ISO 11898-2:2026-05 (E)

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

Contents

Page

Foreword ... **iv**

Introduction ... **v**

1 Scope ... **1**

2 Normative references ... **1**

3 Terms and definitions ... **1**

4 Abbreviated terms ... **3**

5 HS-PMA function ... **4**

5.1 Base requirements ... 4
5.2 HS-PMA test circuit ... 4
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 ... 5
5.3.3 Recessive output characteristics, bus biasing inactive ... 6
5.3.4 Dominant output characteristics ... 6
5.3.5 Maximum driver output current ... 8
5.3.6 PMA static receiver input characteristics, bus biasing active and inactive ... 8
5.3.7 Receiver input resistance ... 9
5.3.8 Maximum leakage currents of CAN_H and CAN_L ... 10
5.4 Dynamic parameter ... 10
5.4.1 Driver symmetry ... 10
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 ... 19
5.5.6 Bus biasing procedure ... 24

6 Conformance ... **26**

Annex A (normative) **HS-PMA with SIC mode and FAST mode** ... **27**

Annex B (informative) **ECU and network design** ... **54**

Annex C (informative) **PN physical layer modes** ... **60**

Bibliography ... **61**