

# ISO 11898-2:2024-03 (E)

## Road vehicles - Controller area network (CAN) - Part 2: High-speed physical medium attachment (PMA) sublayer

---

### Contents

	Page
<b>Foreword</b>	iv
<b>Introduction</b>	v
<b>1 Scope</b>	1
<b>2 Normative references</b>	1
<b>3 Terms and definitions</b>	1
<b>4 Abbreviated terms</b>	3
<b>5 HS-PMA function</b>	4
5.1 Base requirements	4
5.2 HS-PMA test circuit	5
5.3 Static parameter	5
5.3.1 Maximum ratings of $V_{CAN\_H}$ , $V_{CAN\_L}$ and $V_{Diff}$	5
5.3.2 Recessive output characteristics, bus biasing active	6
5.3.3 Recessive output characteristics, bus biasing inactive	6
5.3.4 Dominant output characteristics	7
5.3.5 Maximum driver output current	8
5.3.6 PMA static receiver input characteristics, bus biasing active and inactive	9
5.3.7 Receiver input resistance	9
5.3.8 Maximum leakage currents of CAN_H and CAN_L	10
5.4 Dynamic parameter	11
5.4.1 Driver symmetry	11
5.4.2 Optional transmit dominant timeout	11
5.4.3 Transmitter and receiver timing behaviour	11
5.5 Wake-up from low-power mode	15
5.5.1 Wake-up procedures	15
5.5.2 General requirement	15
5.5.3 Basic wake-up	15
5.5.4 Via wake-up pattern	15
5.5.5 Selective wake-up	18
5.5.6 Bus biasing procedure	23
<b>6 Conformance</b>	25
<b>Annex A (normative) HS-PMA with SIC mode and FAST mode</b>	26
<b>Annex B (informative) ECU and network design</b>	55
<b>Annex C (informative) PN physical layer modes</b>	63
<b>Bibliography</b>	64