BOSCH

Data Logger and Sensor Interface C 80

Manual

Version 1.2 08/04/2025

Content

1 Preparation

Use the C 80 only as intended in this manual. Any maintenance or repair must be performed by authorized and qualified personnel approved by Bosch Motorsport.

Operation of the C 80 is only certified with the combinations and accessories that are specified in this manual. The use of variant combinations, accessories and other devices outside the scope of this manual are only permitted when they have been determined to be compliant from a performance and safety standpoint by a representative from Bosch Motorsport.

Read the manual carefully and follow the application hints step by step. Do not hesitate to contact us, contact data can be found on the last page of this document.

Important information on Electromagnetic Conformity

To avoid unwanted interference with the environment (people, animals, electronic devices) or unwanted harm to the environment, it is mandatory that the user of the C 80 carries out an appropriate analysis to determine the electromagnetic interaction the C 80 may have with its individual installation environment.

Disclaimer

Due to continuous enhancements, we reserve the rights to change any illustrations, photos, and technical data within this manual.

Please retain this manual for your records.

Note

In this document, many screenshots are created by way of example for a display. Please consider this and replace the product names with the name of your device.

2 Warnings and Safety Instructions

The classification of the warnings and safety instructions is carried out by the respective signal word (Danger, Warning, Caution) next to the warning symbol.

Danger

⚠ DANGER

Nature and source of danger

Consequences

Warning of death or serious physical injury, which are sure to occur if ignored.

Warning

⚠ WARNING

Nature and source of danger

Consequences

Warning of death or serious injury, which can occur if this is not observed.

Caution

⚠ CAUTION

Nature and source of danger

Consequences

Warning of slight bodily injury in case of Disregard.

Notice

NOTICE

Nature and source of danger

Consequences

Warning of damage to equipment in case of ignoring.

3 Onboard Network Concept

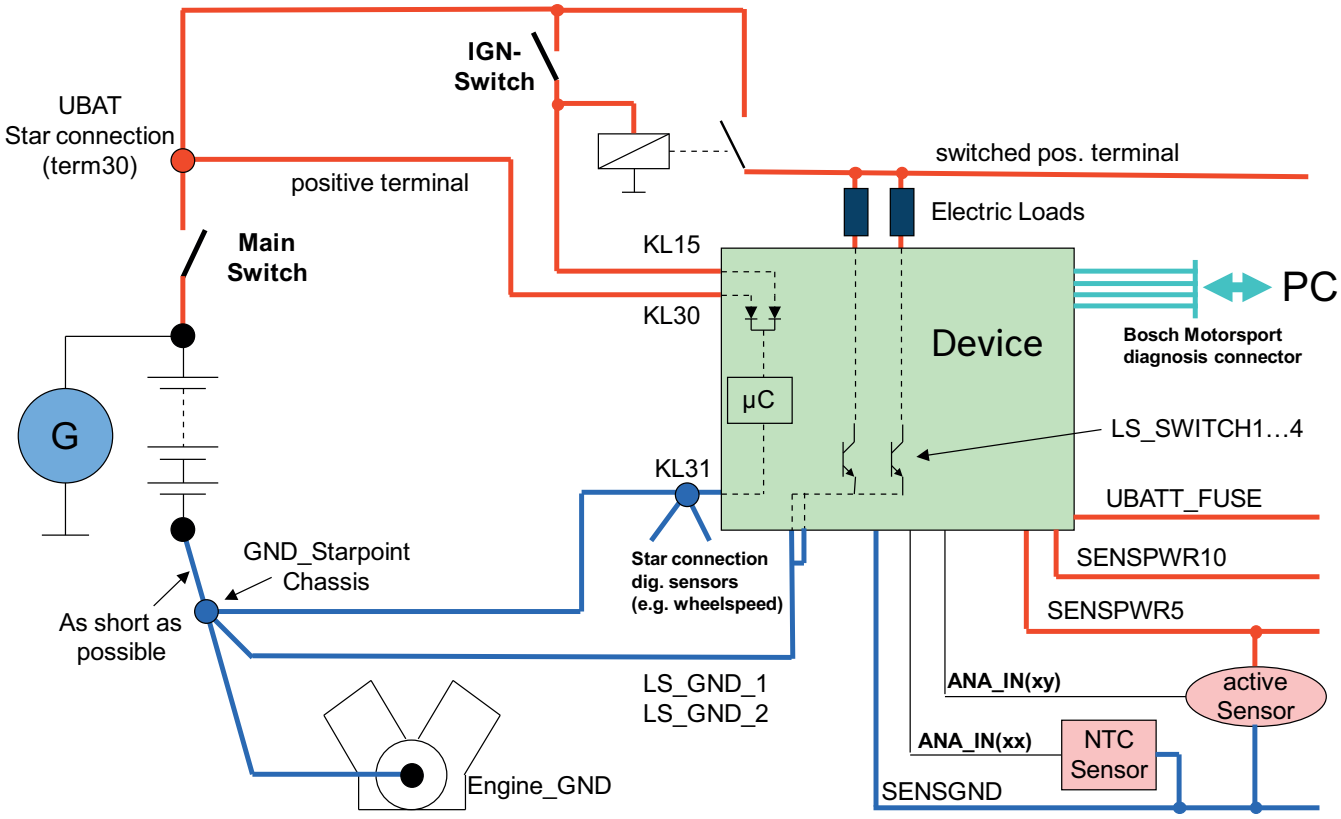
Please ensure that you have a good ground installation. That means:

- A ground that has a solid, low resistance connection to the negative battery terminal
- Connection should be free from dirt, grease, paint, anodizing, etc.
- Use large diameter wire
- More metal-to-metal contact is better!

The following notations for power signals are used:

- KL 15 is a switched battery rail controlled by the IGN-switch
- KL 30 is an unswitched battery positive rail (same as battery positive terminal)
- KL 31 is an unswitched ground rail (same as battery negative terminal)

Be careful to observe current limits of wires and connector pins!



Note

This schematic is not device specific. Please see the section Technical Data for the specifications of your device.

4 Technical Data

We offer the C 80 in two basic versions, on the one hand as a data logger and on the other hand as a sensor interface. Choose between these basic variants and combine or add functionalities now or later.

The data logger C 80 is a professional data logging system for motorsport applications. This allows for synchronized acquisition of engine data from the ECU and chassis data from up to 26 analog and 4 digital input channels. Additional input devices can be connected via Ethernet and CAN buses.

Recorded data from the up to 16 GB logger can be downloaded via high speed Ethernet.

Software upgrades for the C 80 (field upgradable by entering a key) activate tailored configurations like a second logging partition of 4 GB, USB recording, CCP/XCP-master for simple data access to third party devices, as well as additional input channels.

Converters	10 kHz 12 bit AD converters with digital low pass filter
Configurable math channels	
User configurable CAN in/out messages	
Sampling rate	
Online data compression	
Internal logger – FULL_LOG_1 (4 GB memory on Partition 1) enabled, optional in C80 Sensor Interface – PERF_LOG_1 (16 GB memory on Partition 1) optional – FULL_LOG_2 (4 GB memory on Partition 2) optional – 1,500 channels enabled – 1 ms sampling rate enabled – DATA_USB (Data copy to USB flash drive) optional	
Logging rates – Usage of all features: 800 kB/s – Primary logging use case: >1,500 kB/s – Logging data download rate: up to 7.5 MB/s	
3-port network switch	
Telemetry Support via Ethernet (recommended) and RS232	

Mechanical Data

Size	105 x 34.5 x 137.5 mm
Weight	462 g
Protection Classification	IP67 to DIN 40050, Section 9, Issue 2008
Max. vibration	Vibration profile 1 (see Downloads or www.bosch-motorsport.com)
Operating temperature (internal)	0 to 85°C
Operation outside the temperature limits can be tested on request during the manufacturing tests.	

Electrical Data

Supply voltage	8 to 18 V
Max. power consumption (w/o loads)	10 W at 14 V

Inputs

6 x analog channels
0 to 5 V input range
12 bit resolution
1 x 3 kOhm switchable pull up resistor

Sensor Supplies and Screens

4 x PWM outputs (low side switch 2 A each)
1 x sensor supply 5 V ± 1 % (250 mA)

Connectors and Wires

Motorsport connectors double density	2 x 41 pins
Mating connector I ASDD612-41SN	F02U.002.216-01
Mating connector II ASDD612-41SA	F02U.004.180-01

Pin Layout ASDD212-41PN

Pin	Name	Description
1	KL30	
2; 3	KL15	
4; 5	KL31	
6	Ethernet Channel0 Tx plus	Wire Ethernet_0 - TX+
7	Ethernet Channel0 Tx minus	Wire Ethernet_0 - TX-
8	Ethernet Channel0 Rx plus	Wire Ethernet_0 - RX+
9	Ethernet Channel0 Rx minus	Wire Ethernet_0 - RX-
10	Ethernet Schirm	Ethernet Schirm
11	Ethernet Channel1 Tx plus	Wire Ethernet_0 - TX+
12	Ethernet Channel1 Tx minus	Wire Ethernet_0 - TX-
13	Ethernet Channel1 Rx plus	Wire Ethernet_0 - RX+
14	Ethernet Channel1 Rx minus	Wire Ethernet_0 - RX-
15	Ethernet Channel2 Tx plus	Wire Ethernet_0 - TX+
16	Ethernet Channel2 Tx minus	Wire Ethernet_0 - TX-
17	Ethernet Channel2 Rx plus	Wire Ethernet_0 - RX+
18	Ethernet Channel2 Rx minus	Wire Ethernet_0 - RX-
19	CAN_A_H	CAN_A - HIGH
20	CAN_A_L	CAN_A - LOW
21	CAN_B_H	CAN_B - HIGH
22	CAN_B_L	CAN_B - LOW
23	USB Power	500mA USB_Power
24	USB Data Plus	USB_OTG_Plus

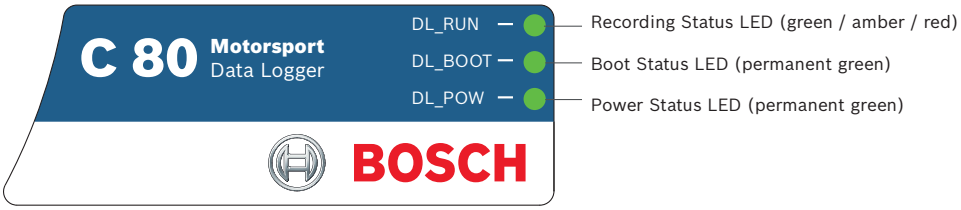
Pin	Name	Description
25	USB Data Minus	USB_OTG_Minus
26	USB GND	USB_Ground
27	SENSPWR5_1	
28	SENSGND	
29	Timestamp	
30	LS_GND_1	Low-Side Ground2
31	LS_SWITCH_1	lowside switch 2A
32	LS_SWITCH_2	lowside switch 2A
33	LS_SWITCH_3	lowside switch 2A
34	LS_SWITCH_4	lowside switch 2A
35	LS_GND_2	Low-Side Ground2
36	ANAIN_M1_1	0 to 5V Analog
37	ANAIN_M1_2	0 to 5V Analog
38	ANAIN_M1_3	0 to 5V Analog
39	ANAIN_M1_4	0 to 5V Analog
40	ANAIN_M1_5	0 to 5V Analog
41	ANAIN_M1_6	0 to 5V Analog

Pin Layout ASDD212-41PA

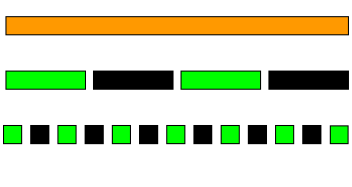
Pin	Name	Description
1	UBATT_FUSE1	
2	SENSPWR10_1	
3	SENSPWR5_2	
4	SENSPWR5_3	
5	SENSPWR5_4	
6; 7	SENSGND	
8	RS232A TX	Transmit Telemetry data
9	RS232A RX	Receive Telemetry data
10	RS232B TX	Transmit GPS data
11	RS232B RX	Receive GPS data
12	RS232_GND	RS232 Ground
13	REV1_P	Hall / Inductive
14	REV1_M	Hall / Inductive
15	REV2_P	Hall / Inductive
16	REV2_M	Hall / Inductive
17	REV3_P	Hall / Inductive
18	REV3_M	Hall / Inductive
19	REV4_P	Hall / Inductive
20	REV4_M	Hall / Inductive
21	ANAIN_M1_7	0 to 5V Analog
22	ANAIN_M1_8	0 to 5V Analog
23	ANAIN_M1_9	0 to 5V Analog

Pin	Name	Description
24	ANAIN_M1_10	0 to 5V Analog
25	ANAIN_M1_11	0 to 5V Analog
26	ANAIN_M1_12	0 to 5V Analog
27	ANAIN_M1_13	0 to 5V Analog
28	ANAIN_M1_14	0 to 5V Analog
29	ANAIN_M1_15	0 to 5V Analog
30	ANAIN_M1_16	0 to 5V Analog
31	ANAIN_M2_1	0 to 5V Analog
32	ANAIN_M2_2	0 to 5V Analog
33	ANAIN_M2_3	0 to 5V Analog
34	ANAIN_M2_4	0 to 5V Analog
35	ANAIN_M2_5	0 to 5V Analog
36	ANAIN_M2_6	0 to 5V Analog
37	ANAIN_M2_7	0 to 5V Analog
38	ANAIN_M2_8	0 to 5V Analog
39	ANAIN_M2_9	0 to 5V Analog
40	ANAIN_M2_10	0 to 5V Analog
41	LAPTRIGGER	

4.1 Status LEDs



Recording Status LED



	Recorded Data	Telemetry
Amber constant • No measurement configuration on Logger	No	No
Blinking green slow • Measurement configuration loaded • Start condition(s) not fulfilled	No	Yes
Blinking green fast • Measurement configuration loaded • Start conditions fulfilled • Logger is recording data	Yes	Yes
Blinking amber slow • Measurement configuration loaded • Measurement setup error (external device missing) • Start condition(s) not fulfilled	No	Yes (but some missing)
Blinking amber fast • Measurement configuration loaded • Measurement setup error (external device missing) • Start conditions fulfilled, Logger is recording data	Yes (but some missing)	Yes (but some missing)
Blinking red fast • Firmware update in progress • Do not power off Logger	No	No
Blinking red slow • Firmware update has finished	No	No
Red constant • Error during firmware update	No	No

4.2 Upgrades

CCP/XCP_MASTER

Enables CCP/XCP master functionality to request data from foreign devices via CAN/CCP protocol, XCP over Ethernet (UDP) or XCP via CAN.
(ASAP2 file from ECU manufacturer required)

FULL_LOG_1 (enabled in C 80 logger)

4 GB memory on Partition 2, 600 kB/s (600 MHz)

PERF_LOG_1 (requires FULL_LOG_1)

16 GB memory on Partition 1, 800 kB/s (866 MHz)

FULL_LOG_2

4 GB memory on Partition 2

IO_EXTENS (included in C 80 Sensor Interface)

20 additional analog channels

4 rotational channels, input Hall
(Input inductive on request, hardware change required)

3 additional sensor supply 5 V (250 mA each)

1 sensor supply 10 V (250 mA)

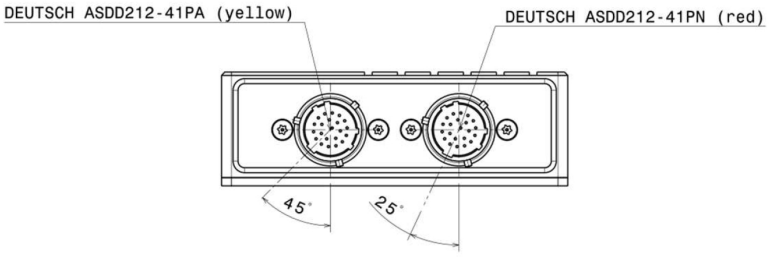
1 sensor supply 12 V (1 A), non-regulated

RS232 GPS

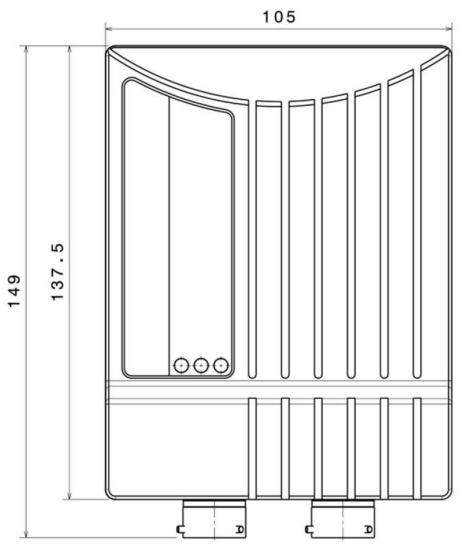
DATA_USB

Data copy to USB flash drive

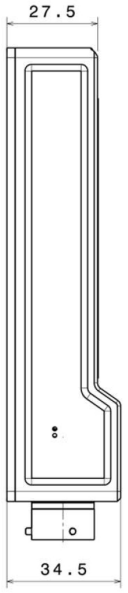
5 Mechanical Drawing



Bottom view
Scale: 1:1



Front view
Scale: 1:1



Left view
Scale: 1:1

6 Communication Channels

CAN bus

The C 80 has two CAN buses configurable as input and output. Different baud rates are selectable. Please note that the C 80 does not contain any CAN termination resistors. Thus the CAN termination resistors need to be integrated into the wiring loom.

Ethernet channels

The C 80 has three 100 MBit full duplex Ethernet communication ports. The ports are internally connected with an Ethernet switch. The Ethernet ports have 'cable auto crossover' functionality.

RS232 ports

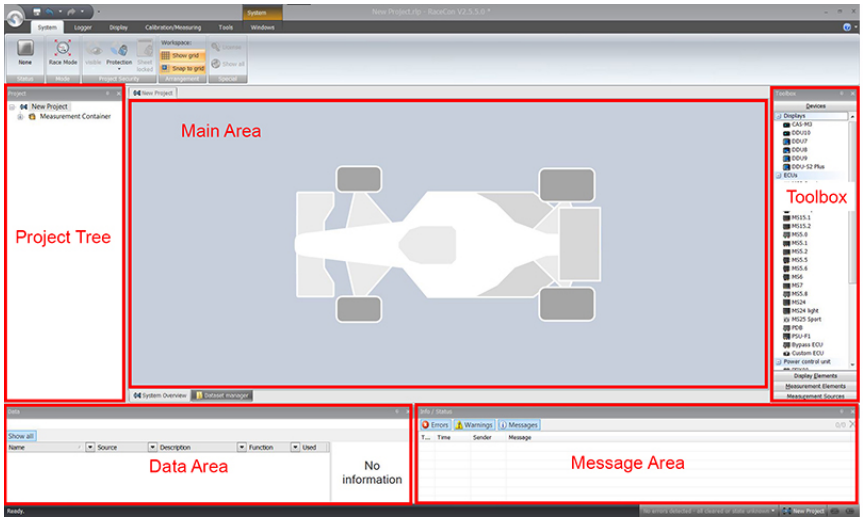
The C 80 has two RS232 serial ports. Baud rate for both ports is programmable. RS232 port 1 is reserved for online telemetry, port 2 can be used for reception of data from a serial GPS receiver.

Vehicle diagnosis connector

The Bosch Motorsport vehicle diagnosis connector is used as a standard interface to connect the vehicle to a PC e.g. via a MSA-Box II. Loom connector: AS012-35SN

Pin	Name	Description	Used for C 80
Pin 1	Terminal 30	Permanent positive	+
Pin 2	Terminal 15	Switched positive	+
Pin 3	Terminal 31	GND	+
Pin 4	CAN High	Diagnostic CAN bus	
Pin 16	CAN Low	Diagnostic CAN bus	
Pin 10	K-Line	ECU diagnosis	
Pin 8	Ethernet RxD +	Ethernet interface	+
Pin 9	Ethernet RxD -	Ethernet interface	+
Pin 11	Ethernet TxD +	Ethernet interface	+
Pin 12	Ethernet TxD -	Ethernet interface	+
Pin 22	Screen	Cable screen	+

7 System Configuration Tool RaceCon



RaceCon is an all integrated software tool for configuration and calibration of Bosch Motorsport hardware products, such as ECUs, displays, loggers. The communication is based on Bosch Motorsport MSA-Box interface.

Calibration of ECU maps and curves
ECU data file and parameter file up- and download
Diagnostic functionality for Bosch Motorsport ECUs
Data file / Work base management
Integrated flash functionality and Bosch sensor database
Configuration of Bosch Motorsport displays, data loggers, CAN modules, ...
Communication via K-Line/CAN/Ethernet (KWP/CCP/XCP)
CAN communication log functionality (baud rate changeable)
Quick data access over Race Mode

PC

IBM PC Pentium/AMD Athlon compatible, min. 1.6 GHz
Min. 2 GB RAM
Min. 1 GB free hard disc space
VGA/WGA monitor (min. 1,024 x 768)
Recommended Operating System: Windows 10

Optional Accessories

MSA-Box II	F02U.V00.327-03

8 First Steps

Install the software required for the operation of the C 80. It is developed for Windows system software. The following software versions are used in this manual:

- C 80 setup, configuration and calibration: RaceCon Version 2.10.
- Measurement data analysis: WinDarab V7

Set up the 100 Mbit ethernet connection to the C 80.

- The ethernet port has “cable auto crossover” functionality.

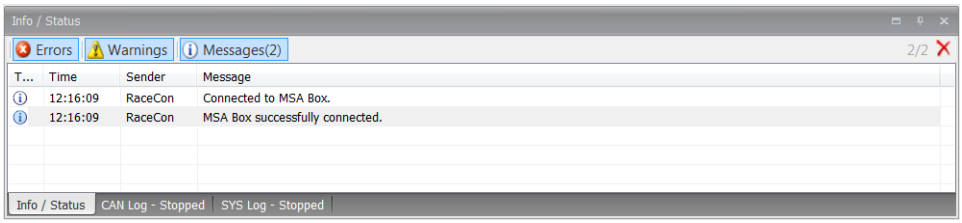
8.1 Connecting the unit to RaceCon

For testing new device configurations, you can connect the device to your computer via MSA-Box or ethernet cable.

Connection via MSA-Box

1. Reassure that the MSA-Box driver is installed properly on your computer. If needed, download the MSA-Box driver from www.bosch-motorsport.com.
2. Connect an ethernet line of the device to the ethernet line of the MSA-Box.

   Please note, that the MSA-Box also requires power supply on the MSA-Box connector of your wiring loom.
3. Open RaceCon and connect the MSA-Box to the computer.
4. In the ‘Info / Status‘ Box of RaceCon, you will receive messages that the connection was successful.



5. Reassure that the device is switched on.
6. ‘Link LED’ at the computer’s network adapter will illuminate.

   If the LED is off, check the wiring harness.

   After you created a RaceCon project with the device, the status icon of the device will switch from grey to one of the following colors: red, orange, green. For further information on how to set up a project, see the chapter “Setting up a new RaceCon Project [▶ 16]”. For the status color, see chapter “Color indication [▶ 27]”.

Connection via Ethernet Cable

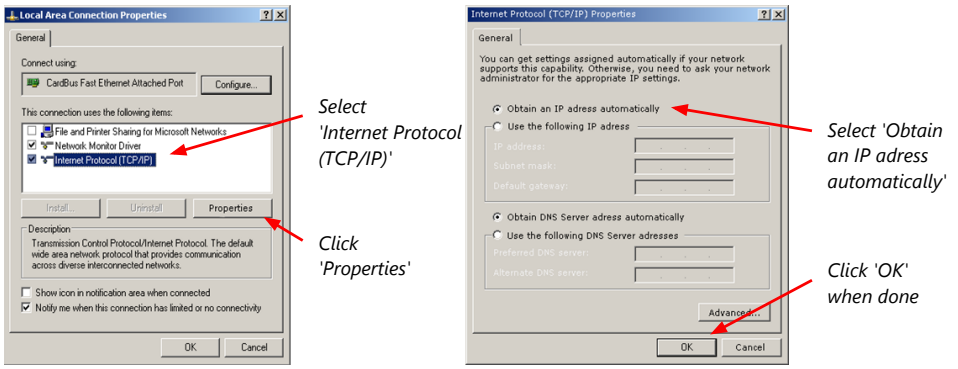
Instead of connecting the ethernet line to the MSA-Box, connect the ethernet directly to your computer.

Troubleshooting while setting up the network interface

The C 80 contains a DHCP server, network addresses can be assigned automatically to the configuration PC. In case of problems during the network connection, please try the following steps:

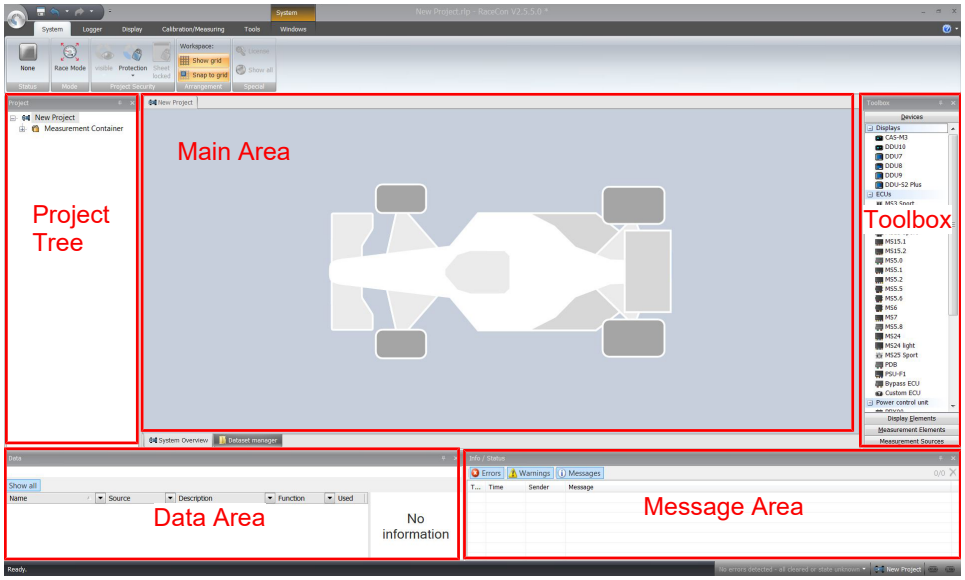
7. Switch off the PC’s firewall.

8. Reconfigure the PC or the MSA-Box network interface settings to obtain an IP address automatically as shown in the pictures below.

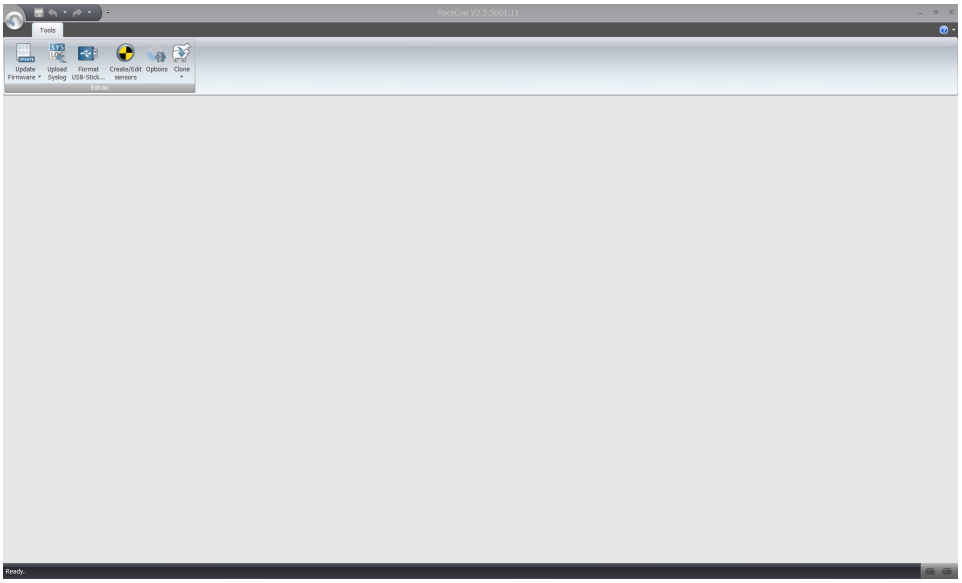


8.2 Setting up a new RaceCon Project

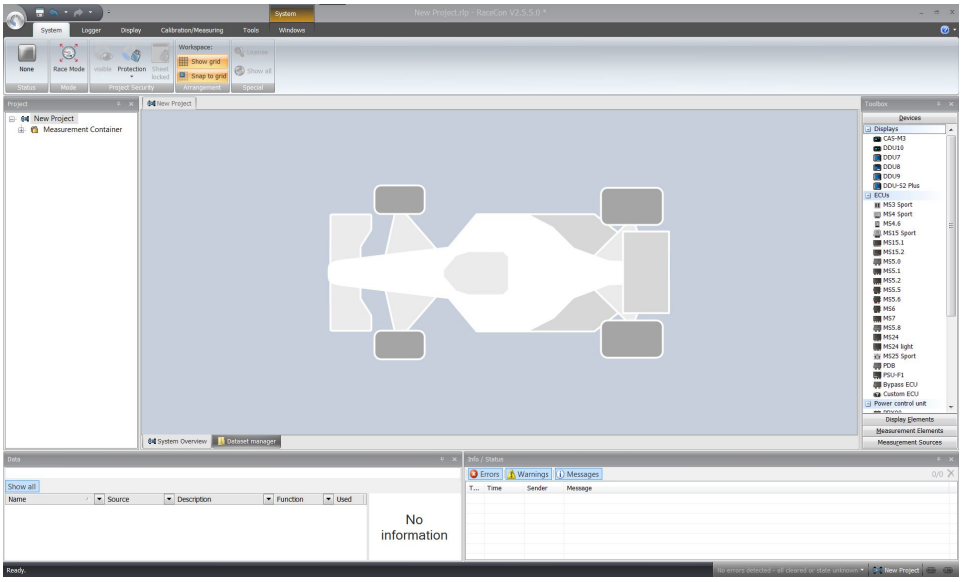
The following screenshot shows an overview of the RaceCon Main Screen with its areas. All (sub-) windows are resizable and dockable. You can find them under the 'Windows' tab.



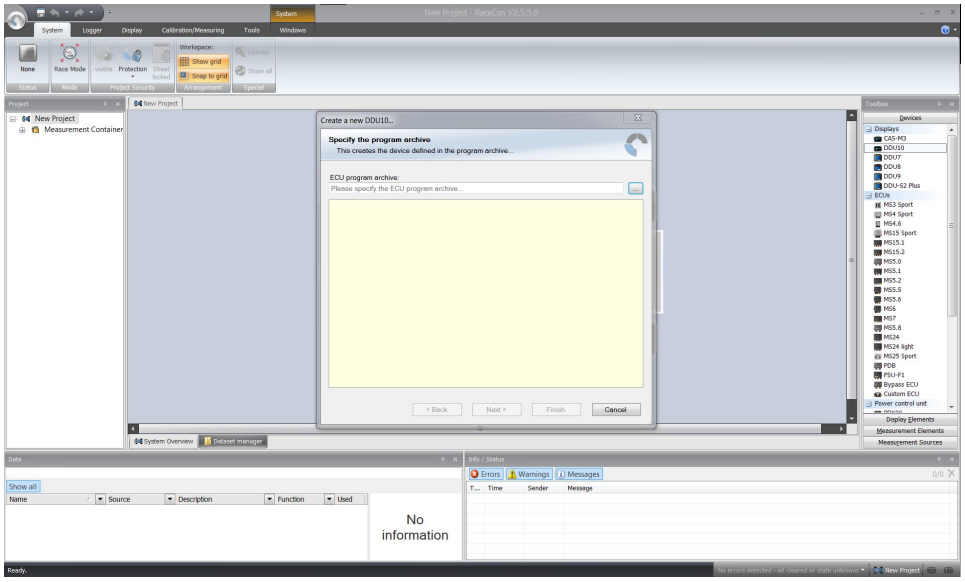
1. Start the RaceCon software.



2. In the ‘File’ menu, select ‘New project’ to create a new project.



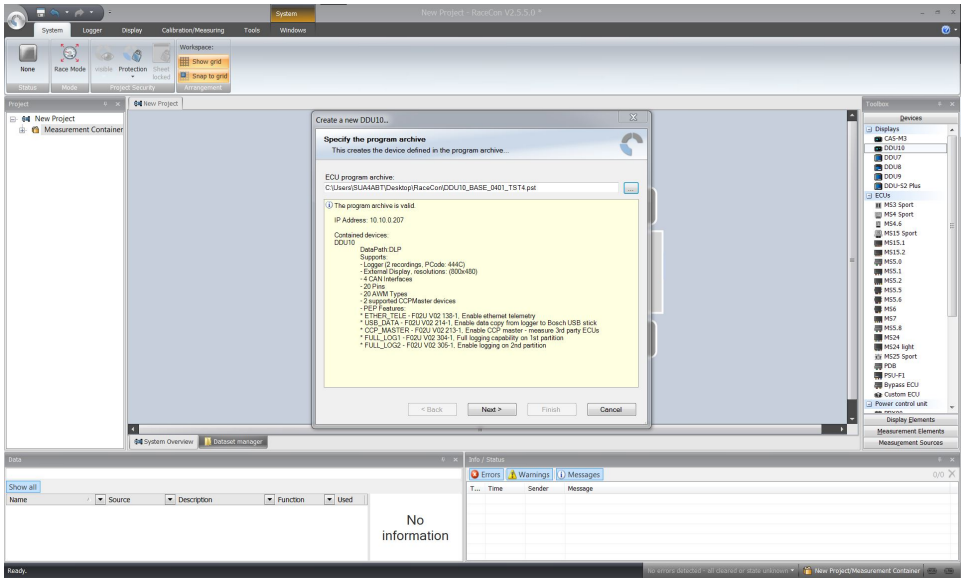
3. In the Toolbox, select the C80 and drag it into the Main Area. A pop up window to specify the C80 program archive appears.



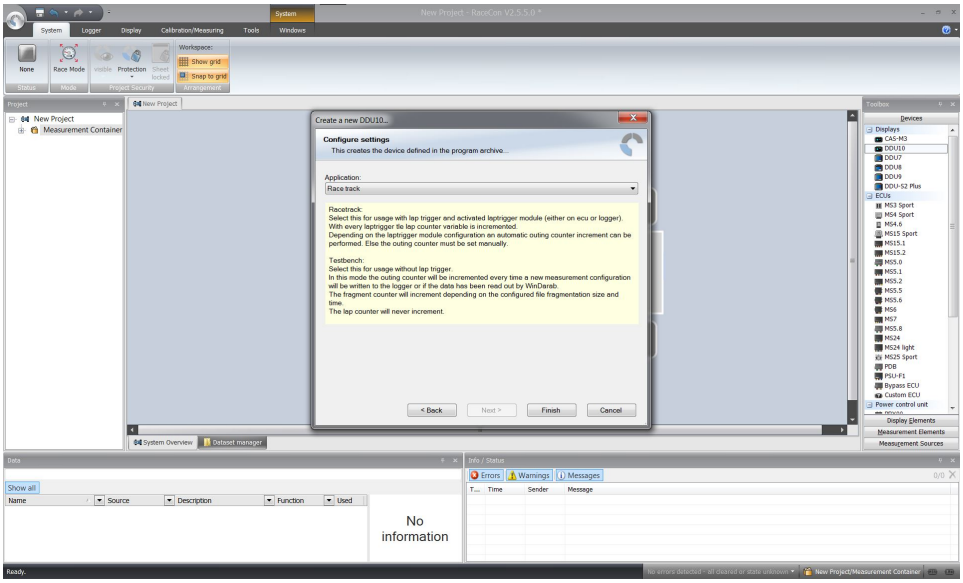
4. Download the firmware for your device:
   - from the RaceConnect project file share for PSU. This .pst file should be provided to RaceCon.
   - from www.bosch-motorsport.com for VCUs, DDUs, and Loggers.
   - You can get firmware for ECUs on request.

An information shows if the archive is valid or not.

5. Click ‘Next’ (for PSU: go on with step 7).

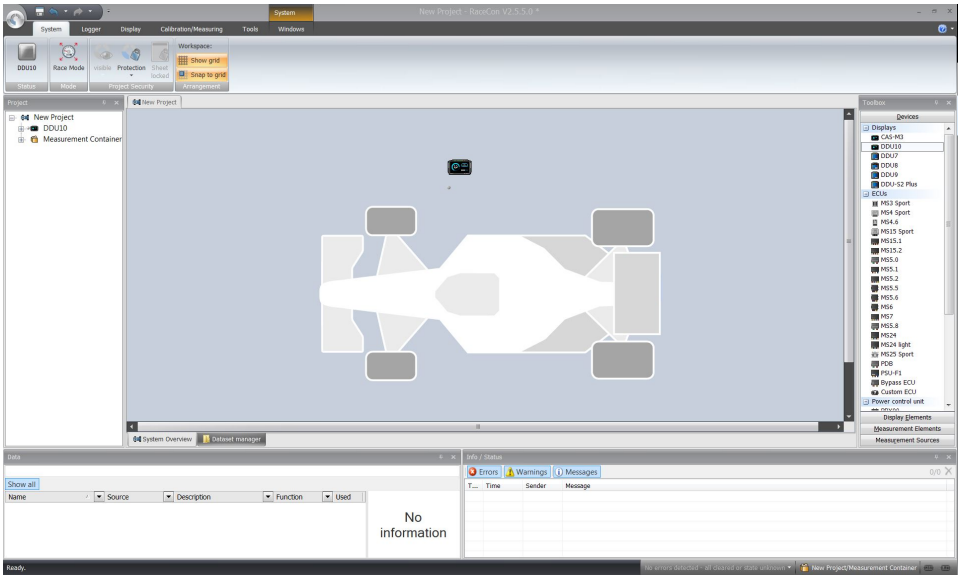


6. Select ‘Race track’ or ‘Testbench’ mode according to your application.



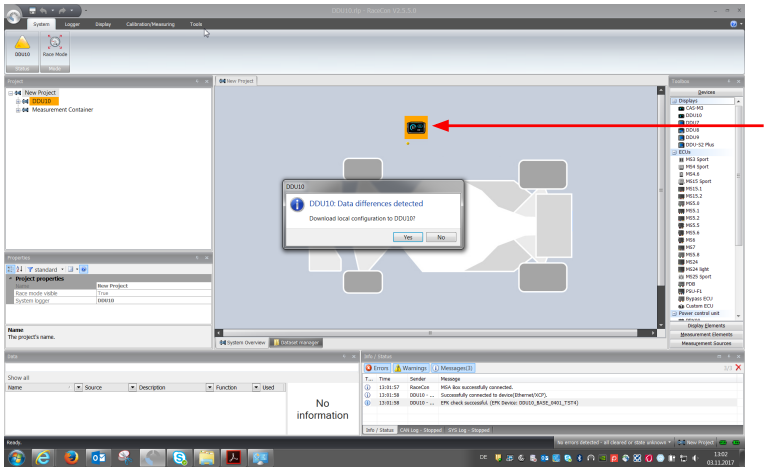
7. Click ‘Finish’.

The C 80 is inserted into the project and RaceCon tries to connect to the device.



RaceCon detects configuration differences between the C 80 and the RaceCon project and asks for permission for data download.

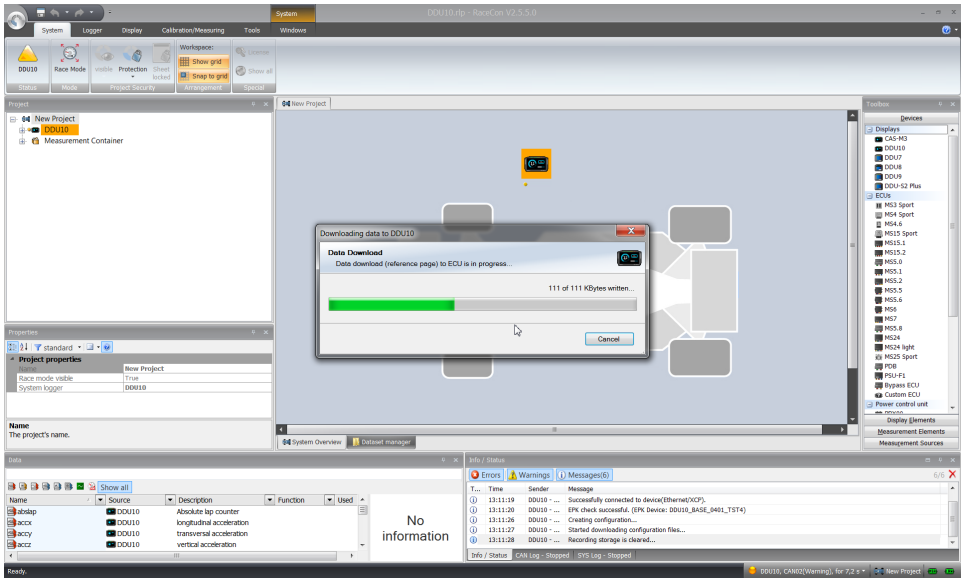
Click ‘Yes’ to download the configurations to the device or ‘No’ to continue without downloading the data.



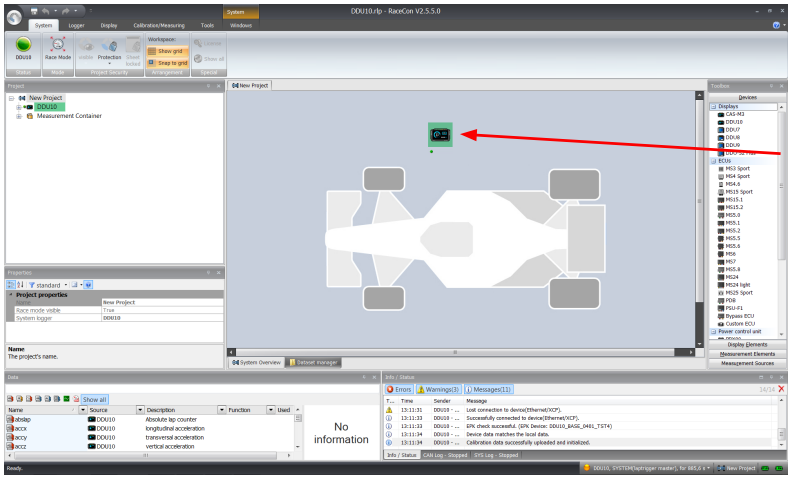
Successful connected, Device "talks" to PC.

If the device turns red, you might need to do a firmware update on the device. For more information see chapter “Firmware update [▶ 134]”.

The download starts and the C 80 carries out a reset.



After the reset, RaceCon reconnects to the C 80. Local configuration on both the PC and C 80 match (indicated by green background and dot). The C 80 is now connected to Race-Con.



Green background and dot indicate matching configuration

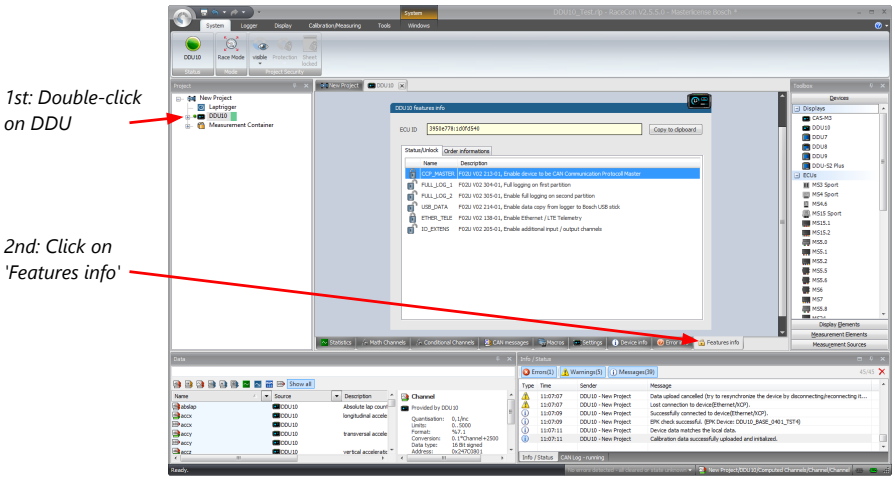
For further information on the color indication, see chapter “Color indication [▶ 27]”.

8.3 Feature activation

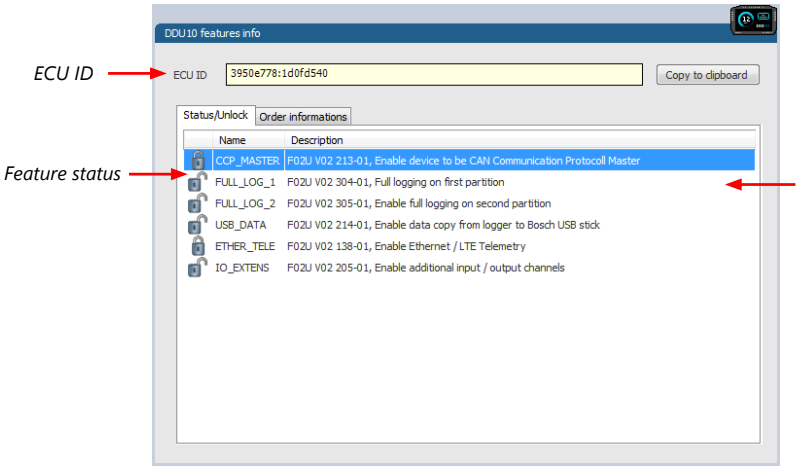
- Optional software feature packages are available for the C 80
- All software feature packages can be purchased prior to delivery or after you have received your device.
- If you have purchased an optional software feature package, it must be activated before it becomes operational.
- The feature activation status is stored permanently in the device and requires activating once only.
- As the activation key is device specific, a key delivered with one C 80 does not work on any other C 80.
- When purchasing a software feature package, you have to tell Bosch the ECU ID code.

  The ECU ID code is device specific and can be found in the 'features info' window, shown in the screenshots below.
- If you have not purchased an optional software feature package, the next steps can be skipped.

1. Ensure a connection to the device.
2. To activate a feature, double-click on 'C 80' in the Project Tree.
3. Click on the 'Features info' tab in the Main Area.

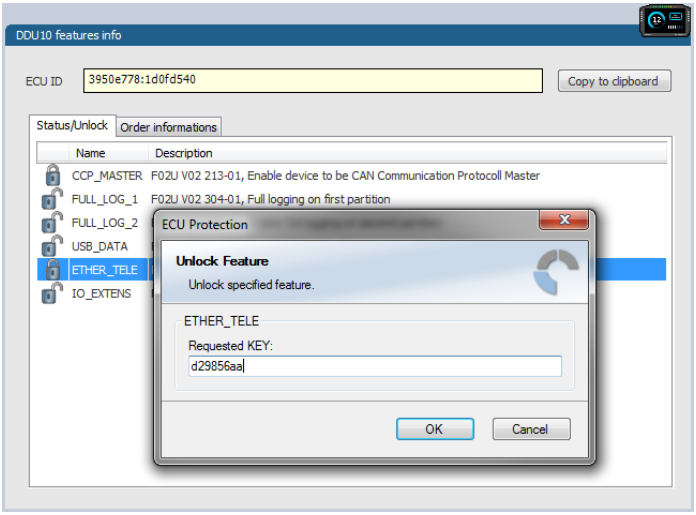


4. The 'C 80 features info' window appears.

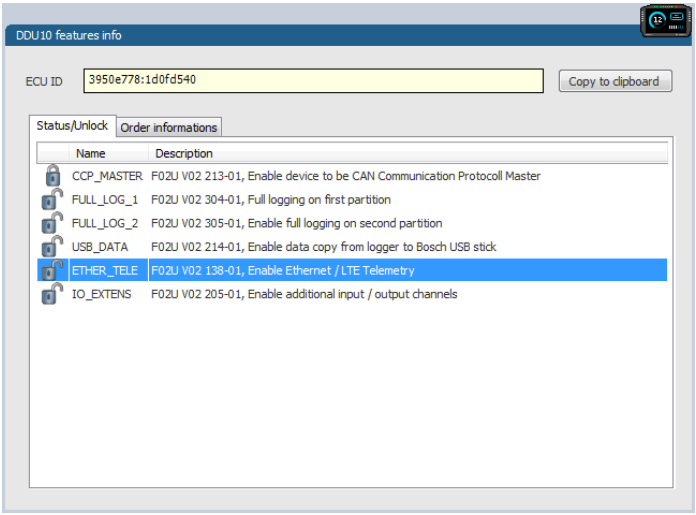


Locked (disabled) *Unlocked (activated)*

5. Double-click on the feature you want to activate. A feature unlock window appears.



6. Enter the activation key you received for this feature on this device and click ‘OK’ when done. The feature’s status changes to ‘unlocked’.

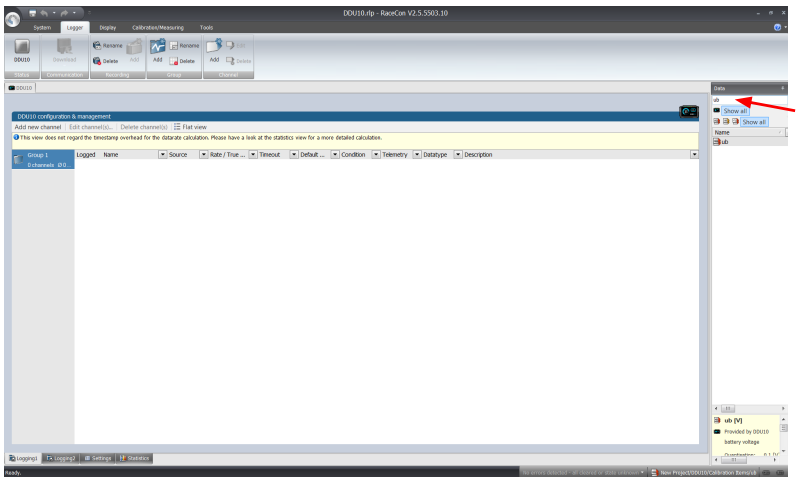


7. Perform these steps to activate other features you purchased.
8. Switch the car’s ignition off and on again to cycle the power of C 80.

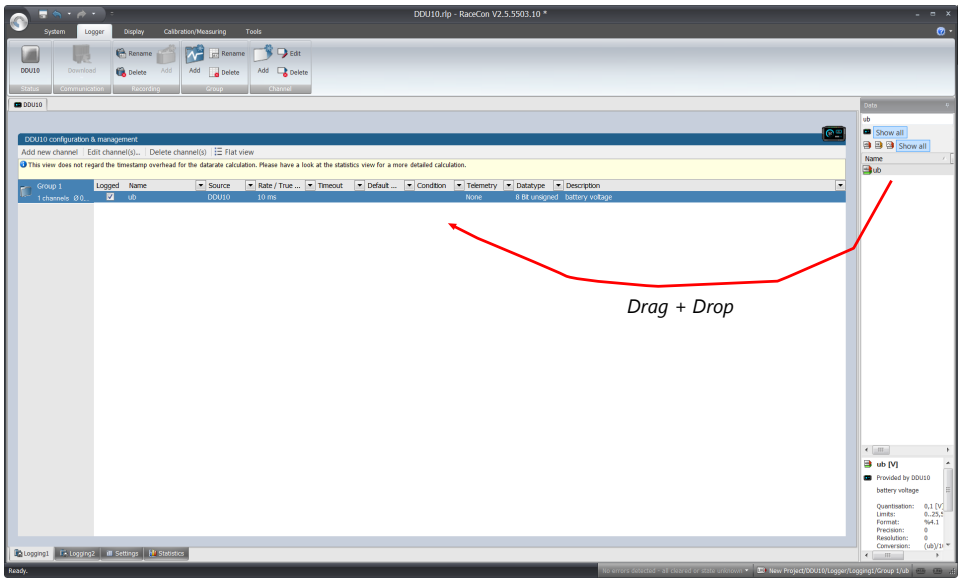
8.4 First recording (Quick Start)

This chapter explains the configuration of the recording of the battery voltage channel. See chapter 'Recording [▶ 94]' for a detailed instruction to configure recordings.

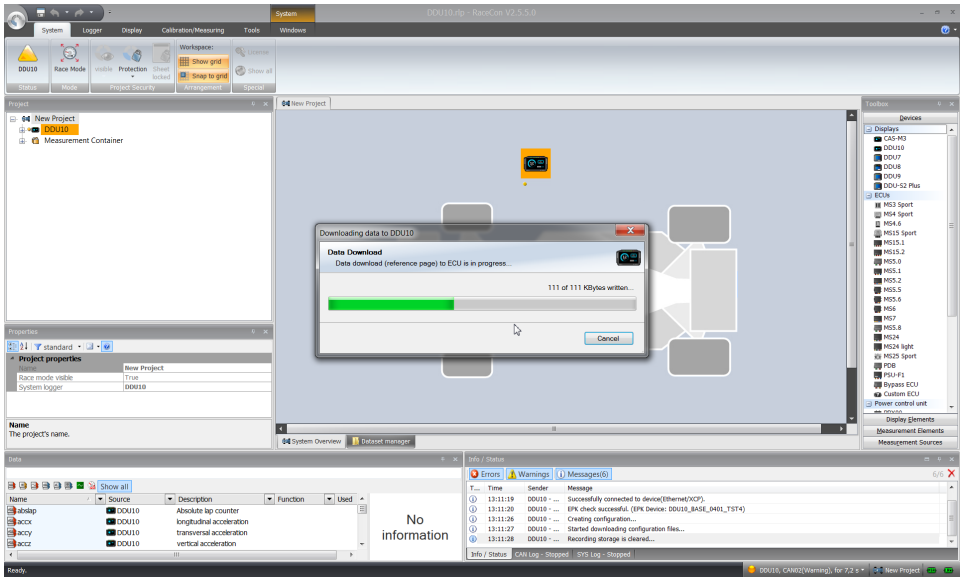
1. Click on the 'Logger' tab to go to the page 'Logger'.
2. Use the search bar in the 'Data' window, to search for 'ub' (measurement channel for battery voltage).



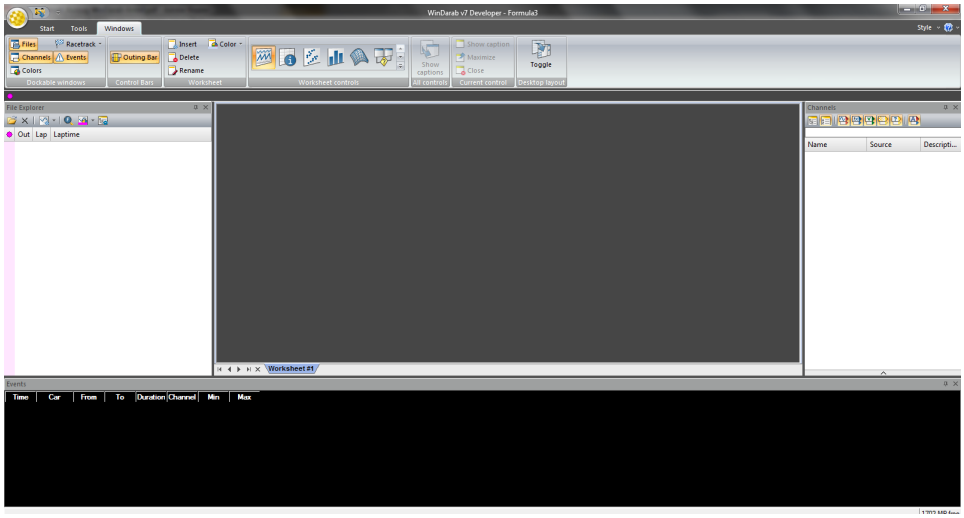
3. Drag and drop the 'ub' measurement channel into the recording area.



4. Click on the 'Download' button in the upper left corner. The configuration download starts and the C 80 carries out a reset. Now you can find the 'ub' measurement channel in the 'Data Area'. As we did not define global start conditions, recording starts immediately.



5. Start the WinDarab software.

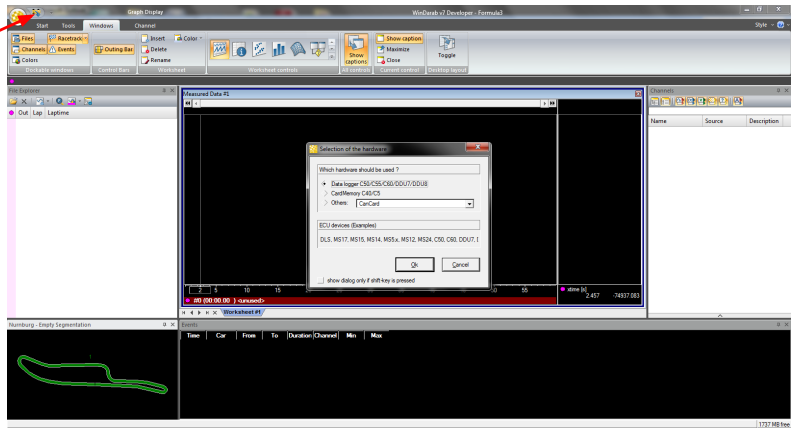


6. Disconnect the C 80 network cable.

7. Click on the ‘Read Data from Logging Device’ icon.

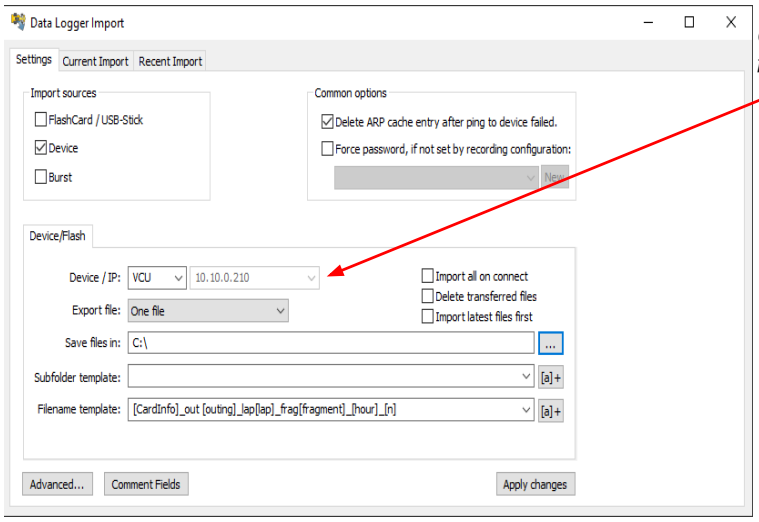
   Choose your logger and click ‘OK’ when done. The ‘Data Logger Import’ dialog opens. Refer to the WinDarab V7 manual for instructions on how to use the ‘Data Logger Import’ dialog and for more detailed descriptions and instructions.

Click 'read data from logging device'



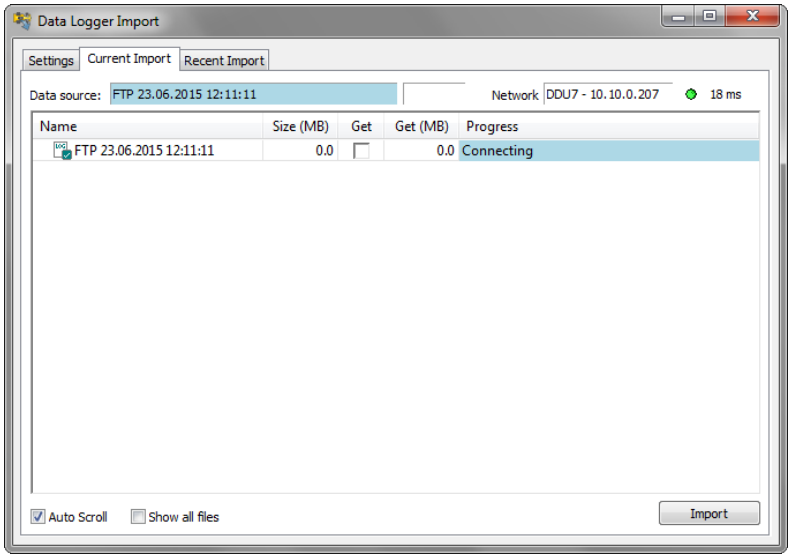
8. Choose the device and the IP address for the device.

   Click ‘Apply changes’ when done.

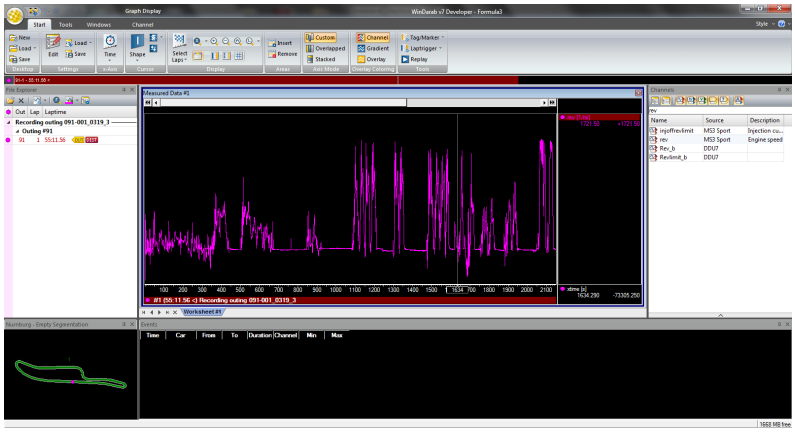


Choose your Device / IP from dropdown list

9. Connect the C 80 network cable.
10. Click on the ‘Current Import’ tab.
11. Click on ‘Import’ in the lower right corner. If the ‘Import all on connect’ box is checked, the data transmission from the C 80 starts automatically. Measurement files are stored automatically in the folder defined under ‘Settings’.



12. Click on ‘Close’ when the transmission has finished.
13. Click on the Start button and choose ‘Open measurement file’.
14. Select the measurement files from the storage folder.
15. Click on ‘Open’.
16. Click on ‘New Desktop’ to open a new measurement data window.
17. Drag the ‘ub’ measurement channel from the channel list and drop it into the measurement data window. The ‘ub’ measurement channel‘s graph is displayed.

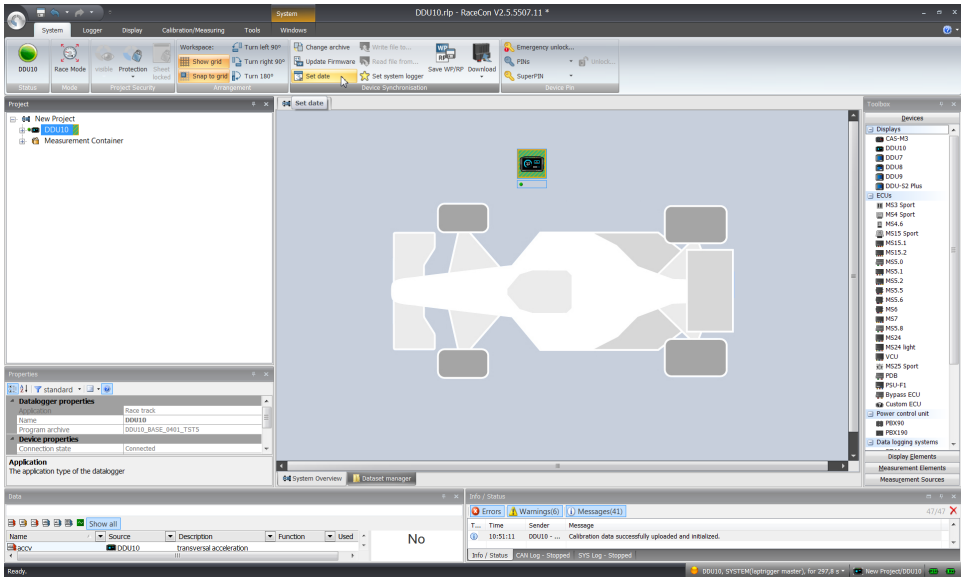


8.5 Set date and time

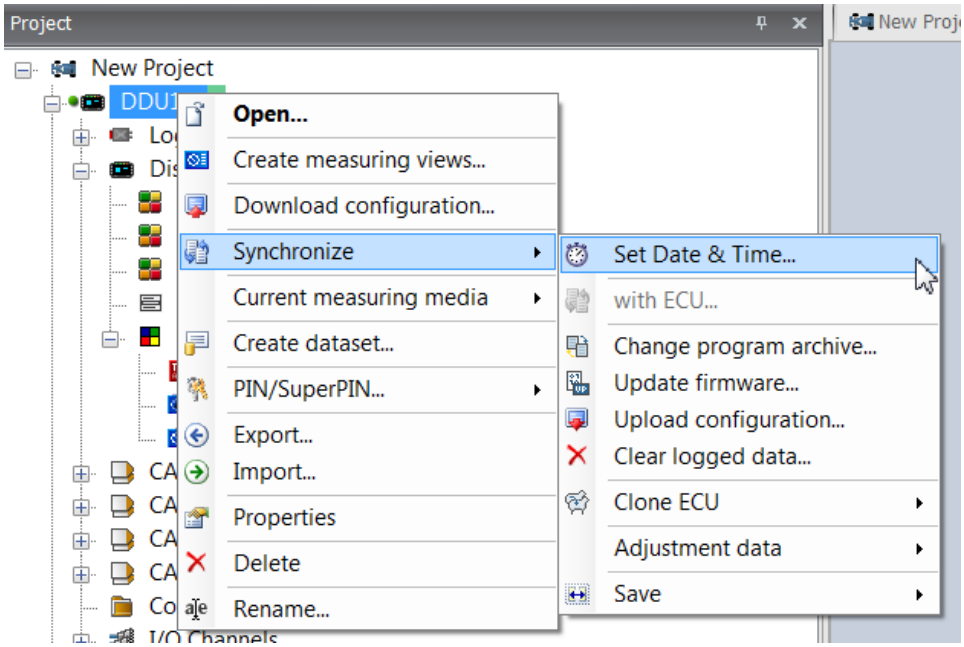
The C 80 is equipped with a real time clock which is supplied by an internal accumulator. Once this accumulator is charged correctly by 12 V supply of the display, ‘Date & Time’ can be programmed by RaceCon.

Reassure that the time is set correctly, if the device has not been used for more than two weeks.

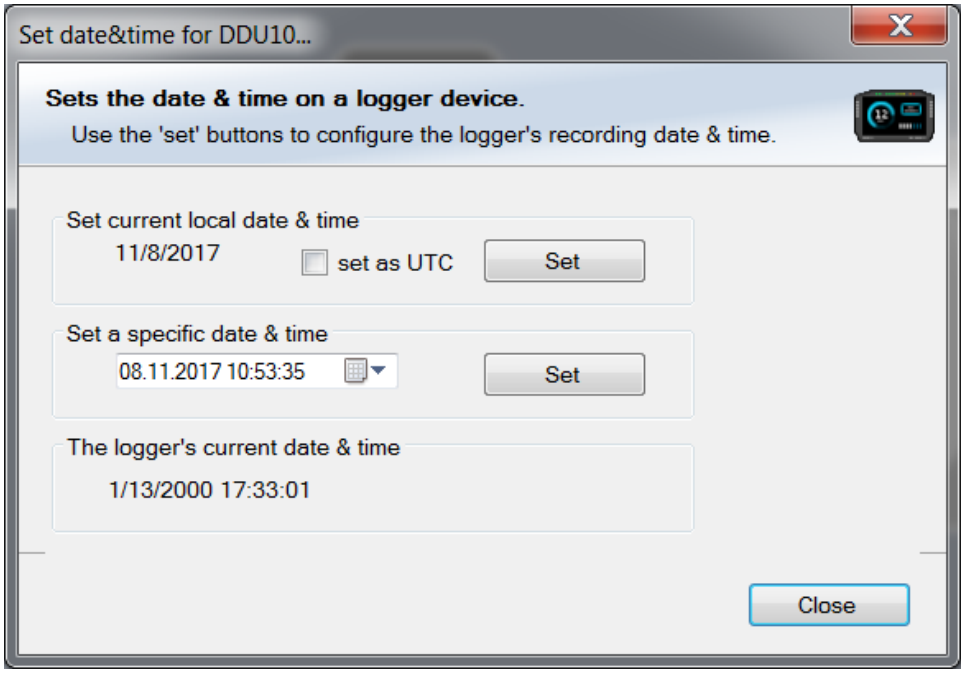
1. Connect the C 80 to the PC.
2. Click on the ‘Set date’ button in the ‘System’ tab menu.



3. Alternatively, click on ‘Set Date & Time’ in the context menu of the device. A ‘Set Date & Time’ menu opens



4. Set the current local date and time as coordinated universal time.
5. At 'Set a specific date & time' click and type on the value you want to change or choose from the dropdown menu.

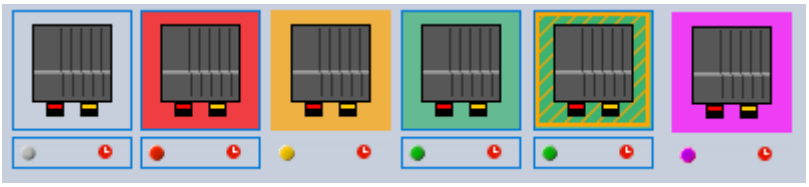


8.6 Color indication

The color indication in RaceCon visualizes different messages, such as differences between tool and device, status of the device configuration or the accrual of errors.

Visible color indications:

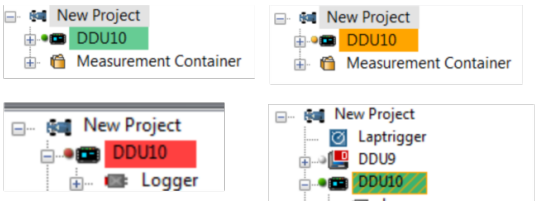
– In the status area in the upper left corner.



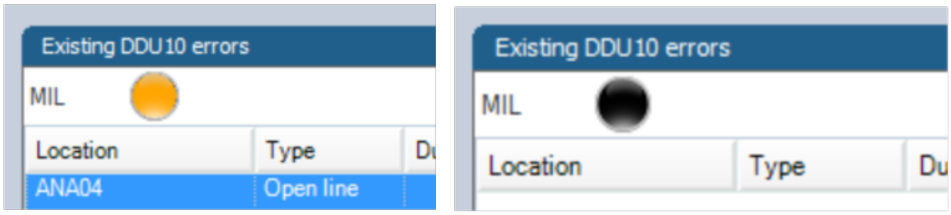
– As a background, as well as a little dot around the display icon in the ‘System window’.

– As a colored stripe beside the device name in the project tree.

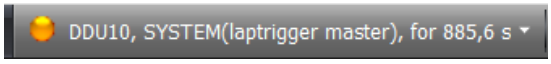
– As a colored background around the device name in the project tree.



– As a colored MIL in the “Error Info” window.



– As a colored dot in the error memory at the bottom.



The colors and their meaning:

– Grey: No connection with the device.

– Green: Matching configuration and firmware between device and project.

– Orange: A different configuration between device and project.

– Red: A different firmware between device and project.

– Purple: Device is bricked, too many resets. Reflash the device, reconsider last changes.

– Colored background with orange stripes: Matching configuration with stored (inactive) errors in the device.

– Blinking colored background with orange stripes: Matching configuration with active errors in the device.

– Black MIL: No errors.

– Orange MIL: Inactive Errors (Error entries existing, but no longer active).

– Blinking MIL (orange/black): Active Errors.

For further information, see chapter Error Memory Properties [▶ 88].

8.7 Assign the Mounting Location

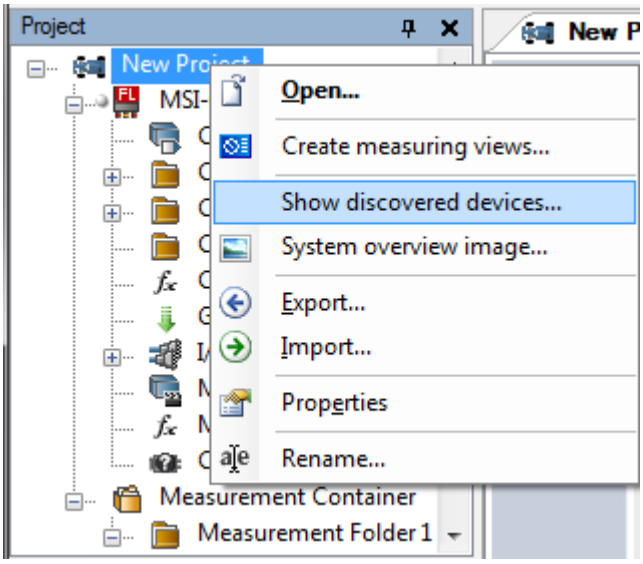
At delivery the default role of the devices is set. There is no need to change this, until you want more than one device of this kind. Up to eight C 80 can be used additionally in one network for I/O expansion and or Multilogging, the mounting location is used for determination between the different C 80.

In case of M60/MSI60, at delivery no mounting location is set. This is signalled by an orange 'RUN' LED on the device. Therefore one must first assign a mounting location to the C 80 before it can be used in the project.

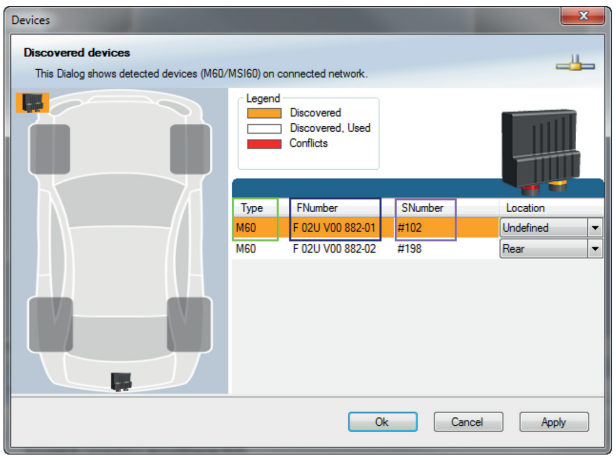
The mounting location is permanently saved in the C 80. If necessary, you can reassign a different mounting location at any time following the same procedure.

A mounting location must not be used several times in one network, this would disturb the functionality of the respective C 80.

1. In the Project Tree right click on the project name e.g. 'New Project' and then select 'Show discovered devices...'.

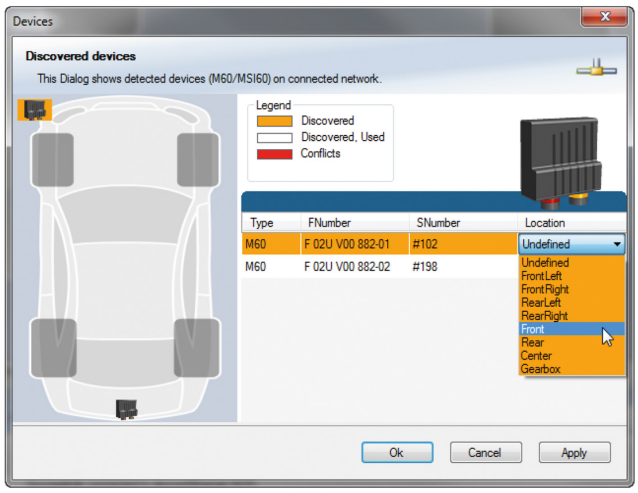


All connected C 80 are listed.

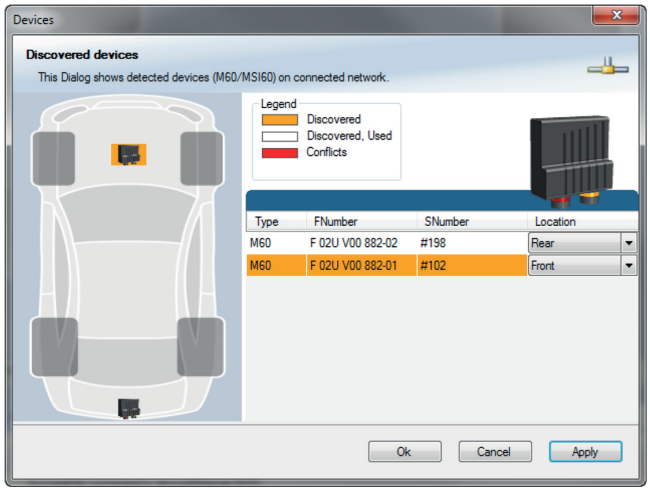


2. Compare the listed device Type, FNumber and SNumber to the identification plate to identify the device you want to make changes to:

3. Assign the desired mounting location (e.g. 'Front') and confirm by clicking 'Apply'.



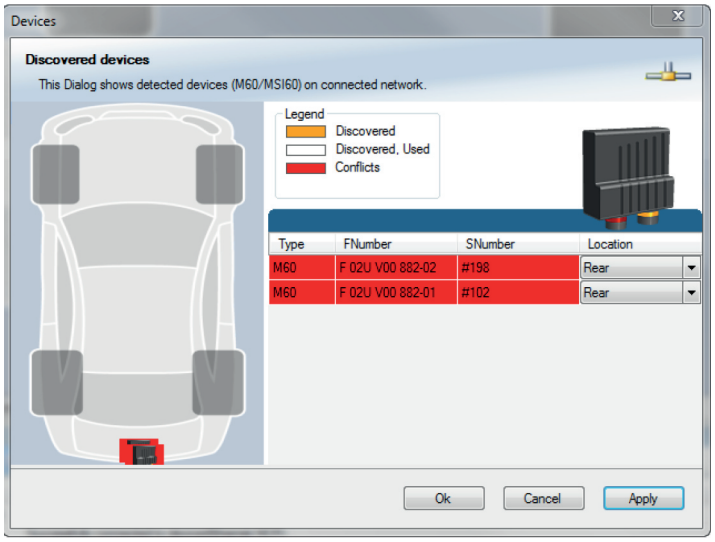
The mounting location is now stored in the device. The device will do a reset and the 'RUN' LED will change to green. The list will show the new mounting location assignment.



It is good practice to physically label the C 80 with its mounting location. Now the device is ready to be used.

A different coloring of the C 80 is used to indicate that the device is already configured in the currently loaded RaceCon project or not (white/orange).

A conflict of several connected C 80 using the same location is indicated by red coloring the involved devices:


Devices
Discovered devices
This Dialog shows detected devices (M60/MSI60) on connected network.
Legend
Discovered
Discovered, Used
Conflicts
Type
FNumber
SNumber
Location
M60
F 02U V00 882-02
#198
Rear
M60
F 02U V00 882-01
#102
Rear
Ok
Cancel
Apply

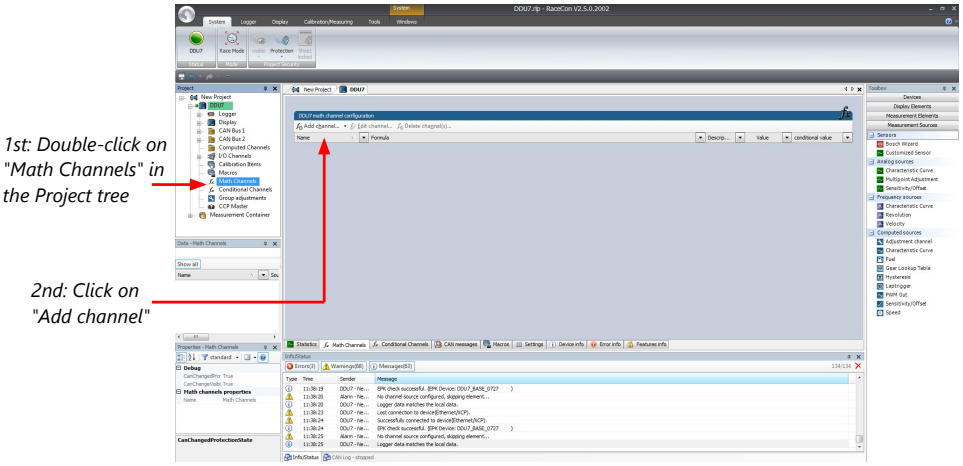
9 Project Configuration

9.1 Math Channels

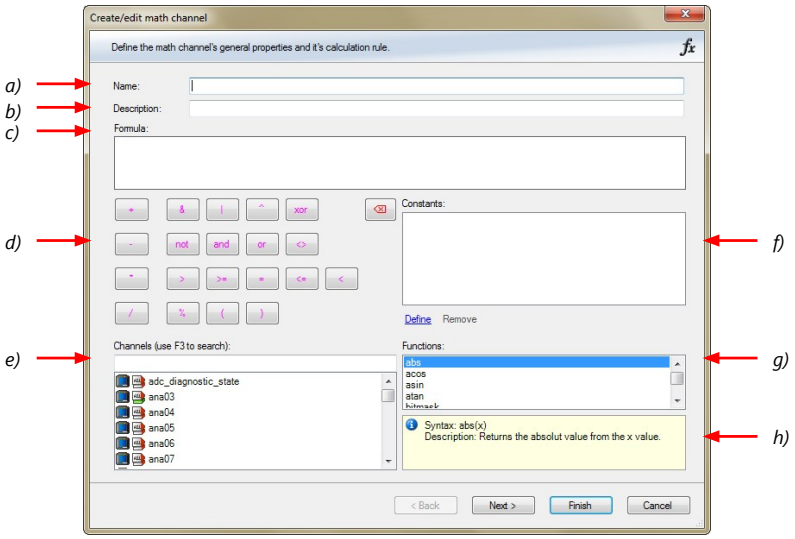
- Arithmetic and logical operations on up to 4 measurement channel(s)
- Numerical result
- Result can be used as input source for various display elements (numeric elements, alarms, bargraphs) and further calculations in the whole RaceCon project

Creating a new Math Channel

1. Follow the steps shown in the screenshot. The “Create/edit math channel” window appears.



2. Define the math channel using the following configuration possibilities:



a) Enter the name of the math channel.
b) Enter a description of the math channel.
c) Enter the formula.
d) Select the logical operator.
e) Choose a measurement channel.
f) Define a value that can be used as a constant in the formula.
g) Choose a function.
h) Describes the function selected above.

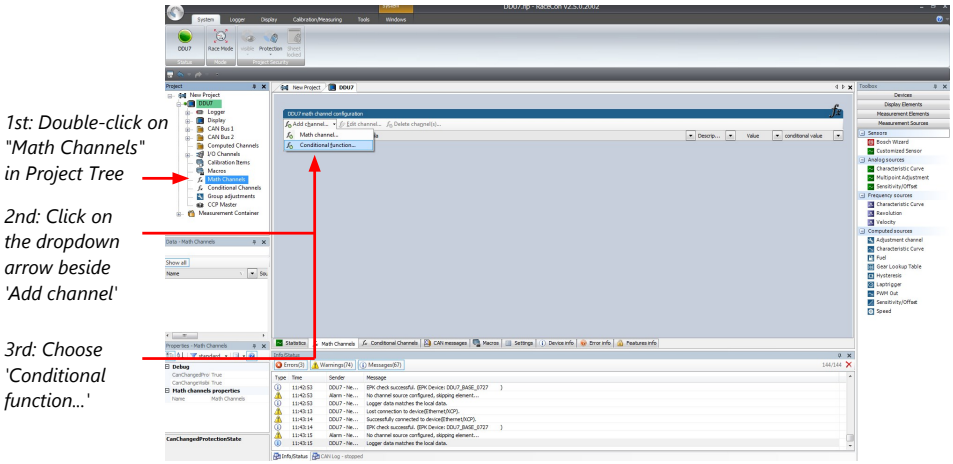
Click ‘Finish’ when done. The math channel is displayed in the math channel window.

9.2 Conditional Functions

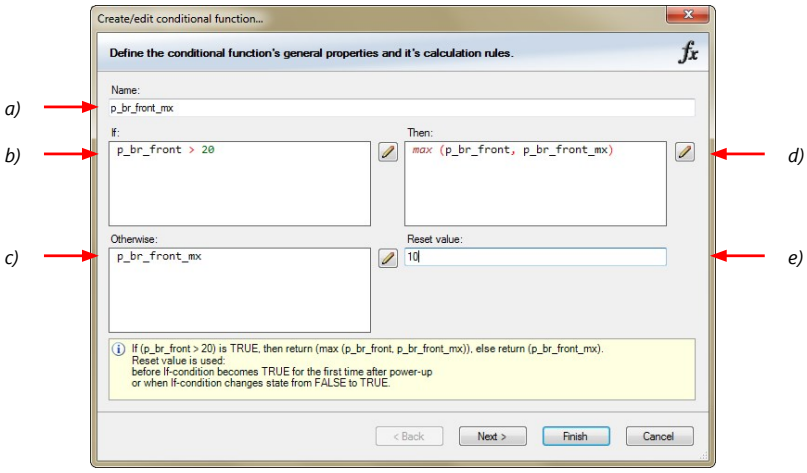
- Arithmetic and logical operations on one or more measurement channel(s)
- If-Else structure with reset
- Numerical result
- Result can be used as input source for various display elements (numeric elements, alarms, bargraphs) and further calculations in the whole RaceCon project.
  All math and conditional channels can be used globally in the whole RaceCon project.

Creating a new Conditional Function

1. Follow the steps shown in the screenshot. The “create/edit math channel” window appears.



2. Define the math channel using the following configuration possibilities:



a) Enter the name of the conditional function.
b) Enter the If-condition. Click pencil symbol to open an editor to enter expressions.
c) Enter the Then-condition. Click pencil symbol to open an editor to enter expressions.
d) Enter the Otherwise-condition. Click pencil symbol to open an editor to enter expressions.
e) Enter the reset value (must be a number).

Click ‘Finish’ when done.

The conditional function works the following way:

The program always calculates the condition entered in the IF window and checks if the condition is TRUE or FALSE.

If the condition entered in the IF window is TRUE, the program calculates the condition entered in the THEN window. The returned value is the content of the new variable (entered in “Name”).

If the condition entered in the IF window is FALSE, the program calculates the condition entered in the OTHERWISE window. The returned value is the content of the new variable (entered in “Name”).

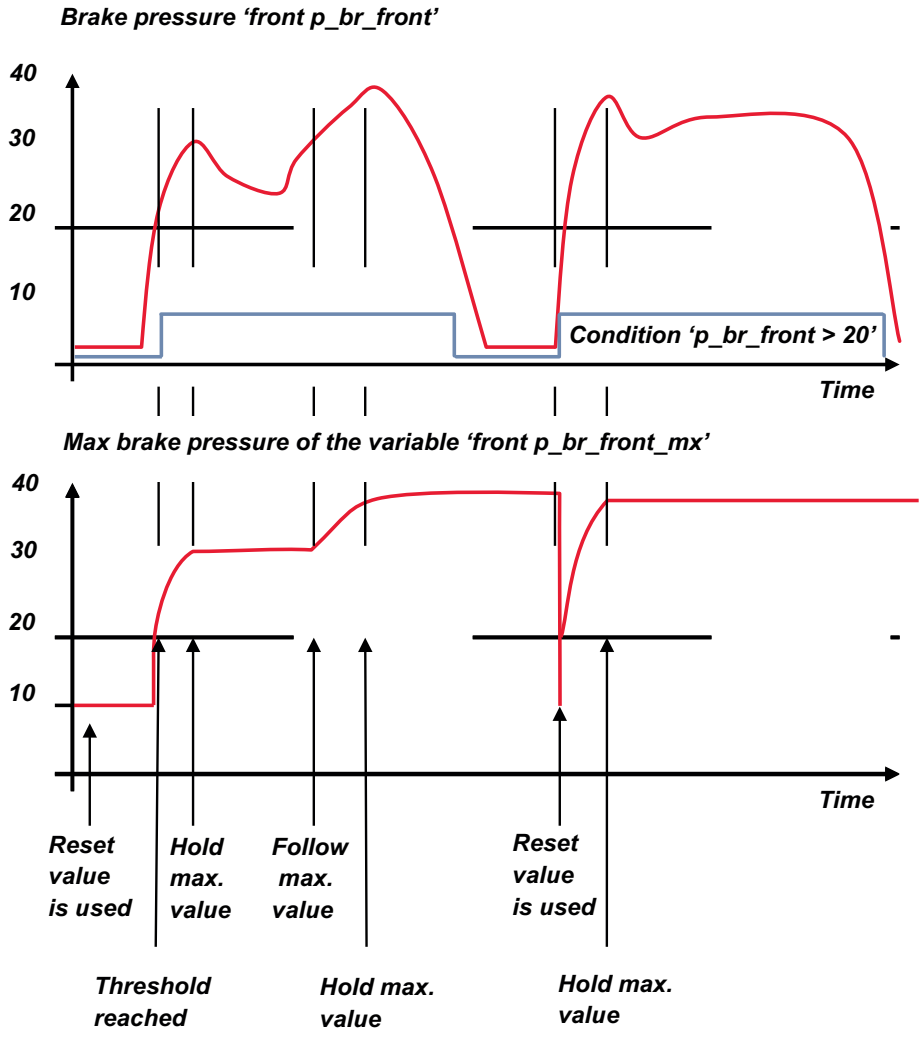
The reset value is always set for the new variable (entered in “Name”):

- before the If-condition becomes TRUE for the first time after power-up
- when the If-condition changes state from FALSE to TRUE.

An example of a condition to set up the maximum front brake pressure is given on the next page.

The conditional function is displayed in the C 80 math channel window.

Example: Setting up a condition for maximum front brake pressure



- At power-up, the reset value (10) is used for ‘p_br_front_mx’.

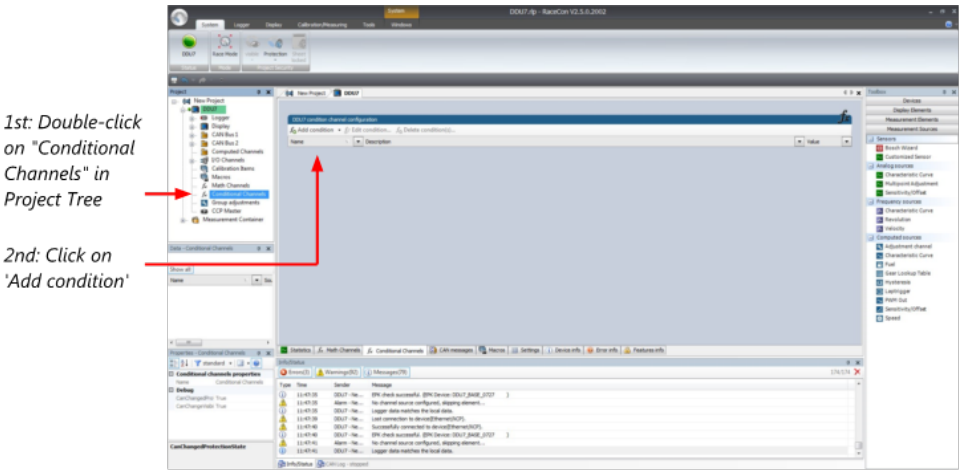
- ‘p_br_front’ rises to 30. As ‘p_br_front’ is > 20 (condition is TRUE), the condition ‘max (p_br_front, p_br_front_mx)’ in the THEN window is triggered. The condition sets the bigger value as new value for ‘p_br_front_mx’. As ‘p_br_front’ (30) is bigger than ‘p_br_front_mx’ (10), the new value for ‘p_br_front_mx’ is set to 30.
- Although ‘p_br_front’ falls to 25, the value of ‘p_br_front_mx’ stays 30. This is caused by the THEN-condition, because p_br_front_mx’ (30) is still bigger than p_br_front’ (25).
- ‘p_br_front’ rises to 40. As ‘p_br_front’ (40) is bigger than ‘p_br_front_mx’ (30), the new value for ‘p_br_front_mx’ is set to 40.
- As ‘p_br_front’ falls below 20, the IF-condition turns to FALSE. Now the OTHERWISE-condition is triggered. Because the condition ‘p_br_front_mx’ sets the value of ‘p_br_front_mx’ and the value is already set to 40, nothing changes.
- When ‘p_br_front’ rises to 40, the IF-condition changes to TRUE again and triggers the THEN-condition. Now the reset value (10) is used for ‘p_br_front_mx’ in the THEN-condition.
- The new value of ‘p_br_front_mx’ is 40 because 40 is bigger than 10.

9.3 Conditional Channels

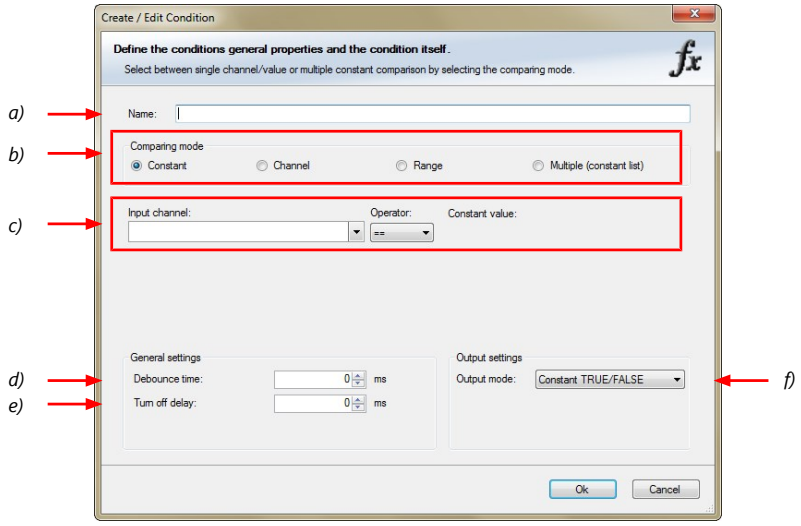
- Logical operations on measurement channel(s)
- If-Else structure with reset
- Logical result
- Result can be used as input source for alarm display elements and further calculations in the whole RaceCon project.

Creating a new Conditional Channel

1. Follow the steps shown in the screenshot. The “Create/edit condition” window appears.



2. Define the condition channel, using the following configuration possibilities:



a) Enter the name of the conditional channel.

b) Select the comparing mode:

- Constant: Compare a measurement channel with a constant value.
- Channel: Compare a measurement channel with a measurement channel.
- Range: Compare a measurement channel with a defined value range.
- Multiple: Compare a measurement channel with up to 5 constant values.

c) Depending on the chosen comparing mode, you can enter the following values:

- Constant: Choose the measurement channel or condition, the operator and enter the value of the channel.
- Channel: Choose the measurement channel or condition, the operator and the measurement channel or condition to be compared.
- Range: Choose the measurement channel or condition, the operator and define the minium and maximum value.
- Multiple: Choose the measurement channel or condition, the operator and enter the value of up to 5 constants.

d) Enter the minimal time to detect the signal of the measurement channel, to avoid high-frequent switchovers.

e) Enter the time by which the signal of the measuring channel is delayed after its end.

f) Choose the output setting of the result.

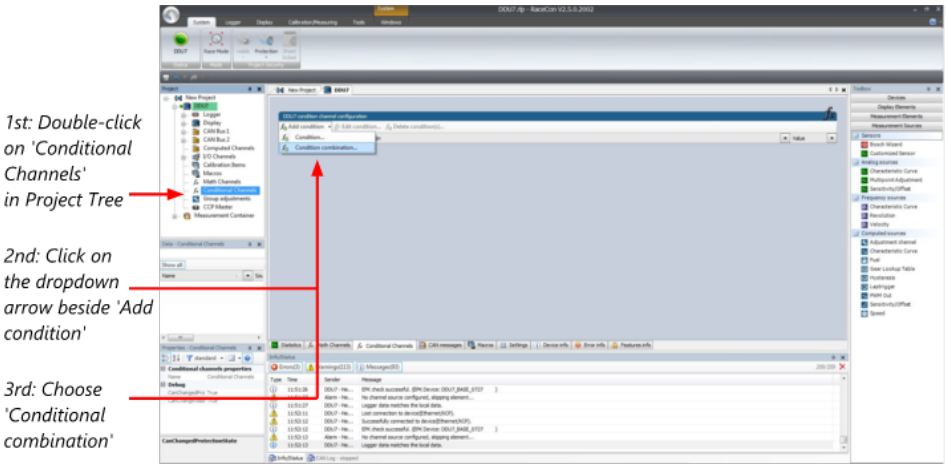
- Constant TRUE/FALSE: Result is as a constant with the value TRUE or FALSE.
- Blinking: Result is a blinking, if the condition is fulfilled.
- Pulse: Result is a short one-time pulse, if the condition is fulfilled.
- Toggling output: Result is a pulse that lasts until the next condition is fulfilled.
- Click ‘Ok’ when done. The conditional channel is displayed in the C 80 condition channel window.

9.4 Condition Combination

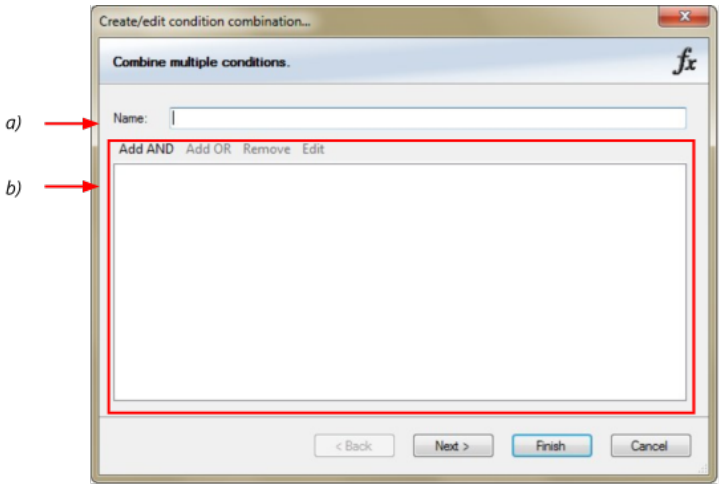
- Combination of several (up to 16) conditional channels for more complex calculations
- Logical results
- All conditions can be used globally in the whole C 80 project.

Creating a new Condition Combination

Follow the steps shown in the screenshot.



The "Create/edit condition combination" window appears. Define the condition combination, using the following configuration possibilities:

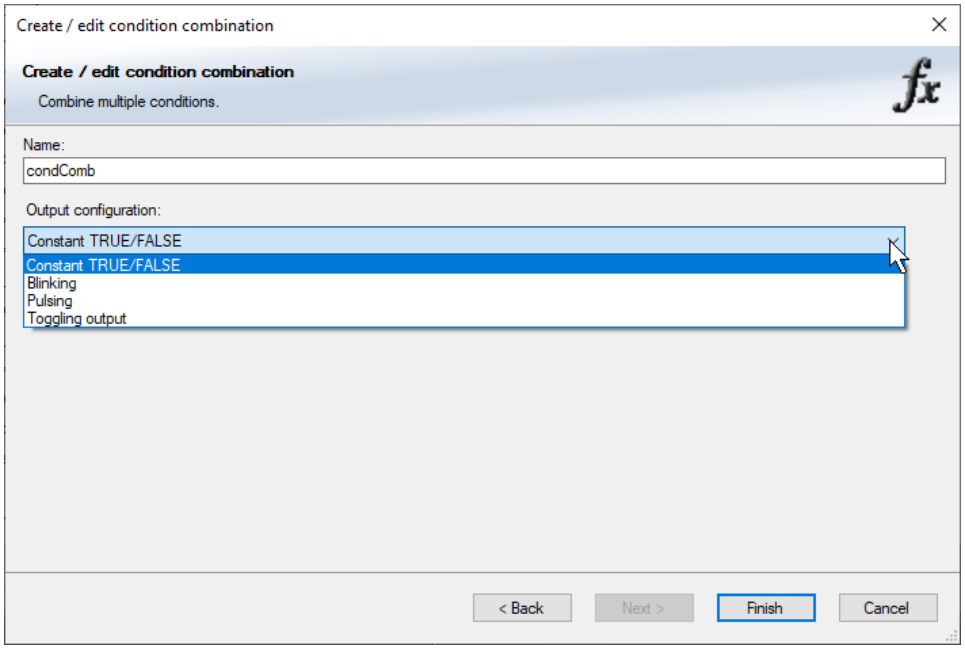


a) Enter the name of the condition combination.

b) Create the condition combination in the window.

- Choose a channel (condition, conditional function, math, measurement channel with binary values) to be compared.
- Combine multiple conditions, by adding 'AND' or 'OR' relations.
- To negate a condition, click with the right mouse-button on the condition and select 'Negation (!)'.
- Combine several (up to 16) conditions.

Click 'Next' to go to the next page. Choose the output setting of the result:



- Constant TRUE/FALSE: Result is as a constant with the value TRUE or FALSE.
- Blinking: Result is a blinking, if the condition is fulfilled.
- Pulsing: Result is a short one-time pulse, if the condition is fulfilled.
- Toggling output: Result is a pulse that lasts until the next condition is fulfilled.

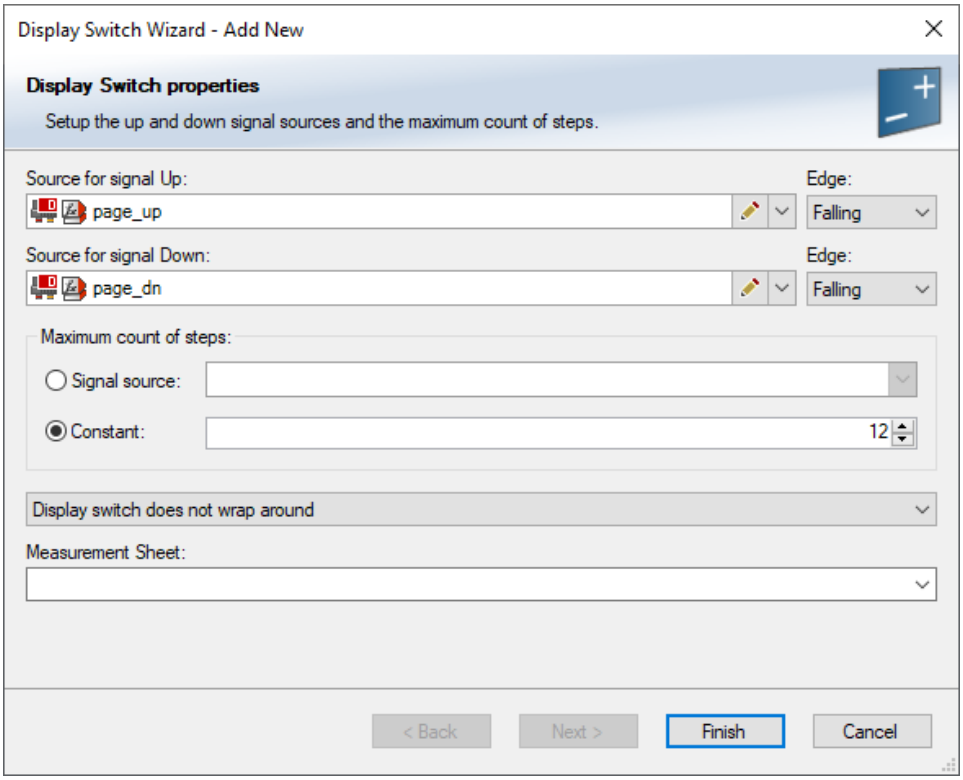
Click ‘Finish’ when done. The conditional combination is displayed in the C 80 condition channel window.

9.5 Display Switch Module

You can use the Display Switch Module to switch display pages and brightness. The output is a display page or brightness output that can be used in display configurations. The value sustains over a power cycle.

The conditions for incrementing/decrementing the value can be set freely. The maximum value can be set as constant or read from a measurement.

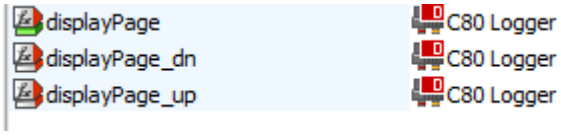
The page can be configured to wrap around. In this case, no page down condition is needed.



The resulting outputs are the display switch value and the input conditions.

Measurement label	Function
name	page or brightness value
name**_dn**	input condition for decrement
name**_up**	input condition for increment

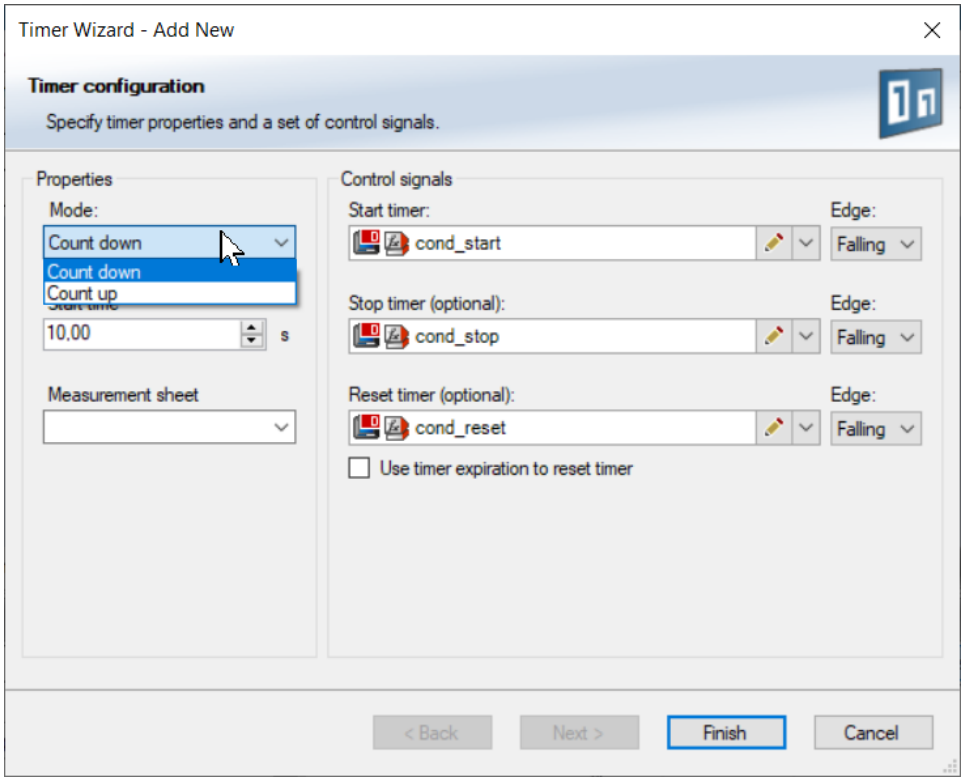
Example:



9.6 Timer Module

The Timer Module is designed to implement timing triggers, i.e. for rallye stage timing or minimum pit time calculations. Any event in the system can be used for starting, stopping and resetting the timer.

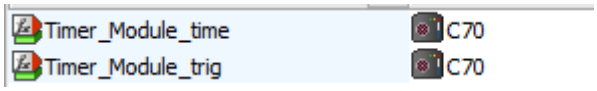
Up counting mode and down counting mode are available, triggers are fired at set time (up counting) or at zero (down counting). The running timer will keep its state over a power cycle.



The output channels for this module depend on the name used for the module and are called ..._time and ..._trig.

Measurement label	Function
name_**time**	actual timer value
name_**trig**	trigger set by timer alarm

In this example, the module is named “Timer_Module”. Resulting channels are:

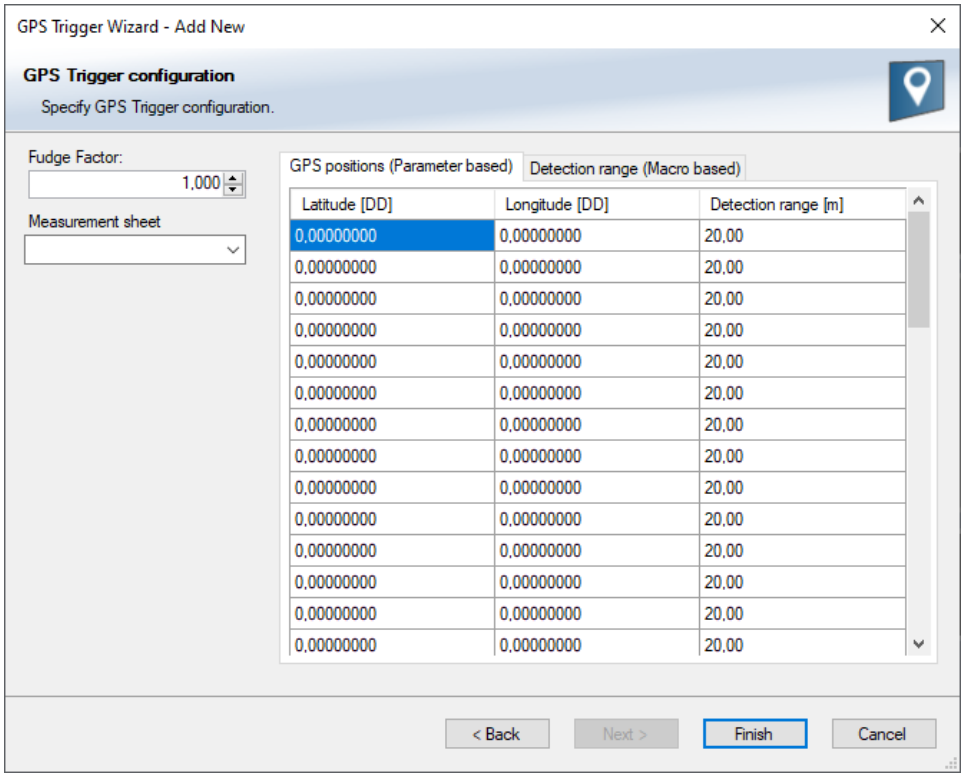


9.7 GPS Trigger Module

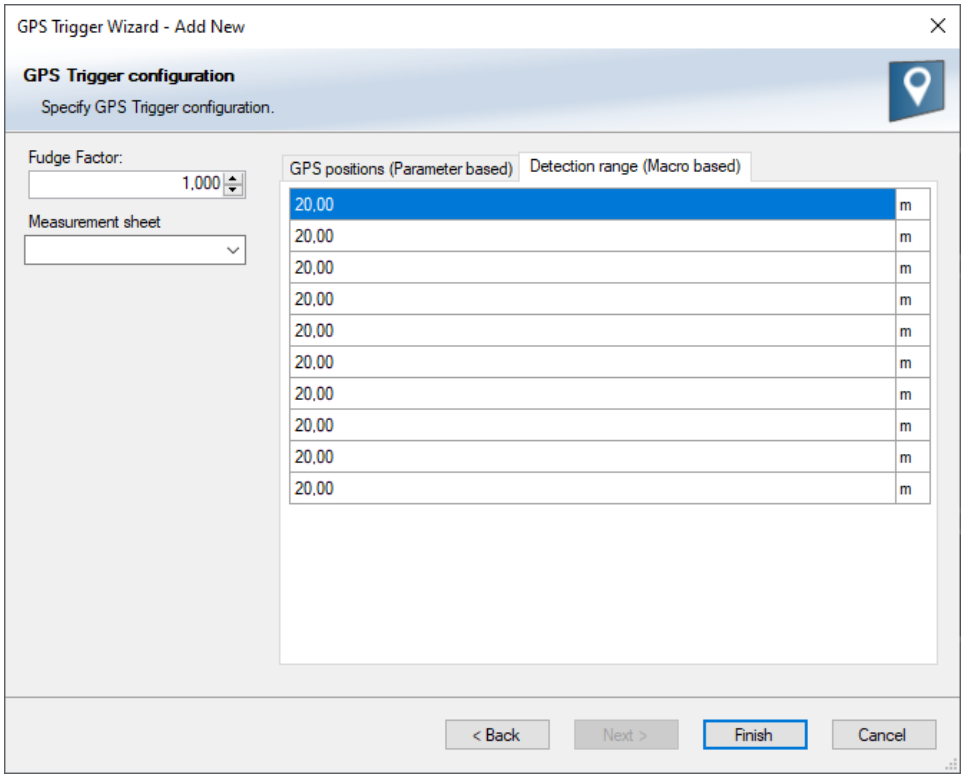
The GPS Trigger Module triggers depending on GPS-position, like the GPS-laptrigger.

There are 50 GPS trigger points for parameter application of latitude/longitude coordinates, as well as 10 macro-based coordinates.

If the car passes one of the trigger points, an output signal is set to 1 shortly. Each trigger requires a defined latitude, longitude, and detection range.



The parameter-based trigger points need to be set manually in RaceCon, the macro-based trigger points will store latitude and longitude values when the configurable trigger condition comes true (i.e., steering wheel button). This trigger condition and the detection range need to be configured in RaceCon.

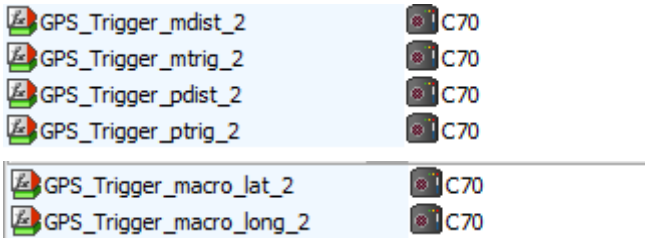


The GPS trigger points can also be used for segment triggering. If used as segment triggers and i.e., 3 trigger points are selected, the laptrigger module will use the first 3 trigger points on the list.

The channel names depend on the name used for the module, in this example GPS_Trigger. Each trigger has a distance and a trigger channel with the abbreviation m for macro or p for parameter based. The trigger channel will be set to 1, when the lowest distance to the trigger point is detected. For the macro-based trigger, the stored latitude and longitude values can be seen with the channels.

Measurement label	Function
name_**lat**	interpolated gps latitude
name_**long**	interpolated gps longitude
name_**ptrig_1..50**	trigger output of parameter based trigger (n)
name_**pdist_1..50**	distance to trigger of parameter based trigger (n)
name_**mtrig_1..10**	trigger output of macro based trigger (n)
name_**mdist_1..10**	distance to trigger of parameter based trigger (n)
name_**macro_lat_1..10**	stored latitude for macro based trigger (n)
name_**macro_long_1..10**	stored longitude for macro based trigger (n)

Example:



9.8 CPU Load Limits

As all microprocessors, the two processors of the C 80 have limited capacities. The current load of the processors can be monitored using the channel “cpu_load_001” or “cpu_load_002”. When configuring your device, please make sure the used CPU load is in a save range below 100 %.

Bosch recommends a maximum CPU load of 85 % (averaged). Exceeding this limit might result in the C 80 not being able to fulfill its required measuring/logging/display tasks or even in crashing and rebooting.

Main factors influencing the CPU load are:

- Number and complexity of math channels
- Number and complexity of conditions
- CAN traffic on both CAN lines
- Display configuration, especially displaying pictures
- Logger configuration (total logging rate [kB/s], conditional measurement rates)

To help respecting the limit of 85 % CPU load, the C 80 creates an error memory entry. To trigger this error entry, the CPU load must exceed the limit for 5 minutes without interruption.

When being confronted with this error memory entry (see ‘Error info’ in RaceCon) or when being confronted with C 80 resets due to complex configuration setups, please consider reducing the demands on the C 80 adapting the influencing factors mentioned above.

10 CAN Configuration

The C 80 has 2 fully configurable CAN bus(es).

- Baudrate 125 kbaud to 1 Mbaud
- 11 Bit or 29 Bit identifiers
- Input configuration: Read messages from CAN bus and convert to C 80 measurement/display variables. CAN bus supports row counter configuration.
- Output configuration: Write RaceCon measurement variables to CAN messages; output frequency and row counter are configurable, CAN gateway functionality (transfer from one bus to another).

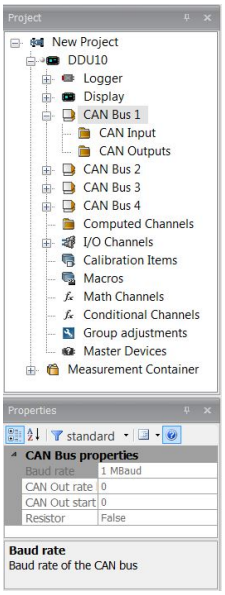
10.1 CAN Bus Trivia

CAN Message

- 11 Bit (standard) or 29 Bit (extended) identifier
- Up to 8 bytes of data payload

CAN Bus

- Needs termination resistors in wiring harness
- All devices connected to the bus must use identical data rate
- Configuration of bus data rate in the 'CAN messages overview' menu. To access the menu, double-click on one of the CAN bus items of the project tree



Row Counter Concept

- Re-use (multiplex) of message identifiers
- One byte of message contains row counter
- 7 bytes payload remaining
- Position of row counter is configurable

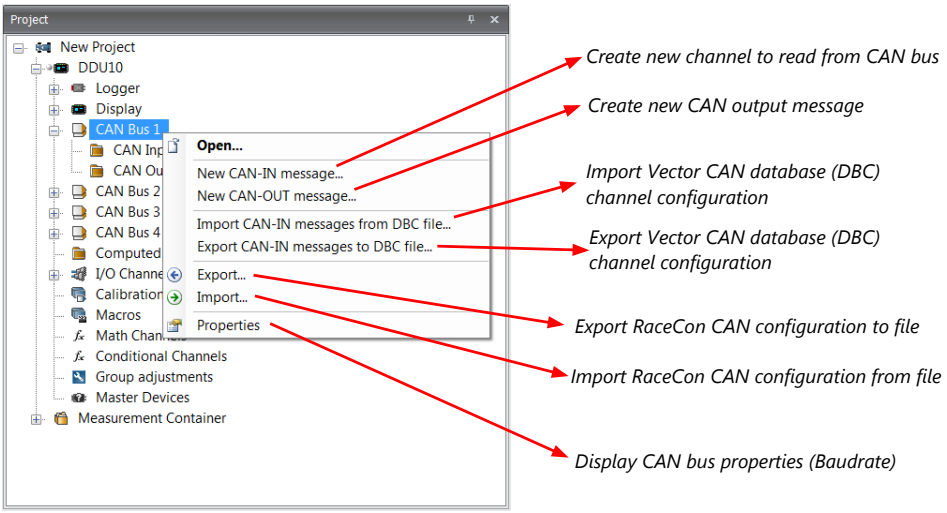
	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
0x100	0	p_oil		t_oil				
0x100	1	s_dam_fl		s_dam_fr				
0x100	2	s_dam_rl		s_dam_rr				

Message Id ***Row Counter*** ***Payload Area***

10.2 CAN input

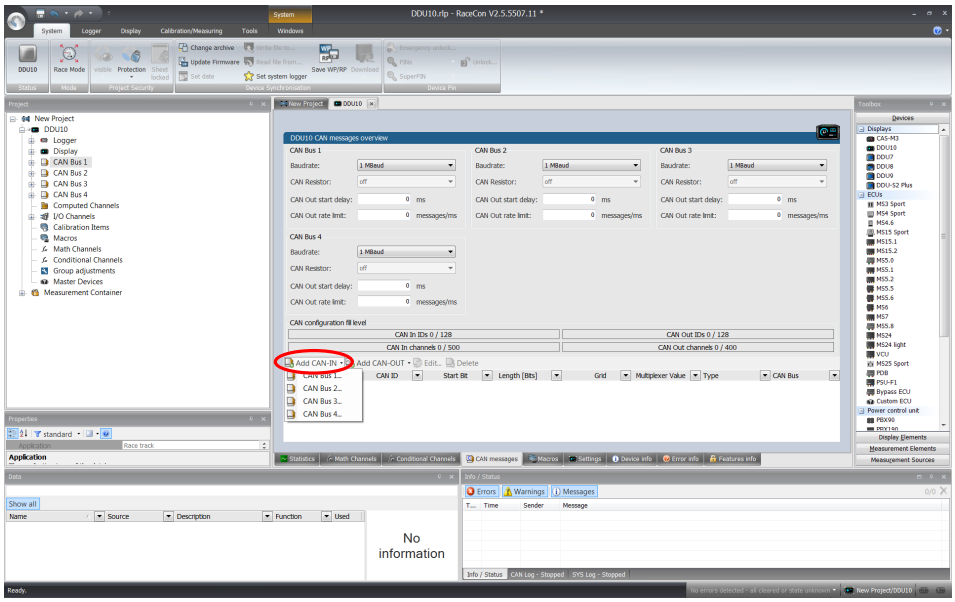
10.2.1 Input configuration

Click with the right mouse button on the desired CAN bus to open the CAN bus drop-down menu.



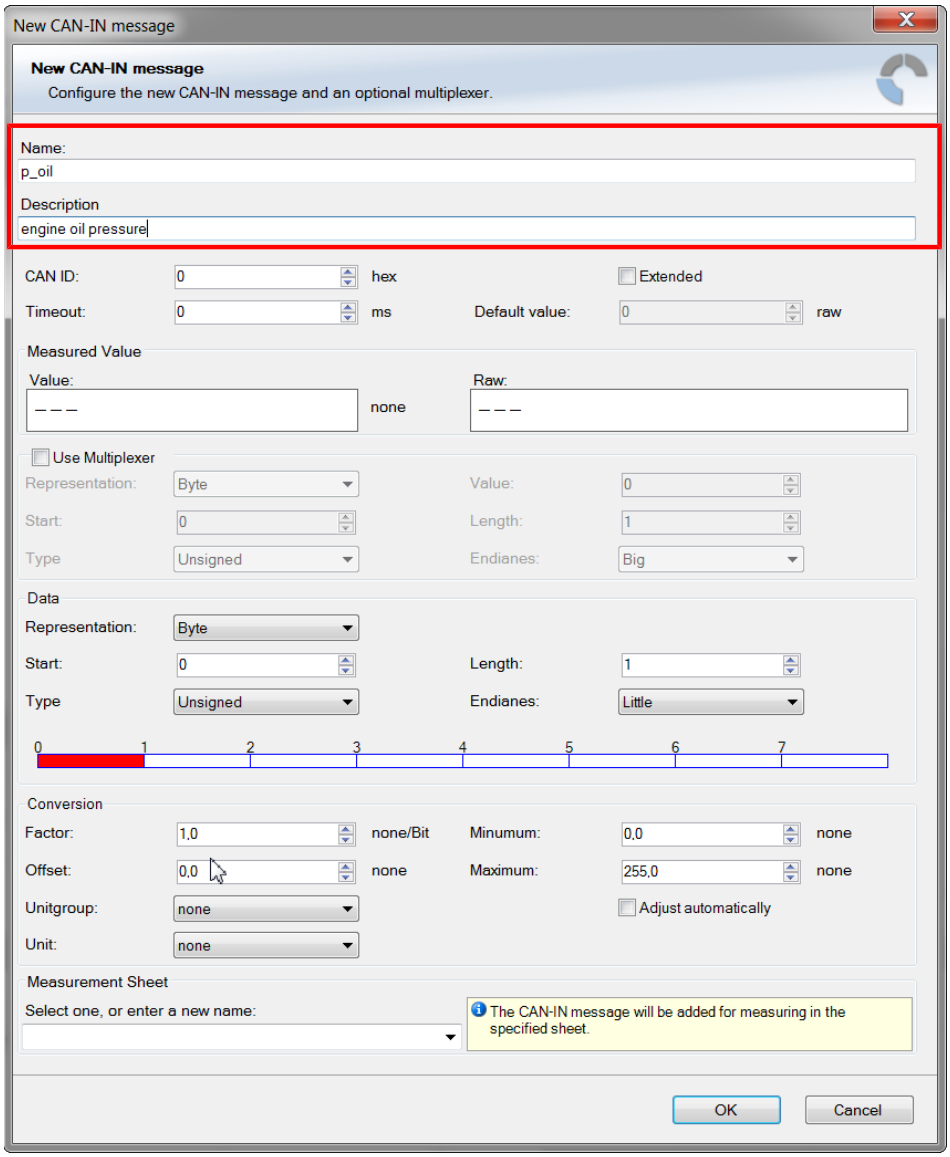
10.2.2 Create new CAN Input channel

1. Double-click on any CAN bus item, to open the "CAN messages overview".
2. Select ‘Add CAN-IN’ and choose the desired CAN bus for the new input channel.

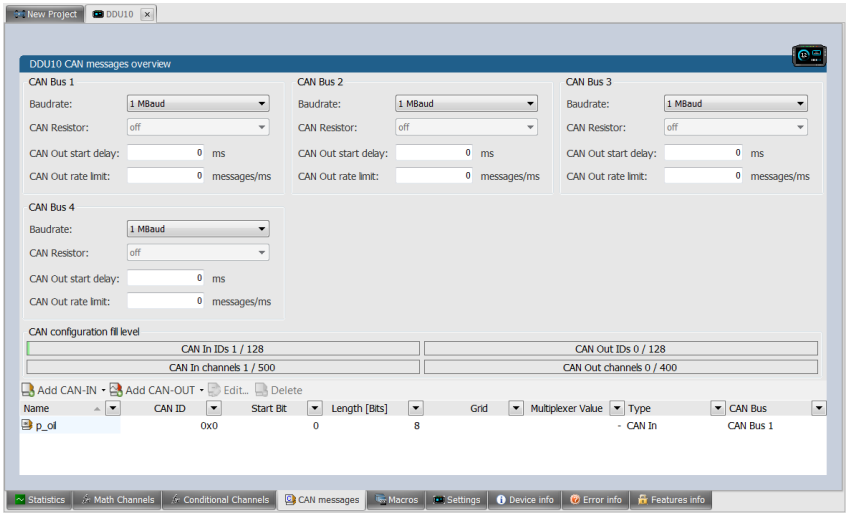


3. A CAN channel configuration window opens.

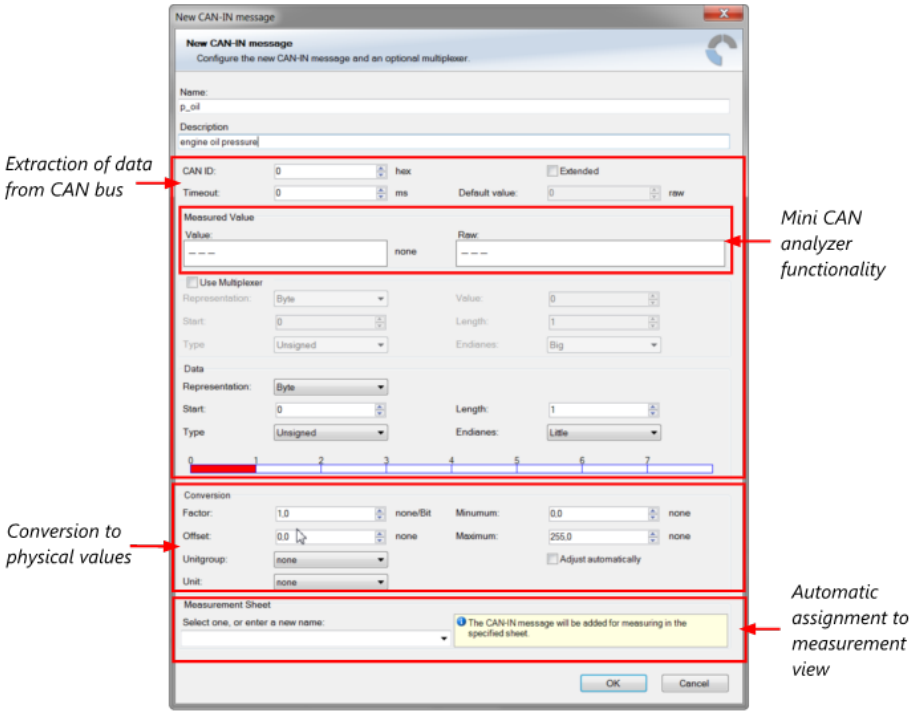
4. Insert the name and description of the channel.



5. Click ‘OK’ when done.
   The channel is listed in the Data window.



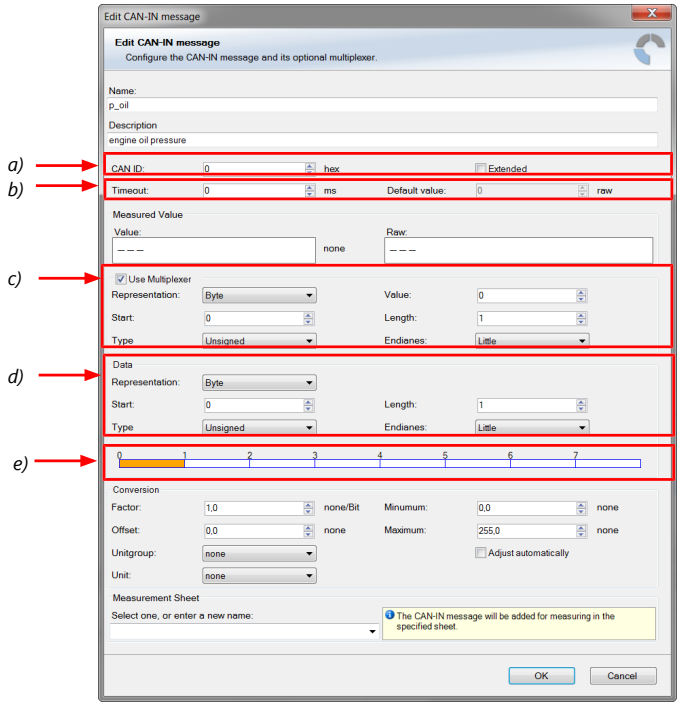
CAN channel configuration



10.2.3 Extracting data from CAN bus

Representation: Byte

Some CAN devices need to be addressed by a byte represented CAN channel. The address can be assigned in this window and is illustrated by a bargraph.



a) Enter CAN message ID. If extended IDs (29 bit) are used, check the box.

b) If replacement values are used, specify time-out period and raw value.

c) If a multiplexer (row counter) is used, check the box.

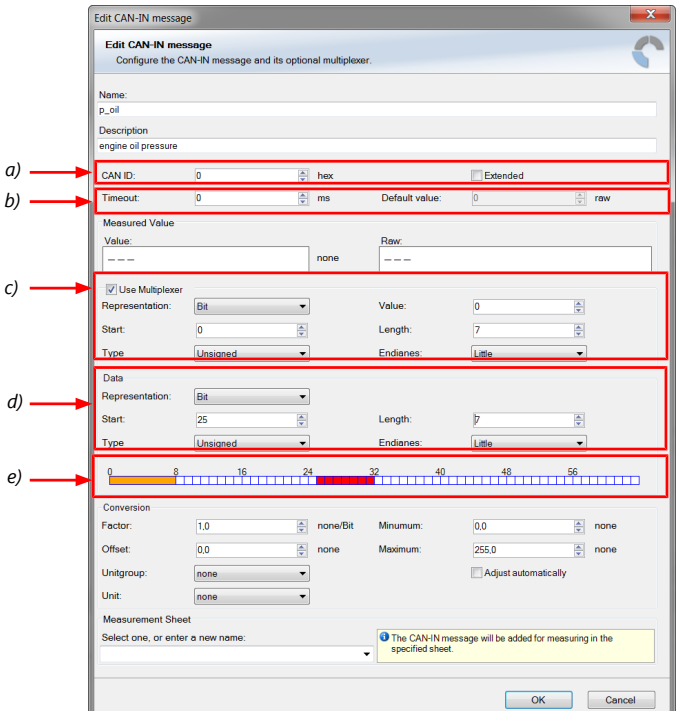
d) Enter data position, length and format.

e) The bargraph shows assignment of the bytes.

- Red colored fields show the assignment of the data bytes.
- Orange colored fields show the assignment of the multiplexer bytes.

Representation: Bit

Some CAN devices need to be addressed by a bit represented CAN channel. The address can be assigned in this window and is illustrated by a matrix table.



a) Enter CAN message ID. If extended IDs (29 bit) are used, check the box.

b) If replacement values are used, specify time-out period and raw value.

c) If a multiplexer (row counter) is used, check the box.

d) Enter data position, length and format.

e) The bargraph shows assignment of the bytes.

- Red colored fields show the assignment of the data bytes.
- Orange colored fields show the assignment of the multiplexer bytes.

Conversion to physical value

a) Enter factor (gain) for conversion to physical value.

b) Enter offset for conversion to physical value.

c) Select type of physical value.

d) Select unit of physical value.

e) Enter minimum physical limit of the channel. (for manual setup)

f) Enter maximum physical limit of the channel. (for manual setup)

g) Check the box to automatically adjust the limits of the channel.

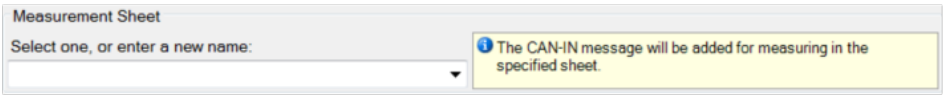
CAN analyzer functionality

This functionality is only available, if a MSA-Box (I or II) is used to connect the C 80 to the PC. Choose the CAN bus that is connected to the MSA-Box to display the raw value and the converted physical value here.

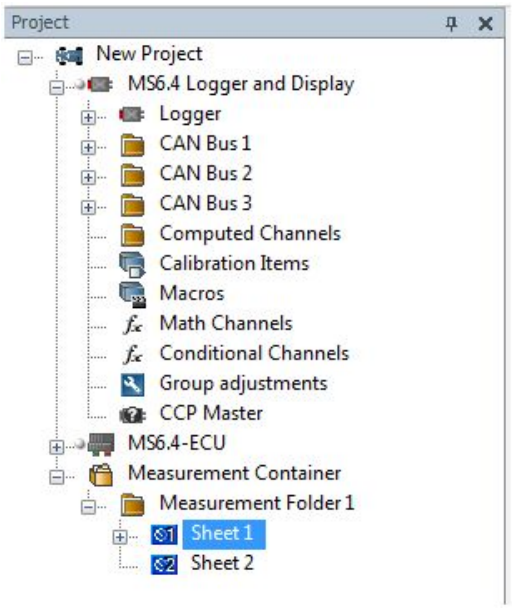
Automatic creation of online measurement sheets

The CAN channel can be automatically inserted into a measurement sheet. Insert a name for a new sheet or select an existing sheet from the list box.

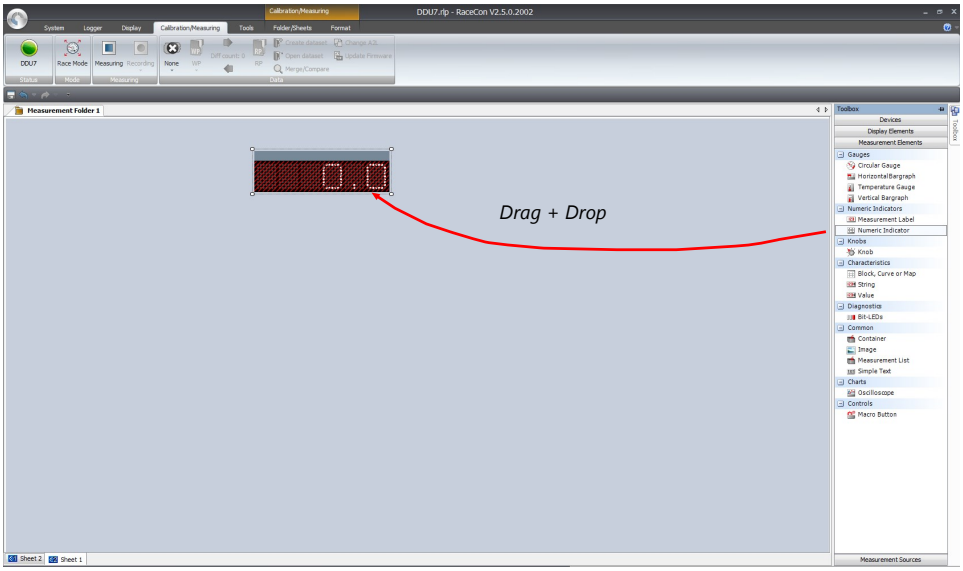
For an online view of the value measured by the C 80, insert the channel in an online measurement sheet which is described in the chapter Setting up an online measurement [▷ 77].



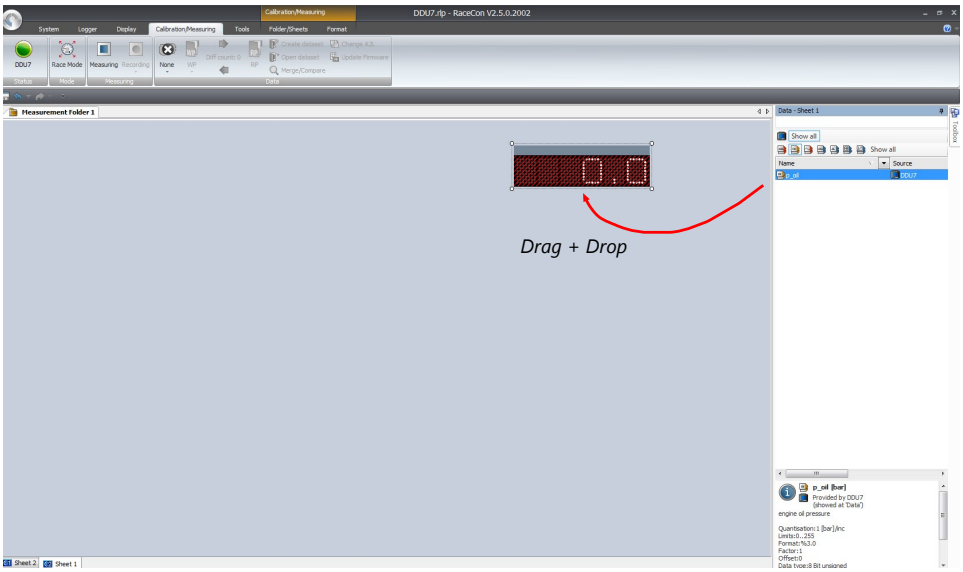
10.2.4 Online view of CAN channels in vehicle



1. Double-click on ‘Sheet 1’ in Project Tree. Measurement Sheet 1 is displayed in Main Area.
2. Click on ‘Measurement elements’ in the Toolbox.
3. Drag the desired Measurement element (e.g. Numeric Indicator) and drop it on the Measurement Sheet.



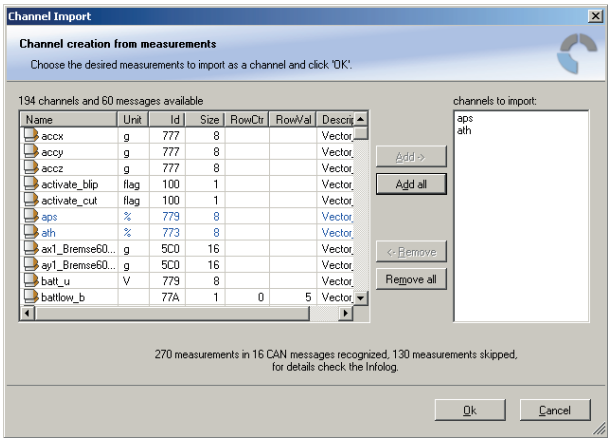
4. Click on folder ‘CAN Input’ of desired CAN bus to display available channels.
5. Drag desired Measurement channel and drop it on the Measurement element.



6. The measurement element displays the values of the assigned channel.
7. Connect PC to the vehicle and switch to ‘Race Mode’ by clicking ‘F11’ on the keyboard to display online data.

10.2.5 Import a CAN database (DBC) file

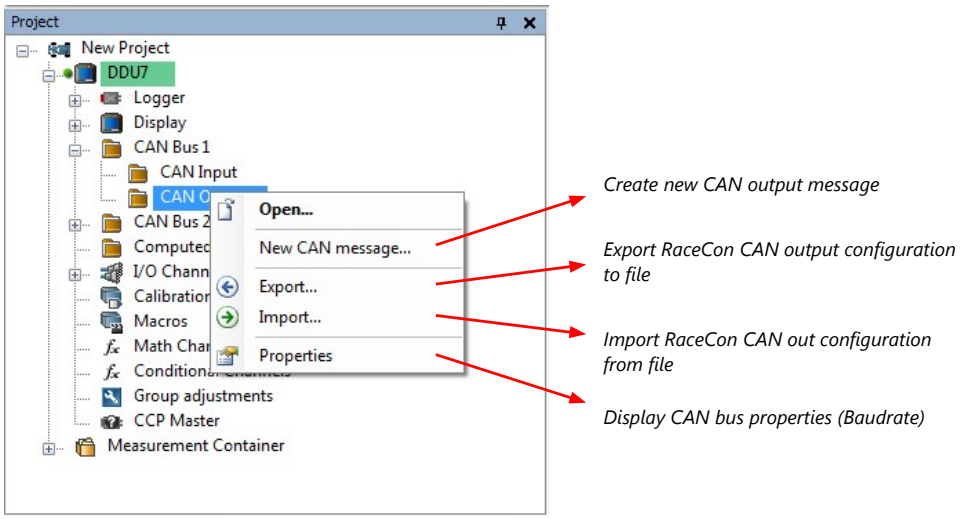
1. Right-click on CAN Input of desired bus (CAN1 or CAN2).
2. Select ‘Import DBC file’ from menu. A file browser opens.
3. Select DBC file to import and click ‘OK’ when done. A channel import window opens.



4. Select desired channels on the left and use the ‘Add’ button to add them to import list.
5. Click ‘OK’ when complete. The channels are inserted in the Data window.

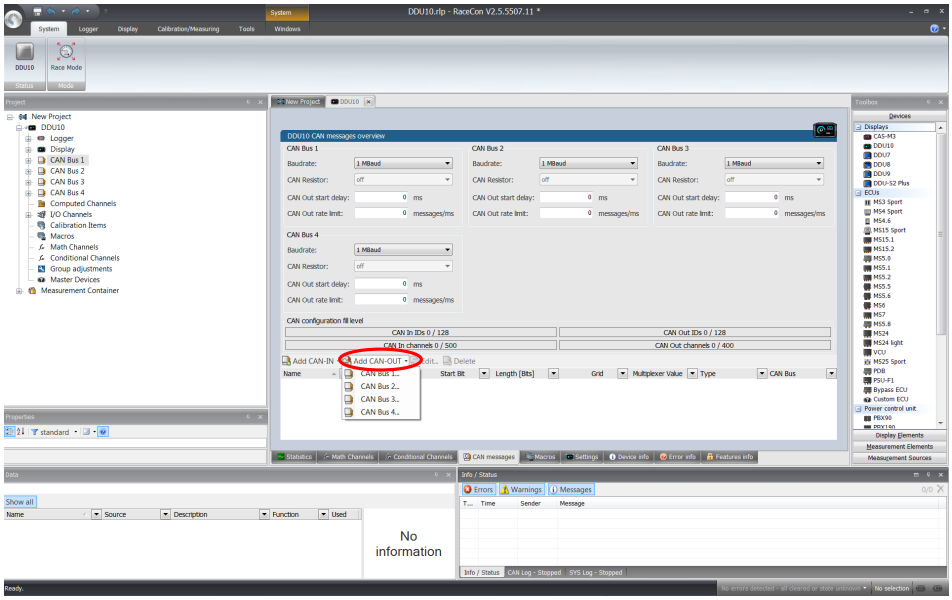
10.3 CAN output

10.3.1 Output configuration

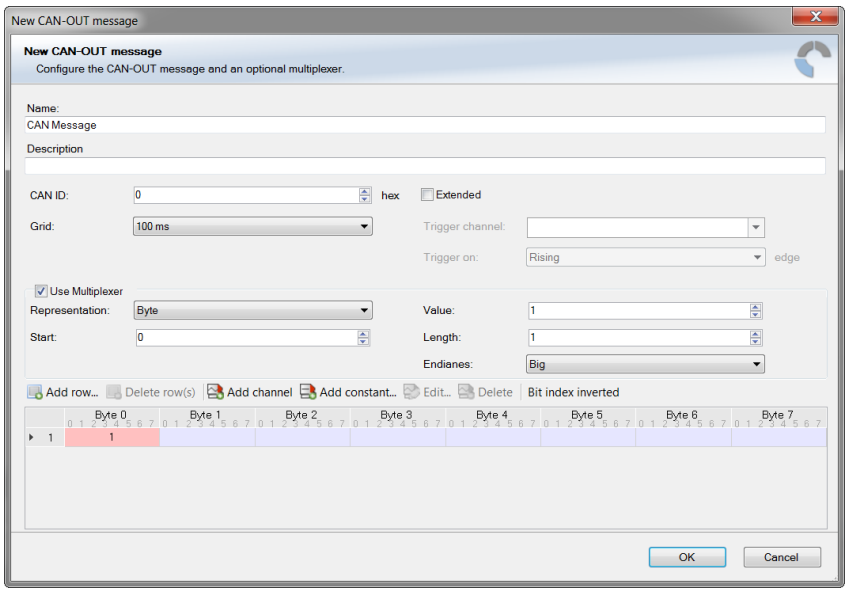


10.3.2 Create a new CAN output message channel

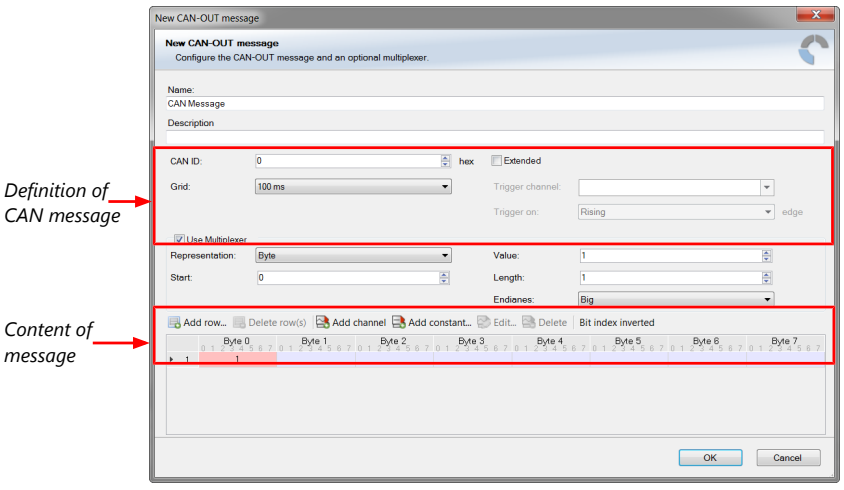
- Double-click on any CAN bus item to open the "CAN messages overview".
- Select ‘Add CAN-OUT’ and choose the desired CAN bus for the new output channel.



– The ‘New CAN-OUT message’ window opens.

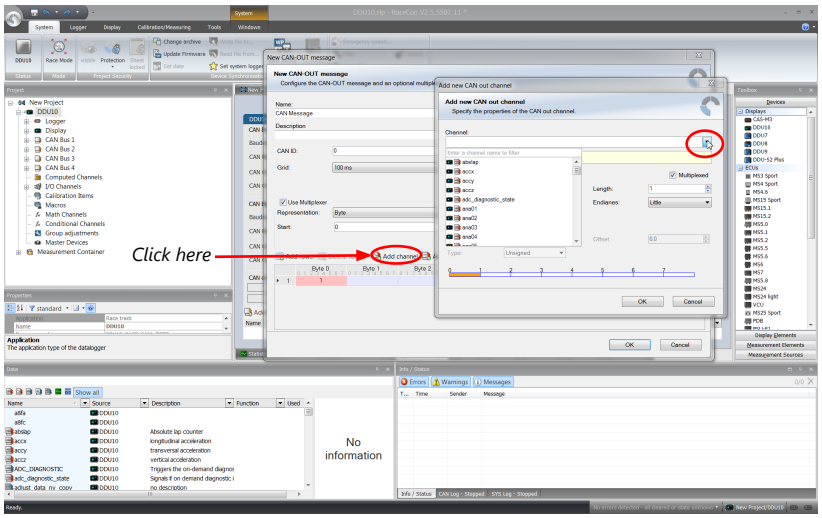


– Enter name of message, description, CAN-Id, and Grid (output interval). Optionally, specify a multiplexer.



– Click on ‘Add channel...’ or ‘Add constant...’, this opens the ‘Add new CAN out channel’ window.

– Select the desired measurement channel and specify the message settings.

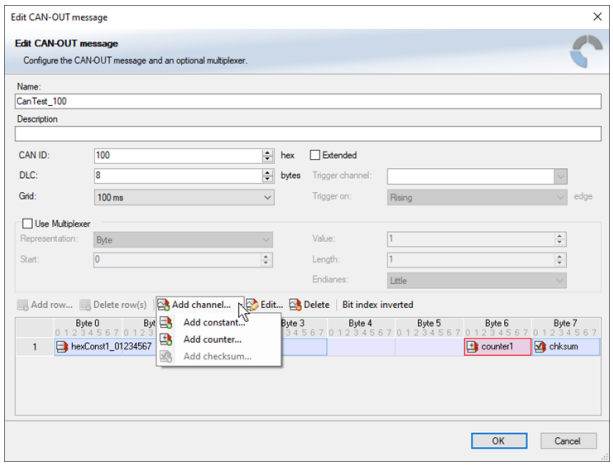


The measurement channel is now assigned to the CAN message.

10.3.2.1 Add CAN out constant

To send a constant value on the CAN, perform the following steps:

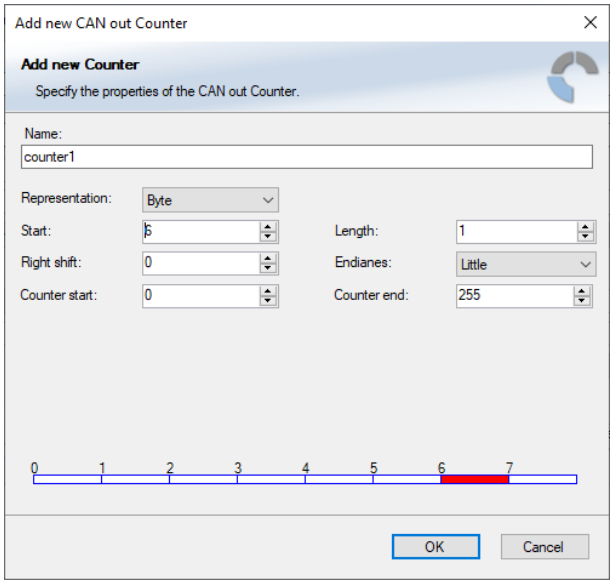
1. Create a new CAN output message or edit an existing message.
2. Click small arrow beside ‘Add channel...’ and select ‘Add constant...’. The ‘Add new CAN Out constant’ window appears.
3. Define the name of the constant, the required value in hex and define the CAN channel settings.
4. Click ‘OK’ when done.



10.3.2.2 Adding CAN out counter

To send a counter value on the CAN, perform the following steps:

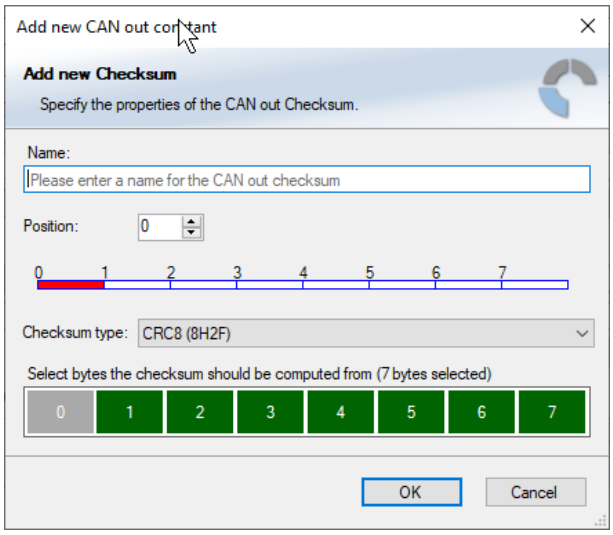
1. Create a new CAN output message or edit an existing message.
2. Click small arrow beside ‘Add channel...’ and select ‘Add counter...’. The ‘Add new CAN out counter’ window appears.
3. Define the name of the counter, define the CAN channel settings.
4. Click ‘OK’ when done.



10.3.2.3 Adding CAN out checksum

To send a checksum on the CAN, perform the following steps:

1. Create a new CAN output message or edit an existing message.
2. Click small arrow beside 'Add channel...' and select 'Add checksum...'. The 'Add new CAN out checksum' window appears.
3. Define the name of the checksum, the algorithm, the byte which should be covered by the checksum and define the CAN channel settings.
4. Click 'OK' when done.



10.4 Multiplexer

Row counter concept

If certain channel messages are not time-critical and can be imported or exported slowly, you can use a multiplexer to put several channel messages on one message identifier.

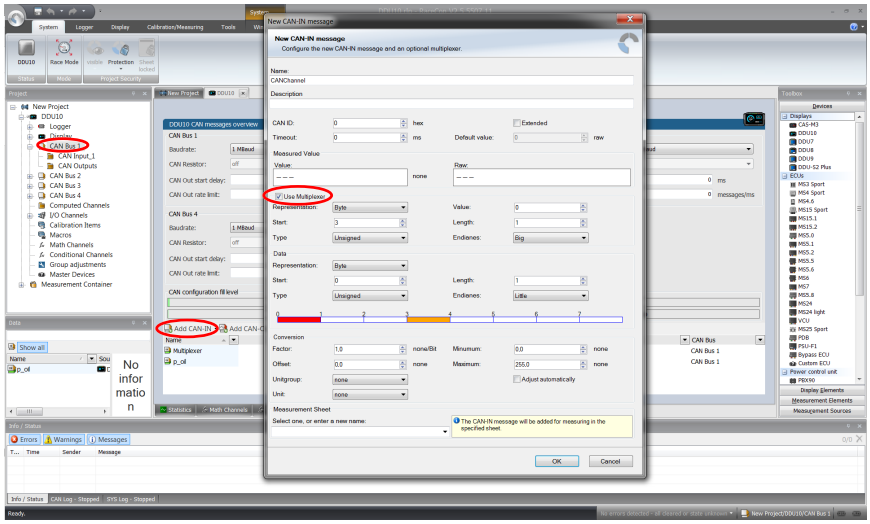
- Re-use (multiplex) of message identifiers by splitting it into several rows.
- Every row is assigned to a unique value of the multiplexer.
- One byte of message contains row counter.

– 7 bytes payload remaining. A multiplexer does not have to consist of one byte only, it can consist of several bytes as well as single bits.

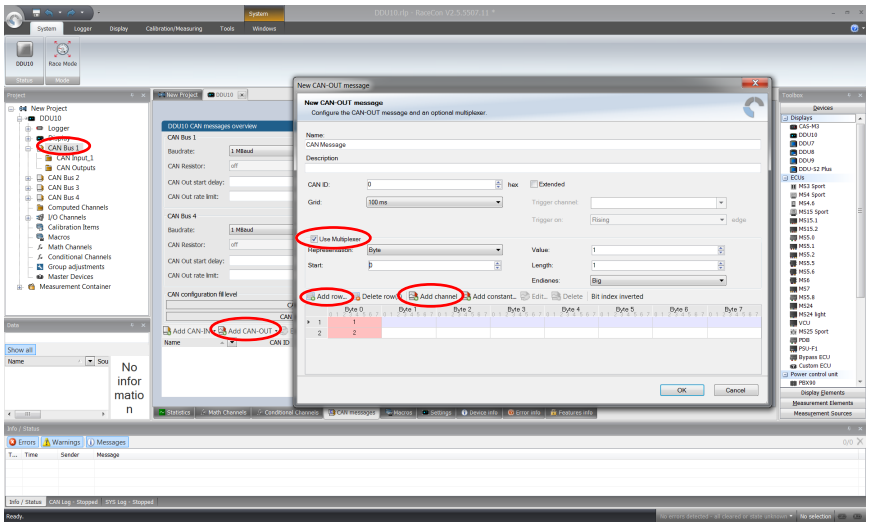
– Position of row counter is configurable.

To use a multiplexer perform the following steps:

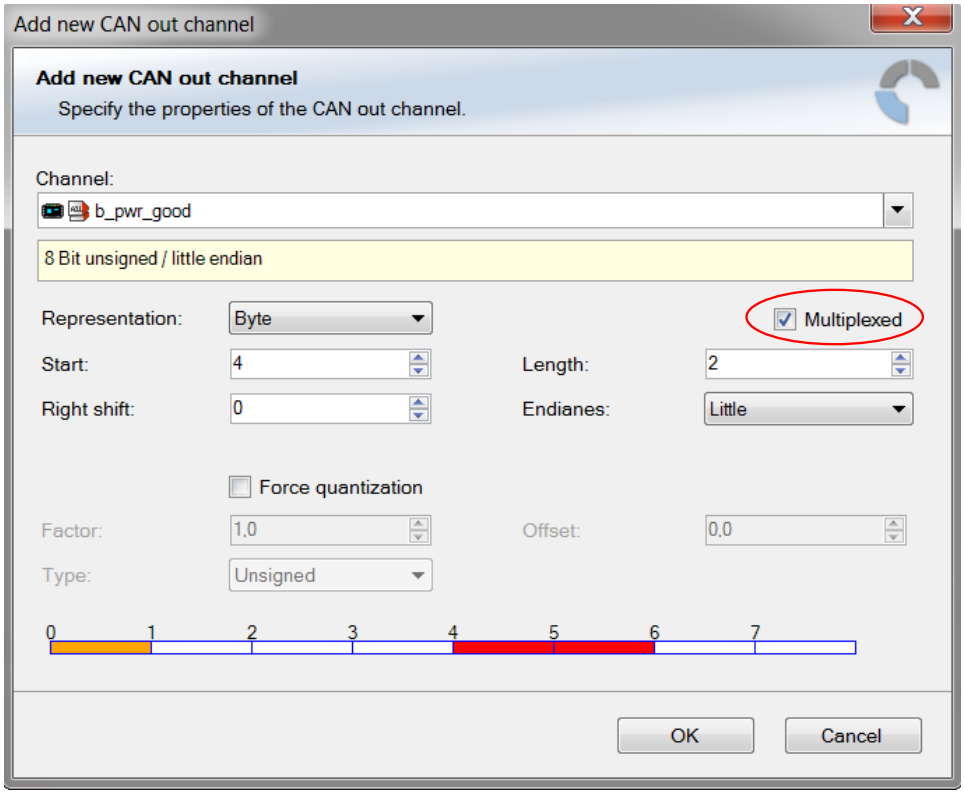
1. Double-click on any CAN bus item to open the “CAN messages overview”.
2. Select ‘Add CAN-IN’ and choose the desired CAN bus for the new input channel.
3. Check the box ‘Use Multiplexer’ and configure the multiplexer for the new CAN-IN channel.



4. To configure the multiplexer for a CAN-OUT channel, select ‘Add CAN-OUT’.
5. Check the box ‘Use Multiplexer’ and click on the button ‘Add row…’ to split the message identifiers into several rows.
6. Click on one row and select ‘Add channel’ to assign a channel to the row.

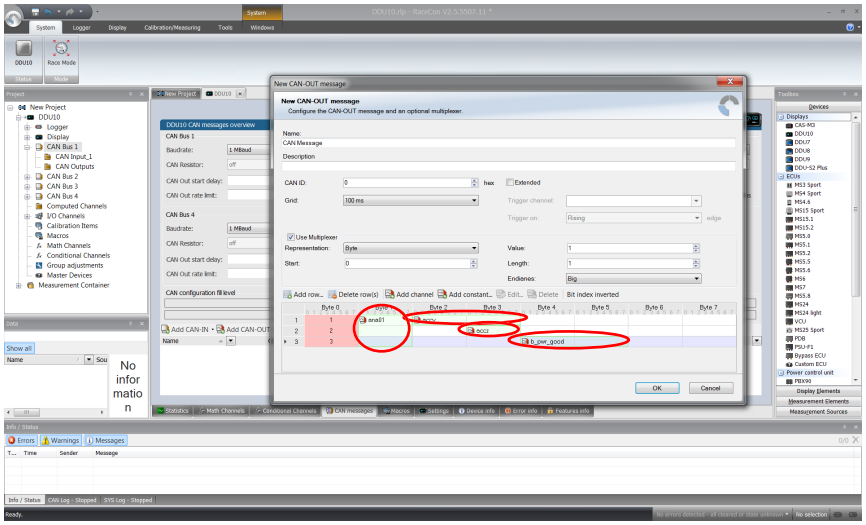


7. The ‘Add new CAN out channel’ dialog opens.
8. Select a channel and configure it. To assign it to the row selected before, check the box ‘Multiplexed’.
9. To move the channel message, change the “Start” value or click and hold the green field in the “Add new CAN out message” window.
10. Click ‘OK’ when done.



11. The channel message is assigned to the selected fields.

12. Click ‘OK’ when done.



11 Export and Import in RaceCon

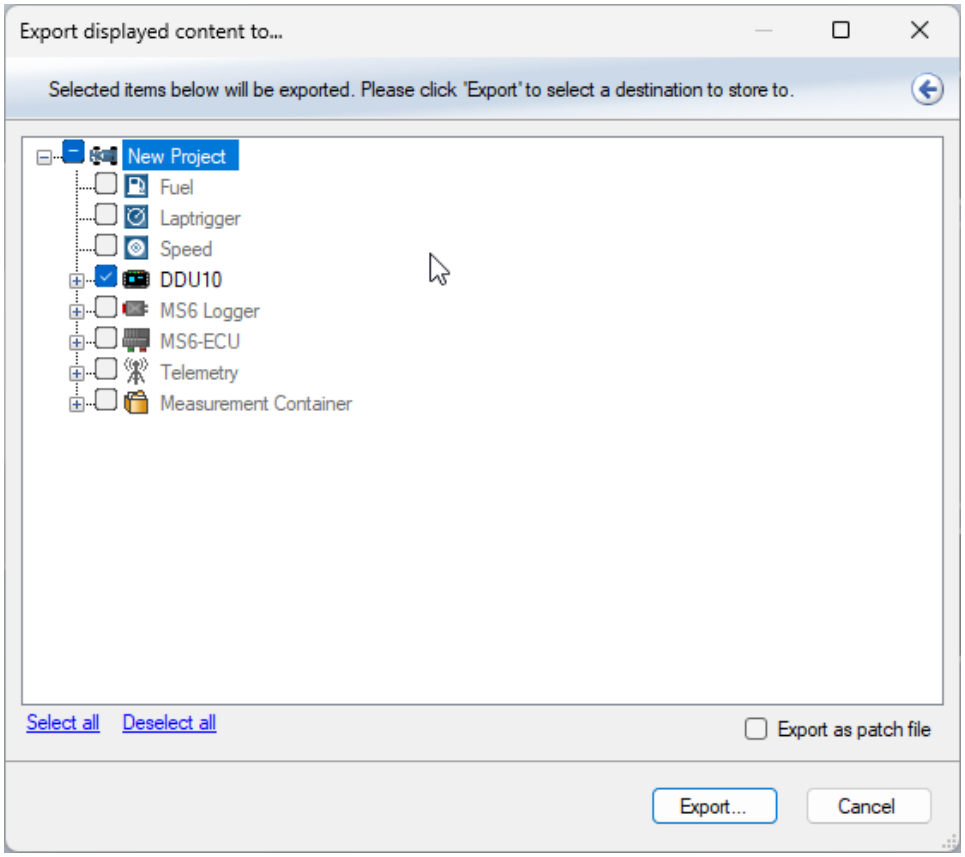
You can perform an export or an import on almost any level in the project tree.

11.1 Export in RaceCon

You can choose to export the whole project or you can export specific parts of the project.

Proceed with the following steps to perform an export:

1. Click with the right mouse button on an item in the project tree.
2. Select 'Export...' from menu. An 'Export Selection' window opens.



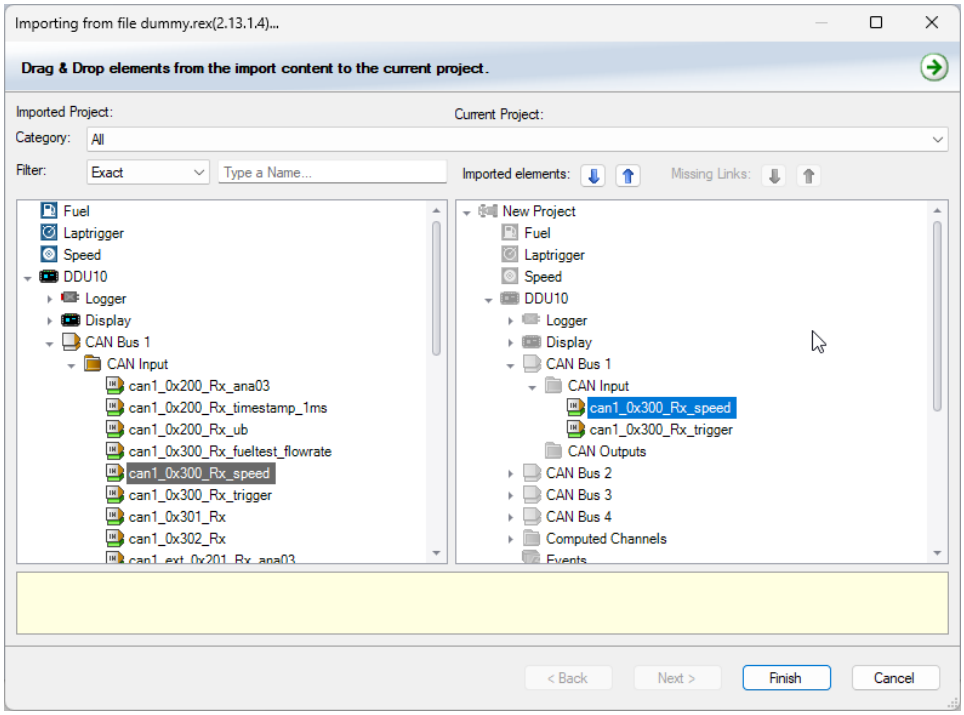
3. Click on 'Export' to select a destination to store.
4. Specify the filename.
5. Click 'Save' when done.

11.2 Import in RaceCon

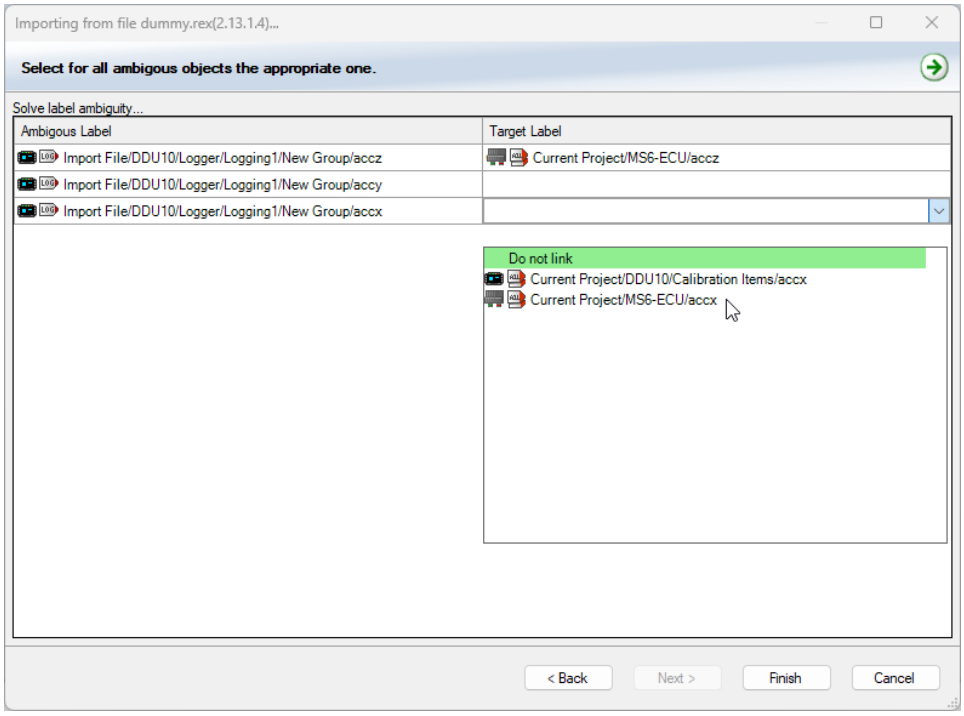
You can choose to import into the whole project or you can import into specific parts of the project.

Proceed with the following steps to perform an import:

1. Click with the right mouse button on any item in the project tree.
2. Select 'Import...' from menu. A file browser opens.
3. Select the input file and click 'Open'. An 'Import Selection' window opens.



4. Select channels to import.
5. Drag and drop the channel to ‘CAN Input’ of desired CAN bus on right hand side.
6. Click ‘Finish’. If a measurement channel belongs to more than one source (e.g. C 80 and MS 6), the ‘Solve Label Ambiguity’ window opens.



7. Assign the ambiguous channels to the desired source.
8. Click ‘Finish’.

12 Analog and Frequency Inputs

Analog inputs

- 0 to 5 V
- 12 bit A/D converter
- Switchable 3.01 kOhm pull-up resistor
- 10 kHz acquisition rate, up to 1 kHz recording rate
- Linear phase digital filter

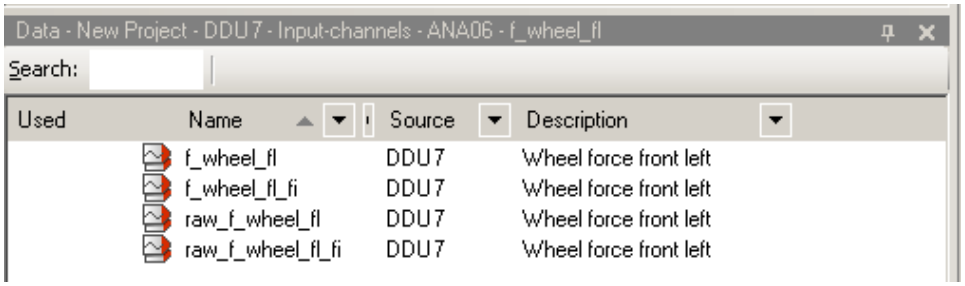
Frequency inputs

- 5 V Hall-effect type, 2.5 V trigger level (DF11 input with current interface or 5 V Hall-effect input with 2.5 V trigger level)
- 20 kHz max. frequency
- 10 ms measurement window

12.1 Analog inputs

12.1.1 Measurements channels

For each analog channel, several ‘subchannels’ are available.



Measurement labels with the characters ‘raw’ show the exact values in mV.

Measurement labels with the characters ‘_fi’ show filtered values.

The word ‘name’ in the table is a placeholder for the channel’s name.

Measurement label	Function
raw_name	mV value of sensor
raw_name_fi	Filtered mV value of sensor
name	Physical value of sensor
name_fi	Filtered physical value

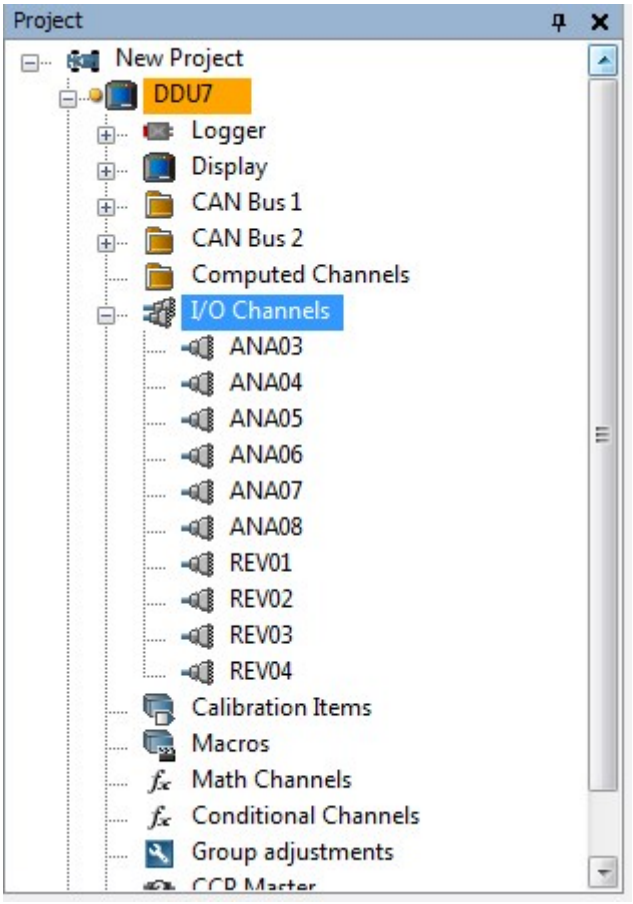
Filtered channels are routed through digital low pass filters:

- C 80 uses A/D converter oversampling and digital filtering to recording rate
- Digital filters eliminate ‘out-of-band’ noise
- Cut-off frequency automatically adjusted to recording rate
- Linear phase – no signal distortion
- Latency compensation – no filter delay in recorded data

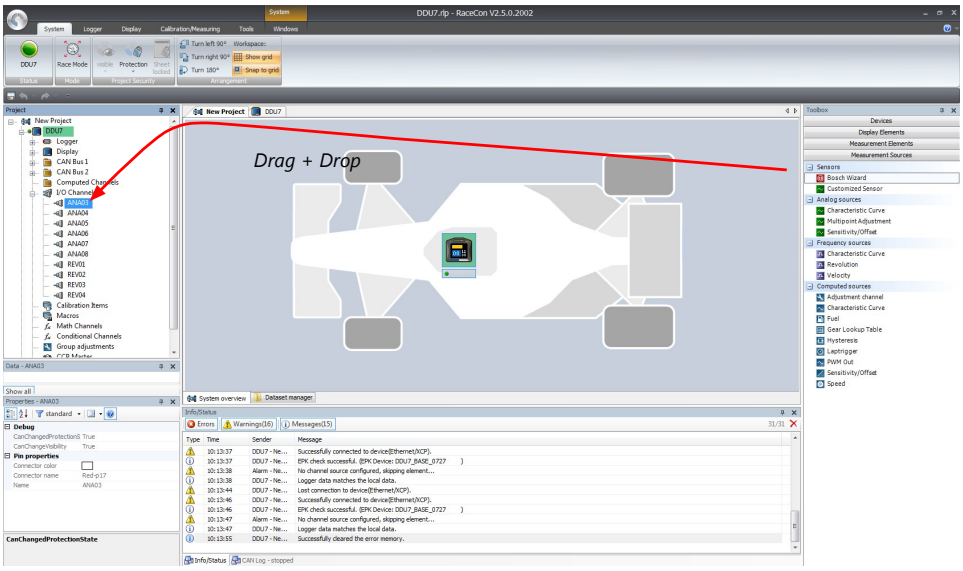
12.2 Configuring inputs

12.2.1 Configuring a predefined Bosch sensor with the 'Bosch Sensor Wizard'

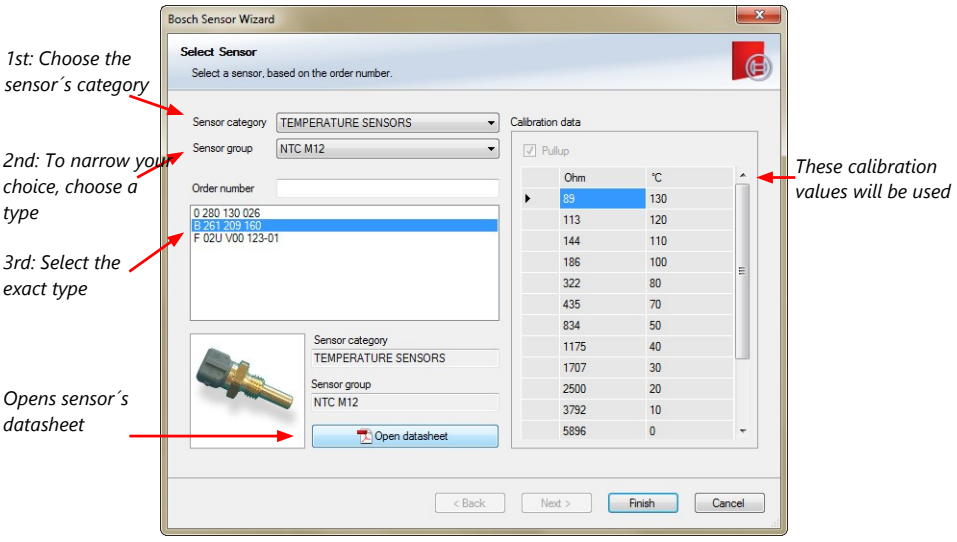
1. Click on ‘Measurement Sources’ in the Toolbox.
2. To expand the list of ‘I/O Channels’, click on ‘+‘ in the C 80 Project Tree.



3. Drag the “Bosch Sensor Wizard” from the Toolbox and drop it on the desired analog input channel in the C 80 Project Tree.

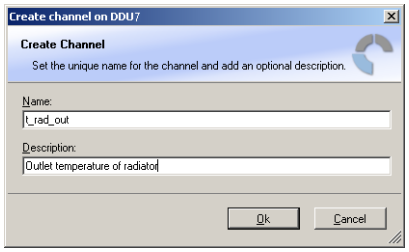


4. The “Bosch Sensor Wizard” opens.

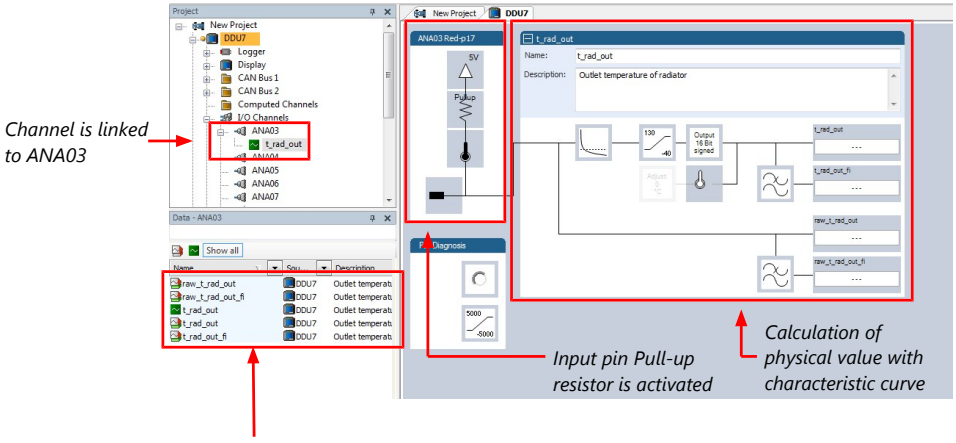


5. Click ‘Finish’ when done.
   The “Create channel” window opens.

6. Enter the channel name and description.



7. Click ‘Ok’ when done.
   The channel is inserted into the C 80 Project Tree.



Available measurements for channel:

Measurement label	Function
raw_name	mV value of sensor
raw_name_**fi**	Filtered mV value of sensor
name	Physical value of sensor
name_**fi**	Filtered physical value

12.2.2 Configuring a generic linear sensor

Example: Acceleration sensor 5 g

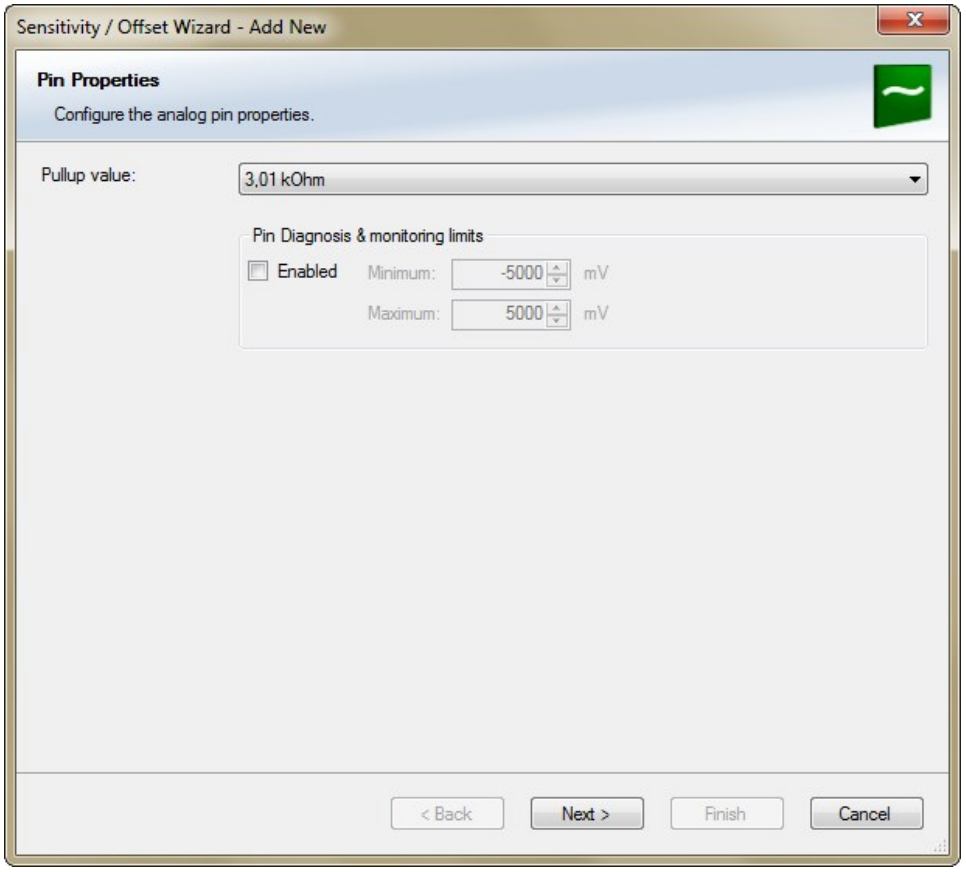
– From sensor data sheet - operating characteristics:

Output Signal					
Zero g (T_A = 25°C, V_{DD} = 5.0 V)(4)	V_{OFF}	2.25	2.5	2.75	V
Zero g (V_{DD} = 5.0 V)	V_{OFF}	2.0	2.5	3.0	V
Sensitivity (T_A = 25°C, V_{DD} = 5.0 V)(5)	S	380	400	420	mV/g
Sensitivity (V_{DD} = 5.0 V)	S	370	400	430.1	mV/g
Bandwidth Response	f_{-3dB}	42.5	50	57.5	Hz
Nonlinearity	NL_{OUT}	–1.0	—	+1.0	% FSO

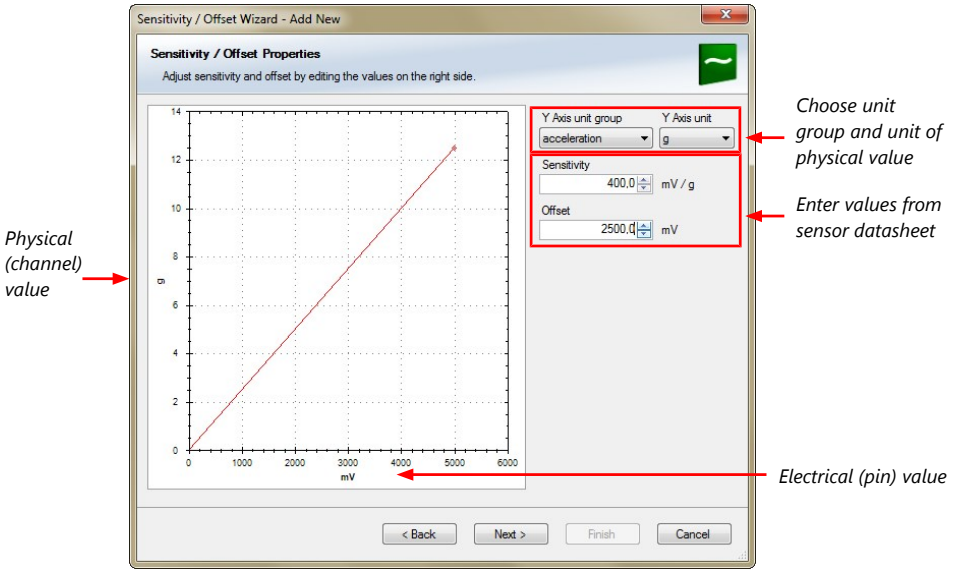
– Sensitivity 400 mV/g, Offset 2,500 mV

– The sensor has a linear output signal with sensitivity and offset

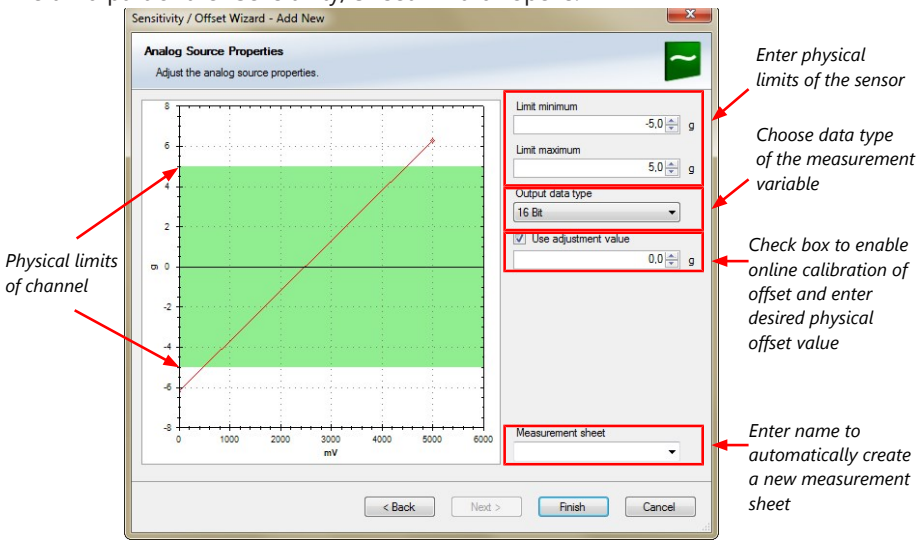
1. Click on ‘Measurement Sources’ in the Toolbox.
2. To expand the list of ‘I/O Channels’, click on ‘+’ in the C 80 Project Tree.
3. Drag the “Sensitivity/Offset” analog signal source from the Toolbox and drop it on the desired analog input channel in the C 80 Project Tree. A “Sensitivity/Offset Wizard” opens.
4. To activate the internal pullup-resistor, check the box. The internal pullup-resistor is used to get a 5 V signal at the analog channel of the C 80. It allows you to use a push-button. The fixed value of the internal pullup-resistor is 3,010 Ohm. If using an additional external pullup-resistor, set up the overall resistance.



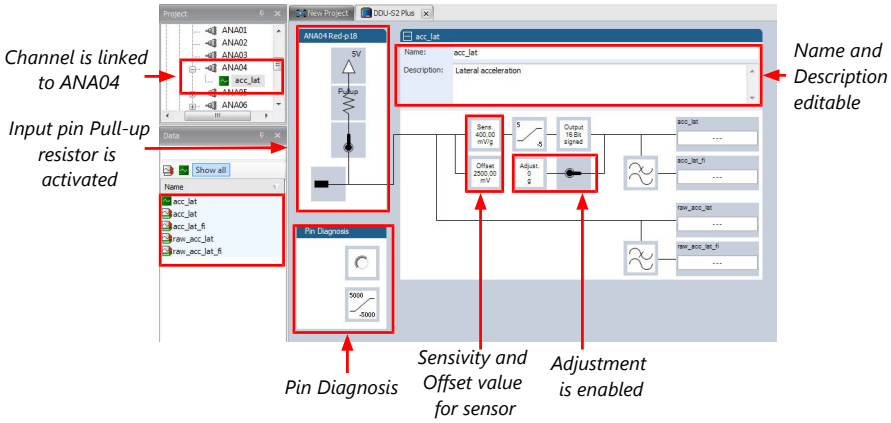
5. Click ‘Next’ when done.
   The second part of the “Sensitivity/Offset Wizard” opens.



6. Click ‘Next’ when done.
   The third part of the “Sensitivity/Offset Wizard” opens.



7. Click ‘Finish’ when done.
8. Enter a channel name and a description.
9. Click ‘OK’ when done.
   The channel is inserted into the C 80 Project Tree.



Available measurements for channel:

Measurement label	Function
raw_name	mV value of sensor
raw_name_**fi**	filtered mV value of sensor
name	physical value of sensor
name_**fi**	filtered physical value

Note

Working with automatically created measurement sheets is explained in chapter 'Setting up an online measurement [▶ 77]'.

12.2.3 Configuring a generic nonlinear sensor

Example: Thermistor 5 kOhm

– From sensor data sheet - resistance values over temperature:

PART NR.: 2381 640 502
HTCLE100E3502

T_{oper} [°C]	R_T [Ω]
-40	166 047
-35	119 950
-30	87 600
-25	64 643
-20	48 179
-15	36 250
-10	27 523
-5	21 078

T_{oper} [°C]	R_T [Ω]
0	16 277
5	12 669
10	9 936
15	7 849
20	8 244
25	5 000
30	4 030
35	3 267

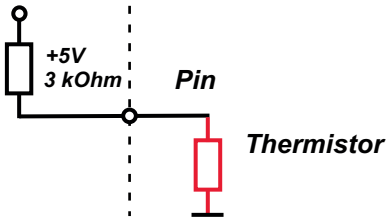
T_{oper} [°C]	R_T [Ω]
40	2 685
45	2 166
50	1 903
55	1 494
60	1 245
65	1 024
70	876
75	740

T_{oper} [°C]	R_T [Ω]
80	628
85	535
90	457
95	399
100	338
105	292
110	251
115	221

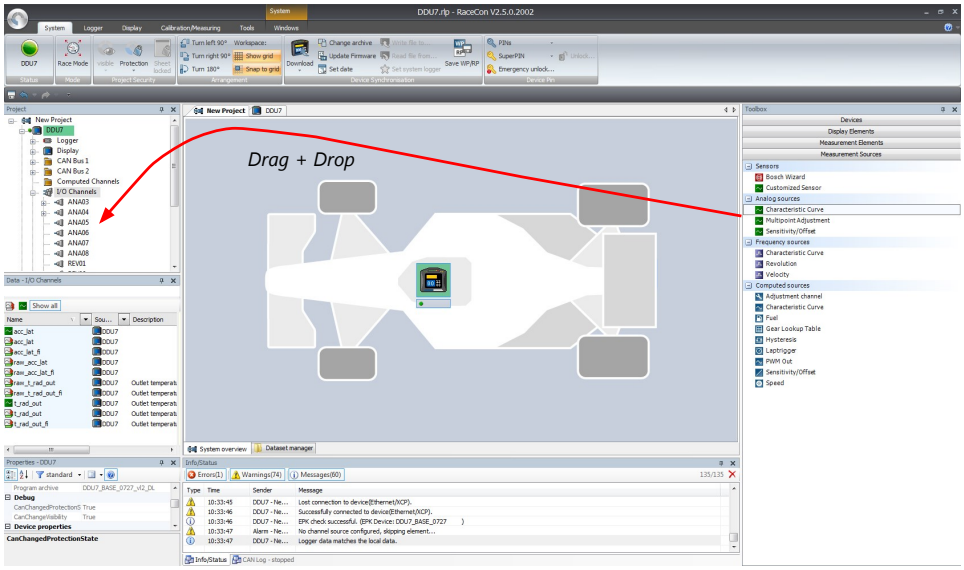
– The sensor has a nonlinear behavior

– Use characteristic curve for linearization

– Input voltage is the ratio between pull-up resistor and thermistor

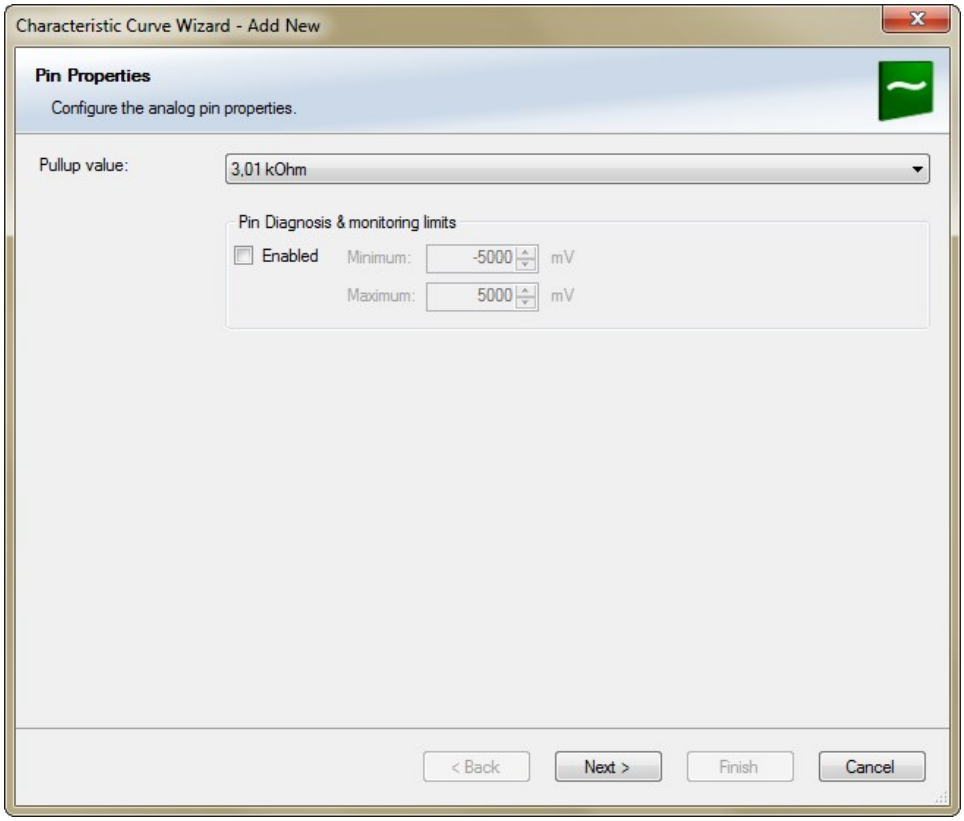


1. Click 'Measurement Sources' in the Toolbox.
2. To expand the list of 'I/O Channels', click on '+' in the C 80 Project Tree.
3. Drag the "Characteristic Curve" analogue signal source from the Toolbox and drop it on the desired analogue input channel in the C 80 Project Tree.

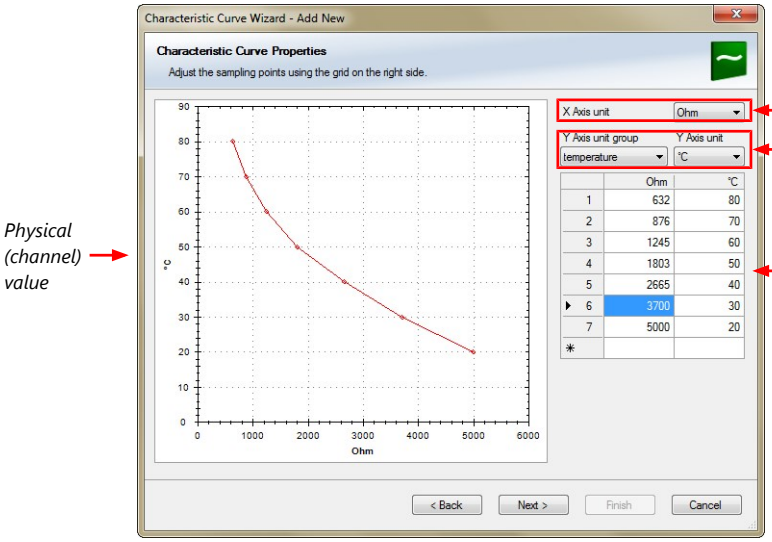


4. A “Characteristic Curve Wizard” opens.

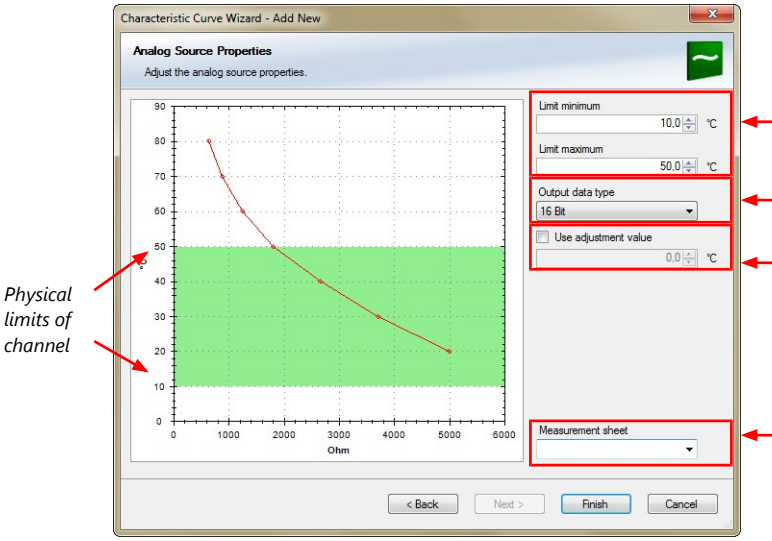
5. To activate the internal pull up-resistor, check the box. The C 80 pull up-resistor is used to get a 5 V signal at the analogue channel of the C 80. It allows you, to use a push-button. The fixed value of the internal pull up-resistor is 3,010 Ohm. If using an additional external pull up-resistor, set up the overall resistance.



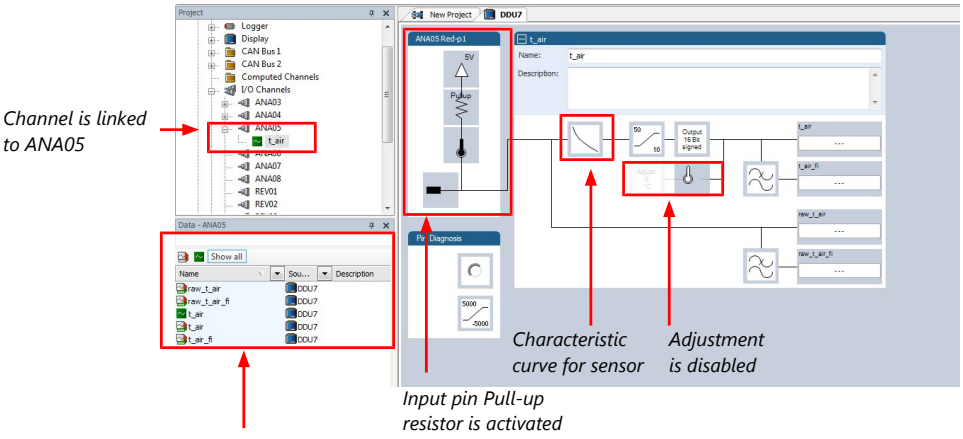
6. Click ‘Next’ when done.
   The second part of the “Sensitivity/Offset Wizard” opens.



7. Click ‘Next’ when done.
   The third part of the “Characteristic Curve Wizard” opens.



8. Click ‘Finish’ when done.
9. Enter channel name and description.
10. Click ‘OK’ when done.
    The channel is inserted into the C 80 Project Tree.



Available measurements for channel:

Measurement label	Function
raw_name	mV value of sensor
raw_name_**fi**	filtered mV value of sensor
name	physical value of sensor
name_**fi**	filtered physical value

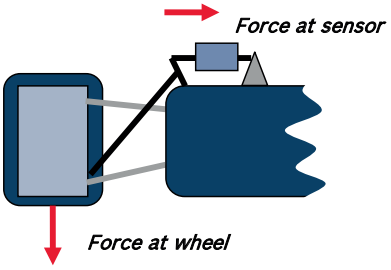
Note

Working with automatically created measurement sheets is explained in chapter 'Setting up an online measurement [▶ 77]'.

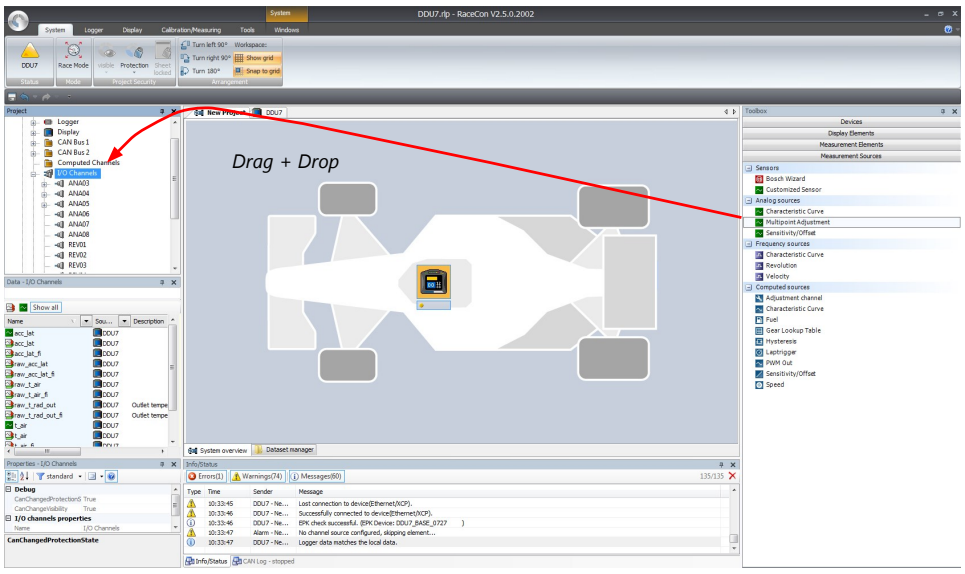
12.2.4 Configuring a multipoint adjustment

Example: Measurement of wheel force

- Physical property 'wheel force' not directly measurable
- Load transfer through suspension kinematics
- Physical value at sensor position defined by vehicle
- Curve definition by online adjustment at vehicle

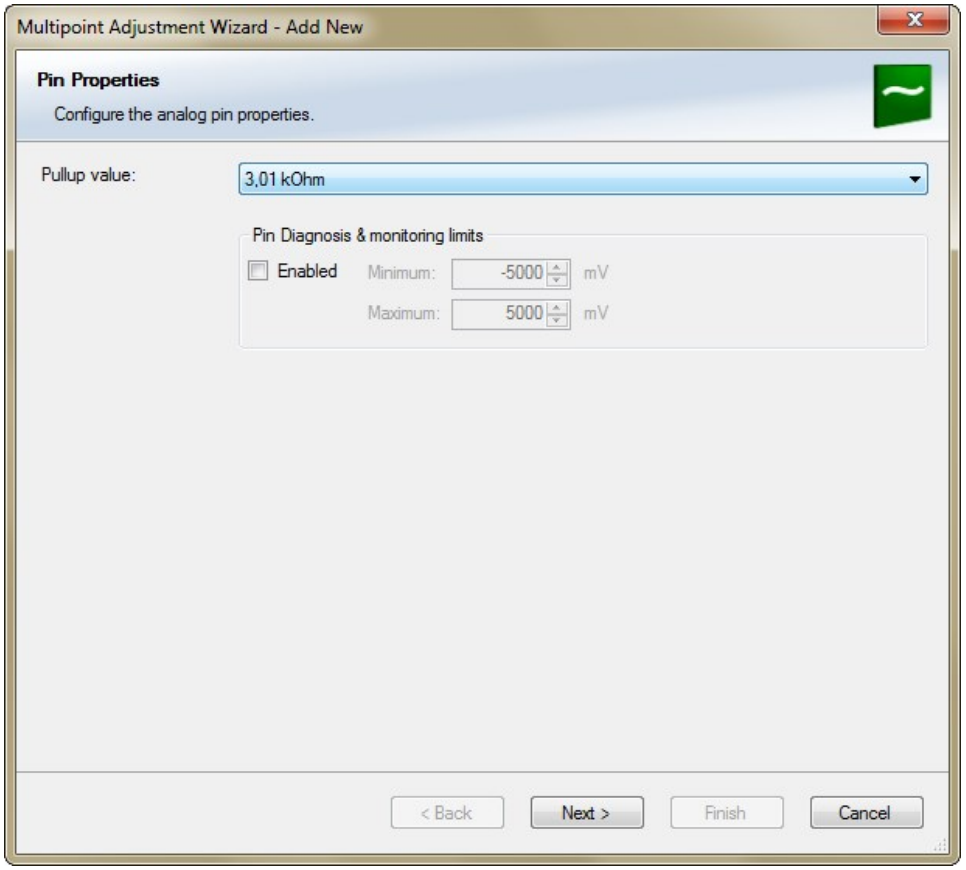


1. Click on 'Measurement Sources' in the Toolbox.
2. Expand the list of 'I/O Channels' by clicking on '+' in the C 80 Project Tree.
3. Drag the 'Multipoint Adjustment' analog signal source from the Toolbox and drop it on the desired analog input channel in C 80 Project Tree.

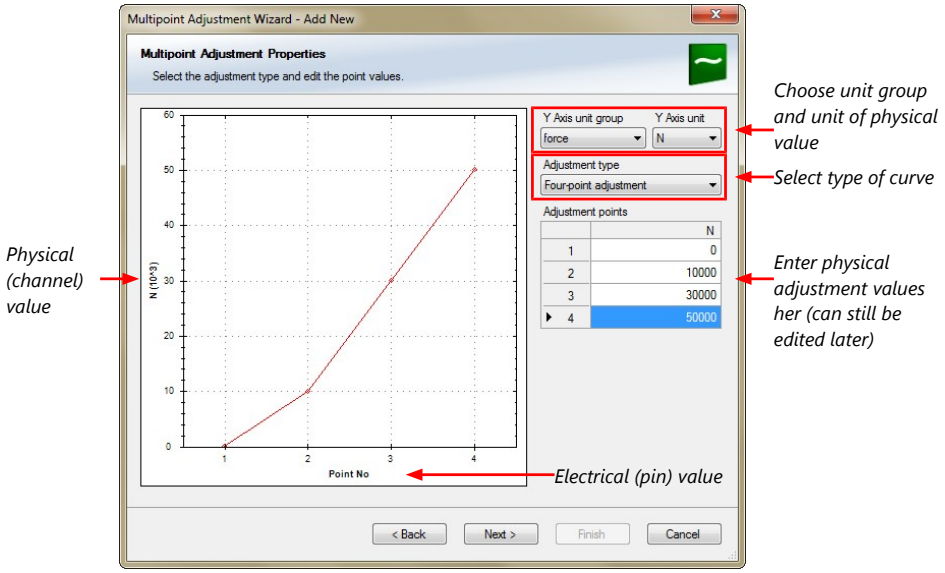


4. A 'Multipoint Adjustment Wizard' opens.

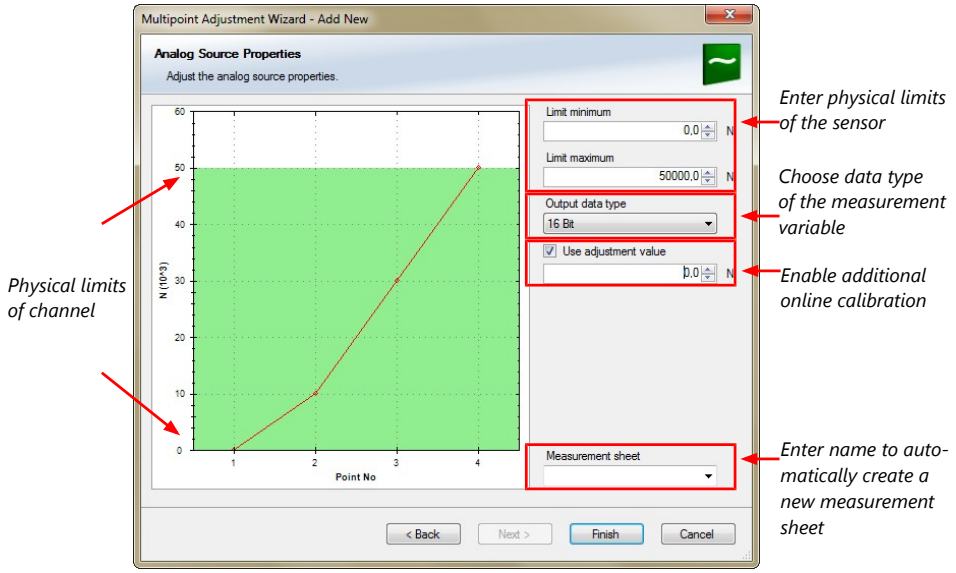
5. To activate the internal pullup-resistor, check the box. The internal pullup-resistor is used to get a 5 V signal at the analog channel of the C 80. It allows you to use a push-button. The fixed value of the internal pullup-resistor is 3.01 kOhm. If using an additional external pullup-resistor, set up the overall resistance.



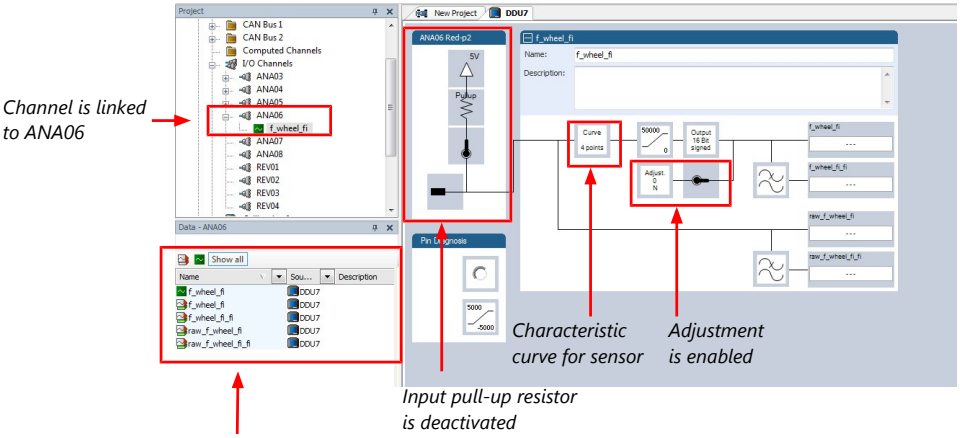
6. Click ‘Next‘ when done.
The second part of the ‘Multipoint Adjustment Wizard‘ opens.



7. Click ‘Next‘ when done.
The third part of the ‘Multipoint Adjustment Wizard‘ opens.



8. Click ‘Finish’ when done.
9. Enter channel name and description.
10. Click ‘OK’ when done.
    The channel is inserted into the C 80 Project Tree.



Available measurements for channel:

Measurement label	Function
raw_name	mV value of sensor
raw_name_**fi**	filtered mV value of sensor
name	physical value of sensor
name_**fi**	filtered physical value

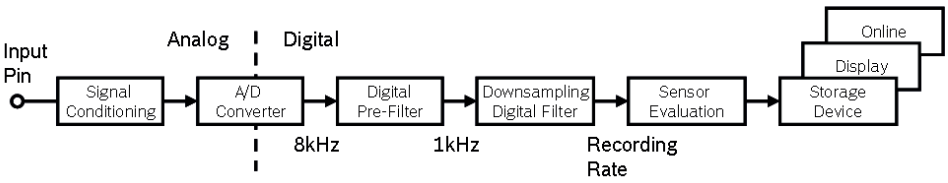
Online definition of the curve is covered in chapter ‘Online calibration of measurement channels [▶ 82]’.

Note

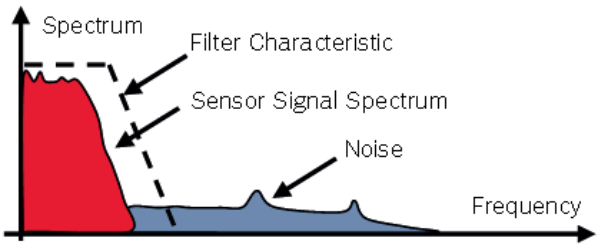
Working with automatically created measurement sheets is explained in chapter ‘Setting up an online measurement [▶ 77]’.

12.2.5 Digital filter details

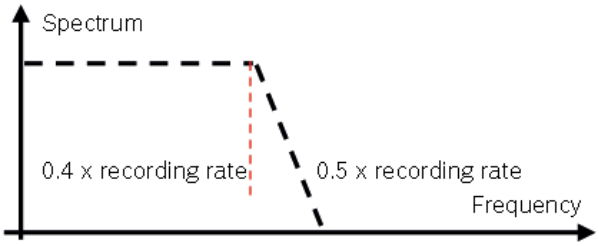
C 80 uses A/D converter oversampling and digital filtering to recording rate.



Digital filters eliminate 'out-of-band' noise



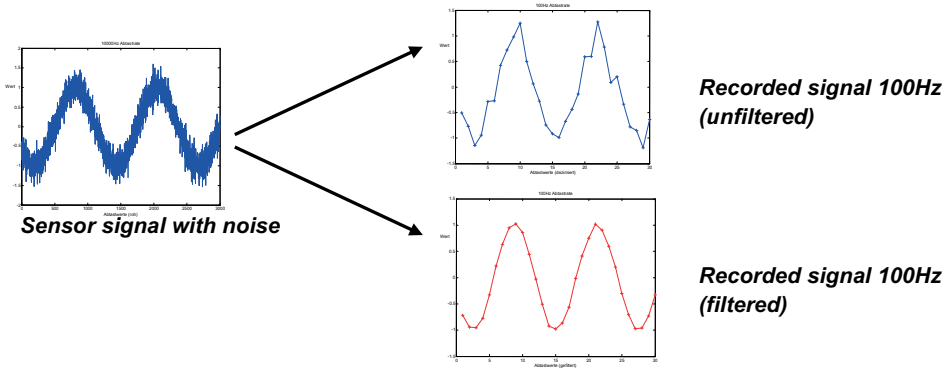
Cut-off frequency automatically adjusted to recording rate



Example:

- 100 Hz recording rate (10 ms)
- <40 Hz pass band (>99 %)
- >50 Hz stop band (<1 %)

Linear phase – no signal distortion



Latency compensation – no filter delay in recorded data

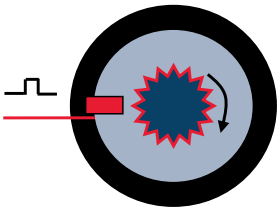
- Filtering is (smart) averaging over several samples
- Filtered signal is delayed with respect to real time signal

- C 80 filters have constant, frequency independent delay
- Delay (e.g. 22 samples at 10 ms) is corrected during recording
- No delay filtered vs. unfiltered in recorded data
- Correction is (of course) not possible for real time data (display, online, PWM out)
- Use filtered data for recording, use unfiltered data for real time

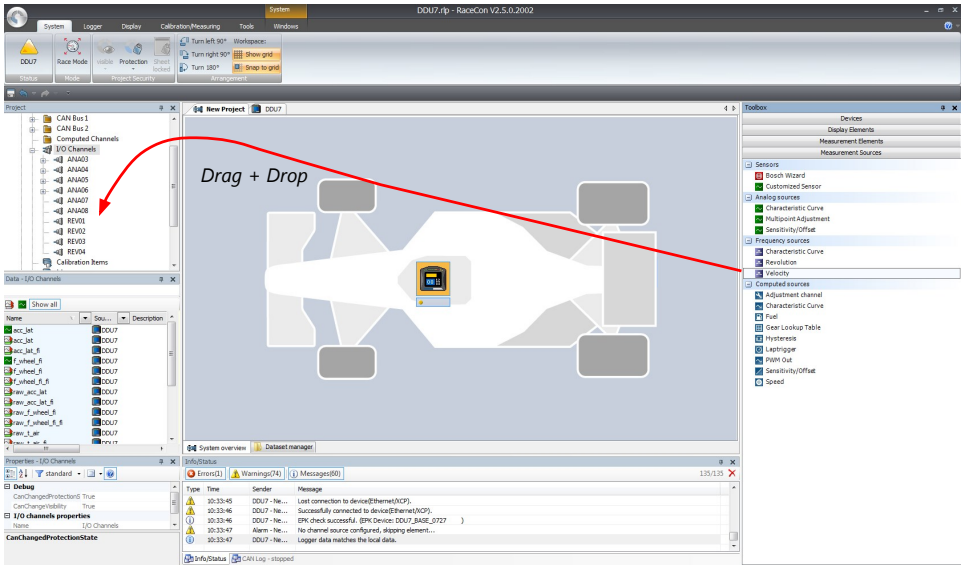
12.2.6 Configuring a frequency input

Example: measurement of wheel speed

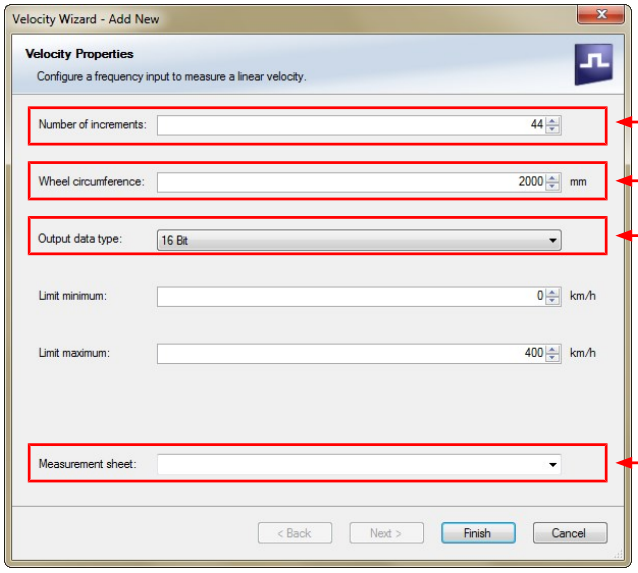
- Pulse wheel attached to wheel
- Each passing tooth of pulse wheel triggers hall sensor
- Calculation of wheel speed with wheel circumference



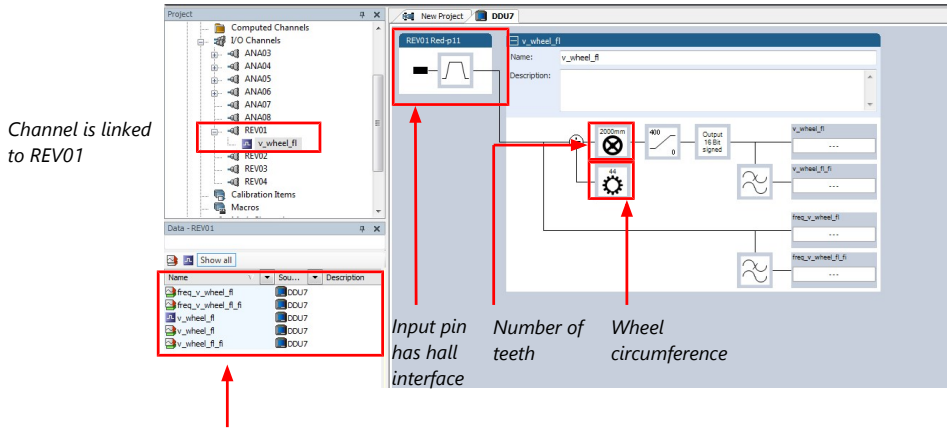
1. Click on ‘Measurement Sources’ in the Toolbox.
2. To expand the list of ‘I/O Channels’, click on the ‘+’ in the C 80 Project Tree.
3. Drag the ‘Velocity’ digital signal source from the Toolbox and drop it on the desired ‘REV’ input channel in the C 80 Project Tree.



4. The ‘Velocity Wizard’ opens.
5. Define the settings for the sensor.



6. Click ‘Finish’ when done.
7. Enter the channel name and description.
8. Click ‘OK’ when done.
   The channel is inserted into the C 80 Project Tree.



Available measurements for channel:

Measurement label	Function
raw_name	mV value of sensor
raw_name_**fi**	filtered mV value of sensor
name	physical value of sensor
name_**fi**	filtered physical value

Note

Measurement of ‘Revolution’ is similar.

12.3 Configuring computed sources

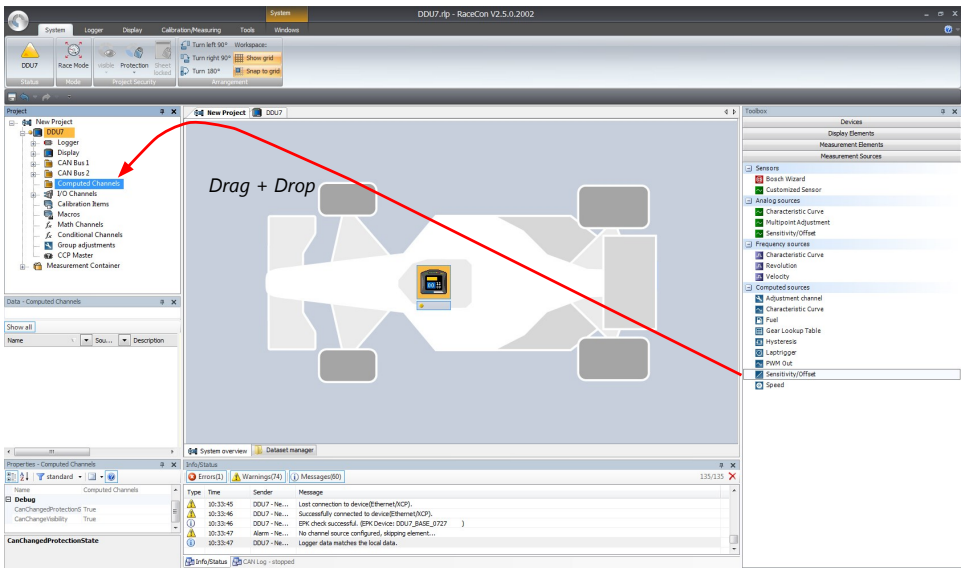
Computed sources receive data from a measurement channel rather than an input pin.

- Sensitivity/Offset calculation on input channel
- Characteristic curve calculation on input channel
- Computed vehicle speed

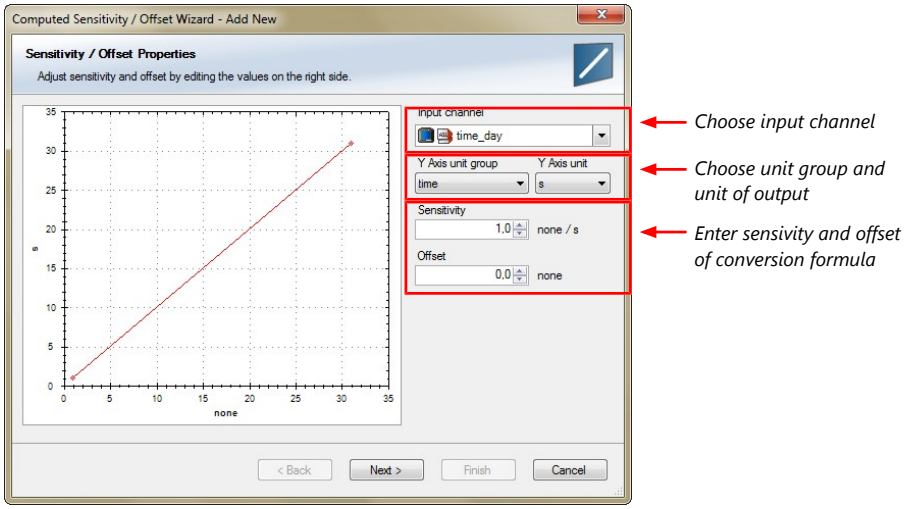
– Lap trigger (covered in a special separate section)

Example: Sensitivity/offset calculation on input channel

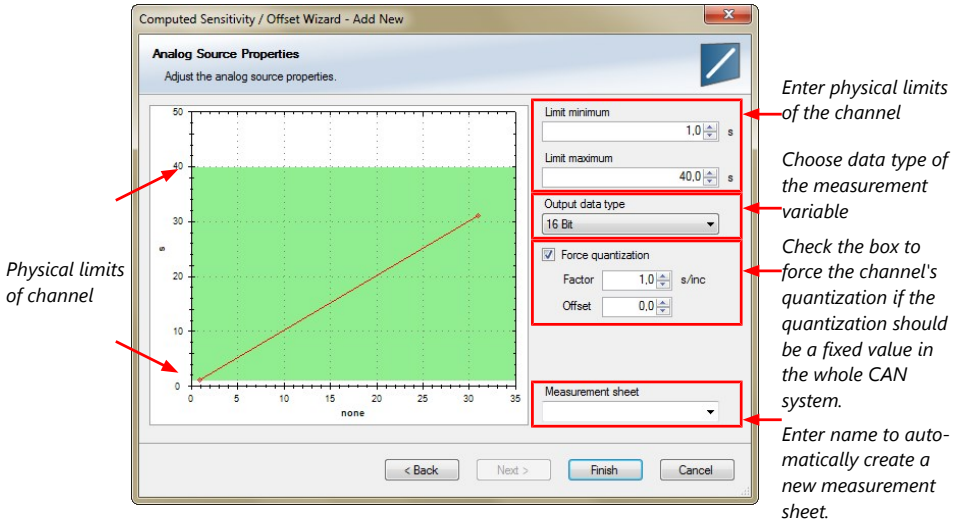
1. Click ‘Measurement Sources’ in the Toolbox.
2. Drag the ‘Sensitivity/Offset’ computed source from the Toolbox and drop it on ‘Computed Channels’ in the C 80 Project Tree.



3. A ‘Computed Sensitivity/Offset Wizard’ opens.



4. Click ‘Next’ when done.
   The second part of the ‘Computed Sensitivity/Offset Wizard’ opens.



5. Click ‘Finish’ when done.
6. Enter channel name and description.
7. Click ‘OK’ when done.

   The channel is inserted into the C 80 Project Tree.

Note

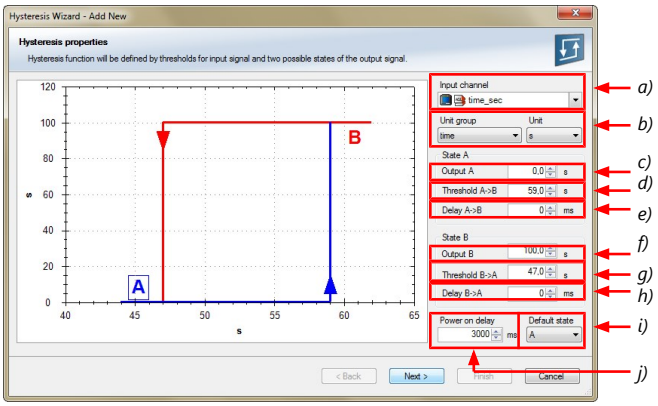
Working with automatically created measurement sheets is explained in chapter ‘Setting up an online measurement [▶ 77]’.

12.4 Hysteresis

The hysteresis function avoids the high-frequent switchover of the measurement channel value. The hysteresis can be adjusted for each input measurement channel individually and can be used for further processing.

1. Click ‘Measurement Sources’ in the Toolbox.
2. Drag the ‘Hysteresis’ computed source from the Toolbox and drop it on ‘Computed Channels’ in the C 80 Project Tree.

   A ‘Hysteresis Wizard’ opens.



a) Choose input measurement channel.

b) Choose unit group and unit of output.

c) Enter output value of state A in the unit selected in b).

d) Enter threshold value when state changes from A to B.

e) Enter delay time when state changes from A to B.

f) Enter output value of state B in the unit selected in b).

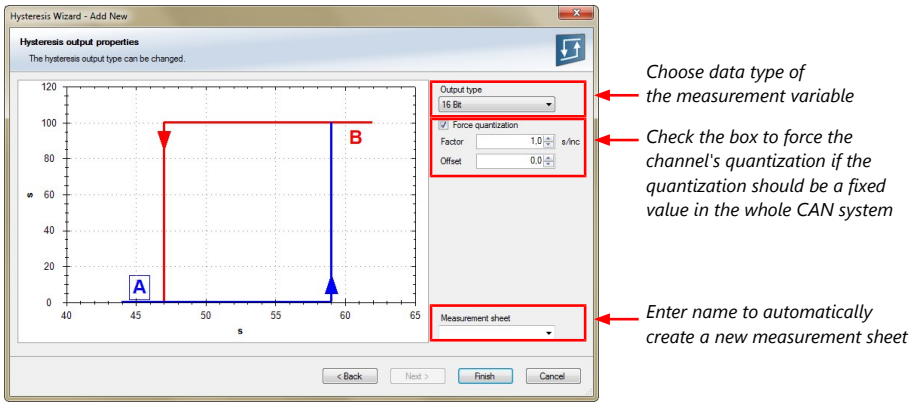
g) Enter threshold value when state changes from B to A.

h) Enter delay time when state changes from B to A.

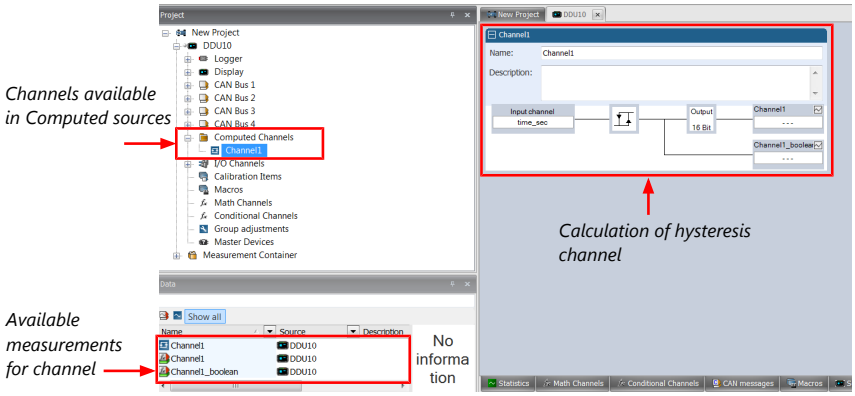
i) Enter time when the hysteresis function is activated after vehicle´s startup.

j) Enter the channel´s state (A or B) at startup.

3. Click ‘Next’ when done.
   The second part of the ‘Hysteresis Wizard’ opens.



4. Click ‘Finish’ when done.
5. Enter channel name and description.
6. Click ‘OK’ when done.
   The channel is inserted into the C 80 Project Tree.



12.4.1 Special functionality: Vehicle speed

This functionality allows:

- high performance vehicle owners to measure wheel spin under acceleration and wheel slip/lock under braking.
- calculating vehicle ‘speed over ground’.

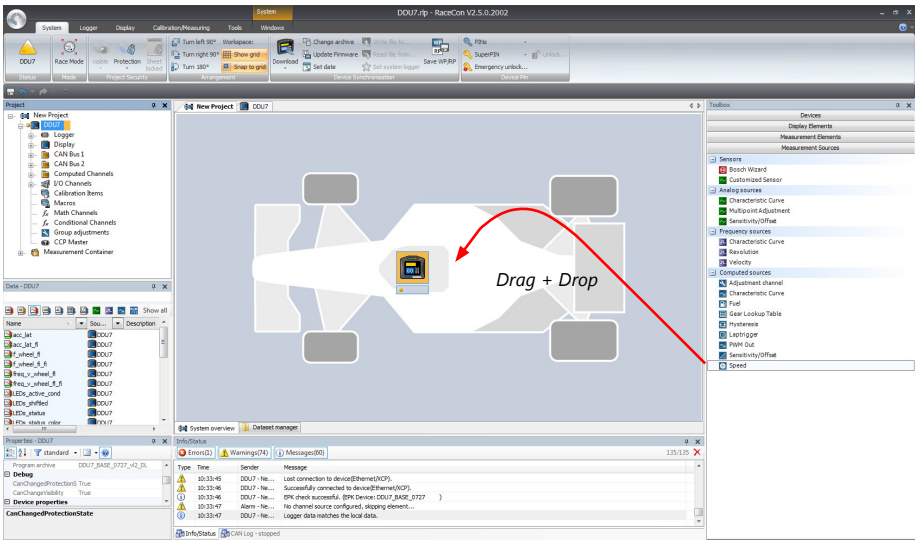
Vehicle speed calculation function

- Calculating vehicle speed of 2 wheel drive: (Wheel speeds of non-driven axle as input)
  - Calculated speed is average of both speeds if speed difference between wheels < limit.
  - Calculated speed is maximum of both speeds if speed difference between wheels > limit.

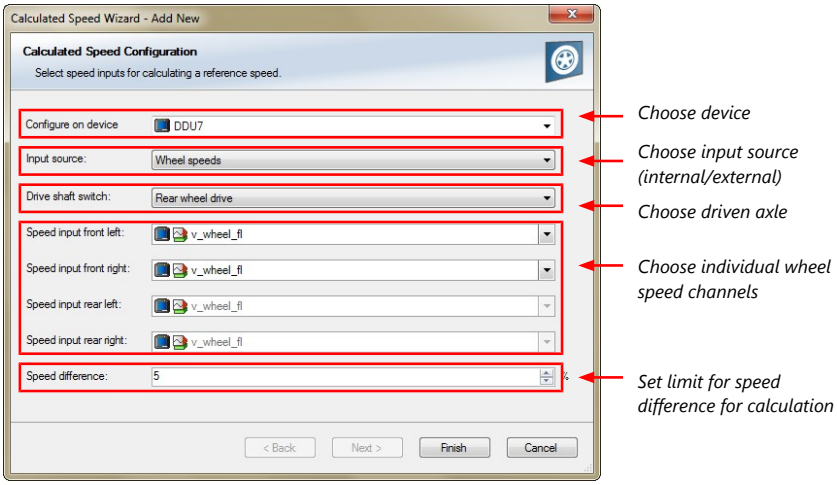
- Calculating vehicle speed of 4 wheel drive: (Wheel speeds of all wheels as input)
  - Calculated speed is speed of 2nd fastest wheel.

12.4.2 Setting up calculated speed

1. Click on tab 'System Overview'.
2. Click on 'Measurement Sources' in the Toolbox.
3. Drag the 'Speed' computed source from the Toolbox and drop it on the project name in the C 80 Project Tree. Do not drop it on 'C 80'!



A 'Calculated Speed Wizard' opens.



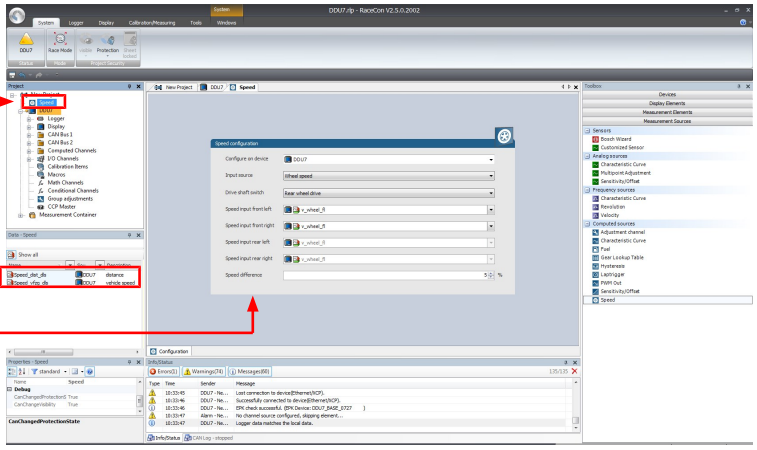
4. Click 'Finish' when done.

   The speed calculation is inserted into the C 80 Project Tree.

Speed calculation in DDU Project Tree

Measurement channels calculated speed and calculated distance

Configuration window



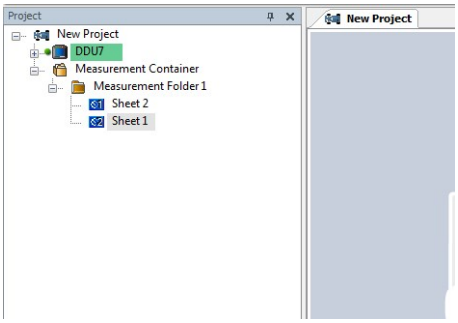
13 Online Measurement and Calibration

- System status and diagnosis
- Check and calibrate sensors in the vehicle
- Live display of sensor values on the PC
- Use RaceCon for diagnosis, online measurement and calibration
- Communication interface: Ethernet
- Communication protocol: XCP

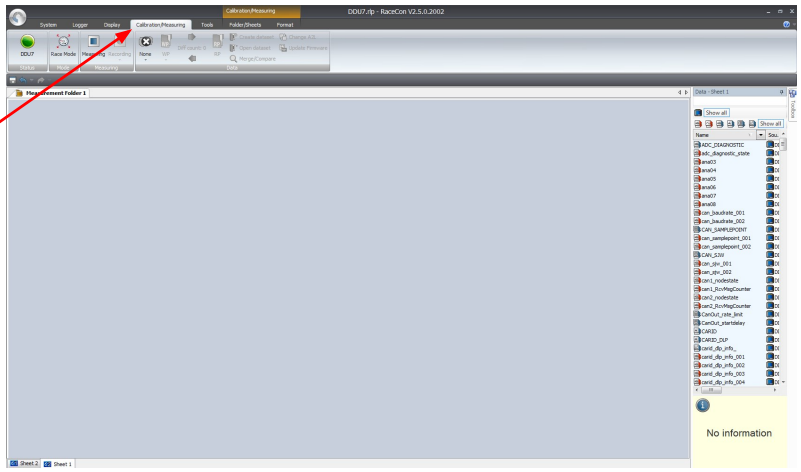
13.1 Setting up an online measurement

C 80 supports online measurement of sensor values and diagnostic variables.

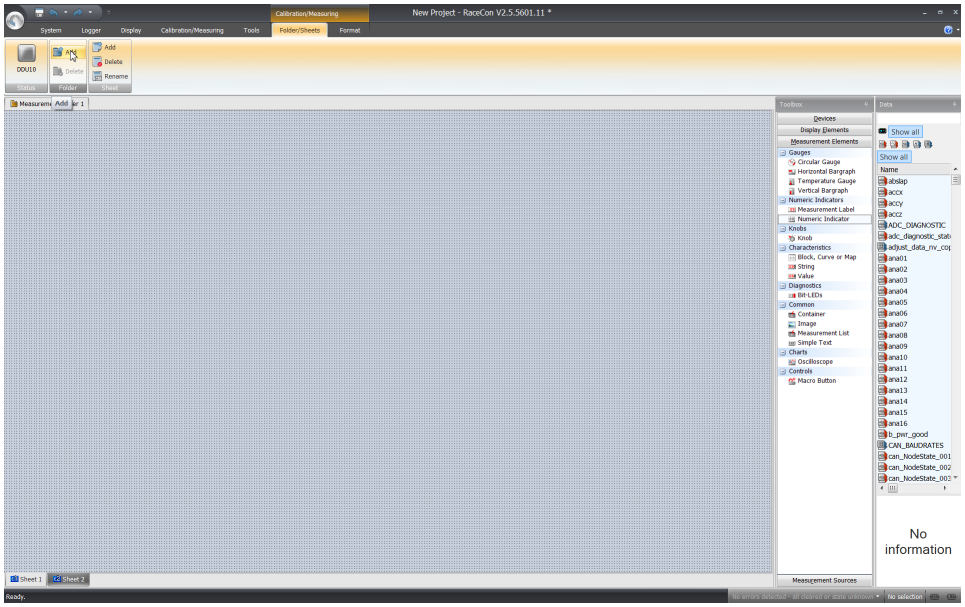
1. Expand ‘Measurement Container’ and ‘Measurement Folder 1’ in the Project Tree and double-click on ‘Sheet1’. Alternatively, click on the ‘Calibration/Measuring’ tab to open the window directly. ‘Sheet 1’ opens in a new ‘Calibration/Measuring’ window.



RaceCon changes automatically to "Calibration/ Measuring"

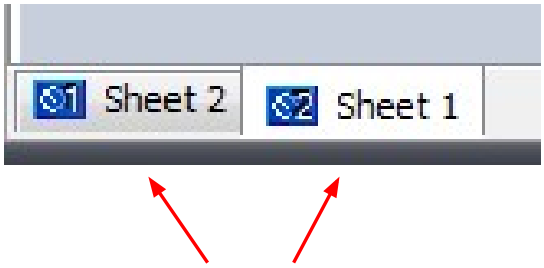


2. Click on the ‘Folder/Sheets’ tab, which appears when you are in the ‘Calibration/ Measurement’ window, to create a new measurement folder.
3. Click on the ‘Add’ button for folders in the upper left corner.



In the menu for sheets, you will find buttons to add, delete and rename new sheets

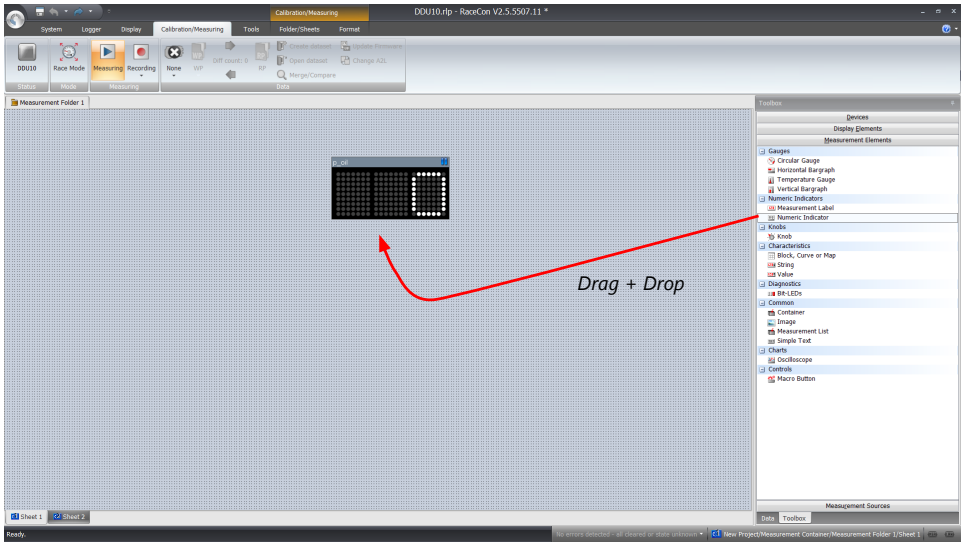
4. To change between different sheets, click on the tabs on the bottom of the 'Calibration/Measuring' window.



Tabs to switch between sheets

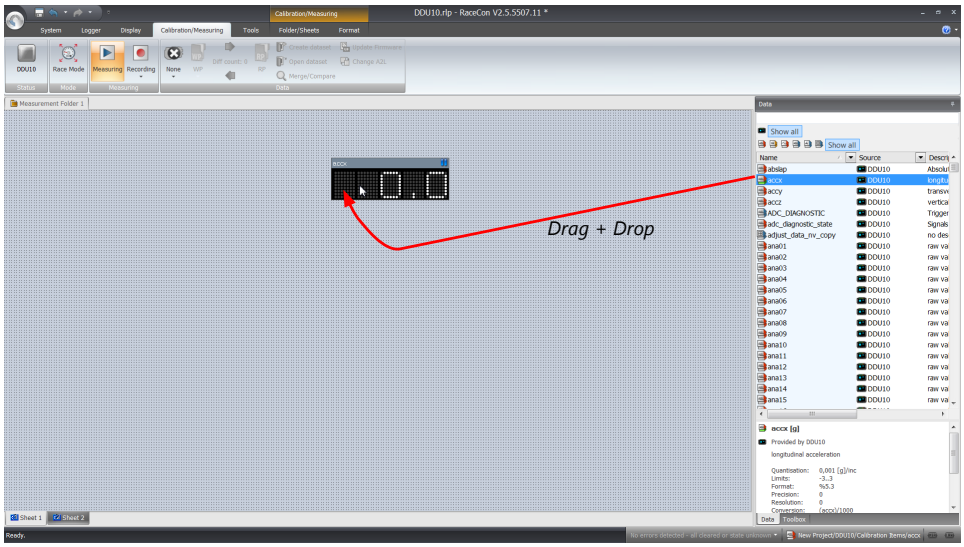
To add an element to a measurement sheet, perform the following steps:

5. Drag a measurement element from the Toolbox and drop it on the measurement sheet.



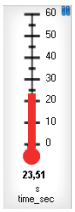
6. Select the desired measurement channel from the 'Data' area and drop it on the measurement element.

If the C 80 shows the green status, the value is displayed.

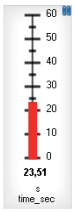


RaceCon offers different types of measurement elements:

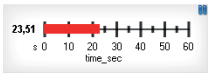
Circular gauge



Temperature gauge



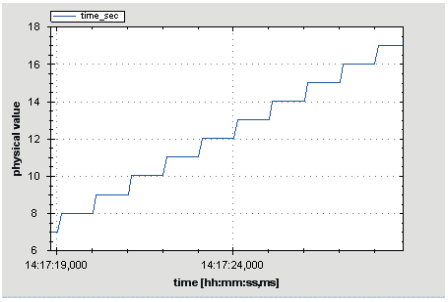
Vertical Bar graph style



Horizontal Bar graph style

Measurement label

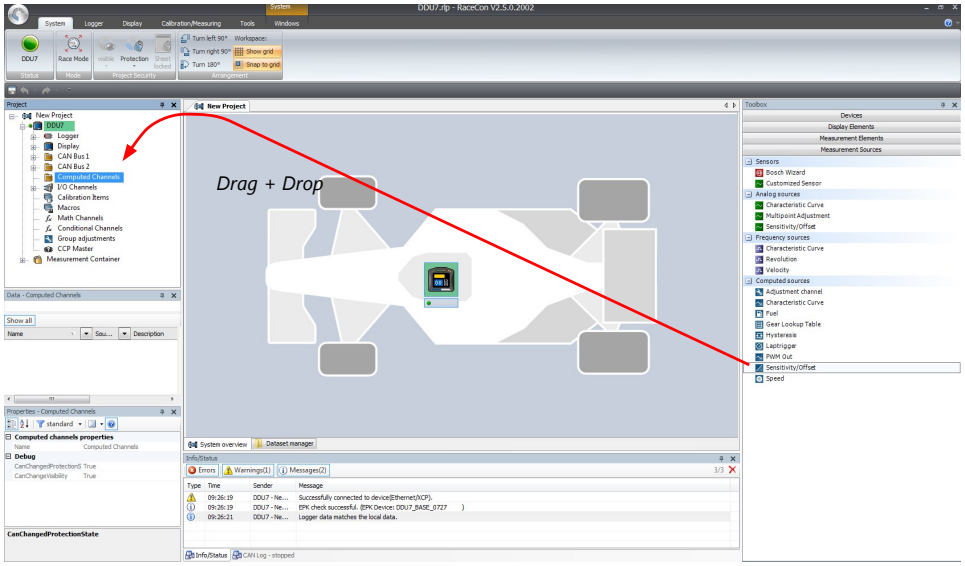
Numeric indicator



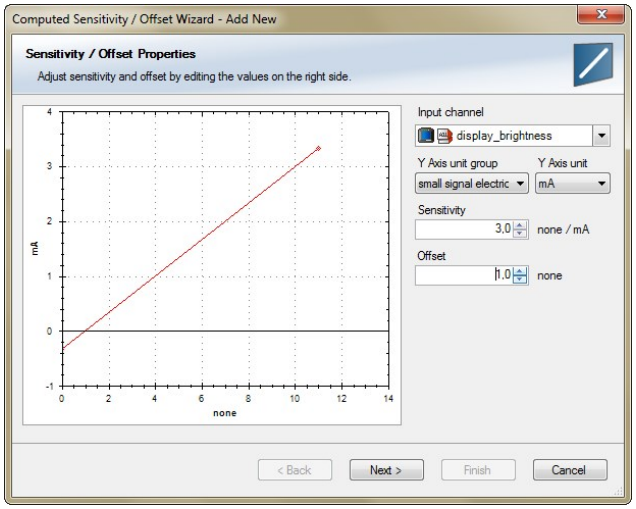
Oscilloscope (Chart)

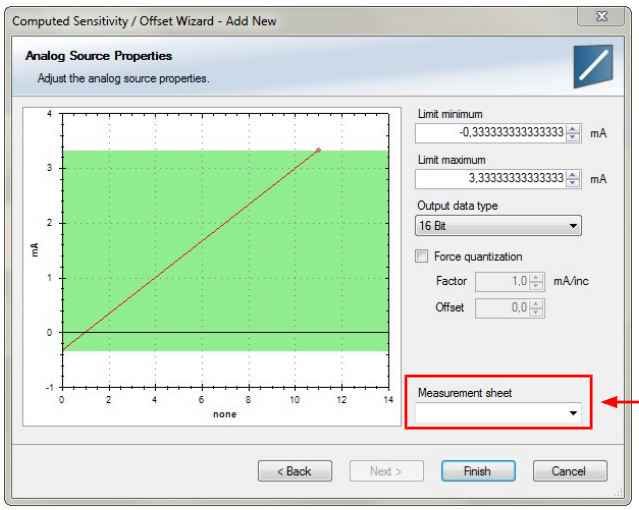
13.1.1 Automatic creation of measurement sheets

RaceCon can create measurement sheets automatically.
You can create and use measurement sheets with the C 80 as well as with all other devices connected to RaceCon.

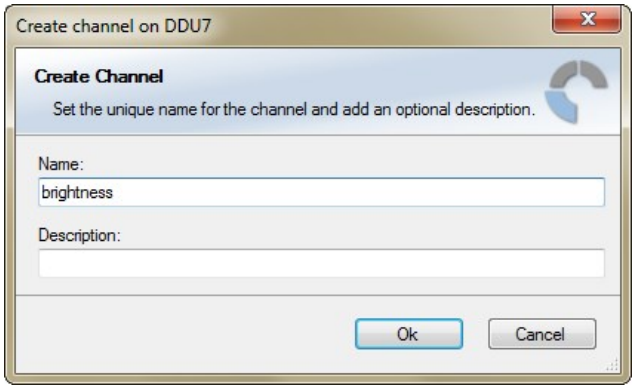


1. During the configuration of a measurement channel, select a measurement sheet from the list box or enter a name for a new measurement sheet.

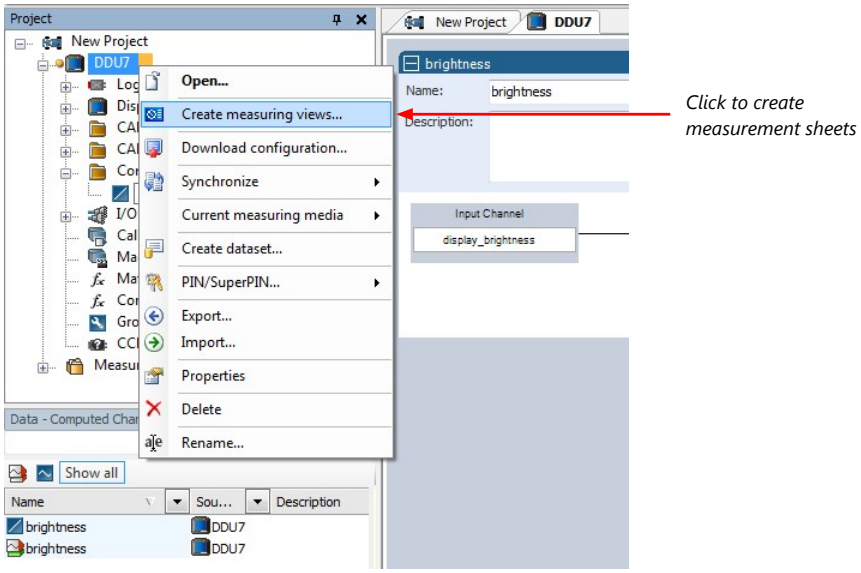




Select existing sheet from list or enter name of new sheet



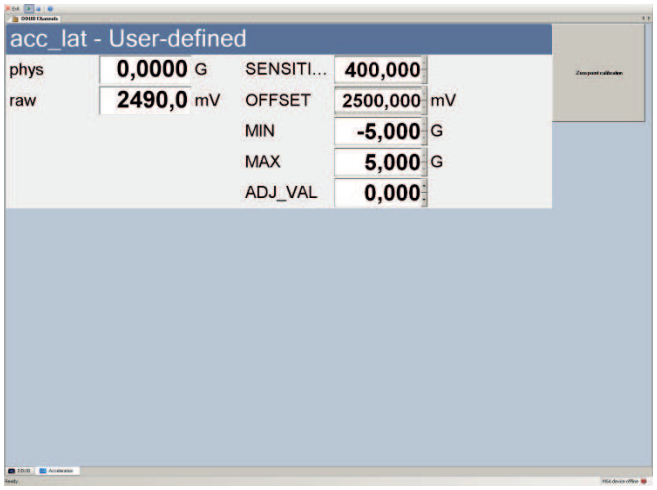
2. To create the sheets, right-click on C 80 and select ‘Create measurement views…’ from the C 80 context menu.



The automatically created sheet is inserted in the Project Tree under ‘Measurement Container’ and ‘Device Channels’. If the C 80 is connected to RaceCon and the status is green, live values of the channels are shown.

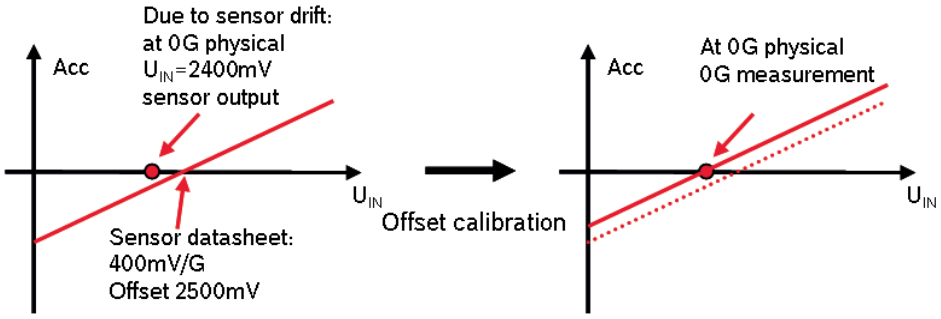
13.1.2 Using the measurement sheets

1. When RaceCon is online, press the ‘F11’ key to switch from ‘Design Mode’ into ‘Race Mode’. The measurement sheet is extended to full screen. The button for offset calibration is active.
2. Switch between different sheets using the tabs at the bottom of the window.
3. Press the ‘Esc’ key to return to ‘Design Mode’.



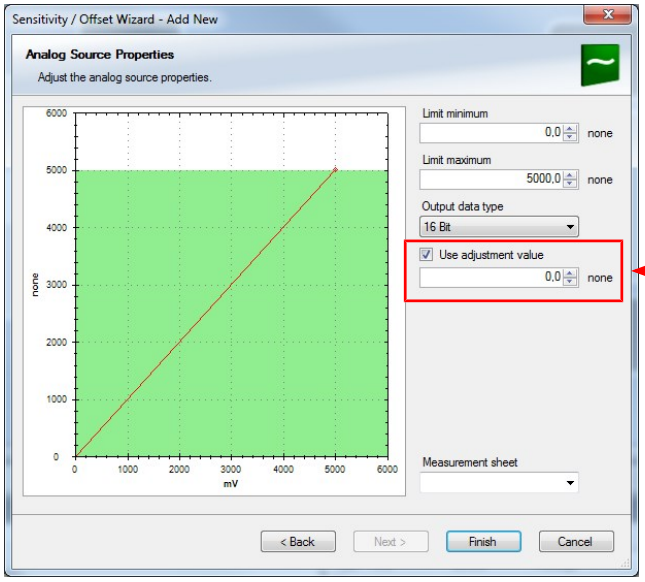
13.2 Online calibration of measurement channels

- Analog sensors drift with age, temperature, etc.
- Manual calibration is necessary
- Solution: online offset calibration
- Example: acceleration sensor



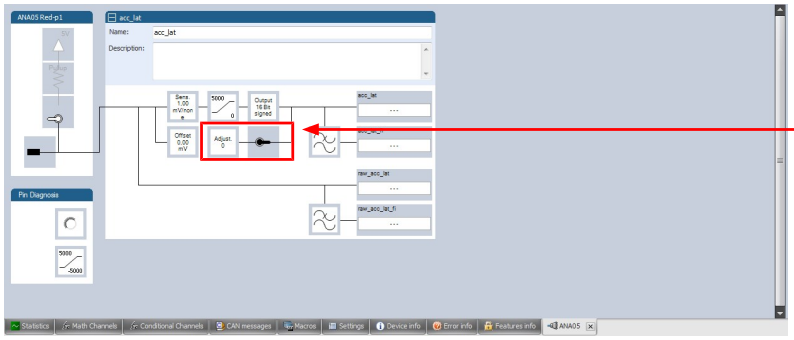
13.2.1 Enable online offset calibration for measurement channel

During creation of the measurement channel



Check box to enable online offset calibration and enter desired physical target value

In the channel view



Activate switch to enable online calibration

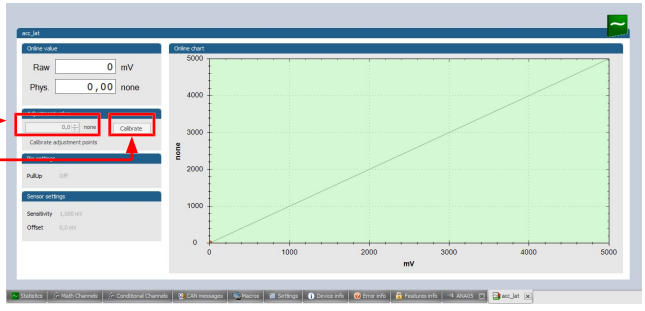
13.2.2 Performing the online offset calibration

C 80 has to be connected to RaceCon to calibrate the sensor's offset.

1. Apply the desired physical condition to the sensor (e.g. 1 G to an acceleration sensor).
2. Open the measurement channel's online page by double-clicking on the measurement channel name in the Data Area.
3. Enter the physical target value (e.g. 1 G) and press the 'Calibrate' button.

Calibration target value

Initiate calibration

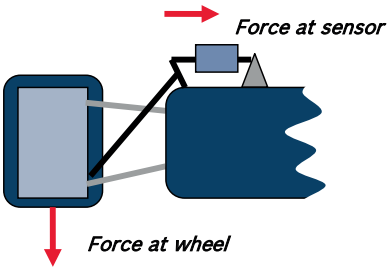


The sensor's offset is now calibrated.

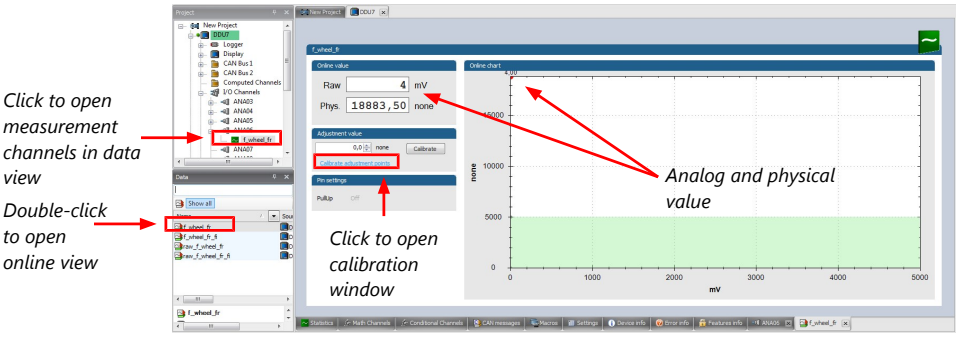
13.3 Online calibration of multipoint adjustment channels

Example: measurement of wheel force

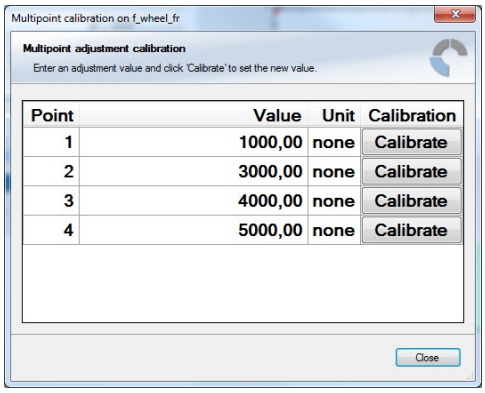
- Physical property ‘wheel force’ not directly measureable
- Load transfer through suspension kinematics
- Physical value at sensor position defined by vehicle
- Curve definition by online adjustment at vehicle



1. Create a multipoint adjustment measurement channel. To create a multipoint channel, see chapter ‘Configuring a multipoint adjustment [▶ 66]’.
2. Download the configuration on the C 80. To connect the C 80 to RaceCon, see chapter ‘Setting up a new RaceCon Project [▶ 16]’.
3. Click on the desired channel in the C 80 Project Tree.
4. Double-click on a measurement channel in the Data Area to open the online view.



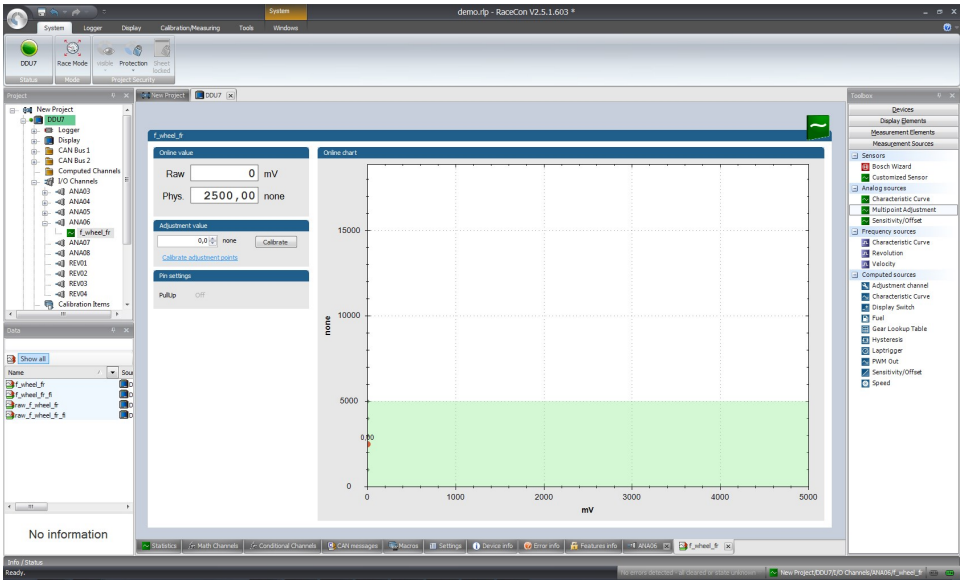
5. Click on ‘Calibrate adjustment points’ to open calibration window.



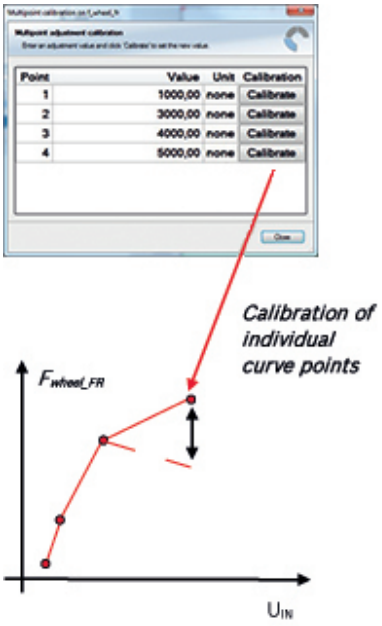
6. Apply the desired physical condition to the sensor (e.g. by applying a force on the wheel).
7. Enter the physical value in the value column of the desired calibration point (e.g. 745 N).

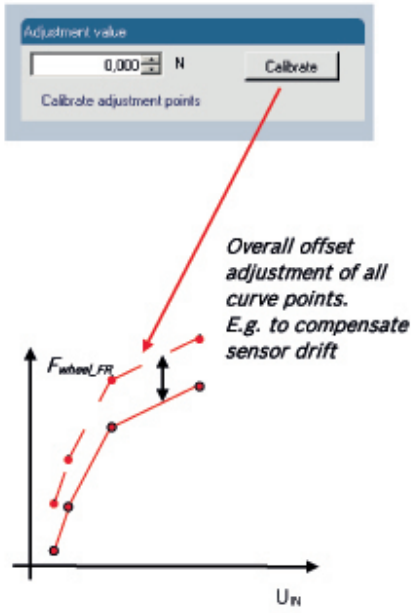
8. Press the ‘Calibrate’ button of the desired calibration point.
9. Repeat for all curve points.
10. Click ‘Close’ when done.

The calibration curve is displayed in the online view.



Adjustment points vs. offset adjustment



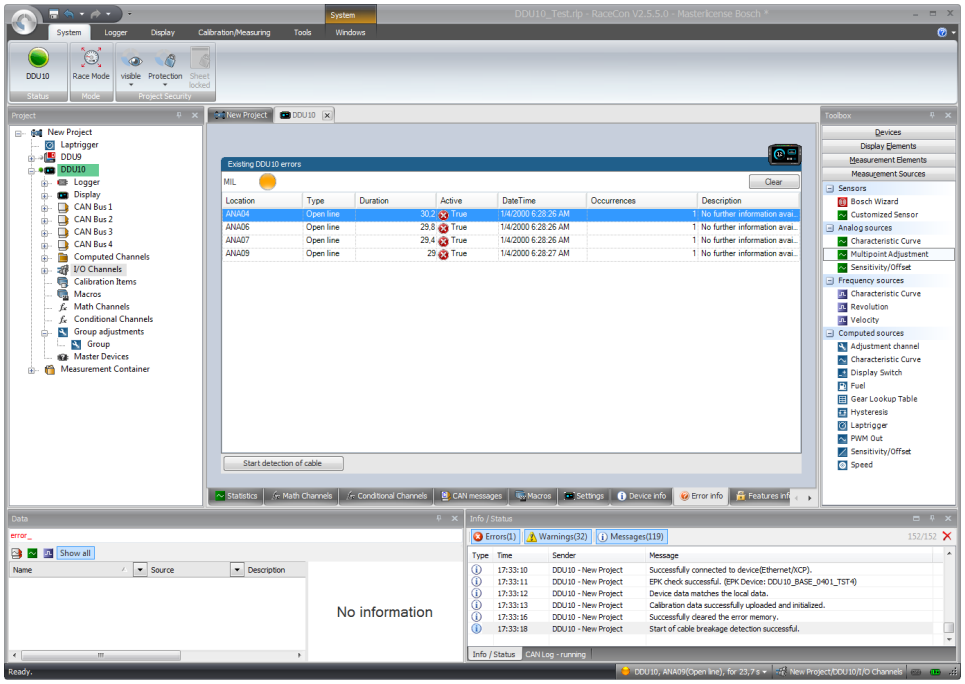


14 Error Memory

In this chapter “Error Memory”, a lot of screenshots are created by way of example for DDU 8. Please consider this and replace the product name ‘DDU 8’ in this case with the name of your product.

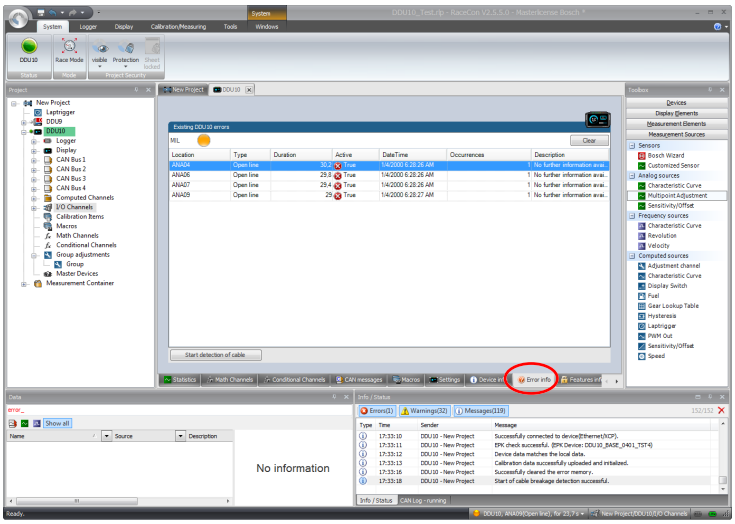
14.1 Error memory representation in RaceCon

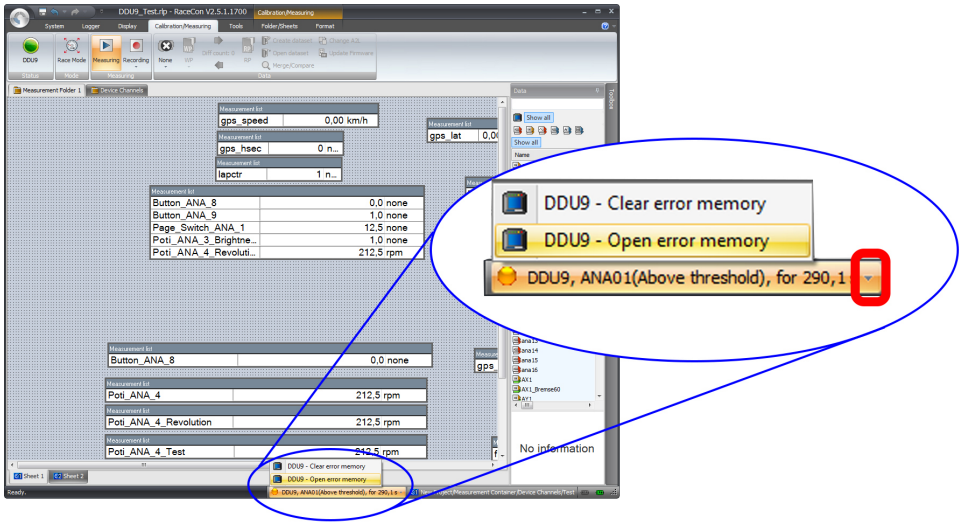
Bosch Motorsport devices feature an error memory. Information on errors can be visualized via RaceCon (online measurement) or can be transmitted via telemetry.



14.1.1 Accessing the memory

The error memory can be accessed as shown in the illustration:





The memory is situated inside the device and is non-volatile. As a consequence, an error which has occurred and has not been cleared by the user will remain in the error memory even after a power cycle. The error state will then reflect if the error is still active or not.

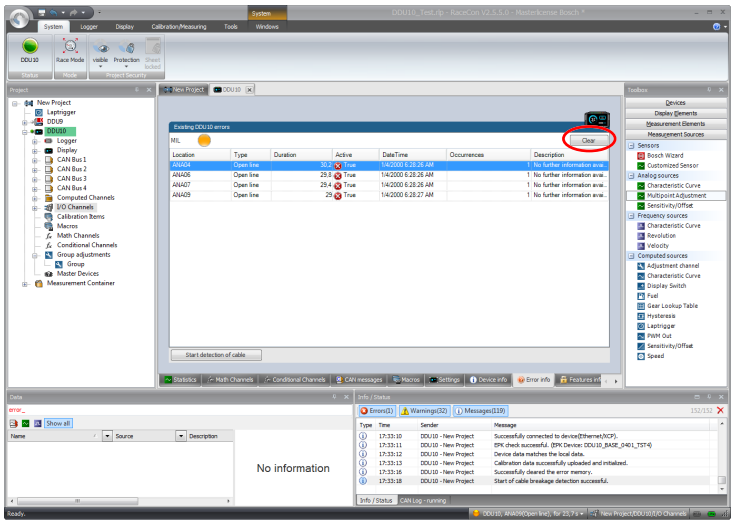
An error is deleted from the list when

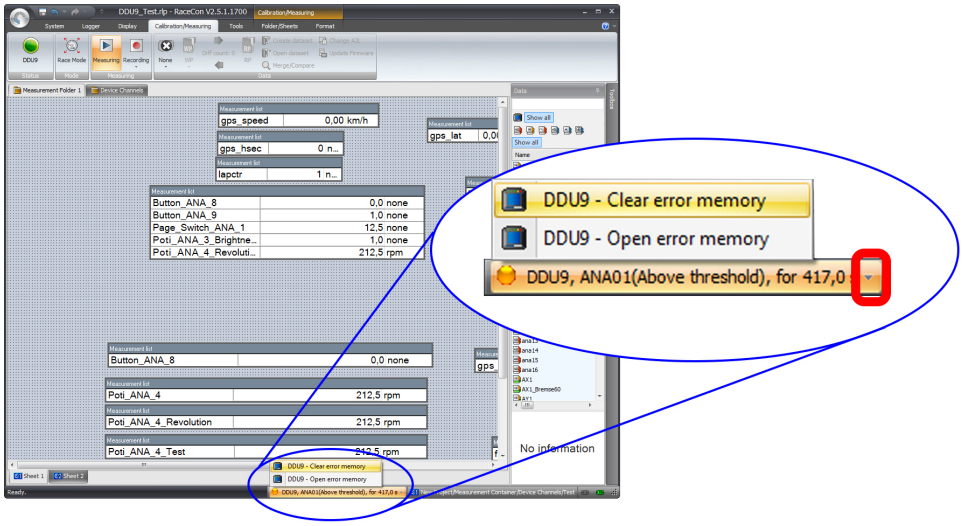
- the user actively clears the error memory
- the user updates the firmware

The error memory is not cleared by a configuration download and is not cleared by a power cycle.

14.1.2 Clearing the error memory

There are two ways of clearing the error memory, both are shown in the following illustration:





14.2 Information on errors available from the error memory

In general, properties of the error memory and properties of an individual error need to be distinguished.

14.2.1 Error Memory Properties

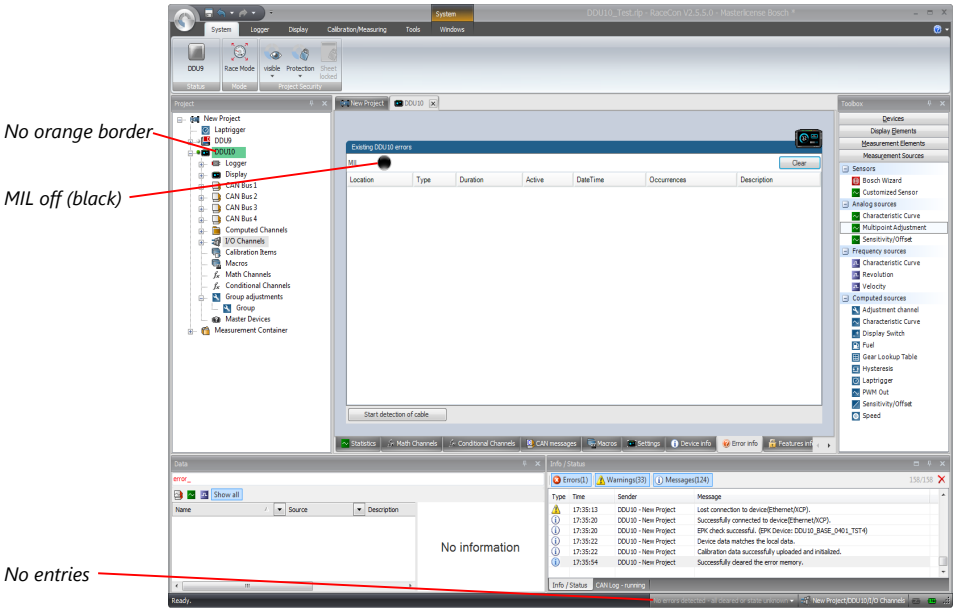
The following property is available for the error memory itself:

- Error Status (device measurement label “error_state”)
  0: no error present in memory
  1: at least one inactive error present in memory, no active errors
  2: at least one active error present in memory

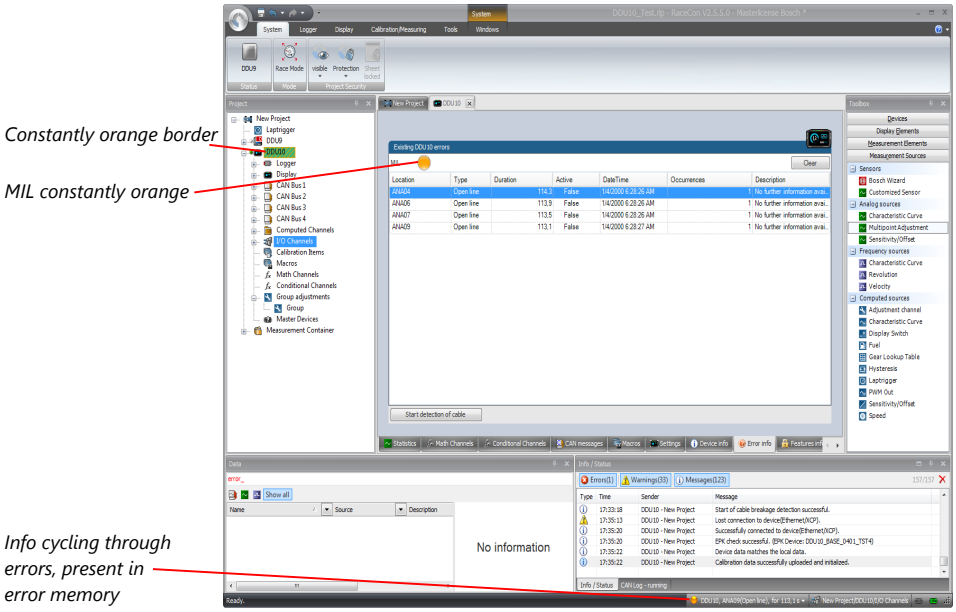
If displayed in a measurement sheet, this property’s value (0, 1 or 2) is translated into a verbal description:

It is also represented by a color scheme within RaceCon (provided RaceCon is online with the system):

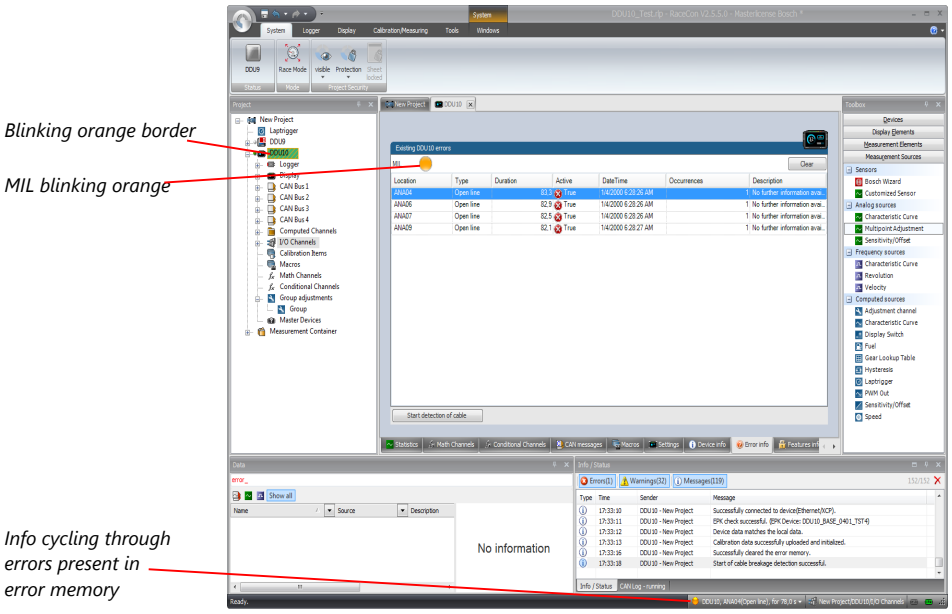
0 (no error present in memory):



1 (at least one inactive error present in memory, no active errors):

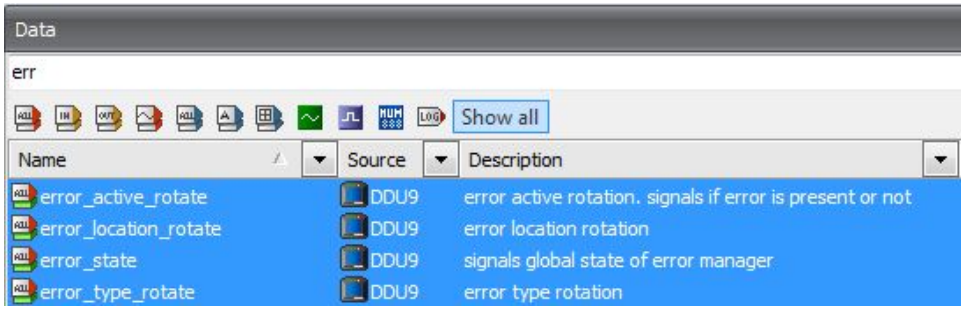


2 (at least one active error present in memory):



14.2.2 Error Properties

The following channels are recognized and memorized inside the devices:

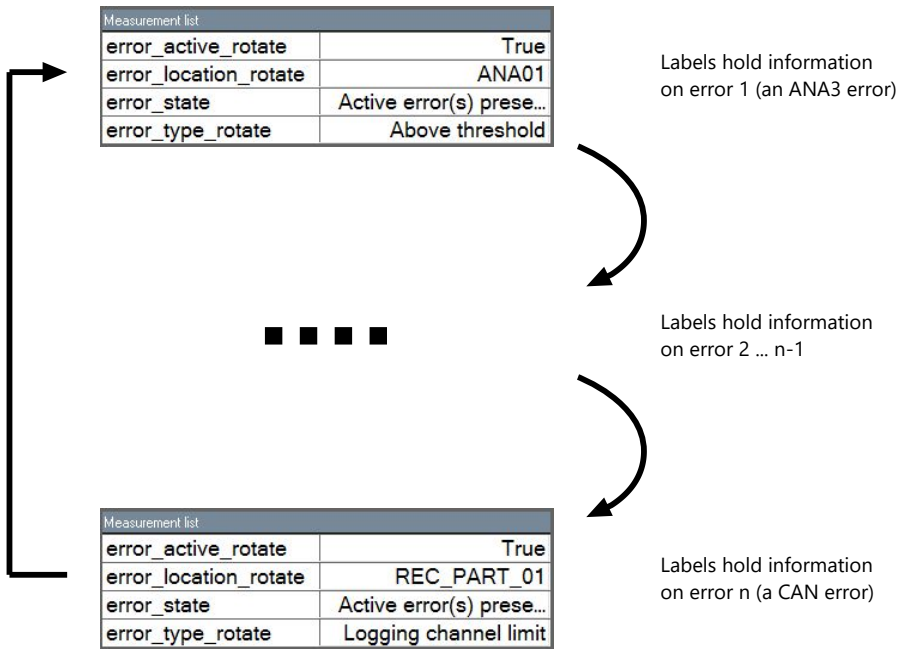


- Error type (device label “error_type_rotate”):
  e.g. “below_threshold” for a violation of the minimum voltage range defined in the configuration, “shortcut_Batt“ for a shortcut to battery voltage etc.
- Error locations (device label “error_location_rotate”):
  e.g. “ANA01” for an error concerning the first ANA channel
- Error durations
  How long has the error been active? If an error encounters a non-active period before being cleared from the memory and is then detected again, the error duration keeps on accumulating. The number of active periods can be seen from the “number of occurrences”.
- Number of occurrences
  How many times has the error been detected since the last time the error memory was cleared.
- Error active state (device label “error_active_rotate”)
  All failure modes are continuously diagnosed; any error detected will be written to the error memory. Once an error is detected, it is qualified as “active”.
  - 1 (TRUE) Error was detected in most recent diagnose run (active)

– 0 (FALSE) Error is inactive: error was not detected in most recent diagnostic run, however the error has not been cleared from the memory by the user and remains in the non-volatile memory

The aforementioned channels (error_active_rotate, error_location_rotate, error_type_rotate) are device specific properties (e.g., C 60) and are not related to the complete RaceCon project (e.g., “error no. 3 from the error memory”). Therefore, only one property label is available in each device. The errors from the error memory (possibly more than one error possible per device) share these three labels. The labels cycle through the errors currently present in the memory and represent the respective property of each error periodically.

The following screenshot shows error properties, which can be displayed or logged:

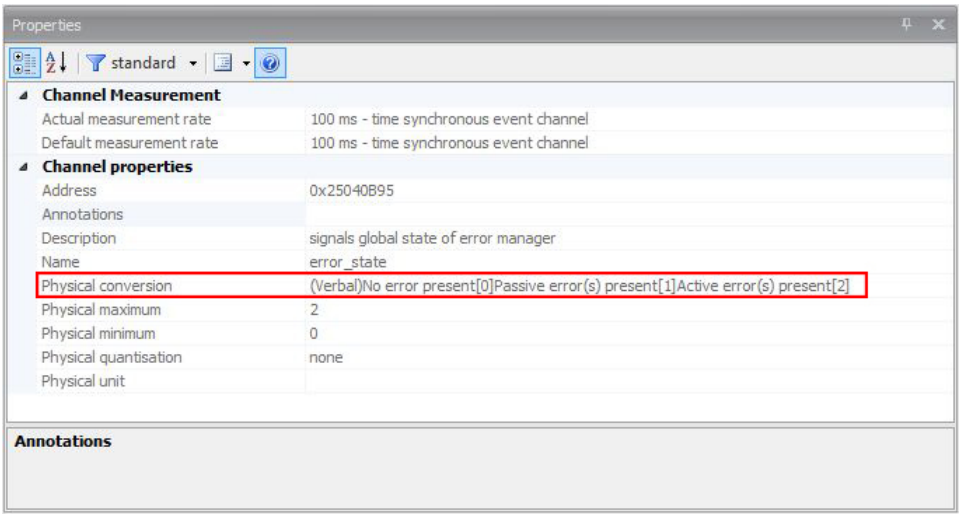


After the last error and its error properties have been displayed, the labels will start again with the first error in the error memory stack and its error properties will be displayed again. Therefore, monitoring these labels over a sufficiently long period provides the information on all individual errors in the error memory.

To understand this behavior, it is recommended to observe the three labels in a measurement sheet (while more than one error is active) and watch the values change periodically:

Measurement list	
error_active_rotate	True
error_location_rotate	REC_PART_01
error_state	Active error(s) prese...
error_type_rotate	Logging channel limit

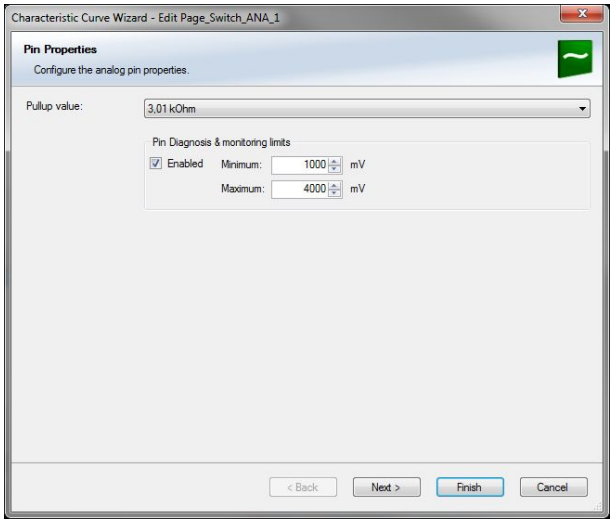
The verbal representation of the numerical codes of these labels can be visualized in the properties window of the measurement page:

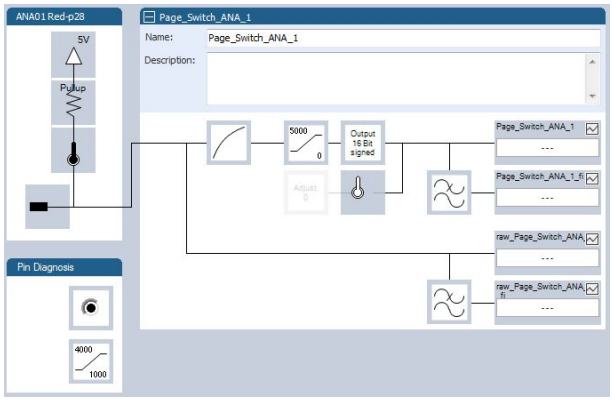


14.3 Analog Input Diagnosis

14.3.1 Monitoring limits / Shortcut Detection / Cable Breakage

The pin diagnosis functionality (check whether measurement is within the desired range) can be activated in the ANA pin setup wizard; to allow for a diagnosis regarding shortcut to ground, shortcut to battery voltage and cable breakage, a minimum / maximum has to be defined.

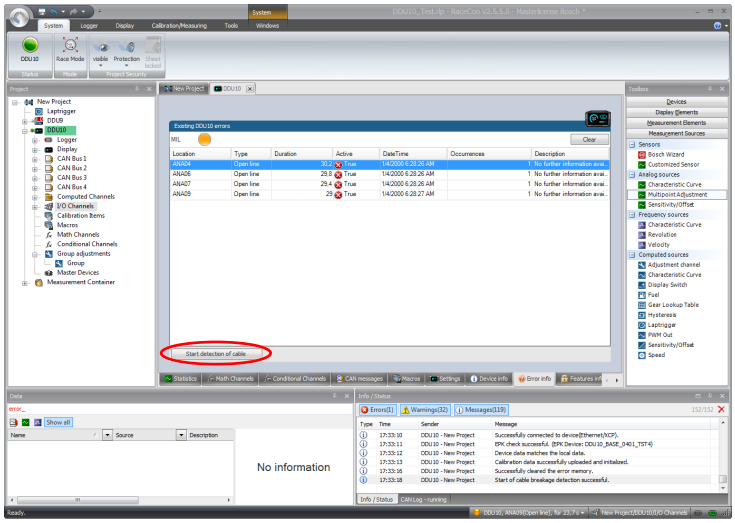




14.3.2 Open Line Detection

The implementation of open line detection consists of pull up resistors being activated and deactivated; evaluating the behavior of the measured value detects cable breakage, regardless of the pull up resistor being activated by the user.

1. Open the Error Memory of the Device.
2. Click "start detection of cable".
3. Check the Error Memory for new fault entries, regarding "Open line errors".



15 Recording

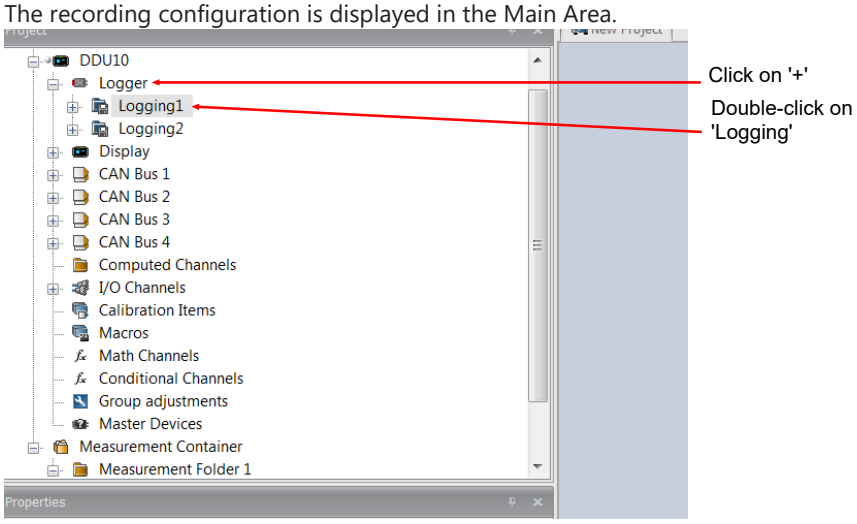
15.1 Features

- Synchronized recording of C 80 analog and digital input channels, C 80 internal measurement channels, ECU data, Data from external sensor interfaces
- Up to two independent recordings
- Measurement rate 1 ms to 1 s
- Two global start conditions (thresholds)
- Up to 16 measurement conditions (fast-slow-switches)

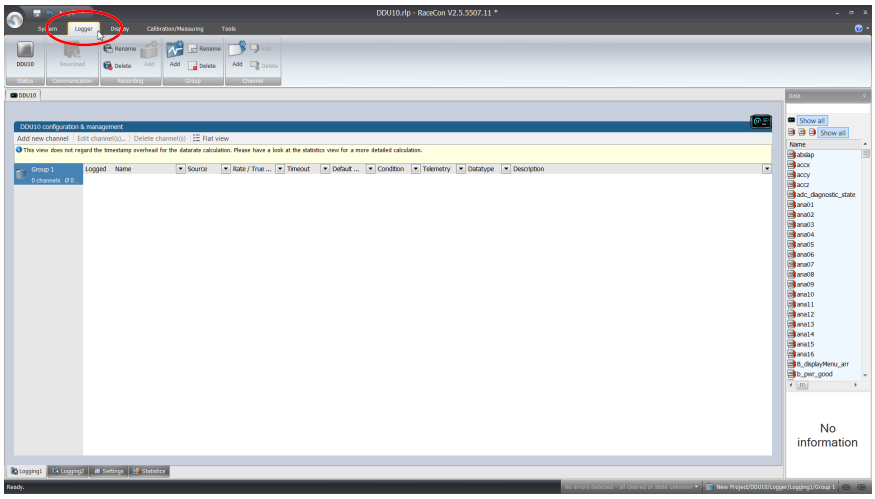
15.2 Configuration of Recordings

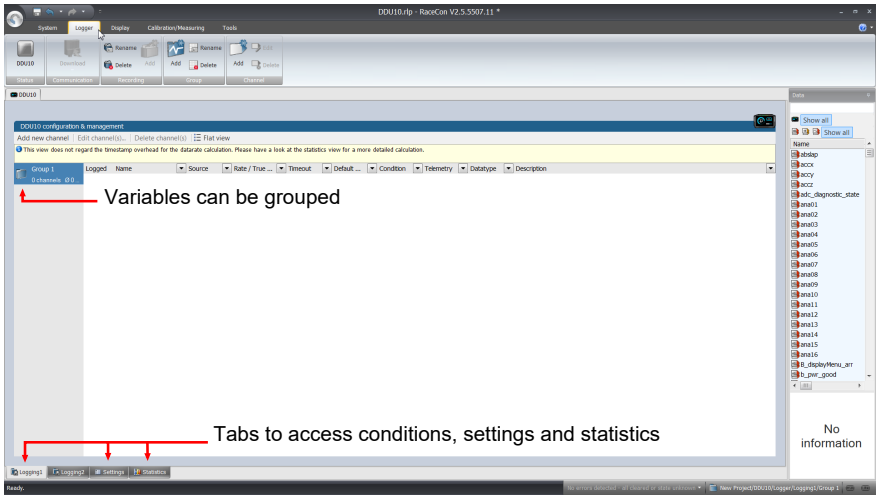
1. Expand the ‘Logger’ list by clicking on ‘+’ in the C 80 Project Tree.
2. Double-click on ‘Logging’ in the C 80 Project Tree.

   The recording configuration is displayed in the Main Area.

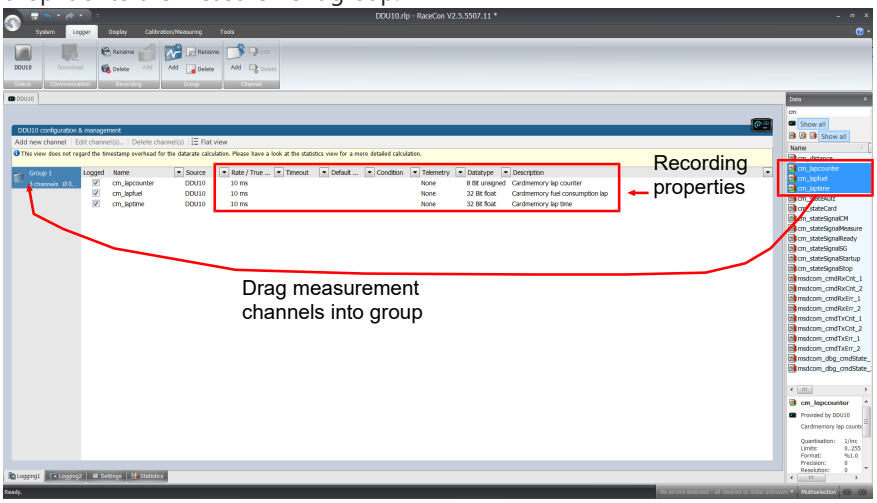


   Alternatively, click on the ‘Logger’ tab to open the configuration directly.



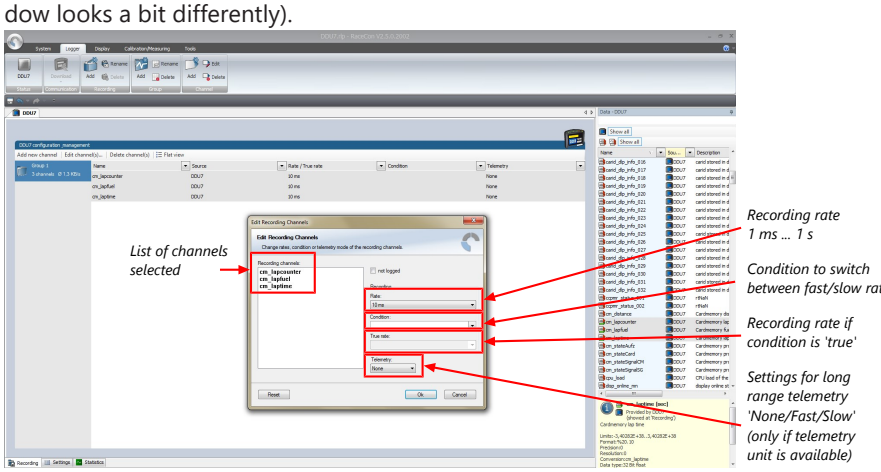


3. To add a measurement channel to a recording, select the wanted channel, drag and drop it onto the measurement group.



4. To edit channel settings, mark the channel(s) and click ‘Edit Recording Channel(s)’.

An ‘Edit Recording Channels’ window opens (if you choose only one channel, the window looks a bit differently).



5. Click ‘OK’ when done.

Note

If no recording condition is defined or the recording condition is ‘false’, measurement channels are recorded at the value chosen in ‘Rate’.

If the condition is ‘true’, measurement channels are recorded at the value chosen in ‘True rate’.

15.2.1 Adding a recording group

Recording channels can be grouped. These groups will also be visible in Darab and will help to get a better overview during the data analysis

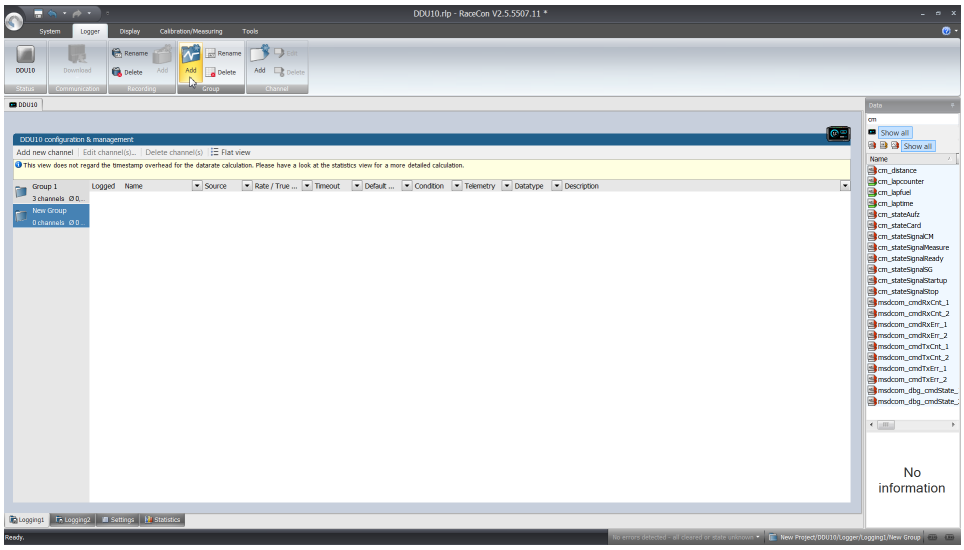
1. To add a new group, select the ‘Logger’ tab.

   The ‘Logger’ window opens.

2. Click on the ‘Add’ button.

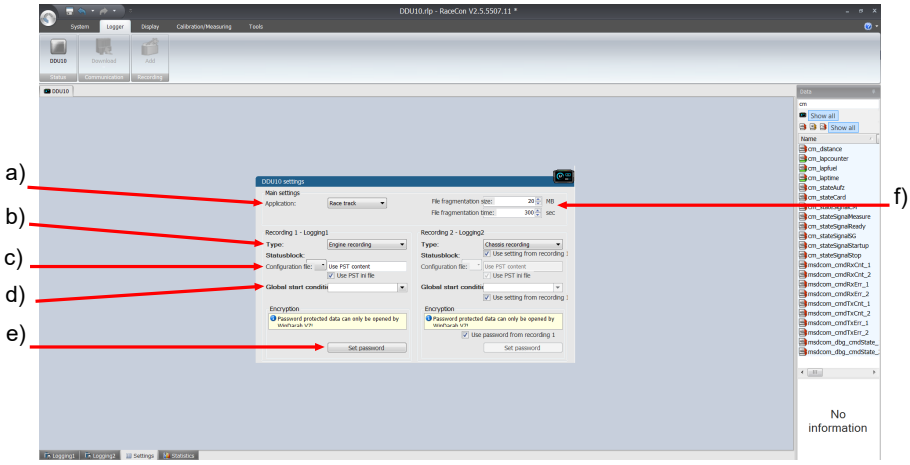
   A new group will be added and can be renamed ‘Gearbox’, ‘Aero’, ‘Engine’, etc..

3. To rename a group, click on the ‘Rename’ button next to the ‘Add’ button.



15.2.2 Logger settings

To display the global C 80 settings, open the ‘Logger’ window and click on the ‘Settings’ tab at the bottom.



a) Choose setting for outing counter mode:

- For testbench (without lap trigger) select ‘Testbench’.
- For racetrack (with lap trigger) select ‘Racetrack’.

b) Choose wether the logging partition shall be named Engine recording or Chassis recording.

c) Advanced setting: Select your logging configuration file, if provided by your Bosch Support Engineer.

d) Choose or create the condition to start recording

e) Enter a password hint and a password (optional).

f) Setting for automatic fragmentation. Do not change!

15.2.3 Recording statistics

The tab ‘Statistics’ shows the channels’ allocation and their current data rate related to the transmission frequency of the C 80 and the whole transmission system.

The overview helps to detect bandwidth bottlenecks of channels. Bandwidth bottlenecks can be solved by changing the logging rate setting for each channel.

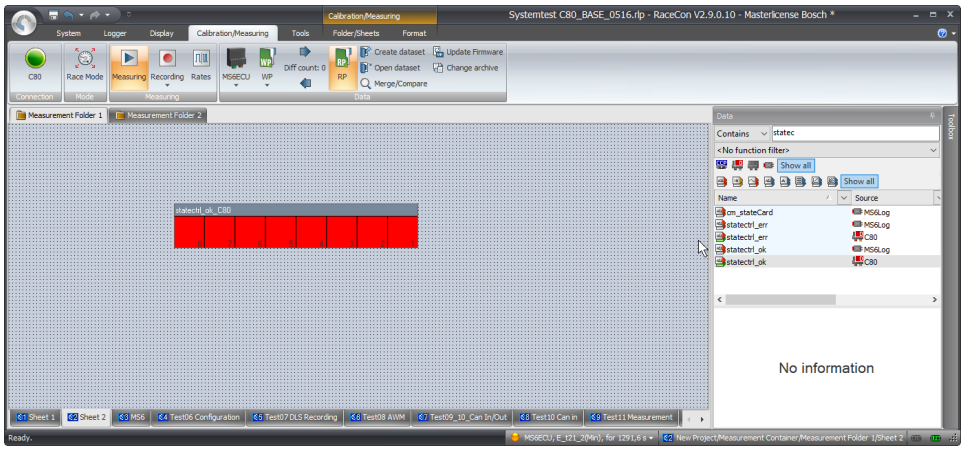
The data rate of the whole system is often less than the data rate of the C 80 and limits the overall transmission speed.

C80 statistics

C80	1 ms	2 ms	5 ms	10 ms	20 ms	50 ms	100 ms	200 ms	500 ms	1 s	sync	Total	Data rate [Kb/s] Recording	Data rate [Kb/s] scrutineering	Data rate [Kb/s] overall
Channels	26 - 28	1 - 3	0 - 6	465 - 471	2	7 - 13	26 - 27	0 - 6	14	0 - 3	0	557	103,02 - 125,40	63,58 - 70,24	166,60 - 195,64
Limit	1080	1080	1080	1080	1080	1080	1080	1080	1080	1080	0	1080			200,00
MS6ECU															
Channels	21	22	18	84	26	0	0	0	0	0	7	178	30,30	73,30	103,60
Limit	1080	1080	1080	1080	1080	1080	1080	1080	1080	1080	1080	1080			300,00
MS6Log															
Channels	1	0	0	0	0	0	0	0	0	0	0	1	0,00	8,00	8,00
Limit	1080	1080	1080	1080	1080	1080	1080	1080	1080	1080	0	1080			200,00
Overall															
Channels													133,32 - 155,70	144,88 - 151,54	278,20 - 307,24
Limit															800,00

15.2.4 Displaying online recording diagnosis ("statectrl_ok")

1. To add a Recording Diagnosis element to a measurement sheet, drag a 'Bit-LED' element from the Toolbox and drop it on measurement sheet.
2. Drag channel 'statectrl_ok' from the Data Area and drop it on the 'Bit-LED' element.



The 'Bit-LED' element shows the state of received channel data in bit-representation. A green highlighted channel means 0, a red highlighted channel means 1.

- Measurement correctly initialized, but recording threshold(s) not reached: 254
- Measurement correctly initialized, C 80 is recording data: 255
- Values less than 254 indicate an error state

15.2.5 Further measurement labels

These additional measurement labels may help you diagnosing the state and operation of the data logging in more detail. There are a few more, but these are usually enough. Please refer to statectrl_ok, mentioned in more detail in chapter 'Recording diagnosis'.

Measurement label	Function
card_part1_size	Size of the first logging data partition in MB.
card_part2_size	Size of the second logging data partition in MB. Attention, second logging can also be stored on first partition, depending on chosen settings (Logger -> Settings).
ftp_UserLoggedIn	This measurement allows to monitor for active FTP connections. RaceCon (WinDCP) and WinDarab may not connect in parallel.
meas_globcond_m01 / _m03	State of the global logging start condition for first / second logging. TRUE means data is actively recorded.
meas_rate_m01 / _m03	Incoming measurement data rate (first / second logging) for further processing. Does not include compression. Active when meas_globcond_m0x is TRUE but may also be active while meas_globcond_m0x is FALSE, if a pretrigger time is configured. In that case data is transferred to the pretrigger buffer, but not necessarily written to storage medias.

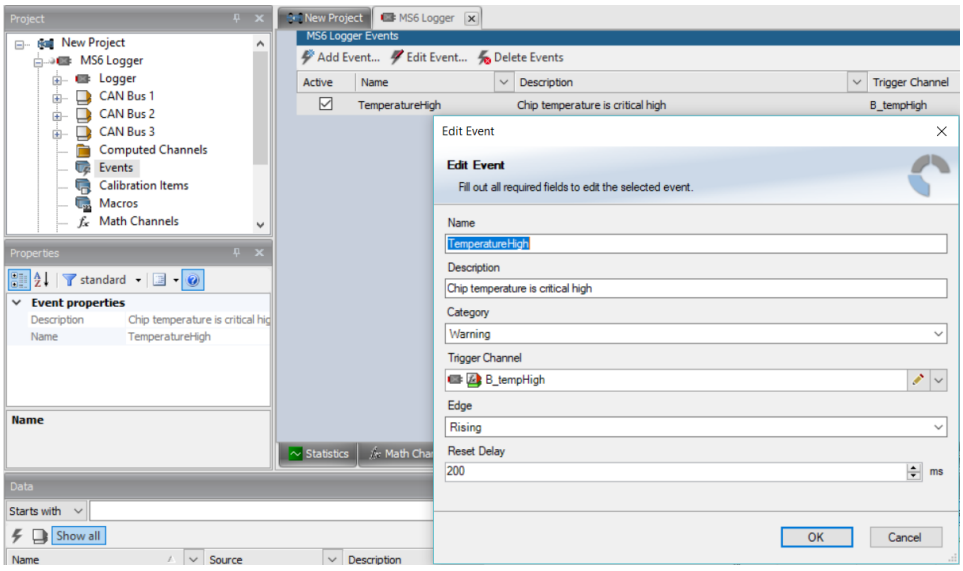
Measurement label	Function
meas_cnt_ecu / _fde	Processed data blocks for first / second logging. This does not ensure writing the data to a storage media, e.g., if pretrigger is configured and meas_globcond is FALSE.
meas_cnt_int / _forked	Processed data blocks per media (internal / USB).
meas_compression_m01 / _m03	Compression factor for first / second logging. For example, factor 2.0 means incoming data can be reduced to half the size, before data is written to storage medias.
meas_pretrig_buf_size_ecu / _fde	Size of data buffered in pretrigger, e.g., while global logging condition is FALSE. Data will be forwarded to storage medias when logging condition becomes TRUE.
meas_backend_buf_size_ecu / _fde	Size of data buffered (for first / second logging) for processing by different storage medias (intern / USB). It is possible, that e.g., internal storage has processed the data already, while USB is still busy writing the data blocks. Data is removed from the buffer as soon as all medias have processed it.
meas_write_rate_intern_001 / _002	Effective data write rate to internal storage media, after compression, for first / second logging.
meas_write_rate_usb_001 / _002	Effective data write rate to USB storage media, after compression, for first / second logging.

15.3 Event logging

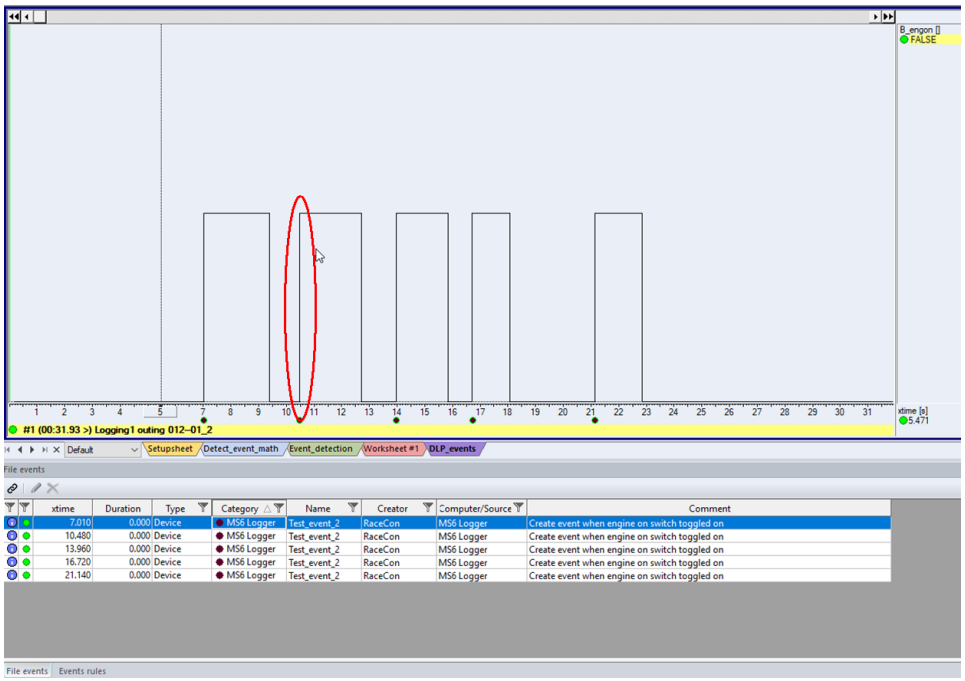
Event Logging implements the possibility to observe a channel if short spikes are expected. With Event Logging, every occurrence of a user defined threshold (more complex conditions are possible) leads to an event being raised. It is listed in a table along with its time stamp, its ID and even with a text string freely definable in RaceCon.

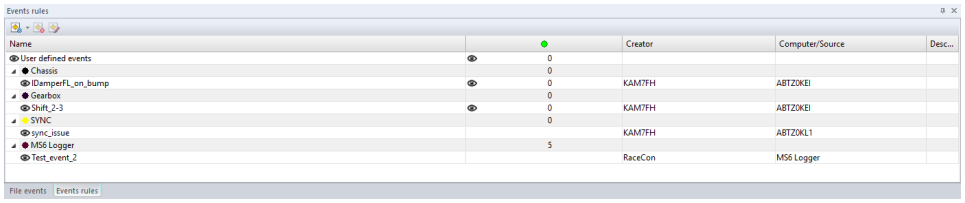
Events are stored as text in logging data and displayed in WinDarab like Darab-Events. Possible use cases are error entry, etc.

Configuration in RaceCon:



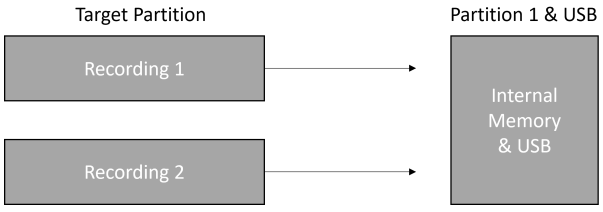
Display in WinDarab:





15.4 Data Logger and USB recording

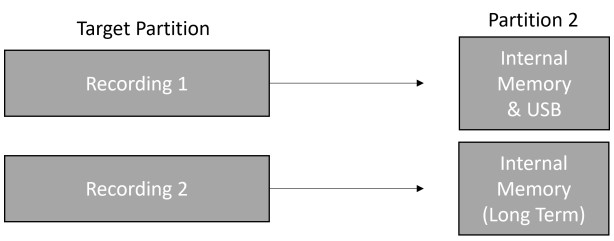
Default settings:



Data from **Recording 1** and **Recording 2** are stored both into the Internal Memory and additionally on the USB stick in copy.

To download the data from the Internal Memory of the logger, the Data Logger must be selected in WinDarab and the data will be downloaded in parallel.

Alternative setting:



Recording 1 is stored on the Internal Memory and additionally on the USB stick in copy. To download this data, the Data Logger must be selected in WinDarab.

Recording 2 is stored on only the Internal Memory. To download this data, the Long Term logger must be selected in WinDarab.

15.5 USB recording

This function requires the installation of Software Upgrades. Look into the datasheet of your device, to see which upgrades are available for your device.

Software Upgrade DATA_USB enables USB recording. To activate Software Upgrade DATA_USB, enter the license key as described in the chapter 'Feature activation' [▶ 21].

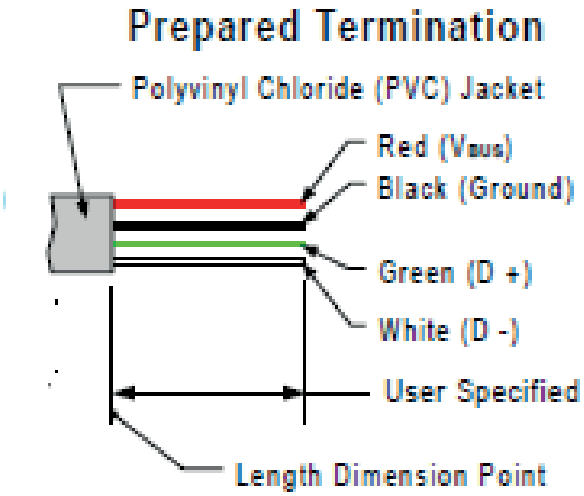
For USB recording, Software Upgrade FULL_LOG_1 should also be enabled.

Wiring harness

Bit	Value
USB_Device_Power	Power (red)
USB_Device_DP	D+ (green)
USB_Device_DN	D- (white)
USB_Device_Gnd	GND (black)

For further information, see the pinlayout of the device.

Colors matching a standard USB cable



Storage device

The recording function can be used with a dedicated Bosch Motorsport USB device. The USB device must be preformatted with the Bosch File System (BFS) in RaceCon before first use.

To format the USB device with the Bosch File System (BFS), do the following steps:

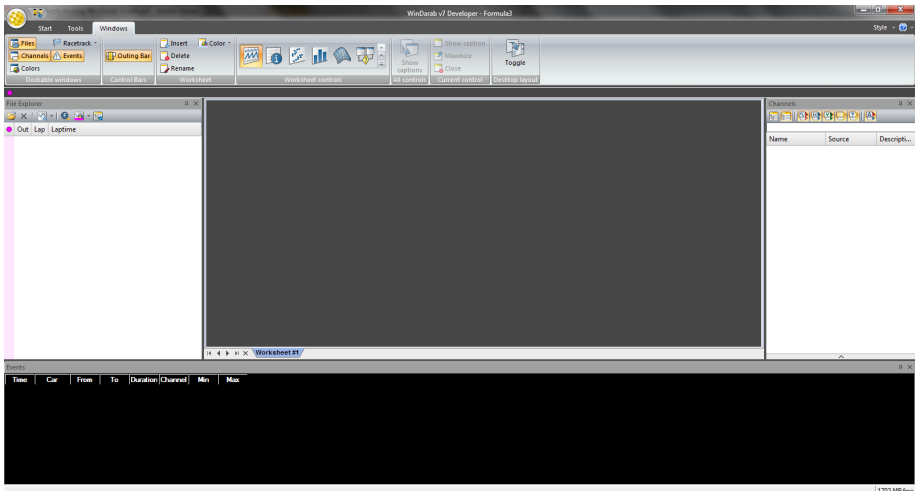
In RaceCon, select 'Tools' - 'Extras' and choose 'Format USB stick'.

Press 'Format'.

An USB device is recognized by Windows as a 'storage medium', but it can only be initialized with RaceCon and read with WinDarab.

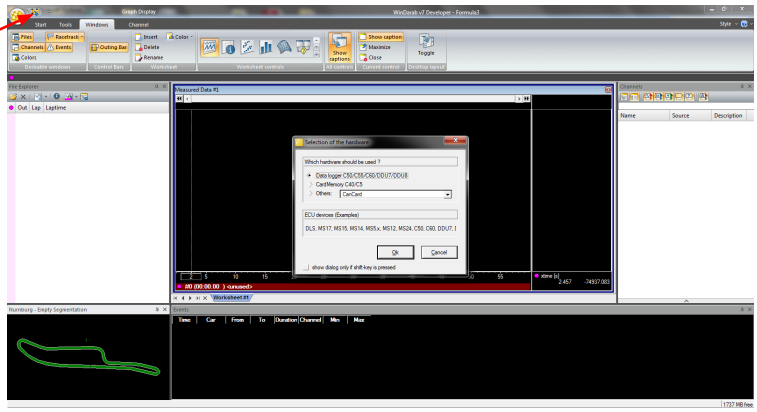
15.5.1 Recording data on USB device

1. Plug an USB device to C 80.
2. Prepare a recording configuration in RaceCon.
3. Power on the system and connect with RaceCon to the vehicle.
4. Download the configuration to the C 80.
5. Record measurement data. If an USB device is present, the C 80 stores the data in parallel on the internal memory and the USB device.
6. Power off the system.
7. Remove USB device from the vehicle.
8. Start the WinDarab software.

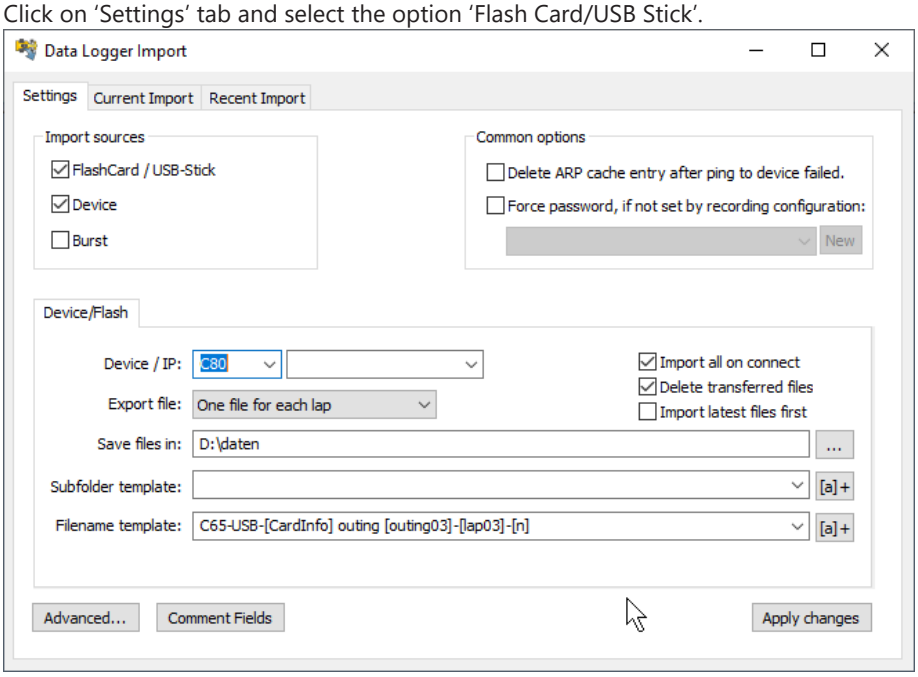


9. Click on the ‘Import/Export’ icon.
10. Select ‘Data logger CXX/DDUX/MSX and click ‘OK’ when done. The ‘Read measurement data’ dialog opens.

Click 'read data from logging device'

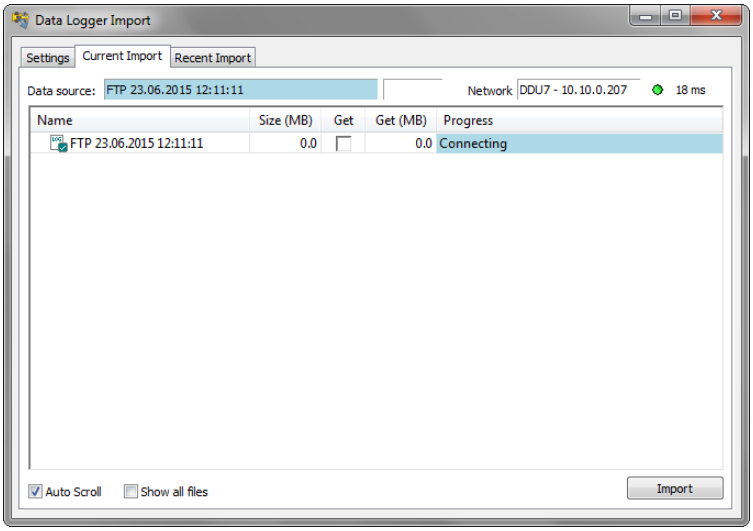


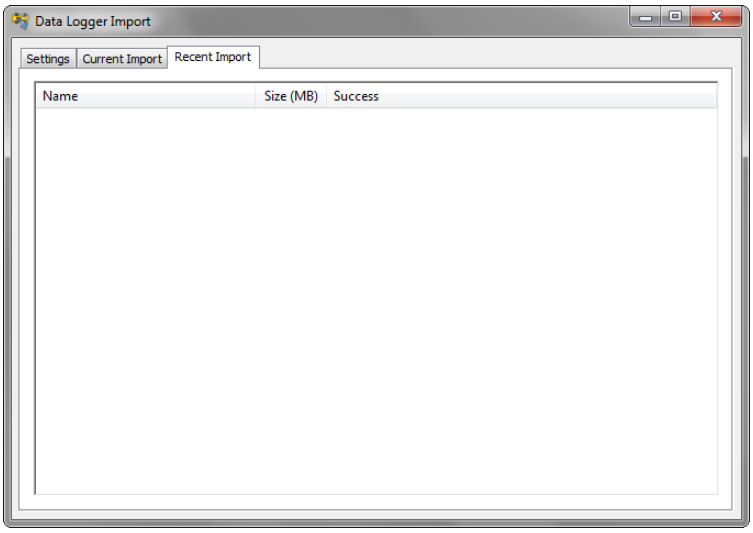
11. Click on ‘Settings’ tab and select the option ‘Flash Card/USB Stick’.



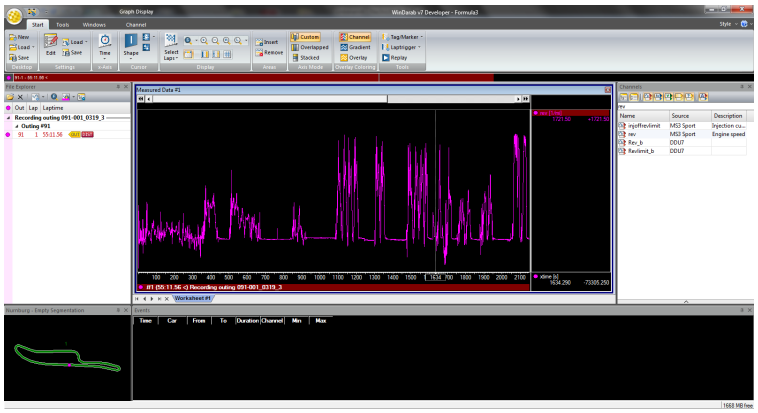
12. Activate ‘Apply changes’.

    Insert the USB device into the PC. Data transmission from device starts automatically. Measurement files are stored automatically in the base folder.





13. Click ‘Close’ when transmission has finished.
14. Click on the Start button and choose ‘Open measurement file’.
15. Select the measurement files from the storage folder.
16. Click on ‘Open’.
17. Click in ‘New Desktop‘ to open a new measurement data window.
18. Drag the desired measurement channel from the Channel list and drop it into the measurement data window. The measurement channel‘s graph is displayed



For more detailed descriptions and instructions, refer to the WinDarab V7 manual.

15.5.2 USB device handling hints

Using the USB device

Always plug the USB device into vehicle before power up to ensure that all measurement data is stored on the USB device.

If the USB device is plugged in after recording has started, only the current data is saved.

Data recorded on the C 80 before the USB device is plugged in will not be saved.

Removing the USB device

Always power off the system before unplugging the USB device!

15.5.3 Troubleshooting

When no data on the USB device is recorded:

Configure the measurement label **usb_mediastate** on a RaceCon measurement view or on a C 80 display page.

The value of **usb_mediastate** reflects the operating condition of the USB bus:

State	Description
0: Wait: Device not found	The USB device is not found (also: waiting for re-plug stick). No USB device inserted. USB device is defect. No electrical connection or wiring harness problem. USB software upgrade not activated (Purchase of unlock code needed).
1: Wait: Device detected	An USB device is found, but not yet installed.

State	Description
2: Ok: Media installed	The USB device is found and is operational (idle). This does not imply that recording data is written!
4: Stop: Device unplugged	The USB device has been removed. The C 80 performs a restart when an USB device is re-plugged in.
5: Error: Media error	The communication to the USB device broke down. The USB device is defect. The USB device is not supported by C 80.
6: Error: Media corrupt	The USB device is not in valid BFS format. (Hint: Re-format the USB device in RaceCon.)

16 Lap Trigger

16.1 Lap trigger (timing beacon)

Why do we need a lap trigger (timing beacon)?

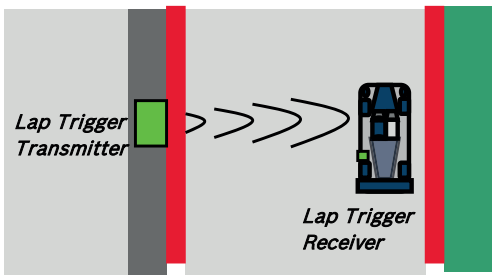
- Vehicle lap time measurement
- Calculation of lap-dependent functions (lap fuel consumption, min/max values)
- Calculation of lap distance dependent functions
- Control of data logging system

Types of Systems

- GPS based (low cost, low precision)
- IR based (low cost, high precision, limited reliability)
- RF (microwave) based (high precision, high reliability)

IR and RF based Systems consists of

- Transmitter (trackside unit)
- Receiver (in-vehicle unit)



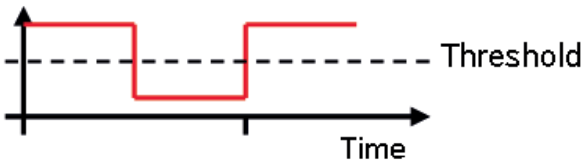
16.1.1 Electrical trigger signal

In C 80 all sources of measurement channels can be used as trigger signal.

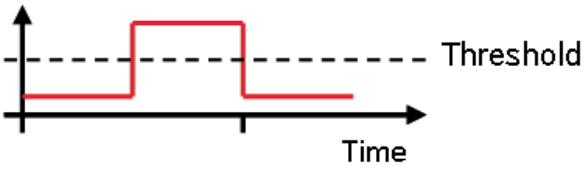
- Analog input
- Digital input
- CAN input

Signal (measurement channel) properties

Low active signal (Bosch triggers): Trigger releases if signal is below the threshold.



High active signal (other manufacturer's triggers): Trigger releases if signal is above the threshold.



Two types of trigger signal:

- Main trigger (end-of-lap at start/finish line)
- Sub-trigger (segment time, optional, not applicable with GPS lap trigger)

Bosch standard:

- Main trigger 20 ms, low active (Recommendation for RaceCon “Detecion Time” setting: 15 ms, Setting must be a slightly shorter period than the signal length of the trigger to avoid a missed trigger due to the update rate)
- Sub trigger 40 ms, low active (Recommendation for RaceCon “Detecion Time” setting: 30 ms)

16.1.2 GPS Lap trigger

The GPS lap trigger uses a GPS signal to trigger the lap timer. To function this timer an external GPS sensor (see GPS Sensor [▶ 121]) has to be connected to the device and a detection point with a detection range has to be defined in RaceCon.

The GPS detection point is defined by the latitude and longitude. The easiest way to get the latitude and longitude of a finishing line is due to a web mapping program such as google maps. With google maps, simply left-klick on the spot where you want to set the detection point. The information about the latitude and longitude will show up, in general the latitude is given at first. You should insert at least five decimal places for sufficient precision.

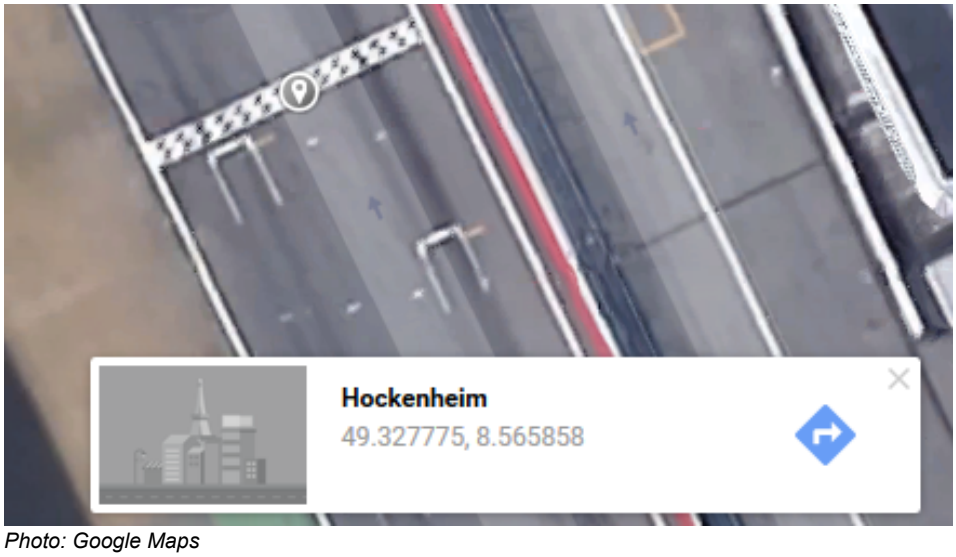


Photo: Google Maps

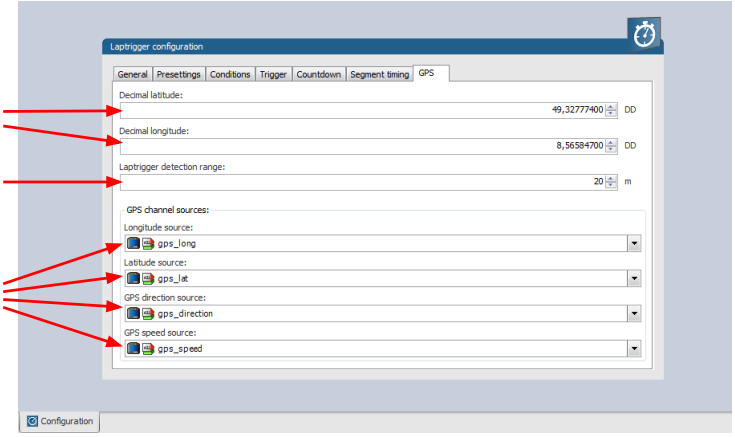
The detection range defines the radius of a circle around the detection point in which the lap trigger can be set. The lap trigger will be set as soon as the distance between the car and the detection point has reached its smallest peak. By this function an imaginary finishing line is calculated inside of the detection circle.

The imaginary finishing line can only be calculated if all channel sources are defined correctly. The latitude and longitude channel sources are mandatory for the functionality. Missing direction or speed source lowers the precision of the system.

Define the latitude and longitude of the GPS detection point.

Define the detection range around the detection point.

Define the channel sources for Longitude, Latitude, Direction and Speed.



Note

The configuration of the sensor update rate and the detection range must insure to receive a valid GPS point in the detection range, despite the occurring vehicle speed near the detection point.

16.1.3 Prevention of false triggers

- Race track topology and transmitter location frequently cause false triggers.
- Software functionality prevents acceptance of false triggers.
- Minimum vehicle speed for acceptance of trigger prevents false triggers while vehicle is stationary in the pits.
- Time based re-trigger protection prevents false triggers due to signal reflections on Home Straight.
- Lap distance based retrigger protection prevents false triggers due to track topology.

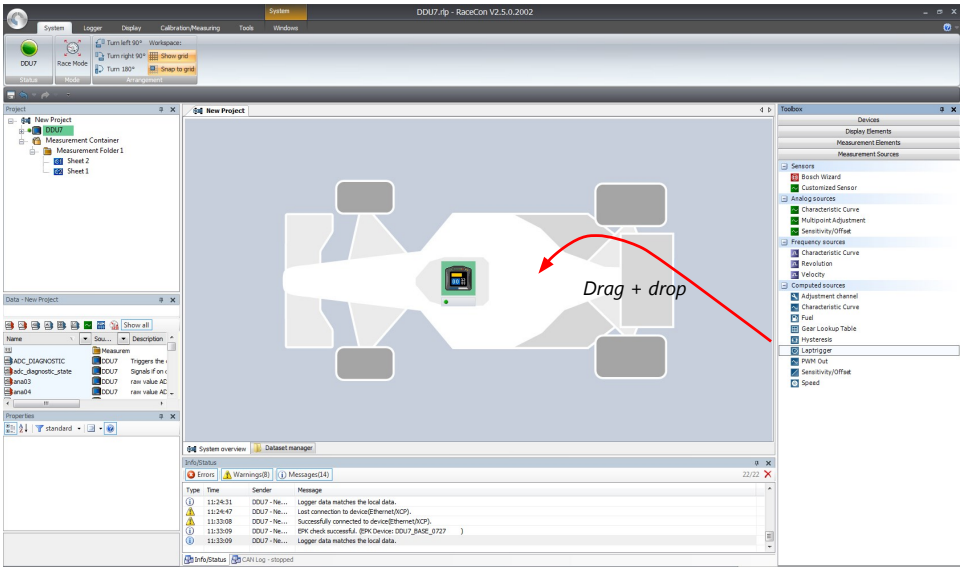
16.1.4 Forced triggers

Lap distance based insertion of ‘forced trigger’.

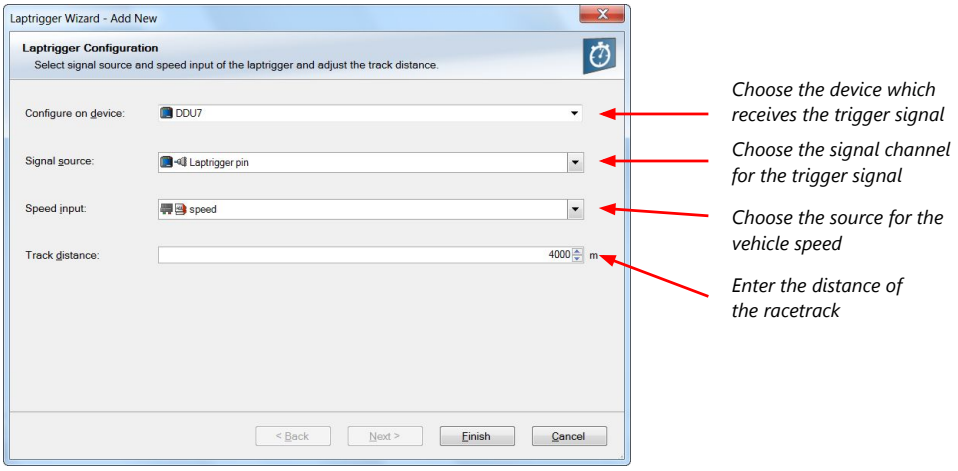
Under race conditions, trigger signals are sometimes missed. Software functionality introduces ‘forced trigger’.

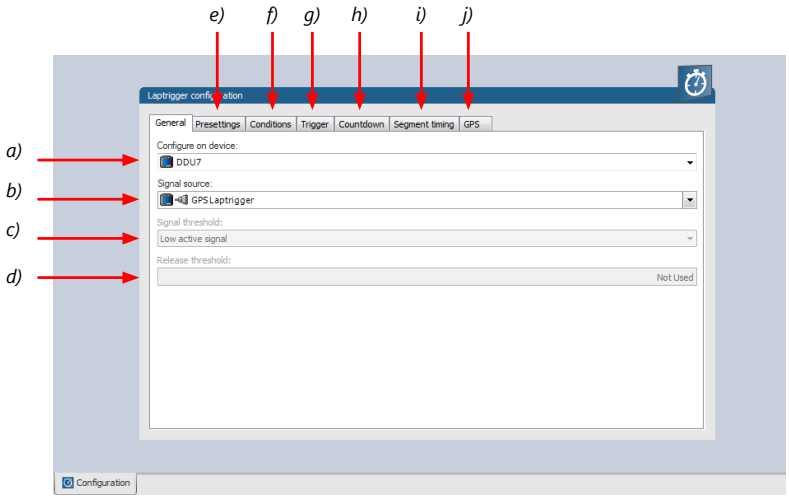
16.1.5 Setting up a lap trigger

1. Click ‘Measurement Sources’ in Toolbox.
2. Drag ‘Laptrigger’ into ‘System Overview’. Do not drop it on ‘C 80’!



A ‘Laptrigger Wizard’ window opens.





a) Change signal device, if desired.

b) Change signal channel, if desired.

c) Choose signal threshold. See chapter 'Electrical trigger signal' for details.

d) Define threshold of input channel signal when trigger is released. Only possible, if no digital source is selected as signal source.

e) Define presettings for trigger. See chapter 'Lap trigger presettings' for details.

f) Define condition settings; change signal for vehicle speed, define speed settings. See chapter 'Distance based retrigger protection' and 'Distance based forced trigger' for details.

g) Define settings for main trigger. See chapter 'Lap timing' for details.

h) Define settings for counddown timer. See chapter 'Countdown timer' for details.

i) Define settings for sub trigger. See chapter 'Segment timing' for details.

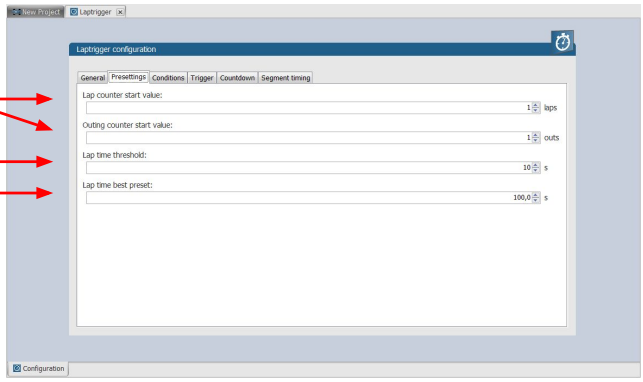
j) Define settings for a GPS lap trigger. See chapter 'GPS lap trigger' for details. Only applicable if the signal source is set to 'GPS lap trigger'.

Click ‘Finish’ to complete the operation. A pre-configured lap trigger window opens.

Preset values for lap counter and outing counter

Minimum laptime that a new 'best laptime' is accepted

Preset value for 'best laptime'

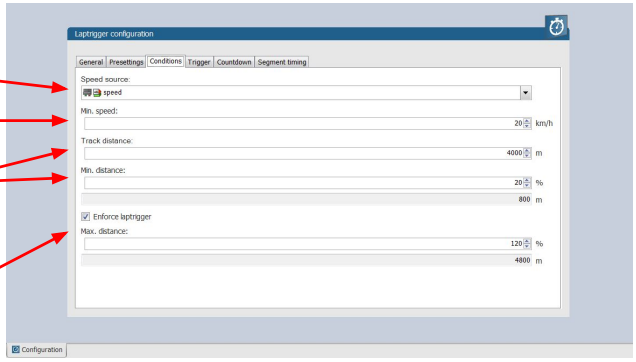


Change signal for vehicle speed, if desired.

Enter minimum speed for trigger release.

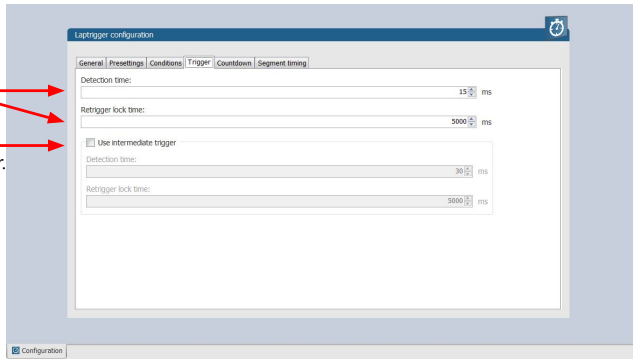
Define settings for distance based retrigger protection.

Define settings for distance based forced trigger.

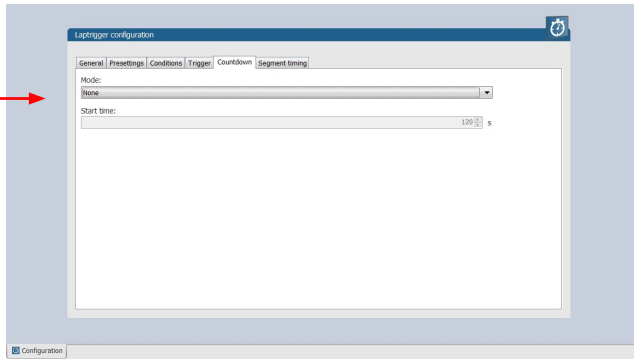


Define settings for lap timing (main trigger).

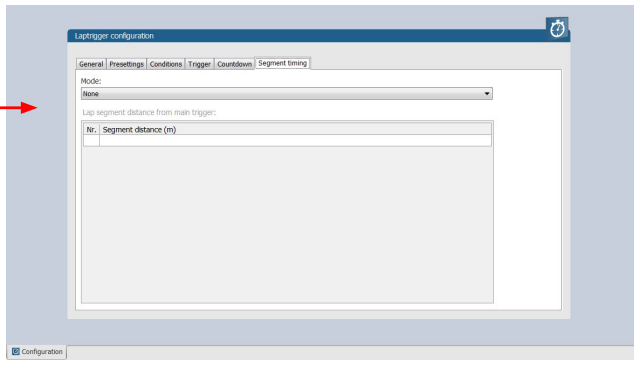
Define settings for sub trigger. Not applicable with a GPS lap trigger.



Define settings for countdown timer.



Define settings for segment timing.

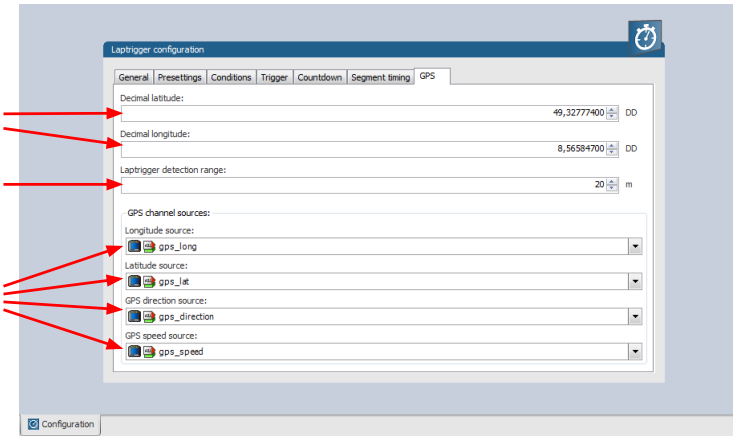


Only applicable for a GPS Laptrigger

Define the latitude and longitude of the GPS detection point.

Define the detection range around the detection point.

Define the channel sources for Longitude, Latitude, Direction and Speed.

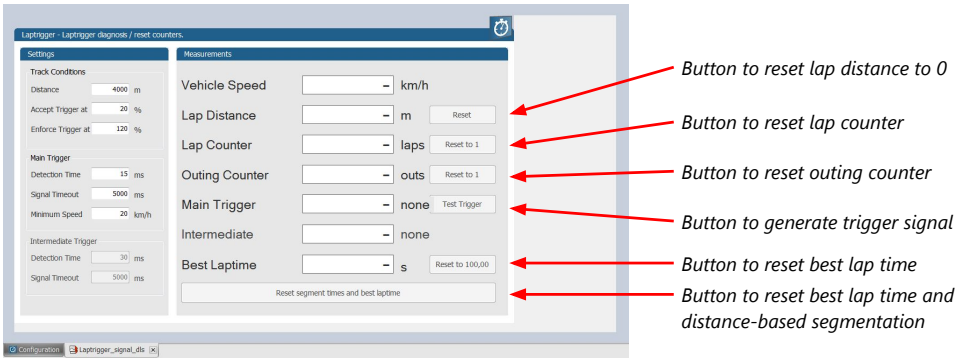


16.1.6 Lap trigger channel diagnosis/counter reset

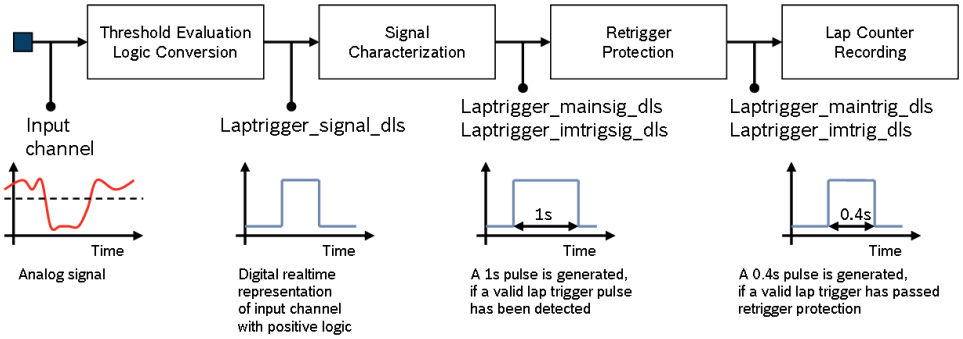
To display a quick lap trigger channel diagnosis and to reset counters use the diagnosis page in RaceCon. Any ‘Laptrigger_xxx’ channel can be displayed.

Double-click on any ‘Laptrigger_xxx’ channel in the Data Area. Example: ‘laptrigger_lap-dist_dls’

A diagnosis window opens in Main Area.

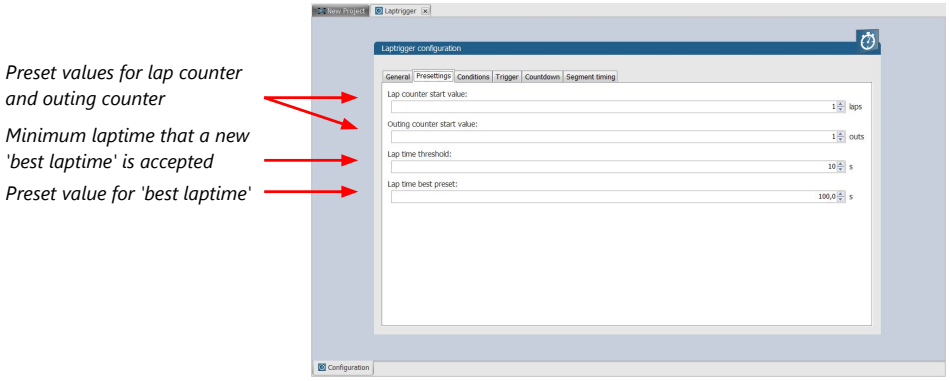


Lap trigger diagnosis scheme

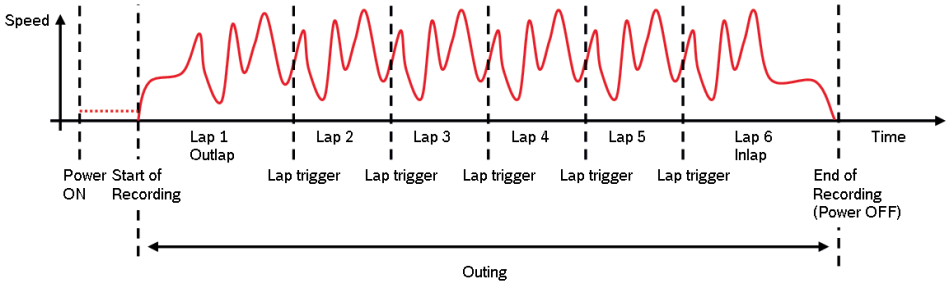


16.1.7 Lap trigger presettings

When the reset buttons on the diagnosis page are activated, these values are used.



16.2 Counting outing/laps/fragments



Functionality

– Power ON: system + measurement is initialized but not yet started

- Global start condition fulfilled: recording starts
- Reception of valid lap trigger: recording of lap completed, new lap starts
- Power OFF or Global start condition not fulfilled: recording of lap completed, system shutdown

The system is counting:

Outing:

- The outing counter is incremented with each power cycle when at least one valid lap (not by forced lap trigger) was recorded

Lap:

- Leaving the pits to lap trigger
- Lap trigger to lap trigger
- Enforced lap trigger (see Distance based forced trigger [▶ 115])

Fragment:

- Test bench operation
- Power cycle on track or box (e.g. engine stalled)
- File fragmentation size [MB], time [sec]

Channels for display

To display counters use the following channels:

Channel	Function
Laptrigger_outcnt_dls	Outing counter
Laptrigger_lapctr_dls	Lap counter
Fractr	Fragment counter

Counting in WinDarab

To automatically name recorded files use filename templates in WinDarab dialog:

Filename template	Function
[outing]	Value of outing counter
[lap]	Value of lap counter
[fragment]	Value of fragment counter

[###03] indicates: ‘always use 3 digits with leading zeros’.

16.3 Lap timing

There are different possibilities to adjust the lap trigger to the timing situation.

The detection time defines the minimum time the input signal changes its state. E.g. a low active signal needs to be below the threshold for min. 15 ms to release the trigger.

Channels for display

To display lap times use the following channels:

Channel	Function
Laptrigger_lapctr_dls	Number of completed laps

Channel	Function
Laptrigger_laptime_dls	Running laptime
Laptrigger_laptime_best_dls	Laptime of best lap
Laptrigger_laptimeold_dls	Laptime of last lap completed
Laptrigger_laptimeseg_dls	Segment time of last segment
Laptrigger_lapctr_dls	Number of completed laps

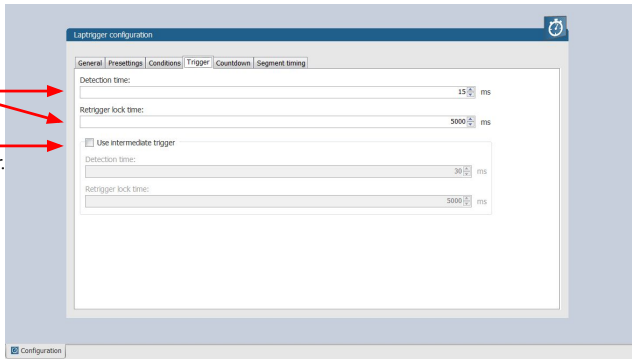
16.3.1 Time based retrigger protection

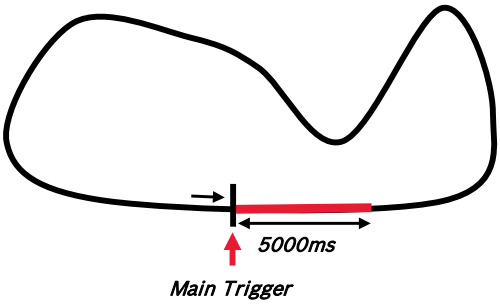
Trigger is locked for 5 s after main trigger was received.

To deactivate time based retrigger protection, set 'Retrigger lock time' to 0 ms.

Define settings for lap timing (main trigger).

Define settings for sub trigger. Not applicable with a GPS lap trigger.





16.3.2 Distance based retrigger protection

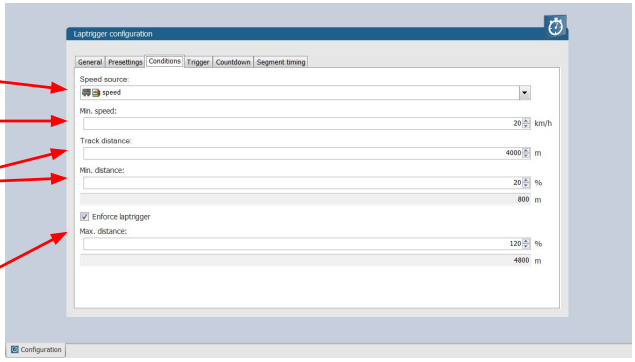
Trigger is locked until configured min distance (i.e. 80 % → 3200 m) of track distance (i.e. 4000 m) has been covered. To deactivate distance based retrigger protection, set min distance to 0 %.

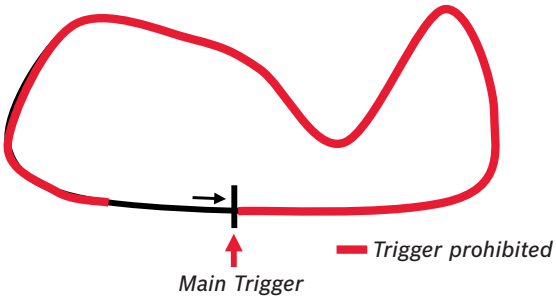
Change signal for vehicle speed, if desired.

Enter minimum speed for trigger release.

Define settings for distance based retrigger protection.

Define settings for distance based forced trigger.

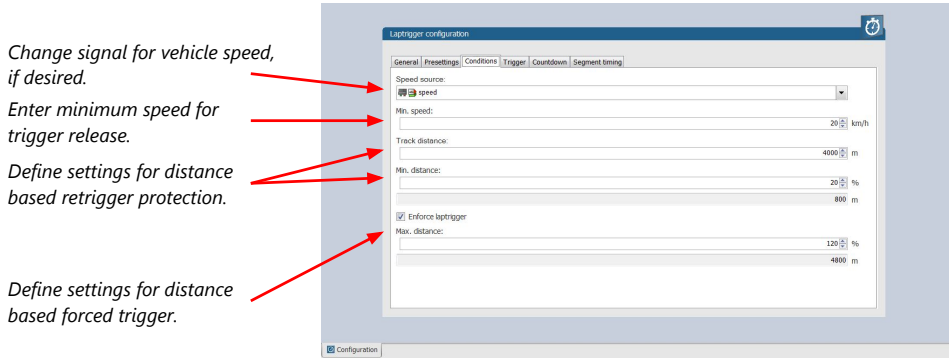


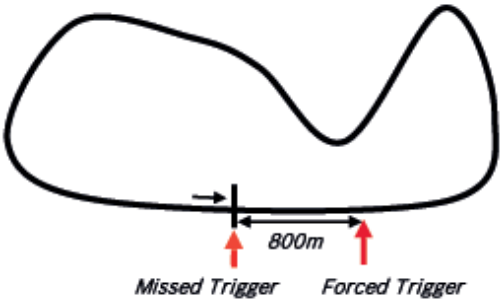


16.3.3 Distance based forced trigger

After a missed main trigger, a forced trigger is inserted, if the configured max. distance (i.e. 120 % → 4800 m) of the track distance (i.e. 4000 m) has been reached. In this case, the channel 'Laptrigger_distlap_dls' starts at the delta between the max. distance and the track distance (i.e. 800 m).

To deactivate distance based forced triggers, uncheck box.





16.4 Segment timing

Segment timing is the calculation of elapsed time for parts of laps (segments).

Segments are defined:

- based on sub-trigger signals (additional transmitters)
- based on distance travelled

Times for segments are compared to:

- Last lap completed
- Fastest lap

Channels for display

To display segment times use the following channels:

Channel	Function
Laptrigger_lapdiff	Time difference between finished lap and last lap
Laptrigger_lapdiffb	Time difference between finished lap and best lap
Laptrigger_lapseg_dlast	Difference of lap segment time compared to last lap
Laptrigger_lapseg_dbest	Difference of lap segment time compared to best lap

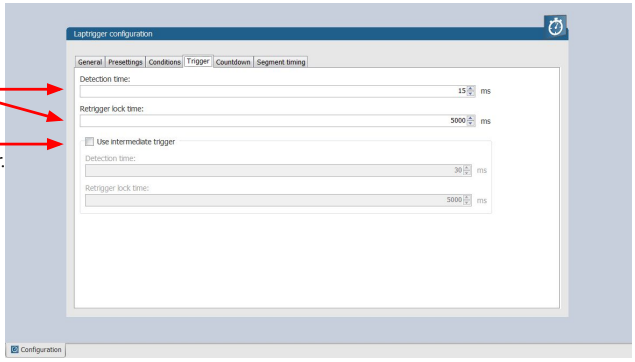
16.4.1 Sub trigger mode

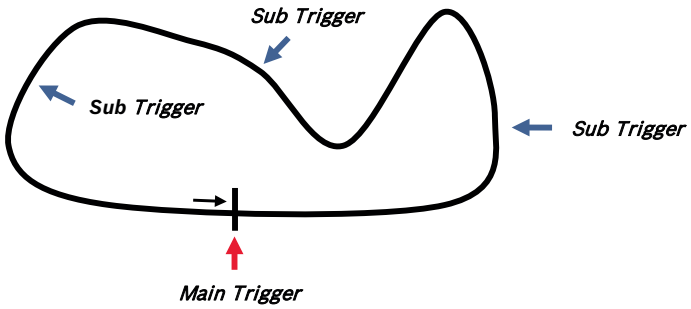
Using main trigger (20 ms pulse) at Start-Finish-Line. 3 sub triggers (40 ms pulse) positioned at 1,000 m, 2,000 m and 3,000 m.

To deactivate sub trigger mode uncheck box.

Define settings for lap timing (main trigger).

Define settings for sub trigger. Not applicable with a GPS lap trigger.





The sub trigger mode cannot be used with the GPS lap trigger.

16.4.2 Distance mode

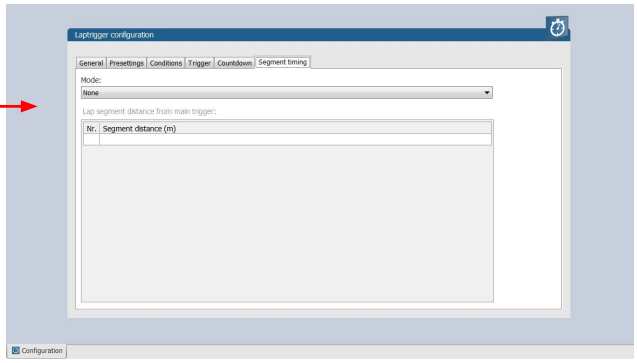
Using main trigger (20 ms pulse) at Start-Finish-Line.

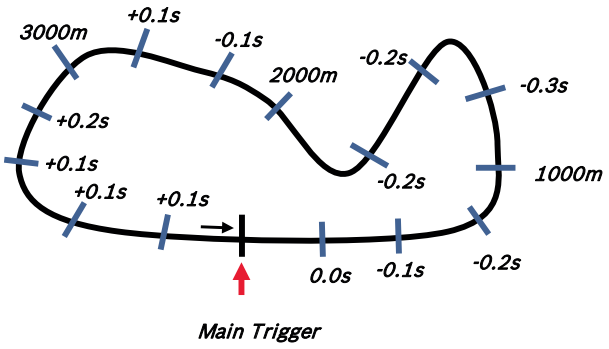
Set ‘Mode’ to ‘Distance’ and enter desired segment distances.

Segment time is automatically calculated at each segment. Time difference to last lap and fastest lap is automatically calculated at each segment.

To deactivate distance mode set ‘Mode’ to ‘None’.

Define settings for segment timing.



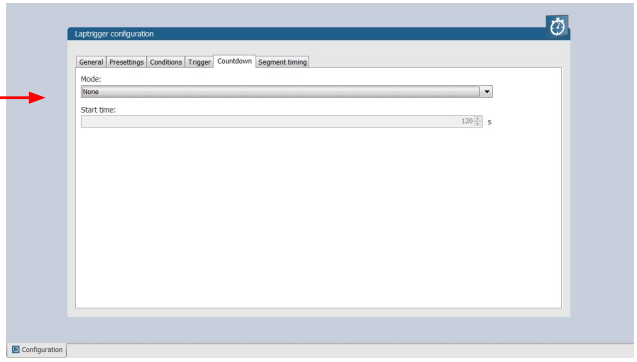


16.5 Countdown timer

Some race classes require a minimum time spent in the pits. An additional lap trigger Tx is configured as a segment trigger positioned at pit entry. The trigger signal starts a timer countdown.

The current value of the timer is stored in the variable **Laptrigger_cntdown_dls** which can be displayed.

Define settings for countdown timer.

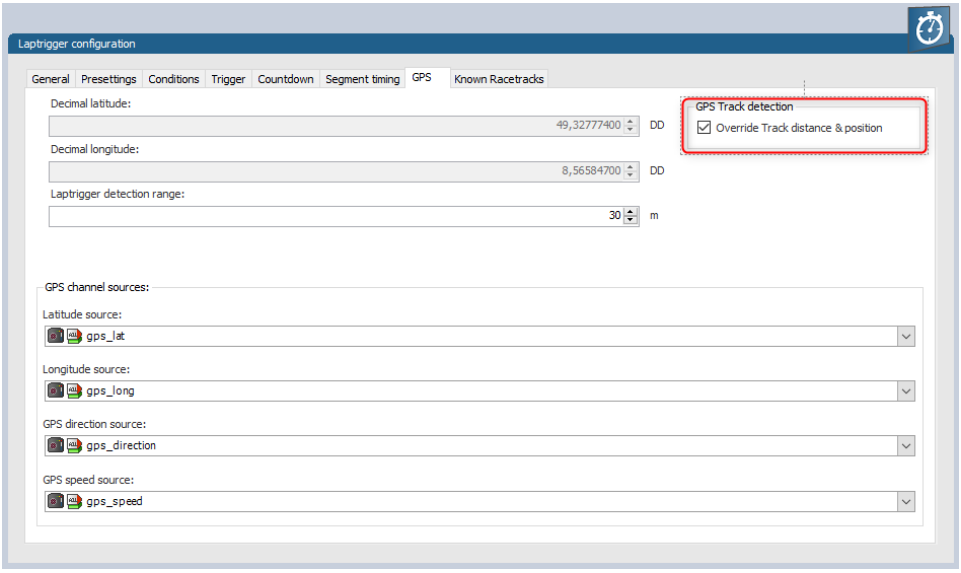


16.6 Automatic GPS Track Detection

With the GPS lap trigger, an automatic track detection can be activated by checking the highlighted box in the lap trigger configuration at the GPS tab.

Activating this functionality will overwrite the GPS trigger point coordinates and the track length with the values of a detected racetrack. The coordinates and the track length will be grayed out in the tool.

The function will compare the current GPS position with the coordinates of the known Racetracks list and use the closest GPS trigger point. If there are track variants with different track length, the system will adapt itself to the correct variant, if it is in the known racetrack list, after ~three detected laps. Please note that the track length needs to be quite accurate, within +/- 100 m, to adapt itself to another variant.

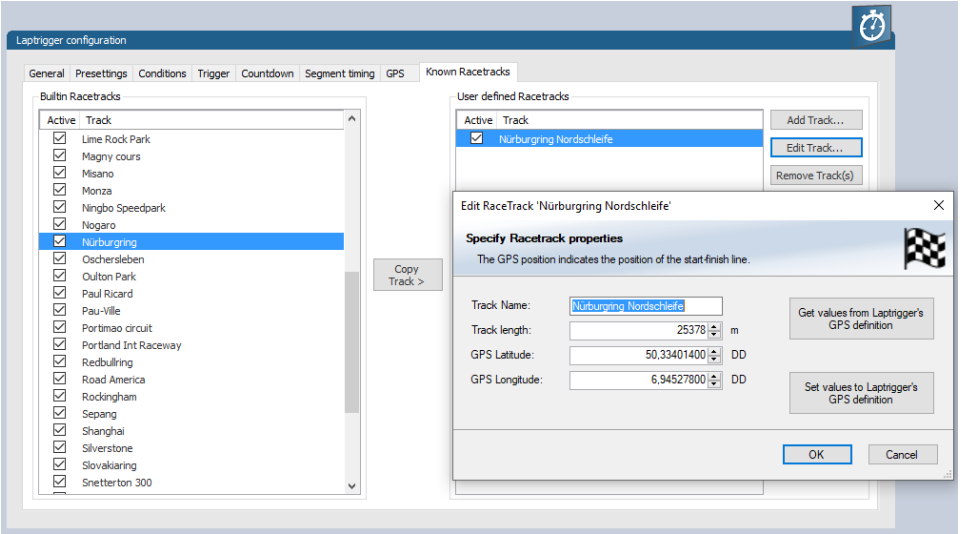


The known Racetrack list can be found in the lap trigger configuration menu within the Known Racetracks tab. It contains a built-in list and a user-defined list. Each track can be activated or deactivated with the checkbox to manually set the variant if needed.

User defined tracks can either be added from scratch with the Add Track button or with the Copy Track button as a modified version of a built in track. Both buttons will open the same Edit Race Track menu.

In the menu a track name, length and the coordinates of the detection point is required. The coordinates can be pulled from the GPS tab with the button “Get values …” or sent to the GPS tab with the button “Set values …”. This allows an easy interaction with the manual GPS lap trigger mode.

The user-defined tracks will be part of the project. If the tracks are required in another project, the lap trigger module can be ex-/imported into another project.



Following signals are assigned to the function:

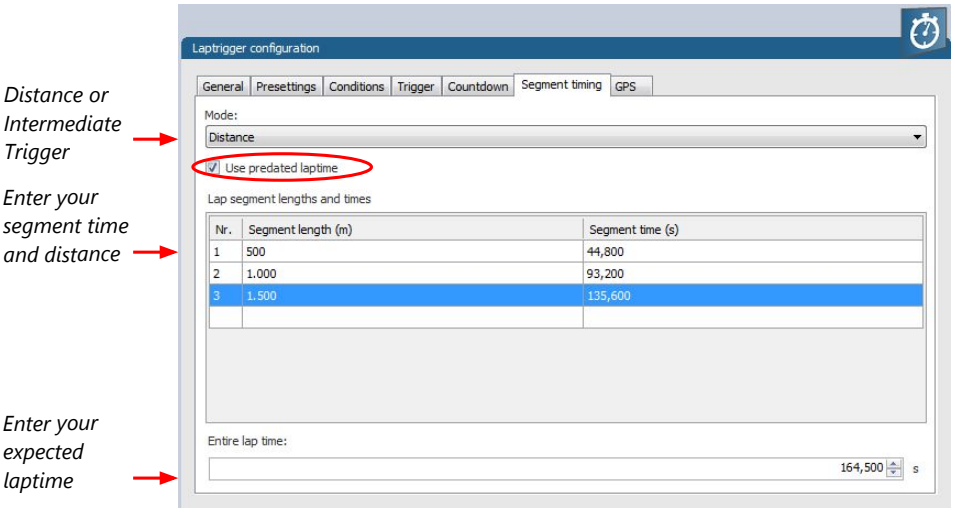
Laptrigger_trackdet_id	Signal will show the track name from the Racetracks list as an enumeration or can show the ID number as raw value. The enumerated name will also be visible in the logging.
Laptrigger_trackdet_laplen	Track length of the used track variant
Laptrigger_trackdet_lat	Latitude GPS coordinate of the used GPS trigger point
Laptrigger_trackdet_long	Longitude GPS coordinate of the used GPS trigger point

16.7 Predicted Laptime

The predicted laptime function allows to compare the current lap- and segment time with the predicted time of an expected lap. Additionally, the function can estimate the laptime of the current lap. This functionality is integrated in the laptrigger module in RaceCon.

16.7.1 Setting up the predicted laptime

To use the predicted laptime function you need to set up a laptrigger as described in the chapter Lap Trigger [▶ 106]. Under the ribbon “Segment timing”, you need to choose your segmentation mode which can either be distance or intermediate trigger based.



For the distance mode, you need to check on an old lap or estimate how long it takes to travel the segment distance. Please enter those values into input field. The values can also be copied and pasted to the input field from an excel sheet as a normal text. In the intermediate trigger, you just need to set the expected time the driver takes to reach the segment trigger.

Note

Please note that the segment time and length is always measured from the start line or where the main lap trigger is set.

16.7.2 Functionality and channel outputs

Following output channels are generated by the predicted laptime function.

Laptrigger_lapdiff_pred_dls	Laptime difference between the predicted and the last laptime
Laptrigger_lapsegdiffpred_dls	lagseg difference between the last segment and the predicted segment
Laptrigger_Lapcurrpred_dls	Estimated laptime of the current lap, based on the predicted laptime and the predicted segment deviations

The channel Laptrigger_lapdiff_pred_dls is updated as soon as the main lap trigger is received. Both other channels are updated as soon as the next segment distance is travelled, or the next intermediate trigger is received.

17 GPS Sensor

17.1 GPS (Global Positioning System)

Space-based global navigation satellite system.

GPS provides positioning, navigation, and timing services to worldwide users.

GPS receiver (sensor) gives digital information about position (longitude, latitude, height), ground speed, course, and status.

Two types of GPS receivers:

CAN output -> Read in messages via CAN Input of C 80 (not covered here)

Serial output -> Read in messages via RS232 Interface of C 80

Serial Interface is characterized by:

Voltage levels: RS232 is standard (+/-12 V), UART (0 V/ 5 V) needs level shifter

Baud rate: 9,600 is standard for GPS, C 80 supports 1,200 to 115,200 baud. GPS Rx interface baud rate must match C 80 interface baud rate. C 80 Baud rate can be set with the 'GPS_BAUDRATE' characteristic Data format: C 80 expects 8 data bits, no parity bit, 1 stop bit (8N1)

17.1.1 Serial interface characterization

Serial Interface is characterized by:

Voltage levels: RS232 is standard (+/-12 V), UART (0 V/ 5 V) needs level shifter

Baud rate: 9,600 is standard for GPS, C 80 supports 1,200 to 115,200 baud. GPS Rx interface baud rate must match C 80 interface baud rate. C 80 Baud rate can be set with the 'GPS_BAUDRATE' characteristic Data format: C 80 expects 8 data bits, no parity bit, 1 stop bit (8N1)

17.2 Protocol

C 80 expects NMEA Protocol (ASCII).

The following messages are decoded:

Message	Function
GGA	GPS fix information
GSA	Overall satellite data
GSV	Detailed satellite data
RMC	Recommended minimum data for GPS
VTG	Vector track and speed over the ground

On most GPS sensors, these messages are activated in the default configuration.

17.3 Sensor recommendation

The system has been tested with the Navilock NL-8004P MD6 Serial PPS Multi GNSS Receiver. This sensor is based on a U-Blox 8 chipset and is fully configurable with the Navilock "U-Center" software. To use this sensor with Bosch Motorsport components the transfer rate, the satellite system and the update rate need to be reconfigured. More information about the configuration can be found in the Appendix.

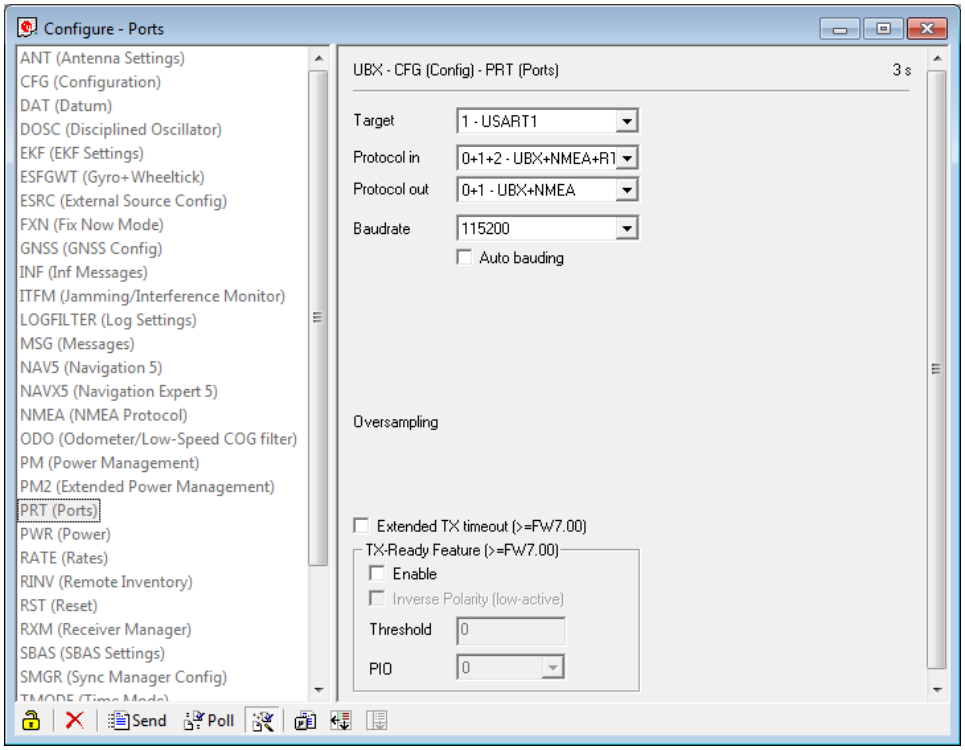
17.3.1 Configuration of the recommended Navilock NL-8004P MD6 Serial PPS Multi GNSS Receiver

For the sensor configuration, the sensor needs to be connected to the Navilock software "U-Center" which is available from Navilock free of charge. Navilock offers a USB connection cable for the sensor.

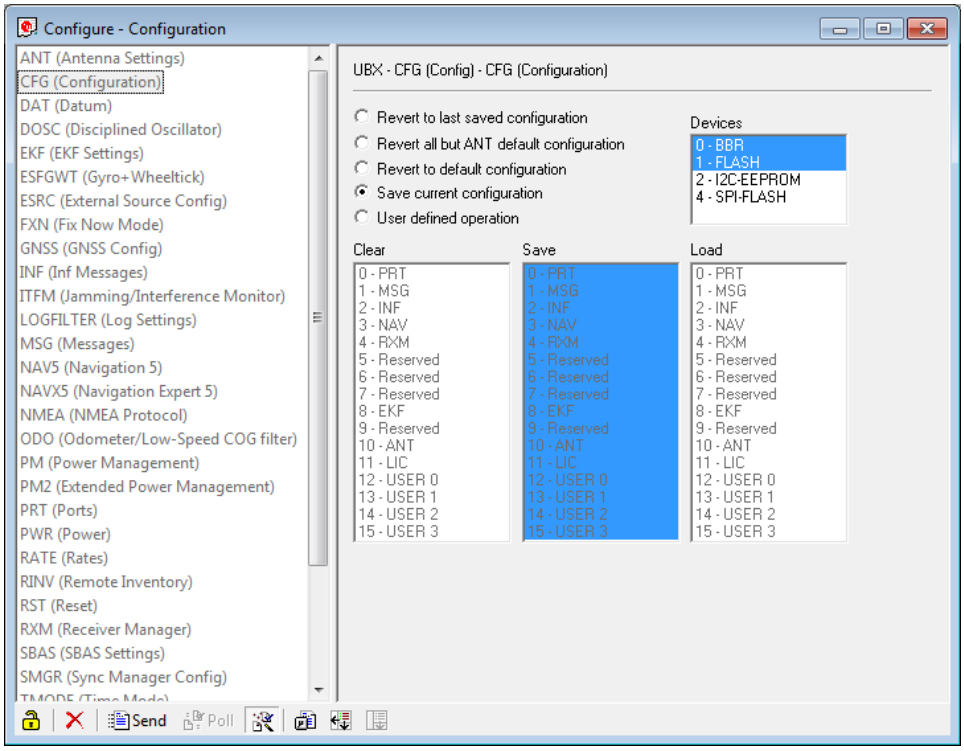
In "U-Center" click **"View"** – **"Configuration View"** to start the configuration. The following 3 points have to be changed:

Transfer Rate

- Click on "**PRT (Ports)".**
- Change the baud rate to a fixed value, this value needs to meet the setting of RaceCon. For a good signal quality we recommend 115,200 baud.
- Click on **"Send"** to store the new setting in "U-Center".

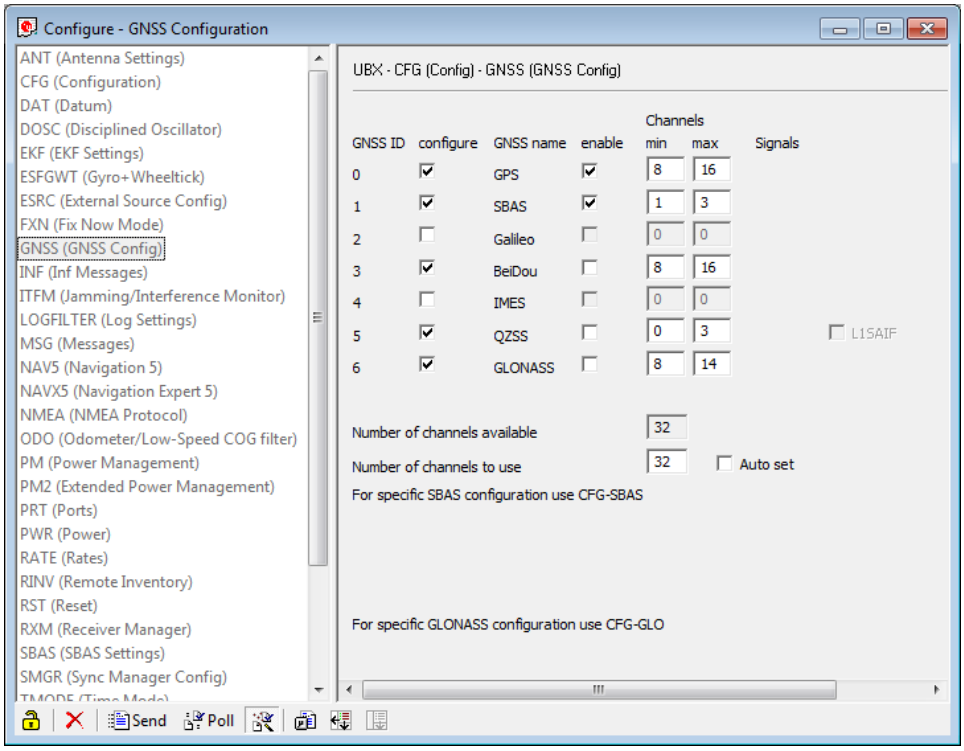


- Click on **"CFG (Configuration)".**
- Click on **"Send"** to save the new setting on the sensor.



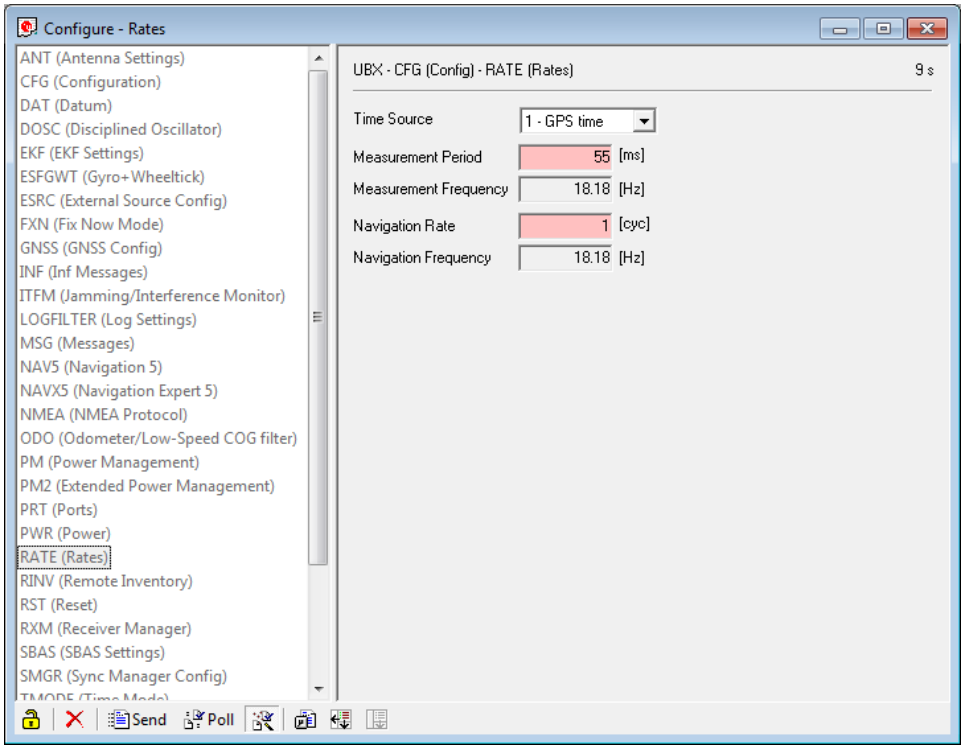
Satellite System

- Click on **“GNSS (GNSS Config)”.**
- Set the ticks as shown in the following picture.
- Click on “**Send**” to store the new setting in “U-Center”.
- As during configuration step 1, click on “**CFG (Configuration)**”.
- Click on“**Send**” to save the new setting on the sensor.



Update Rate

- Click on **“RATE (Rates)”.**
- Change the “Measurement Period” to 55 ms.
- Change the “Navigation Rate” to 1 cyc.
- Values which lead to a lower frequency will lower the precision of the sensor, we recommend the mentioned values.
- Click on “**Send**” to store the new setting in “U-Center”.
- As during configuration step 1, click on “**CFG (Configuration)**”.
- Click on“**Send**” to save the new setting on the sensor.



Note

Sensor needs reception for visible signal.
It takes time to start the sensor.

17.4 Measurement labels

The decoded NMEA messages are copied to these C 80 measurement labels.

Measurement label	Function
gps_PDOP	Position Dilution Of Precision
gps_HDOP	Horizontal Dilution Of Precision
gps_VDOP	Vertical Dilution Of Precision
gps_lat	Latitude +/- [degree]
gps_long	Longitude +/- [degree]
gps_elv	Antenna altitude above/below mean sea level (geoid) in meters
gps_speed	Speed over the ground in kilometers/hour
gps_direction	Track angle in degrees

Measurement label	Function
gps_declination	Magnetic variation degrees (Easterly var. subtracts from true course)
gps_year	Years since 1900
gps_mon	Months since January - [0,11]
gps_day	Day of the month - [1,31]
gps_hour	Hours since midnight - [0,23]
gps_min	Minutes after the hour - [0,59]
gps_sec	Seconds after the minute - [0,59]
gps_hsec	Hundredth part of second - [0,99]
gps_smask	Bit mask over received NMEA sentences (Bit 0 = GGA, Bit 1 = GSA, Bit 2 =GSV, Bit 3 = RMC, Bit 4 =VTG) within last second.
gps_sig	GPS quality indicator (0 = Invalid; 1 = Fix; 2 = Differential, 3 = Sensitive)
gps_fix	Operating mode, used for navigation (1 = Fix not available; 2 = 2D; 3 = 3D)

These measurement labels are arrays, where the indexed element points to the same satellite.

(E.g. gps_info_satsigstrength[3] tells the receiving signal strength of satellite 3. Satellite 3 has the SAT-ID given in gps_info_satid[3])

Measurement label	Function
gps_info_satid[ ]	Satellite PRN number
gps_info_satinuse[ ]	Used in position fix
gps_info_satelevation[ ]	Elevation in degrees, 90 maximum
gps_info_satazimuth[ ]	Azimuth, degrees from true north, 000 to 359
gps_info_satsigstrength[ ]	Signal, 00-99 dB

17.5 GPS troubleshooting

Electrical

Is the transmitter signal of the GPS sensor connected to the receiver pin of serial interface of the C 80?

Is the GPS sensor powered up?

Does the GPS sensor deliver RS232 signal levels?

Is the sensor connected to the „sensor ground“ of the device?

Interface

Do the baud rates of the GPS sensor and the C 80 match?

Is the GPS sensor set up for 8N1 transmission parameters?

Is the GPS sensor set up for NMEA messages?

Are the GGA, VTG, RMC messages activated?

GPS sensor start-up

Does the GPS sensor ‘view‘ the sky?

Did the GPS sensor complete its initial start-up procedure? This may take up to 20 min.

A correct reception is indicated when ‘gps_fix‘ is showing ‘3D Fix‘.

GPS sensor values are frozen

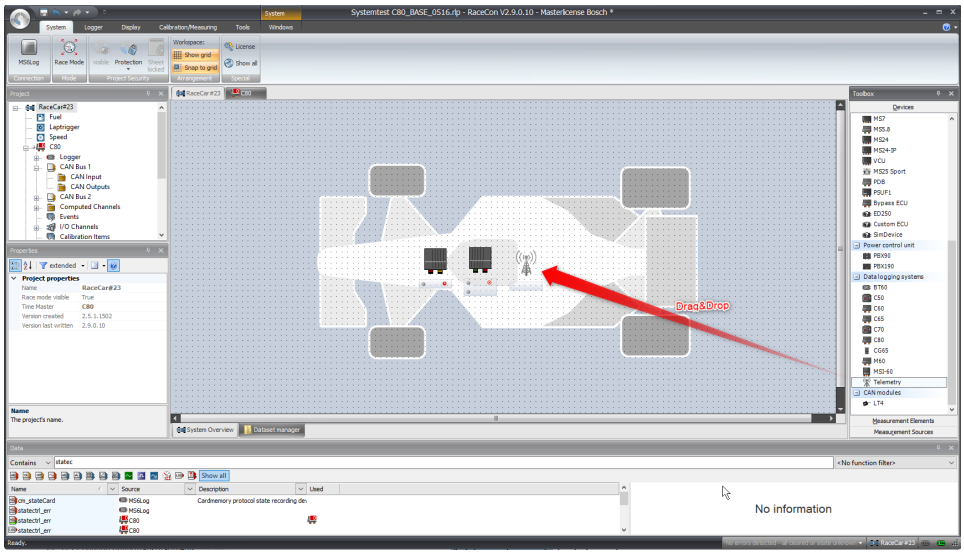
Does the sensor has lost its reception? The old values will be kept if the reception is lost. The gps_smask channel shows which NMEA sentence is received.

18 Telemetry System LTE 65

- Support for long-range online telemetry
- Individual programmable team code
- Fast block – slow block mechanism
- Programmable data rate
- Ethernet or RS232 interface
- Full online track coverage on almost all tracks

18.1 Software setup

Drop Telemetry from Toolbox into system overview.



Adding channels to telemetry

1. Expand the list of ‘Loggers’ by clicking on ‘+’ in the C 80 Project Tree.
2. Double-click on ‘Recording’ in C 80 Project Tree.

   The recording configuration is displayed in the Main Area.
3. Click ‘Edit channel(s)’.

   The ‘Edit Recording Channels’ window appears.
4. Choose between ‘Fast/Slow block’ transmission.

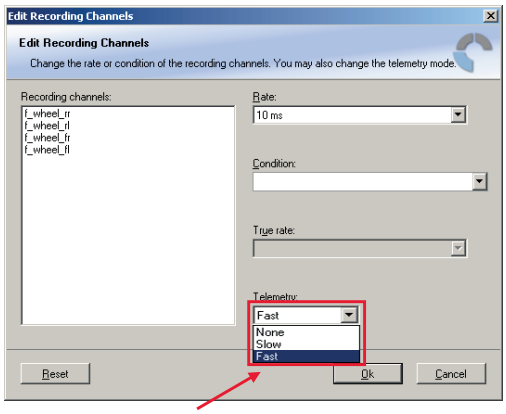
Using fast block/slow block transmission

C 80 telemetry has a bandwidth 200 kBit/s, the used bandwith can be adjusted to cope with the transmitting system. The bandwidth has to be divided into channel information to be transmitted high-frequently and low-frequently using the ‘fast/ slow block’ setting.

Channels are grouped into 8 blocks which are transferred each cycle:

- Fast block (Block 1) is transferred every cycle and used for a high-frequent transmission of channel information (e.g. speed, rpm).
- Slow blocks (Block 2...n) are transferred every n-th cycle and used for a low-frequent transmission of channel information (e.g. tire pressure, oil temperature).

Transmission Scheme



None – channel(s) are not transferred
Slow – channel(s) are transferred in the slow telemetry block
Fast – channel(s) are transferred in the fast telemetry block

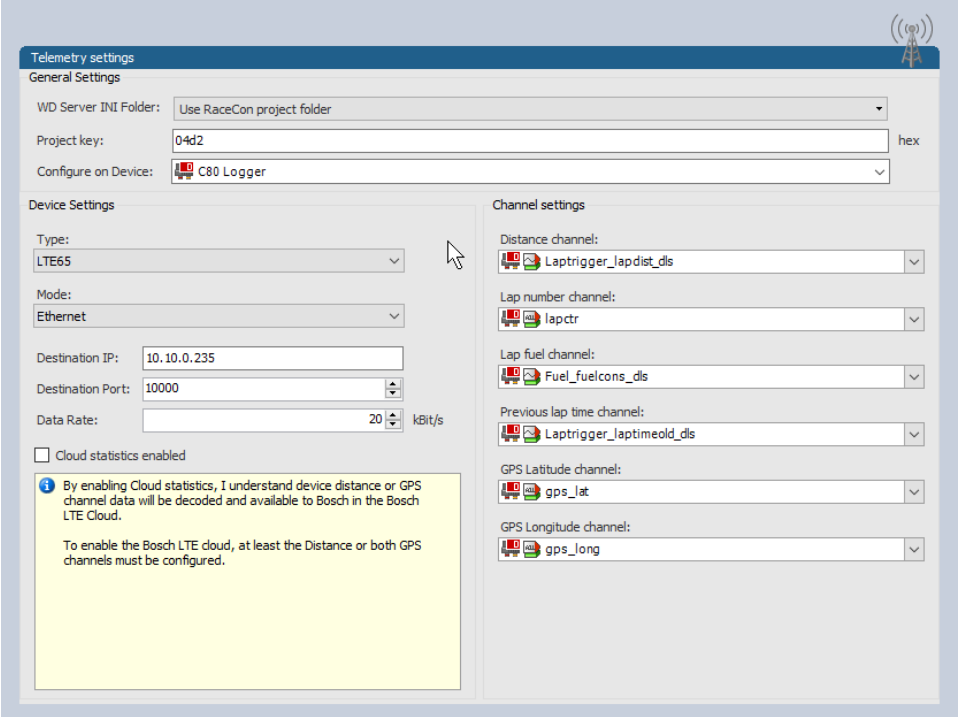
If the maximum bandwidth of a block is reached, a warning will be displayed. To fix this problem you can view the allocation of the channels and data rate in the 'Statistics' tab of the Main Area.

18.2 Telemetry channels with special functionality

The Telemetry system allows the transmission of special information such as running distance of current lap, lap number of current lap and lap time, fuel consumption of last lap completed. You have to assign the channel type to the telemetry channel so that it is recognized accurately by RaceCon.

Channel's names are e.g.: Laptrigger_lapdist_dls, fuelcons, lapctr, Laptrigger_lapdist_dls. Different channel names are possible between different devices (e.g. ECU MS6, laptrigger module used in RaceCon).

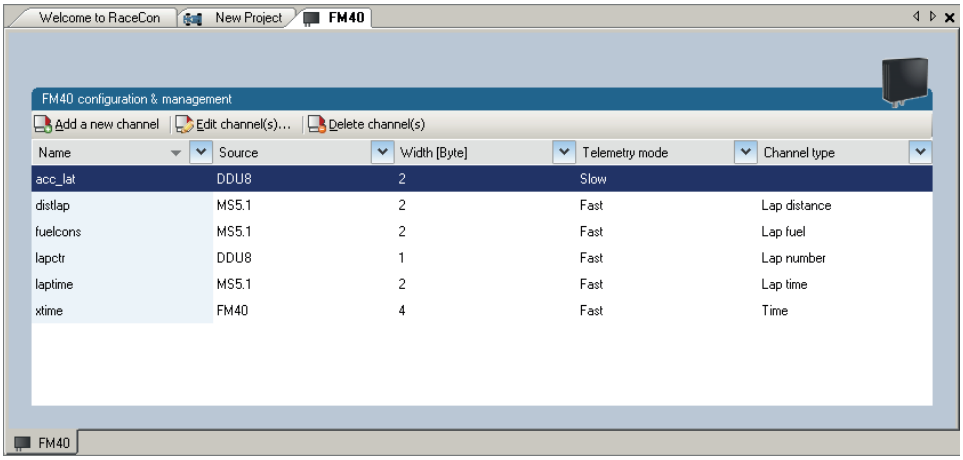
For displaying the position of the car in the cloud, additionally GPS-position and lapdist can be send to the cloud, this is activated with the checkbox "cloud statistics".



1. Assign the desired channels to the channel types. The table below shows the function of the available channel types.
2. Click 'Ok' when done.

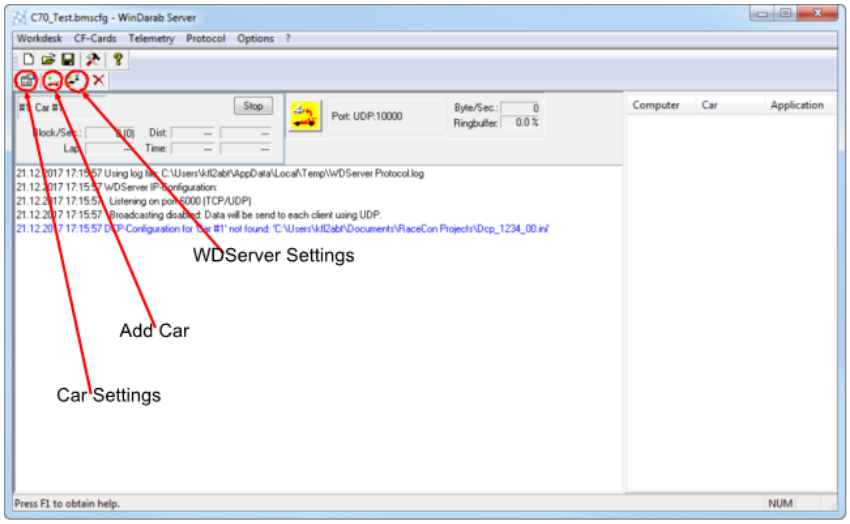
Measurement channel	Function
Distance	Running distance of current lap
Lap number	Lap number of current lap
Lap fuel	Fuel consumption of last lap completed
Lap time	Exact lap time of lap completed

The telemetry channels and their assigned channel types are displayed in the overview list.

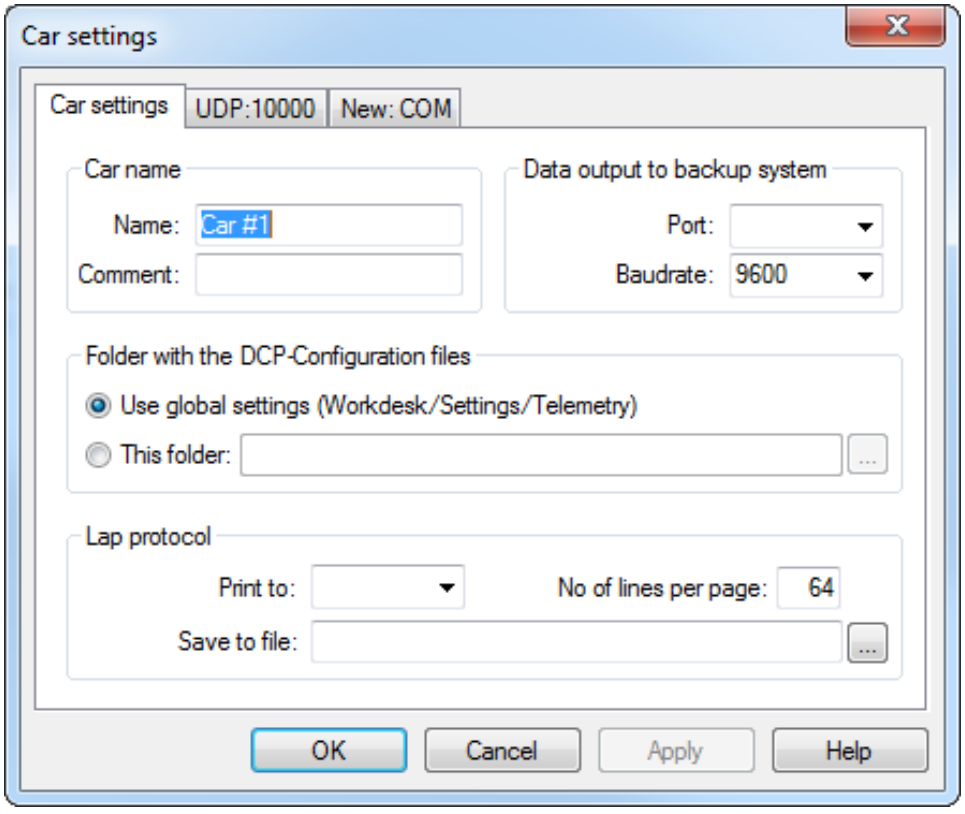


18.3 Setting up car in WDServer

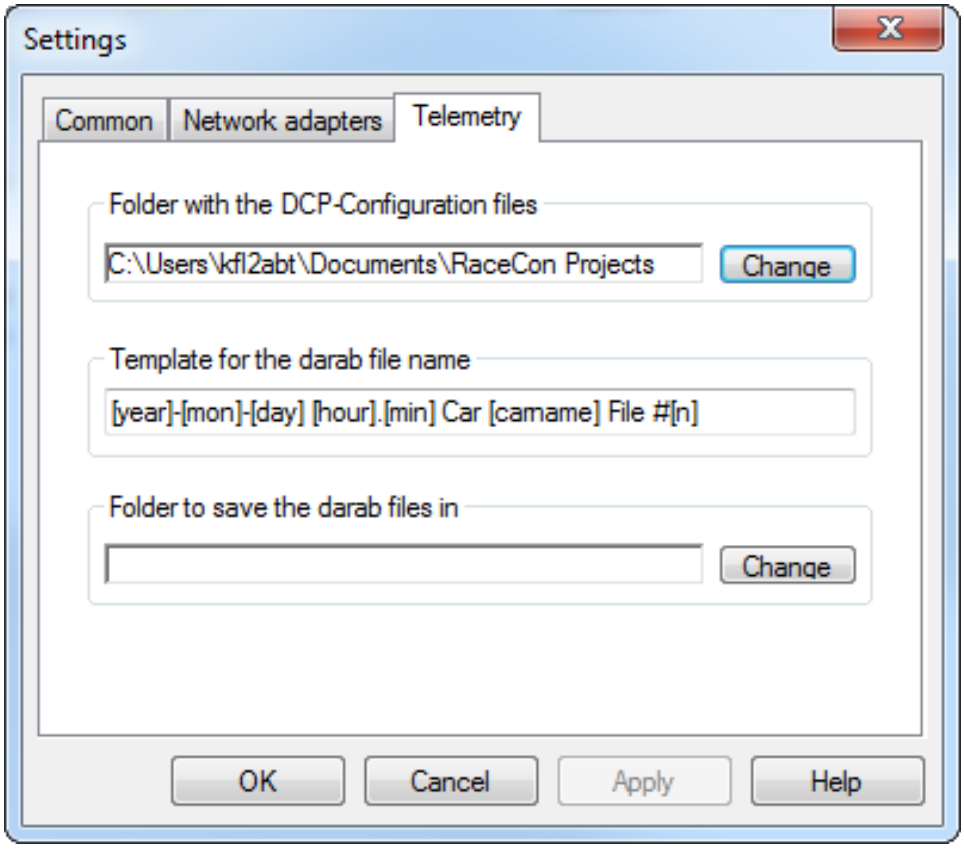
WDServer is a program used to capture data streaming from a transmitter and convert to WinDarab; WDServer also creates a log of the data received over telemetry.



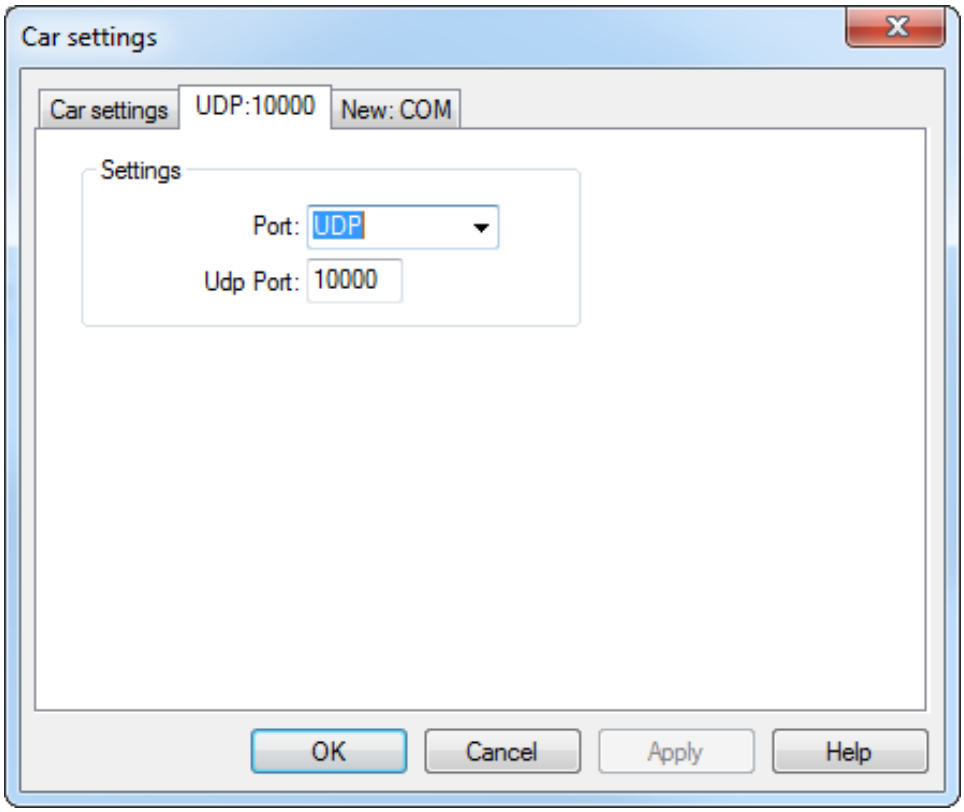
1. To set up a new car, select ‘Add Car’.
2. In the Car settings tab, enter a name for the new vehicle.
   This name will be used as a part of the file name for WDServer’s log of received telemetry data and will show up in WinDarab, when searching for the telemetry stream in the Network folder.



3. You are now at the final step of configuring the telemetry stream. In order for the data to be decrypted by WDServer, two *.ini files must be referenced by WDServer. After the configuration is sent to the logger, these two different *.ini files will be created in the base folder. You can find the base WDServer folder, if you right-click the Telemetry and select ‘Properties’. You can change this folder location for easier access if desired.
4. Define the link to the folder of the *.ini files for each car or define it in the general WDServer settings, under the ‘Telemetry’ tab.

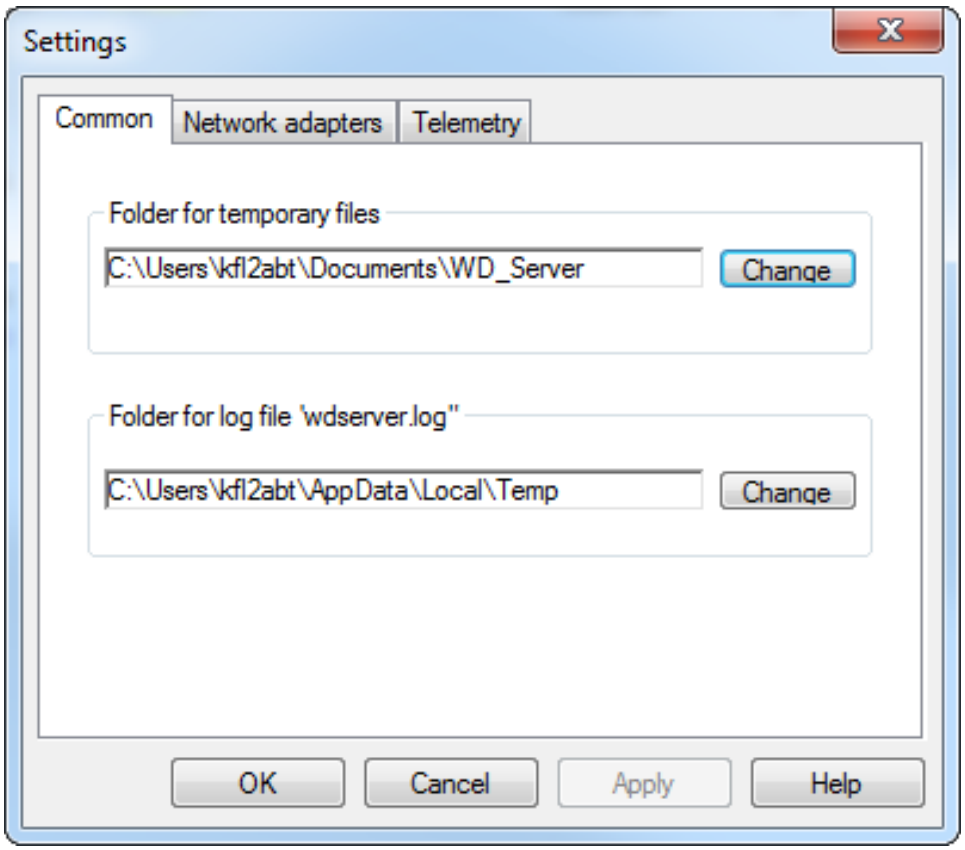


5. Under the 'UDP' tab, select the drop-down menu and type in "UDP".
6. For the UDP Port, type in the port number assigned to the device in RaceCon.
   Each vehicle being read by a single receiver device must have a unique port number.
   This information will be provided by Bosch upon delivery of the devices.



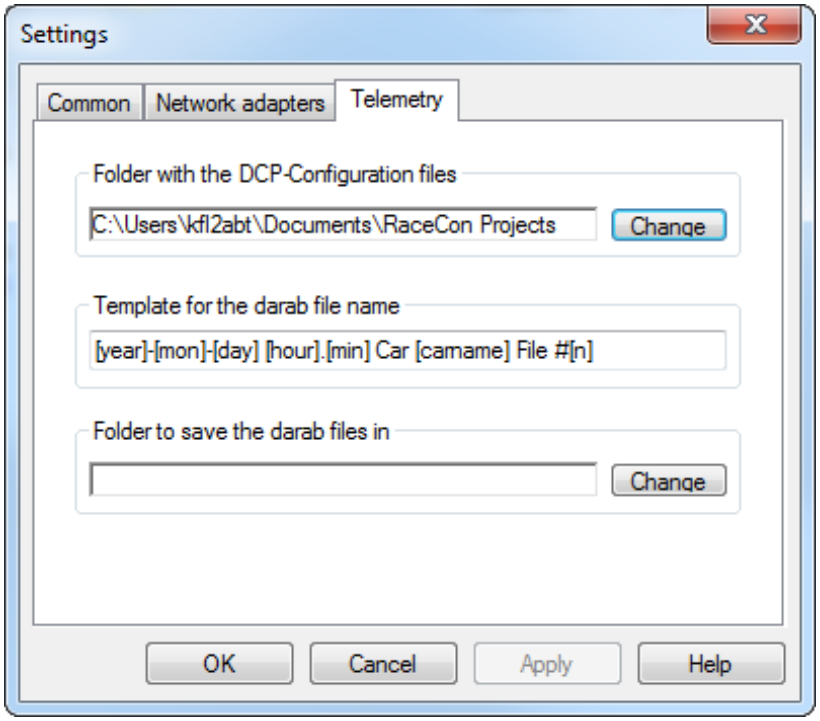
7. Click 'OK', to close the window.

8. Select the button ‘WDServer Settings’.
9. Under the ‘Common’ tab, choose directories where WDServer can store its temporary files and log files. These are created during telemetry reception and can be used to help diagnose issues.



Under the ‘Telemetry’ tab, the first section requests a folder path for the DCP- Configuration files. This is the folder path where RaceCon stored the *.ini files required by WD-Server.

10. Click on the “Change” button next to this section and navigate to this folder.
    A template can also be specified for the file nomenclature for logged telemetry as well as a save location.

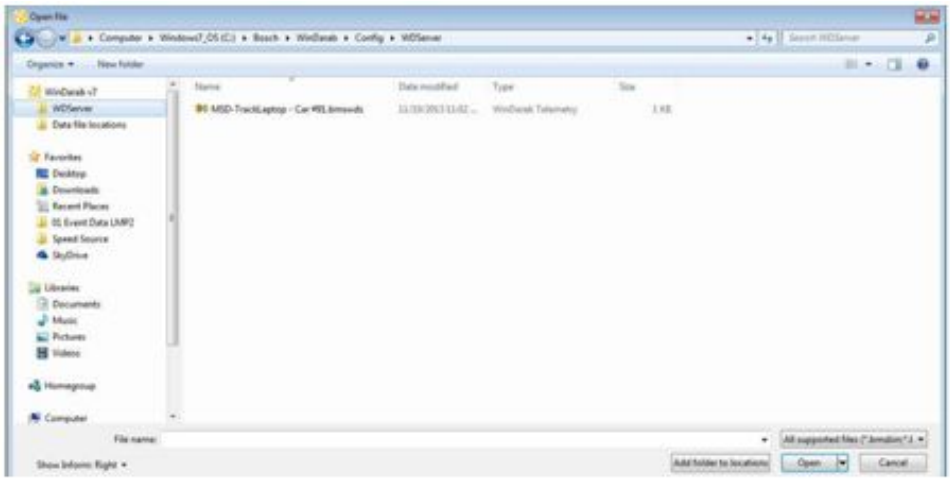


– To ensure proper communication between WDServer and the receiver, do not delete any old *.ini files from this folder path. As mentioned in section 5, RaceCon will generate a new *.ini file each time a project is synchronized; each new *.ini file instance has an incremented file name. Retaining all of these *.ini file iterations will ensure that WDServer always has a reference to whichever configuration is programmed into your vehicle's logger system.

– If the RaceCon project for the vehicle resides on a different computer, than that which is used for telemetry, then all *.ini files for a given project should be transferred to the telemetry computer after every data synchronization in RaceCon. WDServer may have trouble recognizing *.ini files stored on removable media, so best practice is to copy these files to the telemetry computer's hard drive.

18.4 Loading the telemetry data

The following is an example of a file name and data format for Car #91. File is typically located in WinDarab/Config/WDServer:



In the File Explorer, click 'Open' and navigate to the data set. Under 'Network', search for the car or cars that are required for viewing.

19 Firmware

19.1 Firmware and configuration

C 80 holds 2 types of data:

Firmware: The software (PST program file) of the C 80.

Configuration: The default parameters for controlling the output of the C 80.

19.2 Firmware update

Firmware updates are performed via XCP. Following standards are supported:

- ASAM MCD-1 (XCP); Version 1.5.0; Date: 2017-11-30
- ASAM MCD-2 MC (ASAP2 / A2L); Version 1.7.1; Date: 2018-01-30

Additional files for firmware update (like ProF-Scripts for INCA) will be provided by BOSCH.

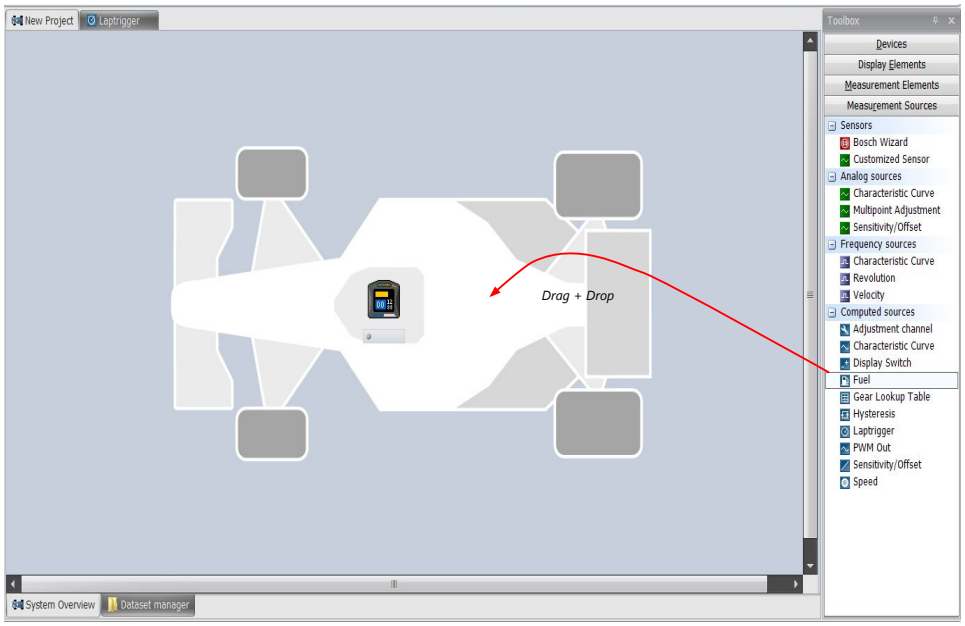
20 Cloning the Unit

Chapter left intentionally blank

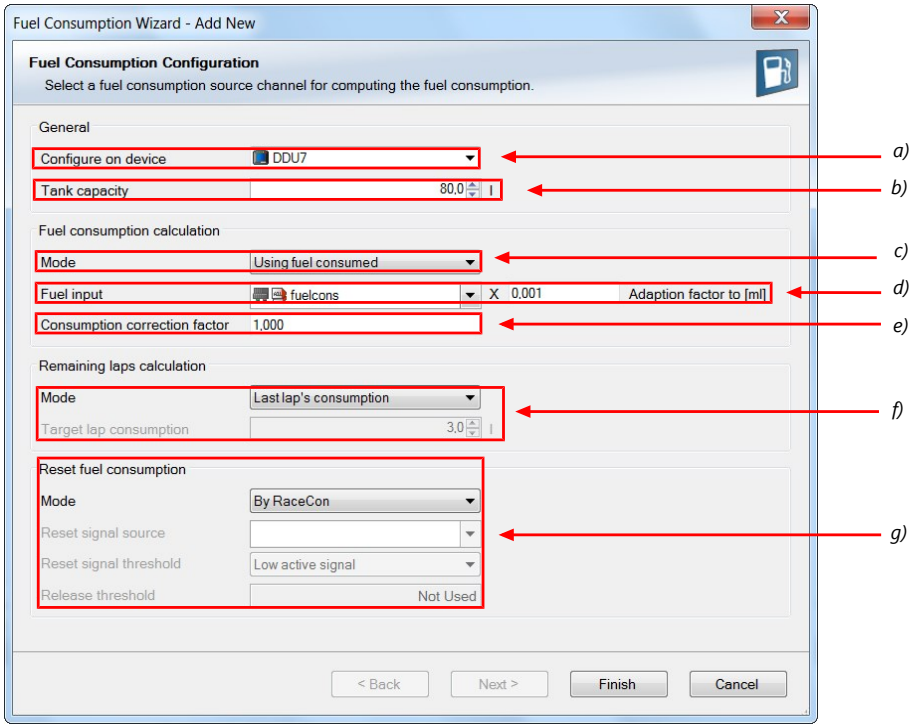
21 Fuel Consumption Calculation

21.1 Setting up fuel consumption calculation and tank management

1. Select ‘Measurement Sources’ in Toolbox.
2. Drag ‘Fuel’ element and drop it on the vehicle in System Overview. Do not drop it on the C 80!



A ‘fuel consumption wizard’ opens.



a) Change device for fuel calculation, if desired.

b) Enter tank capacity of vehicle.

c) Choose calculation mode:

- using fuel consumed (summed-up fuel consumption)
- using fuel flow rate (momentary fuel consumption)

d) Choose input channel and enter adaption factor. Use adaption factor to adapt value of input channel to:

- 1ml per inc for summed-up fuel consumption
- 1ml/s per inc for momentary consumption

e) Enter factor to correct calculated consumption in device vs. 'real' consumption of vehicle, if required.

f) Choose method to calculate remaining laps with fuel in tank, if desired:

- using fuel consumption of last lap completed
- using target lap consumption (entered in the field 'Target lap consumption')

g) Choose values to initiate a reset of fuel consumption, if desired:

- Manually using RaceCon
- On 'power down' (assuming that the tank is filled each time the ignition is turned off)
- By signal source as input channel (e.g. a switch connected to input pin)

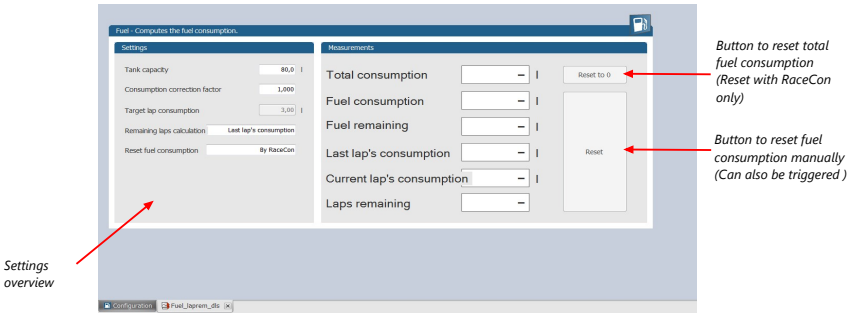
Press 'Finish' when done.

21.2 Fuel consumption diagnosis/counter reset

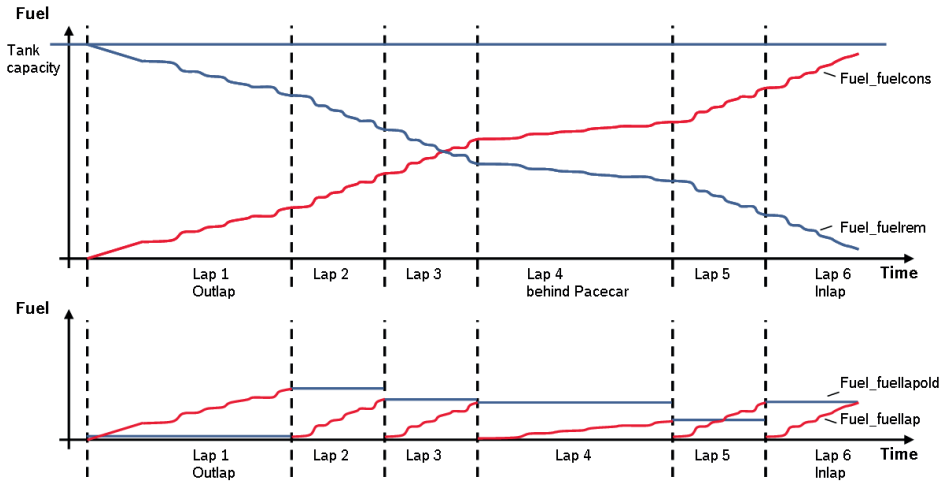
To display a fuel consumption diagnosis and to reset counters, use the diagnosis page in RaceCon.

Double-click on any 'fuel_xxx' channel in channel list.

A diagnosis window opens in Main Area.



Example



Measurement label	Function
Fuel_fuelcons_dls	Running fuel consumption, starting at '0'
Fuel_fuelrem_dls	Remaining fuel in tank, starting at tank capacity
Fuel_fuellap_dls	Fuel consumption for current lap, starting at '0'
Fuel_fuellapold_dls	Fuel consumption of last lap completed
Fuel_laprem_dls	Remaining laps with fuel in tank

22 RaceCon Shortcuts

The table shows important shortcuts simplify controlling the C 80 in RaceCon.

Shortcut	Function
General navigation	
F1	Open RaceCon help
F2	Rename selected object
F3	Select Data Area
F4	Select Project Tree
F5	-
F6	Start the data comparison
F7	Start dataset manager
F8	Toggle WP/RP
F9	Start measurement
CTRL + F9	Start recording
F10 or Alt	Go to menu bar
F11	Toggle display to fullscreen 'Race Mode'
F12	Enlarge main screen
CTRL + Tab	Switch between opened windows
Project Tree	
Plus (+) at numeric pad or right cursor	Expand selected node
Minus (-) at numeric pad or left cursor	Close selected node
Star (*) at numeric pad	Open all nodes
DEL	Delete seleted object
Display page, measurement page	
Cursor	Move selected display element one grid unit in chosen direction
SHIFT + cursor	Enlarge/reduce selected display element one grid unit
Tab	Switch between display elements

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Lead	7439-92-1

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The primary ANTLR guy:

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parrt@antlr.org

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24 Disposal

Hardware, accessories and packaging should be sorted for recycling in an environment-friendly manner.

Do not dispose of this electronic device in your household waste.

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