

simplyCAN

USB-to-CAN Adapter

USER MANUAL

4.01.0001.22001 1.2 en-US ENGLISH



Important User Information

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1 User Guide

Please read the manual carefully. Make sure you fully understand the manual before using the product.

1.1 Target Audience

This manual addresses trained personnel who are familiar with CAN and the applicable standards. The contents of the manual must be made available to any person authorized to use or operate the product.

1.2 Document History

Version	Date	Description
1.0	March 2019	First release
1.1	January 2020	Adjusted max. bus load, removed Windows 7 installation
1.2	October 2020	Corrections tested OS, minor corrections, added FCC

1.3 Trademark Information

Ixxat® is a registered trademark of HMS Industrial Networks AB. All other trademarks mentioned in this document are the property of their respective holders.

1.4 Conventions

Instructions and results are structured as follows:

- ▶ instruction 1
- ▶ instruction 2
 - result 1
 - result 2

Lists are structured as follows:

- item 1
- item 2

Bold typeface indicates interactive parts such as connectors and switches on the hardware, or menus and buttons in a graphical user interface.

```
This font is used to indicate program code and other
kinds of data input/output such as configuration scripts.
```

This is a cross-reference within this document: [Conventions, p. 4](#)

This is an external link (URL): www.hms-networks.com

Safety advice is structured as follows:

	<p>Cause of the hazard!</p> <p>Consequences of not taking remediate action.</p> <p>How to avoid the hazard.</p>
---	---

Safety signs and signalwords are used dependent on the level of the hazard.

 *This is additional information which may facilitate installation and/or operation.*

	<p>This instruction must be followed to avoid a risk of reduced functionality and/or damage to the equipment, or to avoid a network security risk.</p>
---	--

	<p>Caution</p> <p>This instruction must be followed to avoid a risk of personal injury.</p>
---	--

	<p>WARNING</p> <p>This instruction must be followed to avoid a risk of death or serious injury.</p>
---	--

2 Safety Instructions

2.1 Information on EMC



Risk of interference to radio and television if used in office or home environment! The product is a class B device.

Use exclusively included accessories or HMS accessories that are intended for use with the device. Use exclusively shielded cables.

Make sure that the shield of the interface is connected with the device plug and the plug on the other side.

2.2 General Safety Instructions

- ▶ Protect product from moisture and humidity.
- ▶ Protect product from too high or too low temperature (see [Technical Data, p. 11](#)).
- ▶ Protect product from fire.
- ▶ Do not paint the product.
- ▶ Do not modify or disassemble the product. Service must be carried out by HMS Industrial Networks.
- ▶ Store products in dry and dust-free place.

2.3 Intended Use

The device is used to connect computer systems to CAN networks to exchange data for example to configure a device via CAN or to read device diagnosis data. The simplyCAN is intended for the connection to a computer via the USB interface.

3 Scope of Delivery

Included in the scope of delivery:

- simplyCAN device

The following is available via download from www.simplycan.info:

- simplyCAN bus monitor
- installation file *setup.bat*
- programming API
- programming examples
- user manual

A CAN bus termination can be ordered separately.

4 Product Description

The simplyCAN is an active USB adapter which enables the user to connect a computer with a CAN network to monitor the network traffic and to interact with other network devices. The simplyCAN is a plug and play device due to the easy installation and the easy-to-use CAN programming interface.

Features

- USB 1.1 Full-Speed (12 MBit/s)
- 1 x CAN high-speed channel according to ISO 11898-2
- D-Sub 9 fieldbus connection, pin allocation according to CiA 303-1
- USB cable with plug type A



Windows: the simplyCAN is tested Windows 10 (64 bit).

Linux: the simplyCAN is tested using Ubuntu 16.04 (32 bit) on Linux kernel version 4.15 as well as Ubuntu 20.04 (64 bit) on Linux kernel version 5.4, and Raspberry OS 10 (buster) kernel version 5.4 (32 bit).



To access the USB interface administrator rights might be necessary.



The performance is limited to 50-60 % for Rx and Tx directions each. For a busload higher than 50-60 % data loss is possible.

5 Installation



Insufficient power supply!

Connect the device directly to the computer or to self-powered hubs to ensure sufficient power supply. Extension cables may cause connection issues.



USB interface supports hot plug!

It is possible to plug or unplug the device during operation.

On Windows 10 and Linux the USB interface is automatically installed when plugged in, without a driver installation.

- ▶ Download the simplyCAN package for the operating system in use from www.simplycan.info and unpack the files.



*The COM interface for the simplyCAN is showed as **USB Serial Device (COMx)** in the device manager when plugged in. To show the simplyCAN as **lxxat simplyCAN (COMx)** in the device manager, execute the file `setup.bat`.*

- ▶ Plug the USB connector in the USB port of computer.
 - Hardware is automatically found and installed.
 - USB LED is green flashing.
- ▶ If necessary install a bus termination (see [CAN Bus Termination, p. 10](#)).
- ▶ Connect the CAN fieldbus connector to the CAN fieldbus.
- ▶ Start the simplyCAN bus monitor (see [Operation, p. 8](#)).

Connectors

The shield of the USB cable is connected to ground using a 100 nF capacitor. The shield of the CAN connector is connected to CAN ground via a 1 MΩ resistor and a 10 nF capacitor. USB_shield is connected to CAN_shield via a 4.7 nF capacitor.



For best noise immunity connect the shields of the CAN cables directly to the device ground.

Pin Allocation D-Sub 9	
Signal	Pin No.
CAN high	7
CAN low	2
CAN GND	3, 6

6 Operation

6.1 simplyCAN Bus Monitor

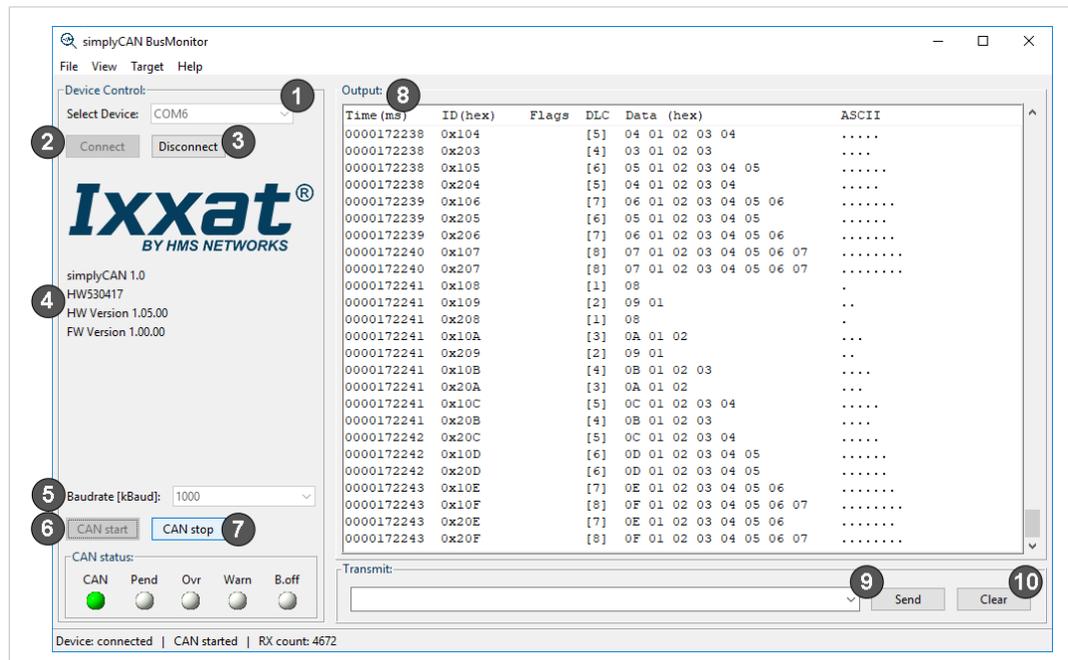


Fig. 1 simplyCAN bus monitor

- ▶ Start the simplyCAN bus monitor.
 - If one simplyCAN is connected to the computer, the device is automatically selected and connected (1).
- ▶ If several simplyCAN are connected to the computer, select the desired device (1) and click button **Connect** (2).
 - Information about the device are displayed (4).



The simplyCAN bus monitor can be opened several times to connect several simplyCAN devices simultaneously.

- ▶ To change the device, click button **Disconnect** (3), select the device in drop-down list **Select device** (1) and click button **Connect** (2).
- ▶ Select the desired CiA baudrate (5).
- ▶ To start the communication, click button **CAN start** (6).
 - CAN messages are shown in the window **Output** (8).
 - In transmitted messages the time stamp is 0 and the flag **S** is displayed.
- ▶ To send a message, enter the message in the **Transmit** line (9) (see [Transmit Messages, p. 9](#) for more information).
- ▶ Click button **Send** (9).
 - If the entered message is valid, the message is transmitted.
 - If the entered message is invalid, the error message **Syntax error** and a description of the message format is shown.
- ▶ Stop the communication with button **CAN stop** (7).

- ▶ Clear the output window with button **Clear (10)**.



For a busload higher than 50-60 % data loss is possible. Data loss is signalled by the **Ovr** LED in the simplyCAN bus monitor.

Transmit Messages

Syntax: <id> [R] [E] [<data>...]

- **id**: identifier (decimal or hexadecimal)
- **R**: remote transmit request for message
- **E**: message in Extended frame format (29 bit)
- **data**: data bytes of the message (decimal or hexadecimal), in RTR messages the first data byte contains the DLC



If hexadecimal values are used, they must begin with 0x.

Example: 256 in dec is 0x100 in hex

Examples	
Message in simplyCAN bus monitor	Description
0x100 0x11 0x22 0x3 0x44	11 bit message with ID 100 (hex) and 4 data bytes
0x1FE1200 E 1 2 3 4 5 6 7 8	29 bit message with ID 1FE1200 (hex) and 8 data bytes
123 R 8	11 bit remote frame with ID 123 and DLC=8
0x1FE1200 R 8	29 bit remote frame with ID 1FE1200 (hex) and DLC=8

6.2 USB LED

The USB LED reflects the status of the USB communication.

LED state	Description	Comments
Off	Power off	No power or device defect
Green flashing	No active connection	Device ready to use, simplyCAN bus monitor or API must be started to use the device
Green	Active connection	Device in use

6.3 CAN LED

The CAN LED reflects the status of CAN communication.

LED state	Description	Comments
Off	No communication	No communication, device not connected to CAN
Green flashing	Communication OK	LED is triggered with each message.
Red flashing	Communication with errors	Controller is in state <i>error warning</i> or in state <i>error passive</i> , communication is possible.
Red	Bus off	Controller is in state <i>bus off</i> , no communication possible.

7 Additional Components

7.1 CAN Bus Termination

There is no bus termination resistor for the CAN bus integrated in the device. HMS Industrial Networks offers a bus termination resistor as a feed through connector.



Fig. 2 CAN bus termination resistor

- ▶ For ordering information see www.ixxat.com.

8 Technical Data

USB interface	USB 1.1, Full-Speed (12 MBit/s)
CAN bitrates	10 kbit/s to 1 Mbit/s, only CiA recommended bit rates are supported: 10, 20, 50, 125, 250, 500, 800, 1000
CAN transceiver	TI SN65HVD251
CAN bus termination	None
Dimensions	80 x 50 x 22 mm
Weight	Approx. 100 g
Power supply	Via USB, 5 V DC/100 mA
Galvanic isolation	800 V DC/500 V AC for 1 min
Operating temperature	-20 to +70 °C
Storage temperature	-40 to +85 °C
Relative humidity	10 % to 95 %, non condensing
Housing material	ABS plastic
Protection class	IP40

9 Troubleshooting

USB LED is off after connecting.

No power or defect device

- ▶ Make sure that the device is correctly connected to the USB port.
- ▶ Connect the device directly to the computer or to self-powered hubs.

Extension cable is used and device is not working.

Extension cables may cause connection issues.

- ▶ Remove the extension cable.
- ▶ Connect the device directly or via an active USB hub to the computer.

10 Cleaning

- ▶ Disconnect the device from power supply.
- ▶ Remove dirt with a soft, chemical untreated, dry cloth.

11 Support/Return Hardware

11.1 Support

- ▶ For problems or support with the product request support at www.ixxat.com/support.
- ▶ If required use support phone contacts on www.ixxat.com.

11.2 Return Hardware

- ▶ Fill in the form for warranty claims and repair on www.ixxat.com/support/product-returns.
- ▶ Print out the Product Return Number (PRN resp. RMA).
- ▶ Pack product in a physically- and ESD-safe way, use original packaging if possible.
- ▶ Enclose PRN number.
- ▶ Observe further notes on www.ixxat.com.
- ▶ Return hardware.

12 Disposal

- ▶ Dispose of product according to national laws and regulations.
- ▶ Observe further notes about disposal of products on www.ixxat.com.

13 API Documentation

13.1 API Functions



To show the use of the functions, examples in C, C# and Python are included in the simplyCAN download package available on www.simplycan.info.

13.1.1 simply_open

Opens the serial communication interface. The message filter of the CAN controller is opened for all message identifiers.

```
bool simply_open(char *serial_port);
```

Parameter

Parameter	Dir.	Description
<i>serial_port</i>	[in]	Name of the serial communication port (e.g. <i>COM1</i> or <i>/dev/ttyACM0</i>). Use the simplyCAN bus monitor to detect on which serial COM port the simplyCAN is connected. With Windows it is also possible to use the device manager and with Linux the command <code>ls -l /dev/serial/by-id</code> . For C and Python the included programming examples show how to determine the serial port.

Return Value

Return value	Description
true	Function succeeded
false	Error occurred, call <code>simply_get_last_error</code> for more information.

13.1.2 simply_close

Closes the serial communication interface and resets the CAN controller.

```
bool simply_close(void);
```

Return Value

Return value	Description
true	Function succeeded
false	Error occurred, call <code>simply_get_last_error</code> for more information.

13.1.3 simply_initialize_can

Initializes the CAN controller.

```
bool simply_initialize_can(uint16_t bitrate);
```

Parameter

Parameter	Dir.	Description
<i>bitrate</i>	[in]	CAN bitrate as integer value, possible values: 10, 20, 50, 125, 250, 500, 800, 1000

Return Value

Return value	Description
true	Function succeeded
false	Error occurred, call <code>simply_get_last_error</code> for more information.

13.1.4 `simply_identify`

Gets firmware and hardware information about the simplyCAN device.

```
bool simply_identify(identification_t *p_identification);
```

Parameter

Parameter	Dir.	Description
<code>p_identification</code>	[out]	Pointer to the identification structure

Identification Structure

```
typedef struct _identification {
    uint8_t fw_version[8];
        // Zero terminated firmware version string e.g. "1.00.00"
    uint8_t hw_version[8];
        // Zero terminated hardware version string e.g. "1.00.00"
    uint8_t product_version[8];
        // Zero terminated product version string e.g. "1.00.00"
    uint8_t product_string[30];
        // Zero terminated product string e.g. "simplyCAN 1.0"
    uint8_t serial_number[9];
        // Zero terminated serial number e.g. "HW123456"
} identification_t;
```

Return Value

Return value	Description
true	Function succeeded
false	Error occurred, call <code>simply_get_last_error</code> for more information.

13.1.5 `simply_start_can`

Starts the CAN controller. Sets the CAN controller into mode *running* and clears the CAN message FIFOs. In mode *running* CAN messages can be transmitted and received.

```
bool simply_start_can(void);
```

Return Value

Return value	Description
true	Function succeeded
false	Error occurred, call <code>simply_get_last_error</code> for more information.

13.1.6 `simply_stop_can`

Stops the CAN controller. Sets the CAN controller into mode *init*. Does not reset the message filter of the CAN controller. Only stop the CAN controller when the `CAN_STATUS_PENDING` flag is not set.

```
bool simply_stop_can(void);
```

Return Value

Return value	Description
true	Function succeeded
false	Error occurred, call <code>simply_get_last_error</code> for more information.

Remarks

To ensure that all messages are transmitted before stopping the CAN controller, read the CAN status until the `CAN_STATUS_PENDING` flag is no longer set.

13.1.7 `simply_reset_can`

Resets the CAN controller (hardware reset) and clears the message filter (open for all message identifiers). Sets the CAN controller into mode *init*.

```
bool simply_reset_can(void);
```

Return Value

Return value	Description
true	Function succeeded
false	Error occurred, call <code>simply_get_last_error</code> for more information.

13.1.8 simply_can_status

Gets the status of the CAN controller.

```
bool simply_can_status(can_sts_t *can_sts);
```

Parameter

Parameter	Dir.	Description
<i>can_sts</i>	[out]	Status as bit coded 16 bit value (see CAN status structure)

CAN Status Structure

```
typedef struct _can_sts {
    uint16_t sts;
    // bit coded status flags (see CAN status definitions)
    uint16_t tx_free;
    // number of free elements in CAN message tx fifo
} can_sts_t;
```

CAN Status Definitions

```
/* CAN status definitions */
#define CAN_STATUS_RUNNING          (0x01)
#define CAN_STATUS_RESET           (0x02)
#define CAN_STATUS_BUSOFF          (0x04)
#define CAN_STATUS_ERRORSTATUS     (0x08)
#define CAN_STATUS_RXOVERRUN       (0x10)
#define CAN_STATUS_TXOVERRUN       (0x20)
#define CAN_STATUS_PENDING         (0x40)
```

Return Value

Return value	Description
true	Function succeeded
false	Error occurred, call <code>simply_get_last_error</code> for more information.

13.1.9 `simply_set_filter`

Sets the 11 or 29 bit message filter of the CAN controller. To set the 29 bit message filter, the MSB in parameter value must be set.

```
bool simply_set_filter(uint32_t mask, uint32_t value);
```

Parameter

Parameter	Dir.	Description
<i>mask</i>	[in]	11 or 29 bit CAN message identifier mask
<i>value</i>	[in]	11 or 29 bit CAN message identifier value, set MSB to set the 29 bit message filter

Return Value

Return value	Description
<code>true</code>	Function succeeded
<code>false</code>	Error occurred, call <code>simply_get_last_error</code> for more information.

Remark

With the mask/value filter (available for 11 bit and 29 bit identifiers) possible valid identifiers based on bit masks can be defined.

Binary representation of mask:

- binary positions with value 1 are relevant for the filter
- binary positions with value 0 are not relevant for the filter

Binary representation of value:

- Defines the values for the positions that are marked as relevant (1) in mask.
- Values in positions that are marked as not relevant (0) in mask are ignored.

The following formula expresses the condition under which an identifier passes the filter:

- if $(value \& mask) == (identifier \& mask)$ then identifier is valid

Example 11 Bit Identifier

	hex	bin
Value	0x700	0111:0000:0000
Mask	0x700	0111:0000:0000
Result	0x700	0111:0000:0000
Any identifier between 0x700 and 0x7FF passes the filter, as only the first 3 bits of the mask are marked as relevant.		

Example 29 Bit Identifier

	hex	bin
Value	0x90003344	1001:0000:0000:0000:0011:0011:0100:0100
Mask	0x1F00FFFF	0001:1111:0000:0000:1111:1111:1111:1111
Result	0x10003344	0001:0000:0000:0000:0011:0011:0100:0100
256 identifier between 0x10003344 and 0x10FF3344 pass the filter, where the last two bytes are 0x3344.		

To allow 29 bit messages to pass the filter, the MSB in parameter value must be set.

Further Examples

Value	Mask	Valid message identifiers which pass the filter
0x100	0x7FF	0x100
0x100	0x700	0x100–0x1FF
0x000	0x000	0x000–0x7FF

13.1.10 `simple_receive`

Receives a single CAN message.

```
int8_t simple_receive(can_msg_t *can_msg);
```

Parameter

Parameter	Dir.	Description
<code>can_msg</code>	[out]	Pointer to the CAN message structure the received CAN message is copied to

CAN Message Structure

```
typedef struct _can_msg {
    uint32_t timestamp;           // in milliseconds
    uint32_t ident;              // MSB=1: extended frame
    uint8_t dlc;                  // MSB=1: remote frame
    uint8_t payload[8];
} can_msg_t;
```

Return Value

Return value	Description
1	Message received
0	No message available in the receive queue
-1	Error occurred, call <code>simple_get_last_error</code> for more information.

13.1.11 `simple_send`

Writes a CAN message to the transmit FIFO. To check if the message is transmitted, request the CAN status with [simple_can_status](#).

```
bool simple_send(can_msg_t *can_msg);
```

Parameter

Parameter	Dir.	Description
<code>can_msg</code>	[in]	Pointer to a CAN message to be transmitted (see CAN Message Structure)

Return Value

Return value	Description
true	Function succeeded
false	Error occurred, call <code>simple_get_last_error</code> for more information.

Remark

With `simple_send` CAN messages are not transmitted immediately but they are written to the transmit FIFO. Check if the message is transmitted with [simple_can_status](#). If the `CAN_STATUS_PENDING` flag is set, the message is not yet transmitted. Request the CAN status until the `CAN_STATUS_PENDING` flag is not set any more.

13.1.12 `simply_get_last_error`

Gets the last error code. After reading the error code with `simply_get_last_error` the error code is set to 0. Each error can only be read once.

```
int16_t simply_get_last_error(void);
```

Return Value

Return value	Error	Description
0	<code>SIMPLY_S_NO_ERROR</code>	No error occurred
-1	<code>SIMPLY_E_SERIAL_OPEN</code>	Unable to open the serial port
-2	<code>SIMPLY_E_SERIAL_ACCESS</code>	Access on serial port denied
-3	<code>SIMPLY_E_SERIAL_CLOSED</code>	Serial communication port closed
-4	<code>SIMPLY_E_SERIAL_COMM</code>	Serial communication error
-5	<code>SIMPLY_E_CMND_REQ_UNKNOWN</code>	Command unknown on device
-6	<code>SIMPLY_E_CMND_RESP_TIMEOUT</code>	Command response timeout reached
-7	<code>SIMPLY_E_CMND_RESP_UNEXPECTED</code>	Unexpected command response received
-8	<code>SIMPLY_E_CMND_RESP_ERROR</code>	Command response error
-9	<code>SIMPLY_E_INVALID_PROTOCOL_VERSION</code>	Invalid simplyCAN protocol version
-10	<code>SIMPLY_E_INVALID_FW_VERSION</code>	Invalid device firmware version
-11	<code>SIMPLY_E_INVALID_PRODUCT_STRING</code>	Invalid simplyCAN product string
-12	<code>SIMPLY_E_CAN_INVALID_STATE</code>	Invalid CAN state
-13	<code>SIMPLY_E_CAN_INVALID_BAUDRATE</code>	Invalid CAN baudrate
-14	<code>SIMPLY_E_TX_BUSY</code>	Message not sent, Tx is busy
-15	<code>SIMPLY_E_API_BUSY</code>	API is busy.

13.2 State Diagram

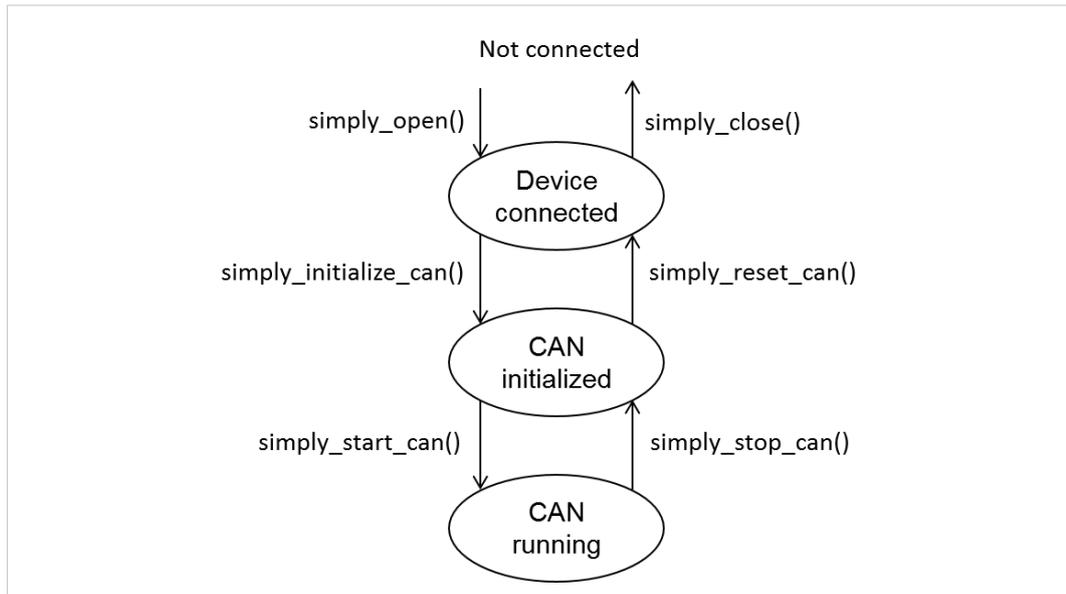


Fig. 3 SimplyCAN states

Function Calls and the Corresponding Valid States	
Function	Valid states
<code>simply_open()</code>	Not connected
<code>simply_close()</code>	Device connected, CAN initialized
<code>simply_initialize_can()</code>	Device connected, CAN initialized
<code>simply_reset_can()</code>	Device connected, CAN initialized, CAN running
<code>simply_start_can()</code>	CAN initialized
<code>simply_stop_can()</code>	Device connected, CAN initialized, CAN running
<code>simply_receive()</code>	CAN initialized, CAN running
<code>simply_send()</code>	CAN running
<code>simply_get_last_error()</code>	All states
<code>simply_can_status()</code>	Device connected, CAN initialized, CAN running
<code>simply_identify()</code>	Device connected, CAN initialized, CAN running
<code>simply_set_filter()</code>	CAN initialized

A Regulatory Compliance

A.1 EMC Compliance (CE)



The product is in compliance with the Electromagnetic Compatibility Directive. More information and the Declaration of Conformity is found at www.ixxat.com.

A.2 FCC Compliance Statement

This device complies with Part 15 of the FCC Rules. Operation is subject to the following two conditions:

- This device may not cause harmful interference.
- This device must accept any interference received, including interference that may cause undesired operation.

Product name	Ixxat simplyCAN
Type of Product	USB-to-CAN adapter
Responsible party	HMS Industrial Networks Inc
Address	35 E. Wacker Dr, Suite 1900 Chicago , IL 60601
Phone	+1 312 829 0601



Any changes or modifications not expressly approved by HMS Industrial Networks could void the user's authority to operate the equipment.



This equipment has been tested and found to comply with the limits for a Class B digital device, pursuant to Part 15 of the FCC rules. These limits are designed to provide reasonable protection against harmful interference in a residential installation. This equipment generates, uses and can radiate radio frequency energy and, if not installed and used in accordance with the instructions, may cause harmful interference to radio communications. However, there is no guarantee that interference will not occur in a particular installation. If this equipment does cause harmful interference to radio or television reception, which can be determined by turning the equipment off and on, the user is encouraged to try to correct the interference by one or more of the following measures:

Reorient or relocate the receiving antenna.

Increase the separation between the equipment and the receiver.

Connect the equipment into an outlet on a circuit different from that to which the receiver is connected.

Consult the dealer or an experienced radio/TV technician for help.

A.3 Disposal and recycling



You must dispose of this product properly according to local laws and regulations. Because this product contains electronic components, it must be disposed of separately from household waste. When this product reaches its end of life, contact local authorities to learn about disposal and recycling options, or simply drop it off at your local HMS office or return it to HMS.

For more information, see www.hms-networks.com.

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