app.canChannelDeviceSelected);
set_param(canTransmitPath{1}, 'ObjConstructor', app.canChannelConstructorSelected);
end
end

```

Using the UI and Model Together

With both the model and UI open, you can explore interacting with the model in the UI. Press "Start Sim" to put the model and UI online. Experiment with the "Driver Inputs" and "Calibrations" sections of the UI to control the model and actuate the cruise control algorithm. You will see the cruise control engagement and speed values plotted in the UI. You can also use the logging and replay features described previously via the UI controls.

Creating a UI in this manner, gives you a powerful and flexible test interface customizable to your application. It is valuable when debugging and optimizing your algorithm in simulation. By changing the selected CAN device from virtual channels to physical channels, you can continue to use the UI to interact with the algorithm running in a rapid prototyping platform or target controller.

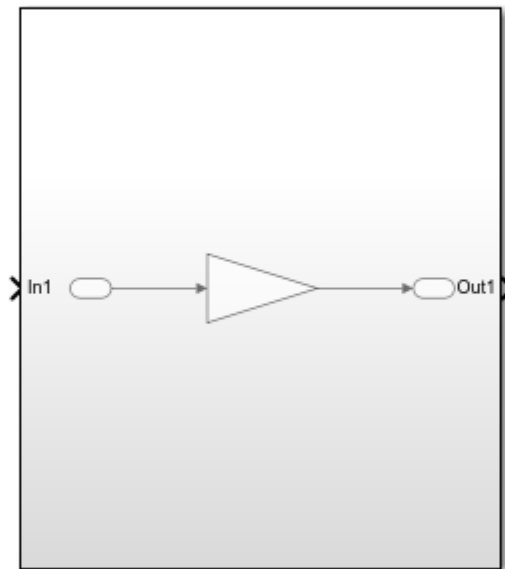
Programmatically Building Models for CAN Communication

This example shows how to programmatically construct a Simulink model to introduce CAN or CAN FD communication using a CAN DBC-file. With the `add_block` and `set_param` functions of Simulink, one can add and fully configure Vehicle Network Toolbox (VNT) blocks to take a basic algorithm and add network communications. The DBC-file contains the CAN messages and signal details. The primary focus is to programmatically configure CAN and CAN FD Pack and Unpack block parameters. This can significantly increase model construction efficiency.

Algorithm Model

The example model (AlgorithmModel.slx) contains a subsystem block called "Algorithm". This block represents any given application algorithm developed in Simulink. A Gain block with value of 2 is inside this subsystem for example purposes. This subsystem has a CAN signal input named "In1". This input value is scaled by the gain value. The scaled value is given as the output of this subsystem named "Out1". The gain value is changeable or the Gain block replaced by a different algorithm by the user for experimentation.

Algorithm Model to be configured for CAN Communication



CAN Database File Access

You can access the contents of CAN DBC-files with the `canDatabase` function. Through this function, details about network nodes, messages, and signals are available.

```
db = canDatabase("CANBus.dbc")
```

```
db =
  Database with properties:
```

```
    Name: 'CANBus'
```

```
Path: 'C:\Users\jpyle\Documents\MATLAB\Examples\vnt-ex60686316\CANBus.dbc'  
Nodes: {'ECU'}  
NodeInfo: [1x1 struct]  
Messages: {2x1 cell}  
MessageInfo: [2x1 struct]  
Attributes: {}  
AttributeInfo: [0x0 struct]  
UserData: []
```

A node "ECU" is defined in the example CAN DBC-file as shown below.

```
node = nodeInfo(db, "ECU")  
  
node = struct with fields:  
    Name: 'ECU'  
    Comment: ''  
    Attributes: {}  
    AttributeInfo: [0x0 struct]
```

The node receives a CAN message "AlgInput" containing a signal "InitialValue". The signal "InitialValue" is the input to the algorithm.

```
messageInfo(db, "AlgInput")  
  
ans = struct with fields:  
    Name: 'AlgInput'  
    ProtocolMode: 'CAN'  
    Comment: ''  
    ID: 100  
    Extended: 0  
    J1939: []  
    Length: 1  
    DLC: 1  
    BRS: 0  
    Signals: {'InitialValue'}  
    SignalInfo: [1x1 struct]  
    TxNodes: {0x1 cell}  
    Attributes: {}  
    AttributeInfo: [0x0 struct]
```

The node transmits a CAN message "AlgOutput" containing a signal "ScaledValue". The signal "ScaledValue" is the output of the algorithm.

```
messageInfo(db, "AlgOutput")  
  
ans = struct with fields:  
    Name: 'AlgOutput'  
    ProtocolMode: 'CAN'  
    Comment: ''  
    ID: 200  
    Extended: 0  
    J1939: []  
    Length: 2  
    DLC: 2  
    BRS: 0  
    Signals: {'ScaledValue'}
```

```

SignalInfo: [1x1 struct]
  TxNodes: {'ECU'}
  Attributes: {}
AttributeInfo: [0x0 struct]
    
```

Programmatically Build the Model

Open the Example Model

Open the example model to be configured.

```
open AlgorithmModel
```

Add and Configure CAN Configuration Block

Add and position a CAN Configuration block in the model.

```
add_block("canlib/CAN Configuration", "AlgorithmModel/CAN Configuration")
set_param("AlgorithmModel/CAN Configuration", "position", [50, 330, 250, 410])
```

Set the "Device" parameter to have the model use the MathWorks virtual CAN device.

```
set_param("AlgorithmModel/CAN Configuration", "Device", "MathWorks Virtual 1 (Channel 1)")
```

Add and Configure CAN Receive Block

Add and position a CAN Receive block in the model.

```
add_block("canlib/CAN Receive", "AlgorithmModel/CAN Receive")
set_param("AlgorithmModel/CAN Receive", "position", [50, 200, 250, 280])
```

Add a Terminator block and position it. This is used to connect the function port of the CAN Receive block. In this example, simple message reception is performed. In general, placing a CAN Receive inside a Function-Call Subsystem is the preferred approach to modeling with CAN blocks.

```
add_block("simulink/Sinks/Terminator", "AlgorithmModel/Terminator")
set_param("AlgorithmModel/Terminator", "position", [310, 210, 330, 230])
```

Set the "Device" parameter to have the model use the MathWorks virtual CAN device.

```
set_param("AlgorithmModel/CAN Receive", "Device", "MathWorks Virtual 1 (Channel 1)")
```

Add and Configure CAN Unpack Block

Add and position a CAN Unpack block in the model. By default, the block is in "Raw Data" mode.

```
add_block("canlib/CAN Unpack", "AlgorithmModel/CAN Unpack")
set_param("AlgorithmModel/CAN Unpack", "position", [350, 220, 600, 300])
```

Set the following parameters in the CAN Unpack block in a single function call:

- DataFormat
- CANdbFile
- MsgList

```
set_param("AlgorithmModel/CAN Unpack", "DataFormat", "CANdb specified signals", "CANdbFile", db.Path
```

If the "DataFormat" and "CANdbFile" parameters are already set on a block, the chosen message is changeable by only including the "MsgList" parameter.

Add and Configure CAN Pack Block

Add and position a CAN Pack block in the model.

```
add_block("canlib/CAN Pack", "AlgorithmModel/CAN Pack")
set_param("AlgorithmModel/CAN Pack", "position", [1000, 220, 1250, 300])
```

Set the following parameters in the CAN Pack block in a single function call:

- DataFormat
- CANdbFile
- MsgList

```
set_param("AlgorithmModel/CAN Pack", "DataFormat", "CANdb specified signals", "CANdbFile", db.Path, "I
```

Add and Configure CAN Transmit Block

Add and position a CAN Transmit block in the model.

```
add_block("canlib/CAN Transmit", "AlgorithmModel/CAN Transmit")
set_param("AlgorithmModel/CAN Transmit", "position", [1350, 220, 1550, 300])
```

Set the "Device" parameter to have the model use the MathWorks virtual CAN device. Also, periodic transmission is enabled with the default timing.

```
set_param("AlgorithmModel/CAN Transmit", "Device", "MathWorks Virtual 1 (Channel 1)")
set_param("AlgorithmModel/CAN Transmit", "EnablePeriodicTransmit", "on")
```

Make Connections Between the Blocks

The CAN blocks and the algorithm block added in the model must now be connected. The port coordinates for all CAN blocks are required.

```
canRxPort = get_param("AlgorithmModel/CAN Receive", "PortConnectivity");
canUnpackPort = get_param("AlgorithmModel/CAN Unpack", "PortConnectivity");
subSystemPort = get_param("AlgorithmModel/Subsystem", "PortConnectivity");
canPackPort = get_param("AlgorithmModel/CAN Pack", "PortConnectivity");
canTxPort = get_param("AlgorithmModel/CAN Transmit", "PortConnectivity");
terminatorPort = get_param("AlgorithmModel/Terminator", "PortConnectivity");
```

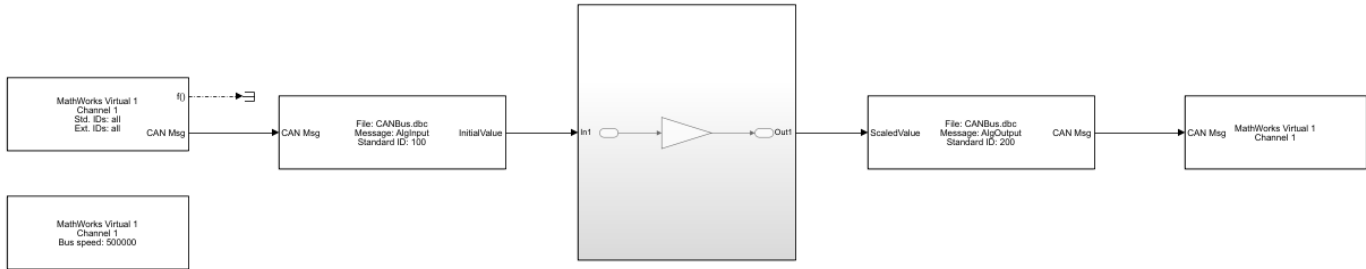
```
[canRxPortFunc, canRxPortMsg] = canRxPort.Position;
[canUnpackPortIn, canUnpackPortOut] = canUnpackPort.Position;
[subSystemPortIn, subSystemPortOut] = subSystemPort.Position;
[canPackPortIn, canPackPortOut] = canPackPort.Position;
canTxPortMsg = canTxPort.Position;
terminatorPortIn = terminatorPort.Position;
```

Add lines to connect all of the blocks in the appropriate order.

```
add_line("AlgorithmModel", [canRxPortMsg ; canUnpackPortIn])
add_line("AlgorithmModel", [canUnpackPortOut ; subSystemPortIn])
add_line("AlgorithmModel", [subSystemPortOut ; canPackPortIn])
add_line("AlgorithmModel", [canPackPortOut ; canTxPortMsg])
add_line("AlgorithmModel", [canRxPortFunc ; terminatorPortIn])
```

Completed Model

This is how the model looks after construction and configuration.



Test the Built Model

Configure a CAN Channel in MATLAB for Communication with the Algorithm Model

Create a CAN channel in MATLAB using channel 2 of the MathWorks Virtual CAN device. It will communicate with the CAN channel in the model. Also, attach the CAN database to the MATLAB channel to have it automatically decode incoming CAN data.

```
canCh = canChannel("MathWorks", "Virtual 1", 2);
canCh.Database = db;
```

For transmission from MATLAB to the model, use the CAN database to prepare a CAN message as input to the algorithm.

```
algInputMsg = canMessage(canCh.Database, "AlgInput");
```

Run the Algorithm Model

Assign the simulation time and start the simulation

```
set_param("AlgorithmModel", "StopTime", "inf")
set_param("AlgorithmModel", "SimulationCommand", "start")
```

Pause until the simulation is fully started.

```
while strcmp(get_param("AlgorithmModel", "SimulationStatus"), "stopped")
end
```

Run the MATLAB Code

Start the MATLAB CAN channel.

```
start(canCh);
```

Transmit multiple CAN messages with different signal data as input to the model.

```
for value = 1:5
    algInputMsg.Signals.InitialValue = value*value;
    transmit(canCh, algInputMsg)
    pause(1)
end
```

Receive all messages from the bus. Note the instances of the "AlgInput" and "AlgOutput" messages, their timing, and signal values.

```
msg = receive(canCh,Inf,"OutputFormat","timetable")
```

```
msg=10×8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
0.009728 sec	100	false	{'AlgInput' }	{[1]}	1	{1×1 struct}
0.15737 sec	200	false	{'AlgOutput' }	{1×2 uint8}	2	{1×1 struct}
1.0121 sec	100	false	{'AlgInput' }	{[4]}	1	{1×1 struct}
1.1574 sec	200	false	{'AlgOutput' }	{1×2 uint8}	2	{1×1 struct}
2.0146 sec	100	false	{'AlgInput' }	{[9]}	1	{1×1 struct}
2.1574 sec	200	false	{'AlgOutput' }	{1×2 uint8}	2	{1×1 struct}
3.0177 sec	100	false	{'AlgInput' }	{[16]}	1	{1×1 struct}
3.1574 sec	200	false	{'AlgOutput' }	{1×2 uint8}	2	{1×1 struct}
4.0219 sec	100	false	{'AlgInput' }	{[25]}	1	{1×1 struct}
4.1574 sec	200	false	{'AlgOutput' }	{1×2 uint8}	2	{1×1 struct}

The `canSignalTimetable` function provides an efficient way to separate and organize the signal values of CAN messages into individual timetables for each.

```
signalTimeTable = canSignalTimetable(msg)
```

```
signalTimeTable = struct with fields:
```

```
AlgInput: [5×1 timetable]
AlgOutput: [5×1 timetable]
```

```
signalTimeTable.AlgInput
```

```
ans=5×1 timetable
```

Time	InitialValue
0.009728 sec	1
1.0121 sec	4
2.0146 sec	9
3.0177 sec	16
4.0219 sec	25

```
signalTimeTable.AlgOutput
```

```
ans=5×1 timetable
```

Time	ScaledValue
0.15737 sec	2
1.1574 sec	8
2.1574 sec	18
3.1574 sec	32
4.1574 sec	50

Stop the CAN channel.

```
stop(canCh)
```

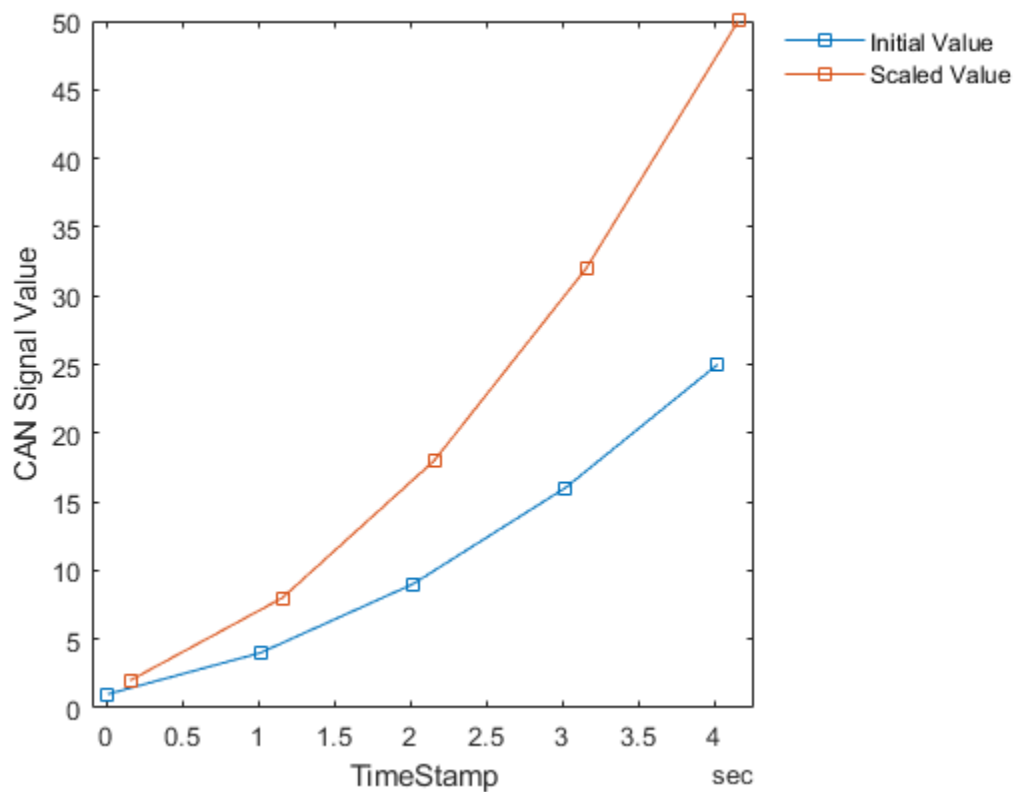

Stop the Algorithm Model

```
set_param("AlgorithmModel", "SimulationCommand", "stop")
```

Plot the Signal Data

Plot the initial and scaled signal values of the CAN messages against the timestamps as they occurred on the virtual bus. Note the change in values as transmitted by MATLAB and the scaling of the data as performed by the model.

```
plot(signalTimeTable.AlgInput.Time, signalTimeTable.AlgInput.InitialValue, "Marker", "square", "MarkerSize", 10, "hold on");
plot(signalTimeTable.AlgOutput.Time, signalTimeTable.AlgOutput.ScaledValue, "Marker", "square", "MarkerSize", 10, "hold off");
xlabel("TimeStamp");
ylabel("CAN Signal Value");
legend("Initial Value", "Scaled Value", "Location", "northeastoutside");
legend("boxoff");
```



Class-based Unit Testing Of Automotive Algorithms Via CAN

This example shows you how to validate the output of a cruise control algorithm using the Vehicle Network Toolbox™ and MATLAB™ class-based unit testing framework.

It uses the MATLAB unit test-class `tCruiseControlAlgorithmVerifier.m` to provide input commands via Controller Area Network (CAN) to a Simulink™ model of a cruise control algorithm to trigger the functional behavior of the algorithm, and then receives feedback from the model through CAN and validates the expected behavior of the algorithm. It also generates a PDF report of the test results, which can be used for analysis. For more information on how to write the test-class, see the `tCruiseControlAlgorithmVerifier.m` file. The dialog in that class helps you understand the method of setting up a test-class and what each individual test does.

This example uses MathWorks™ Virtual CAN Channels to communicate with the algorithm.

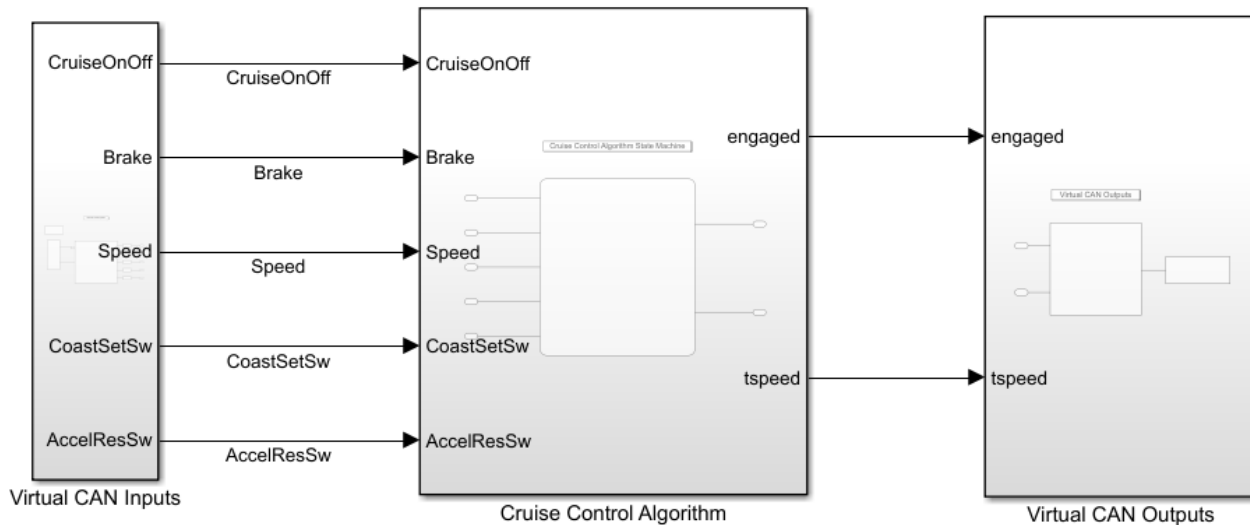
Simulink Model Overview

The cruise control algorithm has a Virtual CAN Inputs block, which houses the setup of the CAN channel using the CAN Configuration block, and receives the message commanded from the MATLAB test-class using the CAN Receive block. It then uses the CAN Unpack block to separate the individual signals from the received CAN message, which are then converted into their appropriate data types and transmitted to the actual cruise control algorithm.

The Cruise Control Algorithm block houses the Cruise Control Algorithm State Machine, which is a Stateflow chart. This algorithm works based on the inputs received from the Virtual CAN Inputs block and is set-up to trigger when the input conditions have reached a certain condition. The outputs of the Stateflow chart are the expected vehicle cruising speed, and algorithm engagement state.

The Virtual CAN Outputs block uses a CAN Pack block to load individual signals into a single CAN message, which are then transmitted onto the CAN bus using the CAN Transmit block. This feedback message is used for verification in the MATLAB test-class.

Cruise Control Algorithm



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Creating a Test Suite

Create a suite of test classes to run. In this example, the `tCruiseControlAlgorithmVerifier.m` is the only test in the suite. You can add additional tests in the same test suite. The 1xN Test array lists the number of tests, not the number of test-classes.

```
suite = testsuite({'tCruiseControlAlgorithmVerifier'})
```

```
suite =  
  1x3 Test array with properties:
```

```
  Name  
  ProcedureName  
  TestClass  
  BaseFolder  
  Parameterization  
  SharedTestFixtures  
  Tags
```

```
Tests Include:
```

```
  0 Parameterizations, 0 Shared Test Fixture Classes, 0 Tags.
```

Creating a Test Runner

Create a test runner to execute a set of tests in the test suite. This defines the runner with no special plugins.

```
runner = matlab.unittest.TestRunner.withNoPlugins
runner =
  TestRunner with properties:
    ArtifactsRootFolder: "C:\Users\sdange\AppData\Local\Temp"
    PrebuiltFixtures: [1x0 matlab.unittest.fixtures.Fixture]
```

Creating a PDF Report Output

Set-up the name of the PDF file in which you want your output to be captured.

```
pdfFile = 'CruiseControlAlgorithmTestReport.pdf'
```

```
pdfFile =
'CruiseControlAlgorithmTestReport.pdf'
```

Add a PDF creating plugin to your test runner. Firstly, construct the plugin.

```
plugin = matlab.unittest.plugins.TestReportPlugin.producingPDF(pdfFile)
```

```
plugin =
  PDFTestReportPlugin with properties:
    IncludeCommandWindowText: 0
    IncludePassingDiagnostics: 0
    LoggingLevel: Terse
    PageOrientation: 'portrait'
```

Associate this plugin with the test runner to generate the PDF report in the working directory.

```
runner.addPlugin(plugin)
```

Running Tests

Run the test suite using the test runner.

```
result = runner.run(suite)
```

```
Generating test report. Please wait.
  Preparing content for the test report.
```

```
  Adding content to the test report.
  Writing test report to file.
```

```
Test report has been saved to:
```

```
\\central-mi\home$\sdange\Documents\MATLAB\Examples\vnt-ex21299704\CruiseControlAlgorithmTestRep
```

```
result =
  1x3 TestResult array with properties:
```

```
  Name
  Passed
  Failed
  Incomplete
  Duration
  Details
```

```
Totals:
```

```
2 Passed, 1 Failed (rerun), 0 Incomplete.
214.3521 seconds testing time.
```

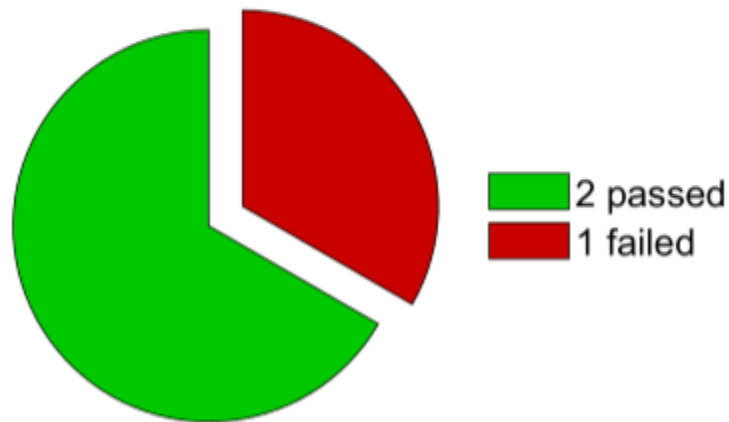
Analyzing the PDF Report

Open the PDF file created with the defined name. The default setting creates it in the current working directory. There are two things to observe in the PDF report:

Overall Result and Result Pie Chart

The overall result states the final outcome based on whether all the tests passed or not. The pie chart shows how many tests passed and failed out of the total number of tests defined.

Number of Tests: 3
Testing Time: 81.8527 seconds
Overall Result: FAILED



Failure Summary Details

The failure summary shows which test failed and for what reason.

Failure Summary

1 test failed.

Name of Failing Test	Failure Reasons
tCruiseControlAlgorithmVerifier/verifyNoCoastingEngagement	Failed by verification. (Details)

Clicking the details tab on the right hand side of the failure name provides a detailed reason for failure, along with the diagnostic message you configured in the tests.

✘ verifyNoCoastingEngagement

The test failed.

Duration: 38.7588 seconds

Event:

Verification failed.

Test Diagnostic:

Actual and Expected Vehicle Speed are not the same

Framework Diagnostic:

Eventually failed.

--> The constraint never passed with a timeout of 20 second(s).

--> IsTrue failed.

--> The value must evaluate to "true".

Actual Value:

logical

0

Evaluated Function:

function_handle with value:

```
@() isequal(feedbackMessageSignalTable.F02_TargetSpeed(end,1), testCase.TestCommandMsg.Signals.S03_VehicleSpeed)
```

Event Location: tCruiseControlAlgorithmVerifier/verifyNoCoastingEngagement

Stack:

In C:\Users\SDange\Desktop\Demo\tCruiseControlAlgorithmVerifier.m (tCruiseControlAlgorithmVerifier.verifyNoCoastingEngagement) at 328

Decoding CAN Data from BLF-Files

This example shows you how to import and decode CAN data from BLF-files in MATLAB for analysis. The BLF-file used in this example was generated from Vector CANoe™ using the "CAN - General System Configuration (CAN)" sample. This example also uses the CAN database file, `PowerTrain_BLF.dbc`, provided with the Vector sample configuration.

Open the Database File

Open the database file describing the source CAN network using the `canDatabase` function.

```
canDB = canDatabase("PowerTrain_BLF.dbc")
```

```
canDB =
```

```
Database with properties:
```

```

    Name: 'PowerTrain_BLF'
    Path: 'C:\Users\rschupba\OneDrive - MathWorks\Documents\MATLAB\Examples\vnt-ex062020'
    Nodes: {2x1 cell}
    NodeInfo: [2x1 struct]
    Messages: {12x1 cell}
    MessageInfo: [12x1 struct]
    Attributes: {11x1 cell}
    AttributeInfo: [11x1 struct]
    UserData: []

```

Investigate the BLF-File

Retrieve and view information about the BLF-File. The `blfinfo` function parses general information about the format and contents of the Vector Binary Logging Format BLF-file and returns the information as a structure.

```
binf = blfinfo("Logging_BLF.blf")
```

```
binf = struct with fields:
```

```

    Name: "Logging_BLF.blf"
    Path: "C:\Users\rschupba\OneDrive - MathWorks\Documents\MATLAB\Examples\vnt-ex062020"
    Application: "CANoe"
    ApplicationVersion: "11.0.55"
    Objects: 43344
    StartTime: 01-Jul-2020 14:47:34.427
    EndTime: 01-Jul-2020 14:48:33.487
    ChannelList: [2x3 table]

```

```
binf.ChannelList
```

```
ans=2x3 table
```

ChannelID	Protocol	Objects
1	"CAN"	8801
2	"CAN"	7575

Read Data from BLF-File

The data of interest was logged from the powertrain bus which is stored in channel 2 of the BLF-file. Read the CAN data using the `blfread` function. You can also provide the DBC-file to the function call which will enable message name lookup and signal value decoding.

```
blfData = blfread("Logging_BLF.blf", 2, "Database", canDB)
```

```
blfData=7575x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
2.2601 sec	103	false	{'Ignition_Info' }	{1x2 uint8}	2	{1x1 struct}
2.2801 sec	103	false	{'Ignition_Info' }	{1x2 uint8}	2	{1x1 struct}
2.3002 sec	100	false	{'EngineData' }	{1x8 uint8}	8	{1x1 struct}
2.3005 sec	102	false	{'EngineDataIEEE' }	{1x8 uint8}	8	{1x1 struct}
2.3006 sec	103	false	{'Ignition_Info' }	{1x2 uint8}	2	{1x1 struct}
2.3008 sec	201	false	{'ABSdata' }	{1x6 uint8}	6	{1x1 struct}
2.3009 sec	1020	false	{'GearBoxInfo' }	{[1]}	1	{1x1 struct}
2.3201 sec	103	false	{'Ignition_Info' }	{1x2 uint8}	2	{1x1 struct}
2.3401 sec	103	false	{'Ignition_Info' }	{1x2 uint8}	2	{1x1 struct}
2.3502 sec	100	false	{'EngineData' }	{1x8 uint8}	8	{1x1 struct}
2.3505 sec	102	false	{'EngineDataIEEE' }	{1x8 uint8}	8	{1x1 struct}
2.3507 sec	201	false	{'ABSdata' }	{1x6 uint8}	6	{1x1 struct}
2.3508 sec	1020	false	{'GearBoxInfo' }	{[1]}	1	{1x1 struct}
2.3601 sec	103	false	{'Ignition_Info' }	{1x2 uint8}	2	{1x1 struct}
2.3801 sec	103	false	{'Ignition_Info' }	{1x2 uint8}	2	{1x1 struct}
2.4002 sec	100	false	{'EngineData' }	{1x8 uint8}	8	{1x1 struct}
:						

View signals from an "EngineData" message.

```
blfData.Signals{3}
```

```
ans = struct with fields:
```

```

    PetrolLevel: 1
      EngPower: 7.5000
      EngForce: 0
    IdleRunning: 0
      EngTemp: 0
      EngSpeed: 750
```

Repackage and Visualize Signal Values of Interest

Use the `canSignalTimetable` function to repackage signal data from each unique message on the bus into a signal timetable. This example creates three individual signal timetables for the three messages of interest, "ABSdata", "EngineData" and "GearBoxInfo", from the CAN message timetable.

```
signalTimetable1 = canSignalTimetable(blfData, "ABSdata")
```

```
signalTimetable1=1136x4 timetable
```

Time	AccelerationForce	Diagnostics	GearLock	CarSpeed
2.3008 sec	-100	0	0	0
2.3507 sec	275	0	0	0

2.4008 sec	275	0	0	0
2.4507 sec	275	0	0	0
2.5008 sec	275	0	0	0
2.5507 sec	275	0	0	0
2.6008 sec	275	0	0	0
2.6507 sec	275	0	0	0
2.7008 sec	350	0	0	0
2.7507 sec	425	0	0	0.5
2.8008 sec	425	0	0	0.5
2.8507 sec	500	0	0	0.5
2.9008 sec	575	0	0	0.5
2.9507 sec	575	0	0	0.5
3.0008 sec	650	0	0	0.5
3.0507 sec	725	0	0	0.5
:				

```
signalTimetable2 = canSignalTimetable(blfdData, "EngineData")
```

```
signalTimetable2=1136x6 timetable
```

Time	PetrolLevel	EngPower	EngForce	IdleRunning	EngTemp	EngSpeed
2.3002 sec	1	7.5	0	0	0	750
2.3502 sec	2	7.5	375	0	0	4
2.4002 sec	3	7.5	375	0	0	10
2.4502 sec	4	7.5	375	0	0	17
2.5002 sec	5	7.5	375	0	0	23
2.5502 sec	6	7.5	375	0	0	30
2.6002 sec	7	7.5	375	0	0	36
2.6502 sec	8	7.5	375	0	0	43
2.7002 sec	9	9	450	0	0	50
2.7502 sec	10	10.5	525	0	0	59
2.8002 sec	10	10.5	525	0	0	69
2.8502 sec	11	12	600	0	0	80
2.9002 sec	11	13.5	675	0	0	92
2.9502 sec	12	13.5	675	0	0	106
3.0002 sec	13	15	750	0	0	121
3.0502 sec	13	16.5	825	0	0	136
:						

```
signalTimetable3 = canSignalTimetable(blfdData, "GearBoxInfo")
```

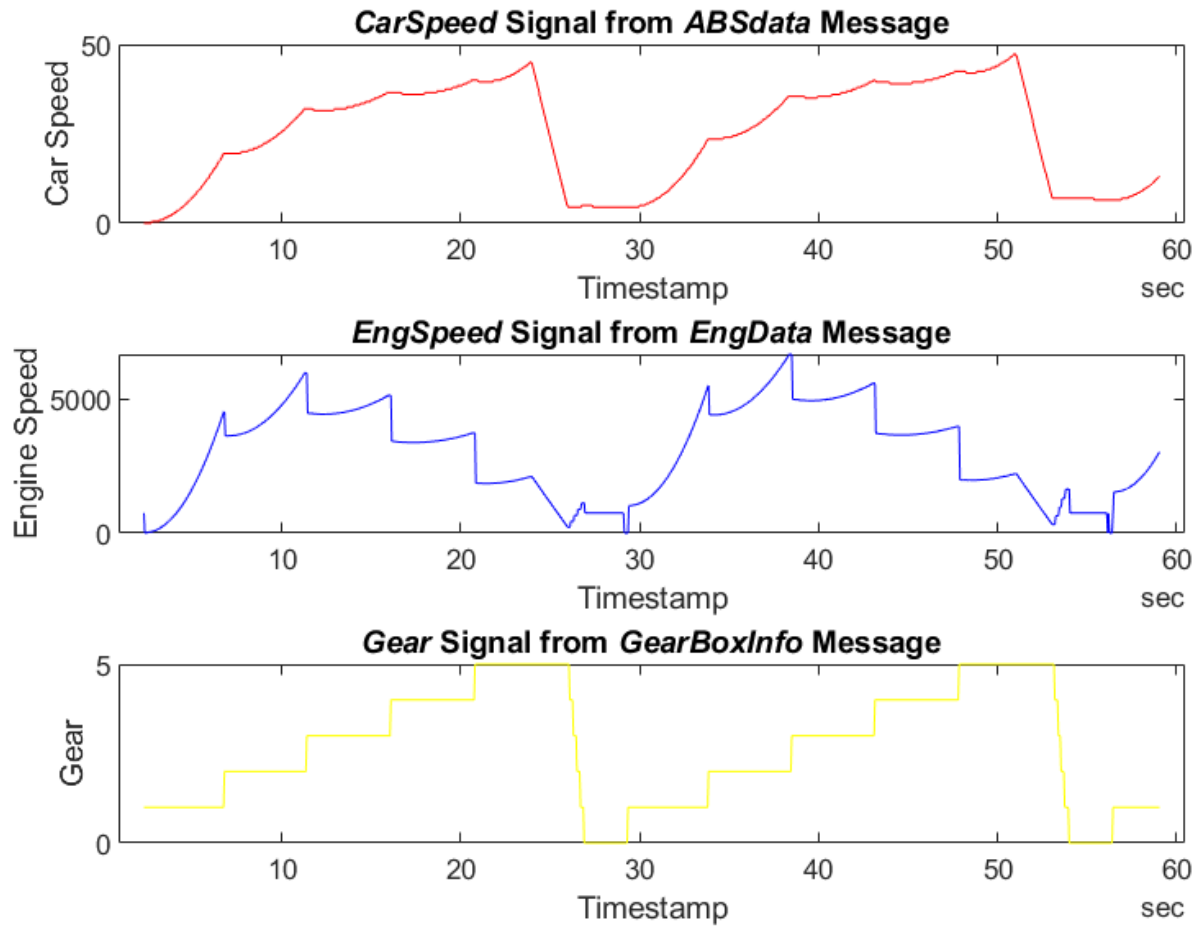
```
signalTimetable3=1136x3 timetable
```

Time	EcoMode	ShiftRequest	Gear
2.3009 sec	0	0	1
2.3508 sec	0	0	1
2.4009 sec	0	0	1
2.4508 sec	0	0	1
2.5009 sec	0	0	1
2.5508 sec	0	0	1
2.6009 sec	0	0	1
2.6508 sec	0	0	1
2.7009 sec	0	0	1
2.7508 sec	0	0	1
2.8009 sec	0	0	1

2.8508 sec	0	0	1
2.9009 sec	0	0	1
2.9508 sec	0	0	1
3.0009 sec	0	0	1
3.0508 sec	0	0	1
⋮			

To visualize the signals of interest, columns from the signal timetables can be plotted over time for further analysis.

```
subplot(3, 1, 1)
plot(signalT timetable1.Time, signalT timetable1.CarSpeed, 'r')
title('\itCarSpeed Signal from \itABSdata Message', 'FontWeight', 'bold')
xlabel('Timestamp')
ylabel('Car Speed')
subplot(3, 1, 2)
plot(signalT timetable2.Time, signalT timetable2.EngSpeed, 'b')
title('\itEngSpeed Signal from \itEngData Message', 'FontWeight', 'bold')
xlabel('Timestamp')
ylabel('Engine Speed')
subplot(3, 1, 3)
plot(signalT timetable3.Time, signalT timetable3.Gear, 'y')
title('\itGear Signal from \itGearBoxInfo Message', 'FontWeight', 'bold')
xlabel('Timestamp')
ylabel('Gear')
```



Decoding CAN Data from MDF-Files

This example shows you how to import and decode CAN data from MDF-files in MATLAB for analysis. The MDF-file used in this example was generated from Vector CANoe™ using the "CAN - General System Configuration (CAN)" sample. This example also uses the CAN database file, `PowerTrain.dbc`, provided with the Vector sample configuration.

Open the MDF-File

Open access to the MDF-file using the `mdf` function.

```
m = mdf("Logging_MDF.mf4")
```

```
m =
```

```
MDF with properties:
```

File Details

```

      Name: 'Logging_MDF.mf4'
      Path: 'C:\TEMP\Bdoc20b_1465442_5924\ib8F4264\25\tpb4bb48cc\vnt-ex42187575\Loggi
      Author: ''
      Department: ''
      Project: ''
      Subject: ''
      Comment: ''
      Version: '4.10'
      DataSize: 1542223
      InitialTimestamp: 2020-06-25 20:41:13.133000000

```

Creator Details

```

      ProgramIdentifier: 'MDF4Lib'
      Creator: [1x1 struct]

```

File Contents

```

      Attachment: [5x1 struct]
      ChannelNames: {62x1 cell}
      ChannelGroup: [1x62 struct]

```

Identify CAN Data Frames

According to the ASAM MDF associated standard for bus logging, the event types defined for a CAN bus system can be "CAN_DataFrame", "CAN_RemoteFrame", "CAN_ErrorFrame" or "CAN_OverloadFrame". This example focuses on extracting the CAN data frames, so the bus logging standard will be discussed using "CAN_DataFrame" event type as example. Additionally, note that a standard CAN data frame has up to 8 bytes for its payload and is used to transfer signal values.

The standard specifies that the channel names of the event structure should be prefixed by the event type name, for instance, "CAN_DataFrame". Typically a dot is used as separator character to specify the member channels, for instance, "CAN_DataFrame.ID" or "CAN_DataFrame.DataLength".

Use the `channelList` function to filter on channel names exactly matching "CAN_DataFrame". A table with information on matched channels is returned.

```
channelList(m, "CAN_DataFrame", "ExactMatch", true)
```

```
ans=2x9 table
```

```

      ChannelName      ChannelGroupNumber      ChannelGroupNumSamples      ChannelGroupAcquisitionName

```

Channel Name	Start	End	Channel
"CAN_DataFrame"	17	8889	CAN1
"CAN_DataFrame"	29	7648	CAN2

The powetrain data of interest was logged from the CAN 2 network. The `channelList` output above shows that the data from CAN 2 network has been stored in channel group 29 of the MDF-file. View the channel group details using the `ChannelGroup` property.

```
m.ChannelGroup(29)
```

```
ans = struct with fields:
  AcquisitionName: 'CAN2'
  Comment: ''
  NumSamples: 7648
  DataSize: 206496
  Sorted: 1
  Channel: [14x1 struct]
```

Within a channel group, details about each channel are stored. View details about channel 2 within channel group 29.

```
m.ChannelGroup(29).Channel(2)
```

```
ans = struct with fields:
  Name: 'CAN_DataFrame.Flags'
  DisplayName: 'Flags'
  ExtendedNamePrefix: 'CAN2'
  Description: 'Combination of bit flags for the message.'
  Comment: 'Combination of bit flags for the message.'
  Unit: ''
  Type: FixedLength
  DataType: IntegerUnsignedLittleEndian
  NumBits: 8
  ComponentType: StructureMember
  CompositionType: None
```

Read CAN Data Frames From the MDF-File

Read all data from all channels in channel group 29 into a timetable using the `read` function. The timetable is structured to follow the ASAM MDF standard logging format. Every row represents one raw CAN frame from the bus, while each column represents a channel within the specified channel group. The channels, such as "CAN_DataFrame.Dir", are named to follow the bus logging standard. However, because timetable column names must be valid MATLAB variable names, they may not be identical to the channel names. Most unsupported characters are converted to underscores. Since "." is not supported in a MATLAB variable name, "CAN_DataFrame.Dir" is altered to "CAN_DataFrame_Dir" in the table.

```
canData = read(m, 29, m.ChannelNames{29})
```

```
canData=7648x14 timetable
   Time      CAN_DataFrame_BusChannel  CAN_DataFrame_Flags  CAN_DataFrame_Dir  CAN_Da
   _____  _____  _____  _____  _____
   2.2601 sec           2                1                1
```

```

2.2801 sec          2          1          1
2.3002 sec          2          1          1
2.3005 sec          2          1          1
2.3006 sec          2          1          1
2.3008 sec          2          1          1
2.3009 sec          2          1          1
2.3201 sec          2          1          1
2.3401 sec          2          1          1
2.3502 sec          2          1          1
2.3505 sec          2          1          1
2.3507 sec          2          1          1
2.3508 sec          2          1          1
2.3601 sec          2          1          1
2.3801 sec          2          1          1
2.4002 sec          2          1          1
:

```

Decode CAN Messages Using the DBC-File

Open the database file using the `canDatabase` function.

```
canDB = canDatabase("PowerTrain_MDF.dbc")
```

```
canDB =
```

```
Database with properties:
```

```

    Name: 'PowerTrain_MDF'
    Path: 'C:\TEMP\Bdoc20b_1465442_5924\ib8F4264\25\tpb4bb48cc\vnt-ex42187575\PowerTrain
    Nodes: {2x1 cell}
    NodeInfo: [2x1 struct]
    Messages: {12x1 cell}
    MessageInfo: [12x1 struct]
    Attributes: {11x1 cell}
    AttributeInfo: [11x1 struct]
    UserData: []

```

The `canMessageTimetable` function uses the database to decode the message names and signals. The timetable of ASAM standard logging format data is converted into a Vehicle Network Toolbox™ CAN message timetable.

```
msgTimetable = canMessageTimetable(canData, canDB)
```

```
msgTimetable=7648x8 timetable
```

Time	ID	Extended	Name	Data	Length	Signals
2.2601 sec	103	false	{'Ignition_Info' }	{1x2 uint8}	2	{1x1 struct}
2.2801 sec	103	false	{'Ignition_Info' }	{1x2 uint8}	2	{1x1 struct}
2.3002 sec	100	false	{'EngineData' }	{1x8 uint8}	8	{1x1 struct}
2.3005 sec	102	false	{'EngineDataIEEE' }	{1x8 uint8}	8	{1x1 struct}
2.3006 sec	103	false	{'Ignition_Info' }	{1x2 uint8}	2	{1x1 struct}
2.3008 sec	201	false	{'ABSdata' }	{1x6 uint8}	6	{1x1 struct}
2.3009 sec	1020	false	{'GearBoxInfo' }	{[1]}	1	{1x1 struct}
2.3201 sec	103	false	{'Ignition_Info' }	{1x2 uint8}	2	{1x1 struct}
2.3401 sec	103	false	{'Ignition_Info' }	{1x2 uint8}	2	{1x1 struct}
2.3502 sec	100	false	{'EngineData' }	{1x8 uint8}	8	{1x1 struct}

```

2.3505 sec    102    false    {'EngineDataIEEE'}    {1x8 uint8}    8    {1x1 struct
2.3507 sec    201    false    {'ABSdata'           }    {1x6 uint8}    6    {1x1 struct
2.3508 sec    1020   false    {'GearBoxInfo'       }    {[ 1]}          1    {1x1 struct
2.3601 sec    103    false    {'Ignition_Info'    }    {1x2 uint8}    2    {1x1 struct
2.3801 sec    103    false    {'Ignition_Info'    }    {1x2 uint8}    2    {1x1 struct
2.4002 sec    100    false    {'EngineData'        }    {1x8 uint8}    8    {1x1 struct
:

```

View the signals stored in the "EngineData" message.

```
msgTimetable.Signals{3}
```

```
ans = struct with fields:
  PetrolLevel: 1
  EngPower: 7.5000
  EngForce: 0
  IdleRunning: 0
  EngTemp: 0
  EngSpeed: 750

```

Repackage and Visualize Signal Values of Interest

Use the `canSignalTimetable` function to repackage signal data from each unique message on the bus into a signal timetable. This example creates three individual signal timetables for the three messages of interest, "ABSdata", "EngineData" and "GearBoxInfo", from the CAN message timetable.

```
signalTimetable1 = canSignalTimetable(msgTimetable, "ABSdata")
```

```
signalTimetable1=1147x4 timetable
      Time      AccelerationForce      Diagnostics      GearLock      CarSpeed
      _____      _____      _____      _____      _____
2.3008 sec      -100              0              0              0
2.3507 sec       275              0              0              0
2.4008 sec       275              0              0              0
2.4507 sec       275              0              0              0
2.5008 sec       275              0              0              0
2.5507 sec       275              0              0              0
2.6008 sec       275              0              0              0
2.6507 sec       275              0              0              0
2.7008 sec       350              0              0              0
2.7507 sec       425              0              0              0.5
2.8008 sec       425              0              0              0.5
2.8507 sec       500              0              0              0.5
2.9008 sec       575              0              0              0.5
2.9507 sec       575              0              0              0.5
3.0008 sec       650              0              0              0.5
3.0507 sec       725              0              0              0.5
:

```

```
signalTimetable2 = canSignalTimetable(msgTimetable, "EngineData")
```

```
signalTimetable2=1147x6 timetable
      Time      PetrolLevel      EngPower      EngForce      IdleRunning      EngTemp      EngSpeed
      _____      _____      _____      _____      _____      _____      _____

```

2.3002 sec	1	7.5	0	0	0	750
2.3502 sec	2	7.5	375	0	0	4
2.4002 sec	3	7.5	375	0	0	10
2.4502 sec	4	7.5	375	0	0	17
2.5002 sec	5	7.5	375	0	0	23
2.5502 sec	6	7.5	375	0	0	30
2.6002 sec	7	7.5	375	0	0	36
2.6502 sec	8	7.5	375	0	0	43
2.7002 sec	9	9	450	0	0	50
2.7502 sec	10	10.5	525	0	0	59
2.8002 sec	10	10.5	525	0	0	69
2.8502 sec	11	12	600	0	0	80
2.9002 sec	11	13.5	675	0	0	92
2.9502 sec	12	13.5	675	0	0	106
3.0002 sec	13	15	750	0	0	121
3.0502 sec	13	16.5	825	0	0	136
:						

```
signalTimetable3 = canSignalTimetable(msgTimetable, "GearBoxInfo")
```

```
signalTimetable3=1147x3 timetable
```

Time	EcoMode	ShiftRequest	Gear
2.3009 sec	0	0	1
2.3508 sec	0	0	1
2.4009 sec	0	0	1
2.4508 sec	0	0	1
2.5009 sec	0	0	1
2.5508 sec	0	0	1
2.6009 sec	0	0	1
2.6508 sec	0	0	1
2.7009 sec	0	0	1
2.7508 sec	0	0	1
2.8009 sec	0	0	1
2.8508 sec	0	0	1
2.9009 sec	0	0	1
2.9508 sec	0	0	1
3.0009 sec	0	0	1
3.0508 sec	0	0	1
:			

To visualize the signals of interest, columns from the signal timetables can be plotted over time for further analysis.

```
subplot(3, 1, 1)
plot(signalTimetable1.Time, signalTimetable1.CarSpeed, 'r')
title('\itCarSpeed Signal from \itABSdata Message', 'FontWeight', 'bold')
xlabel('Timestamp')
ylabel('Car Speed')
subplot(3, 1, 2)
plot(signalTimetable2.Time, signalTimetable2.EngSpeed, 'b')
title('\itEngSpeed Signal from \itEngineData Message', 'FontWeight', 'bold')
xlabel('Timestamp')
ylabel('Engine Speed')
subplot(3, 1, 3)
```



```
plot(signalTimetable3.Time, signalTimetable3.Gear, 'y')
title('\itGear Signal from \itGearBoxInfo Message', 'FontWeight', 'bold')
xlabel('Timestamp')
ylabel('Gear')
```

