Kvaser Hybrid Pro 2xCAN/LIN User's Guide



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https://www.kvaser.com

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1 About this manual

This manual is intended for Kvaser Hybrid Pro 2xCAN/LIN users. This document contains a description of the hardware's properties and general instructions for connecting the device to a computer.

2 Introduction

This section will describe the functions and features of the Kvaser Hybrid Pro 2xCAN/LIN.

2.1 Welcome to Kvaser Hybrid Pro 2xCAN/LIN



Figure 1: Kvaser Hybrid Pro 2xCAN/LIN

Kvaser Hybrid Pro 2xCAN/LIN is a two-channel interface where each channel can be opened independently either as CAN or LIN. The Kvaser Hybrid Pro 2xCAN/LIN is compatible with applications that use Kvaser's CANlib and LINlib.

This guide applies to Kvaser Hybrid Pro 2xCAN/LIN devices using at least firmware and driver versions listed in Table 1. For minimum compatible firmware and driver versions of Kvaser Hybrid Pro 2xCAN/LIN see Table 10 on Page 18.

Device	Product Number	Firmware	Driver (Windows/Linux)
Kvaser Hybrid Pro 2xCAN/LIN	73-30130-01042-0	v3.29	v5.41 (kcany/mhydra)

Table 1: Firmware and driver versions needed to support all functionality present in this guide.

2.2 Major features

- Hybrid USB CAN/LIN interface with Kvaser *t* programmability.
- Supports both LIN master and LIN slave mode
- Supports LIN 1.3 to 2.2
- LIN reference voltage detection
- Supports CAN FD, up to 5 Mbit/s.
- Supports both 11-bit (CAN 2.0A) and 29-bit (CAN 2.0B active) identifiers.
- Kvaser MagiSync – automatic time synchronization (see Section 4.7, Kvaser MagiSync, on Page 18 for more details).
- Powered through the USB connector.
- Fully compatible with J1939, CANopen, NMEA 2000® and DeviceNet.
- 100% compatible with applications written for other Kvaser CAN hardware with Kvaser CANlib and Kvaser LINlib.
- Quick and easy plug-and-play installation.

2.3 Interface

Kvaser Hybrid Pro 2xCAN/LIN provides a CAN/LIN bus interface through a standard USB interface.

2.4 The t programming language

The Kvaser t programming language is event oriented and modelled after C. It can be used to customize the behavior of the Kvaser Hybrid Pro 2xCAN/LIN and other Kvaser t capable devices.

A t program is invoked via hooks, which are entry points that are executed at the occurrence of certain events. These events can be, for example, the arrival of specific CAN messages or a timer expiration.

Like any Kvaser CAN interface, the Kvaser Hybrid Pro 2xCAN/LIN can be used via CANlib on a host computer. The addition of t programs running directly on the Kvaser Hybrid Pro 2xCAN/LIN makes it possible to react much quicker to CAN bus events (for example to speed up file transfer protocols or to simulate missing hardware).

For more information, see the Kvaser t Programming Language guide that can be downloaded at www.kvaser.com/download.

2.5 Restrictions in t functionality

The Kvaser Hybrid Pro 2xCAN/LIN is a dedicated CAN interface, and as such does not contain real-time clock (RTC), logger or SD card functionality, neither does the Kvaser Hybrid Pro 2xCAN/LIN include dedicated I/O pins. This means that the t functionality listed in Table 2 on Page 7 is not available on Kvaser Hybrid Pro 2xCAN/LIN (the table shows version 3.10 of the t language compiler).

Group	Function name
Hooks	`on IoEvent`
Predefined I/O Functions	`kvIoGetNumberOfPins`
	`kvIoPinGetInfo`
	`kvIoPinSetInfo`
	`kvIoConfirmConfig`
	`kvIoPinSetDigital`
	`kvIoPinGetDigital`
	`kvIoPinGetOutputDigital`
	`kvIoPinSetRelay`
	`kvIoPinGetOutputRelay`
	`kvIoPinSetAnalog`
	`kvIoPinGetAnalog`
	`kvIoPinGetOutputAnalog`
Predefined File I/O Functions	`fileOpen`
	`fileClose`
	`fileGets`
	`fileReadBlock`
	`filePuts`
	`fileWriteBlock`
	`fileSeek`
	`fileDelete`
Predefined XML Functions	`xmlOpen`
	`xmlClose`
	`xmlGet`
Predefined t Program Related Functions	`scriptLoad`
Predefined Logger Related Functions	`filterDropMessage`
	`loggerStatus`
	`loggerStart`
	`loggerStop`
Other Predefined Functions	`timeGetDate`

Table 2: Functionality in the t language (v3.10) that is not supported by Kvaser Hybrid Pro 2xCAN/LIN.

2.6 Additional software and documentation

The Kvaser CANlib SDK includes everything you need in order to develop software applications interacting with Kvaser CAN and LIN hardware. The SDK contains full documentation and many sample programs, written in C, C++, C#, Delphi, Python and Visual Basic. Kvaser CAN and LIN hardware is built around the same common software API. Applications developed using one device type will run without modification on other device types.

The latest versions of documentation, software and drivers can be downloaded for free at www.kvaser.com/download.

3 Kvaser Hybrid Pro 2xCAN/LIN hardware

In this section you can read more about the CAN/LIN channels, power supply and LED indicators.

3.1 Hardware installation

For the Kvaser Hybrid Pro 2xCAN/LIN to communicate with the host computer, a compatible version of the Kvaser driver and firmware must be installed.

After the driver has been installed on the host computer, the firmware may then be downloaded and installed on the Kvaser Hybrid Pro 2xCAN/LIN.

The latest version of the driver and firmware can be downloaded from www.kvaser.com/download.

The driver is installed by running the file `kvaser_drivers_setup.exe`.

The Kvaser Hybrid Pro 2xCAN/LIN may be inserted in any free USB socket on the host computer. You do not need to switch the power off before inserting or removing the device.

For information on how to upgrade the firmware, see Section 4.6, Updating the firmware, on Page 18.

3.2 USB connector

The Kvaser Hybrid Pro 2xCAN/LIN has a standard USB type "A" connector.



Figure 2: A standard USB type "A" connector.

3.3 CAN/LIN channels

The Kvaser Hybrid Pro 2xCAN/LIN has two LIN/CAN channels in two seperate 9-pin D-SUB CAN connectors (see Figure 3 on Page 10). See Section 4.4, CAN/LIN connector, on Page 16 for pinout information.



Figure 3: CAN/LIN connector on Kvaser Hybrid Pro 2xCAN/LIN

3.4 Power supply

The Kvaser Hybrid Pro 2xCAN/LIN is powered from the USB port. You also need to apply a reference voltage to the LIN reference power pin when running the channel in LIN mode. See Section 4.4, CAN/LIN connector, on Page 16 for pinout information.

3.5 LED Indicators

The Kvaser Hybrid Pro 2xCAN/LIN has a single power LED as well as one traffic LED and one Informational LED for each CAN/LIN channel as shown in Figure 4 on Page 11. Their functions are described in Section 4.1, Definitions of LED states and colors, on Page 13.



Figure 4: LEDs on the Kvaser Hybrid Pro 2xCAN/LIN.

3.6 Troubleshooting

Use "Kvaser Device Guide" in the Control Panel to verify that the computer can communicate with the Kvaser Hybrid Pro 2xCAN/LIN. If the firmware version shown is all zeros, there are communication problems. If the LEDs are not flashing or do not light up at all, check the power supply.

4 Appendices

In this section you will find technical information about the Kvaser Hybrid Pro 2xCAN/LIN and its connectors.

4.1 Definitions of LED states and colors

The Kvaser Hybrid Pro 2xCAN/LIN has three types of LEDs; Power, Traffic and Info. These are dual colored as shown in Table 3. A device with multiple channels has one Traffic LED for each channel. When the device has more than one channel a space and digit is added on the label, CH 1, CH 2 etc. The red Traffic LEDs are also used to indicate errors by using all red Traffic LEDs simultaneously.

LED	Label	Color
Power	PWR	Green/Yellow
Traffic	CH	Yellow/Red
Info	INFO	Green/Yellow

Table 3: The different type of LEDs.

The following definitions is used to describe the state of an LED:

Off The LED is off and no light is emitted.

Flash The LED is lit up for a very short time. A single flash may be hard to see and a continuous set of flashes will look the same as On.

Slow Blink The LED is repeatedly turned On and Off. The On and Off phase is equal in time.

Fast Blink The LED is repeatedly turned On and Off but with a higher frequency than Slow Blink. The On and Off time is still equal.

On The LED is constantly emitting light.

Slow Waver This is a variant of Slow Blink but instead of being Off, a second color is On. This is only possible with a dual colored LED.

Fast Waver The LED is alternating between two colors as in Slow Waver but using a higher frequency.

Running This means that all LEDs are lit, one at the time, in sequence with every color available i.e. "Power green->Power yellow->Traffic 1 yellow->Traffic 1 red->Traffic 2 yellow->Traffic 2 red->. . . "

As an example, "Slow Waver (Green/Yellow)" means that the LED is slowly blinking by alternating between green and yellow.

The Kvaser Hybrid Pro 2xCAN/LIN has five LEDs as shown in Figure 4 on Page 11. Their functions are shown in Table 4 on Page 14.

LED	Function	Description
PWR (Green)	Power	Steady light when unit is powered and working.
CH 1 (Yellow)	CAN RxTx	Status for CAN/LIN channel 1
CH 2 (Yellow)	CAN RxTx	Status for CAN/LIN channel 2
INFO 1 (Green)	LIN Mode	CH 1 in use as LIN
INFO 1 (Yellow)	LIN Mode	LIN reference voltage is available
INFO 2 (Green)	LIN Mode	CH 2 in use as LIN
INFO 2 (Yellow)	LIN Mode	LIN reference voltage is available

Table 4: LEDs on the Kvaser Hybrid Pro 2xCAN/LIN.

4.1.1 Interface mode

The device is in Interface mode when connected to the host computer via USB. If the Power LED is showing a steady green light, the device is in Interface mode and working correctly. When connected to the computer for the first time, the Power LED will blink slowly in yellow until the driver is installed and the device has received a USB configuration.

When in Interface mode, if the Power LED is yellow for an extended period, something is wrong. Please see Table 5.



The power should never be removed when firmware update is in progress.

Power LED	Traffic LED	Description
Slow Blink (Yellow)	All off (-)	Waiting for USB configuration
Slow Waver (Green/Yellow)	Slow Waver (Yellow/Red)	Firmware configuration error[1]
Slow Waver (Green/Yellow)	All Slow Blink (Yellow)	Power problem[2]

Table 5: Yellow Power LED shows problems in Interface mode.

4.1.2 CAN and LIN usage

Kvaser Hybrid Pro 2xCAN/LIN is ready to be operated as either a CAN or LIN interface when connected to the host computer without further configuration. You can use the same CANlib and LINlib API calls as with other Kvaser interfaces, use CANlib for CAN and LINlib for LIN related usage. Both libraries are included in the Kvaser CANlib SDK, see Section 2.6, Additional software and documentation, on Page 8.

[1] This should not normally happen. If it does, please contact Kvaser support.
[2] This indicates low power supply, such as using an unpowered USB hub.

4.1.3 CAN interface mode

When Kvaser Hybrid Pro 2xCAN/LIN is used as a CAN interface, the traffic LED is used as described in Table 6 on Page 15.

Traffic LED	Description
Off (-)	Idle, no CAN traffic
Flash (Yellow)	CAN message received or sent
Flash (Red)	Error frame received
All Fast Blink (Yellow)	Firmware update is in progress
Fast Blink (Red)	CAN channel is error passive
On (Red)[3]	CAN overrun

Table 6: Traffic LED shows CAN bus status in CAN Interface mode.

4.1.4 LIN interface mode

When Kvaser Hybrid Pro 2xCAN/LIN is used as a LIN interface, the traffic LED is used as described in Table 7.

Traffic LED	Description
Off (-)	Idle, no CAN traffic
Flash (Yellow)	Internal activity or LIN message received or sent
All Fast Blink (Yellow)	Firmware update is in progress

Table 7: Traffic LED shows LIN bus status in LIN Interface mode.

4.2 Start and stop of t programs

All events that a t program will react to are specified using various event hooks. In effect, these are functions which are called when the specific events occur. Among other events, the program can react to starting and stopping itself which this section describes. Read the Kvaser t Programming Language guide that can be downloaded at www.kvaser.com/download for more information.

The "on start" event will be triggered in the Kvaser Hybrid Pro 2xCAN/LIN when any of the following occurs:

- When a t program is started using the CANlib API (`kvScriptStart()`).
- When a t program is started from another t program.

The "on stop" event will be triggered for running t programs during the corresponding cases:

[3]The red Traffic LED indicating overrun will stay on until the device goes bus off.

- When a t program is stopped using the CANlib API (`kvScriptStop()`).
- When a t program is stopped from another t program.

4.3 Technical data

In Table 8 you will find the technical specifications of Kvaser Hybrid Pro 2xCAN/LIN.

CAN/LIN Channels	2 (Individually configurable as CAN or LIN)
CAN Transceivers	TJA1051T/E (Compliant with ISO 11898-2)
CAN Bit Rate	50 kbit/s to 1 Mbit/s
CAN FD Bit Rate	Up to 5 Mbit/s
CAN/LIN Controller	Kvaser CAN/LIN IP in FPGA
Galvanic isolation	Yes
LIN Transceivers	TJA1021T/20
LIN Bit Rate	1 - 20 kbit/s
Time stamp resolution	1 µs
CAN Max message rate	20000 msg/s per channel
Error Frame Detection	Yes
Error Frame Generation	Yes
Silent mode	Yes
Kvaser MagiSync	Yes
Kvaser t programming	Yes
Kvaser CANtegrity	No
Host interface	USB 2.0
Host OS	Windows (7 or later), Linux.
Power consumption	max 280 mA
Hardware configuration	Done by software (Plug & Play).
Dimensions	50 x 170 x 20 mm for body incl. strain relief
Weight	170 g
Operating temperature	−40 °C to +85 °C
Storage temperature	−40 °C to +85 °C
Relative humidity	0 % to 85 % (non-condensing.)

Table 8: Technical Specifications.

4.4 CAN/LIN connector

Kvaser Hybrid Pro 2xCAN/LIN devices that use the 9-pin D-SUB connector (see Figure 5 on Page 17) have the pinning described in Table 9 on Page 17.

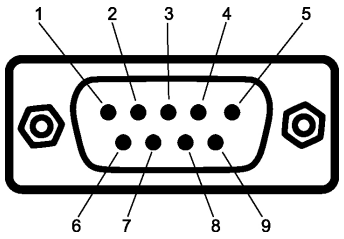


Figure 5: The D-SUB 9 connector pin numbers

D-SUB 9	CAN Function	LIN Function
1	Not connected	Not connected
2	CAN_L channel	Not connected
3	GND	GND
4	Not connected	Not connected
5	Shield	Shield
6	Not connected	Not connected
7	CAN_H channel	LIN_BUS channel
8	Not connected	Not connected
9	Not connected	Reference Voltage

Table 9: Pin configuration of the 9-pin D-SUB connector.

The Reference Voltage (pin 9) is only used as voltage reference and power to the LIN transceiver. The Kvaser Hybrid Pro 2xCAN/LIN itself (including CAN transceiver) is powered through the USB connector. The Reference Voltage (pin 9) must be connected to a voltage supply in the range of 6 V to 27 V (absolute maximum rating is 40V) to ensure proper behaviour of the transceiver. The Kvaser Hybrid Pro 2xCAN/LIN will automatically switch the internal pull-up resistor from (typical) 160 kΩ to 1 kΩ when going from slave mode to master mode.

4.5 CAN bus termination

Every CAN bus must be terminated with a 120 Ω resistor at each end of the bus. The Kvaser Hybrid Pro 2xCAN/LIN does not contain any CAN bus termination, because their inclusion could cause severe disturbance in a system which is already correctly terminated.

For laboratory or testing use, the exact value of the termination resistors is not always critical. Sometimes a single terminator is sufficient. For production, proper termination is essential. If you see error frames on the bus, you should check the termination.



To save yourself a lot of trouble, always terminate the CAN bus properly.

4.6 Updating the firmware

For the Kvaser Hybrid Pro 2xCAN/LIN to communicate with the host computer, compatible versions of the Kvaser CANlib (including driver) and firmware must be installed.

The latest versions of firmware and drivers can be downloaded for free at www.kvaser.com/download.

Connect the Kvaser Hybrid Pro 2xCAN/LIN to your host computer with the USB cable and start the update.exe application. A window opens showing the Firmware Update Instructions; read and follow those carefully.

To check the current firmware version, open "Kvaser Device Guide" which can be found in the Control Panel. Select "Kvaser Hybrid Pro 2xCAN/LIN" in the tree view to the left, and click on the channel. The firmware revision information now appears in the right half of the window.

The absolute minimum firmware and driver versions needed in order to use Kvaser Hybrid Pro 2xCAN/LIN are listed in Table 10.

Device	Min. Firmware Version	Min. Driver Version
Kvaser Hybrid Pro 2xCAN/LIN	v3.28	v5.40

Table 10: Minimum compatible driver and firmware versions of Kvaser Hybrid Pro 2xCAN/LIN.

4.7 Kvaser MagiSync

Time synchronization is needed to achieve accurate and precise time stamping between several host computer-to-bus interfaces connected to one host computer. Since each host computer-to-bus interface uses its on-board clock to set the time stamps.

Kvaser MagiSync is an innovative way to synchronize several different Kvaser USB interfaces. You do not need external cables - you get instant synchronisation when you connect the MagiSync enabled Kvaser USB device.

For this to work the Kvaser USB interfaces must reside on the same USB root hub. If they do not they will not be synchronized, see Figure 6 on Page 19 and Figure 7 on Page 19.

Usually, a computer has a USB controller with one root hub in a computer. If you use that one, you do not need an external USB hub to get your Kvaser Devices synchronized. The easiest way to verify the setup is to view Synchronized Hardware in the Device Tree of "Kvaser Device Guide" in your computer's control panel. If all your hardware is placed in one Kvaser MagiSync Group, then you are ready to go.

When connected correctly, all units are synchronized achieving a high precision virtual clock accurate to the microsecond.

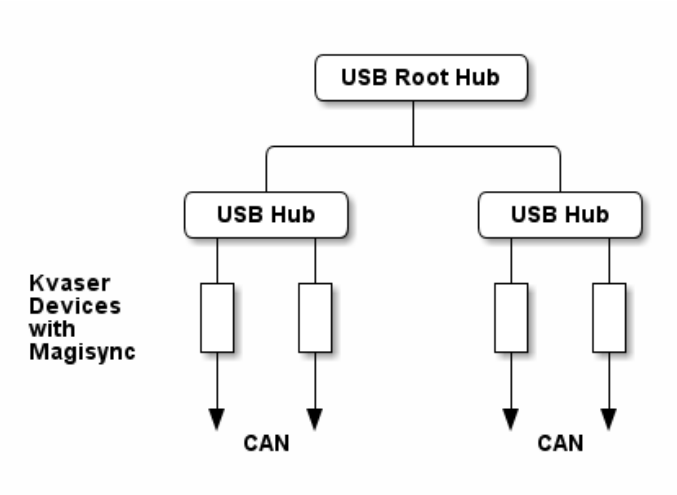


Figure 6: An example setup where all devices are synchronized via MagiSync.

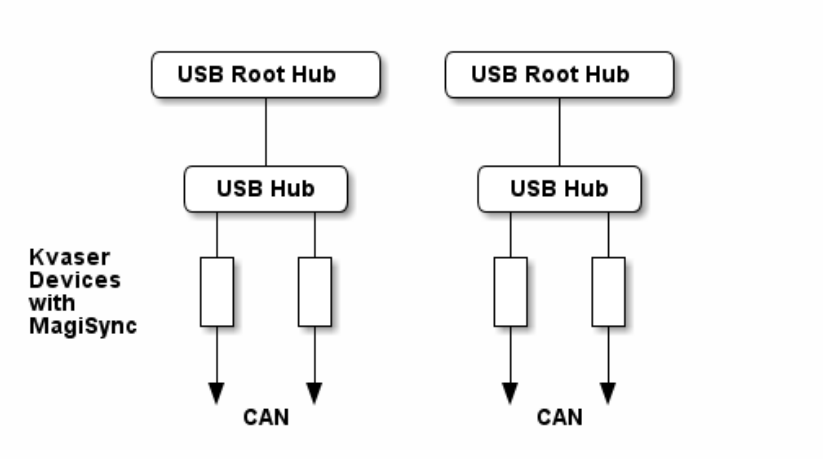


Figure 7: Not all devices are synchronized via MagiSync in this setup.

5 Safety Instructions

5.1 Intended Use

Kvaser interfaces are used to connect computer systems to CAN buses. The Kvaser Hybrid Pro 2xCAN/LIN is intended for connection to a computer via the USB port.

5.2 Usage Warning



WARNING FOR ALL USERS

WARNING! - YOUR USE OF THIS DEVICE MUST BE DONE WITH CAUTION AND A FULL UNDERSTANDING OF THE RISKS!
THIS WARNING IS PRESENTED TO INFORM YOU THAT THE OPERATION OF THIS DEVICE MAY BE DANGEROUS. YOUR ACTIONS CAN INFLUENCE THE BEHAVIOR OF A CAN-BASED DISTRIBUTED EMBEDDED SYSTEM, AND DEPENDING ON THE APPLICATION, THE CONSEQUENCES OF YOUR IMPROPER ACTIONS COULD CAUSE SERIOUS OPERATIONAL MALFUNCTION, LOSS OF INFORMATION, DAMAGE TO EQUIPMENT, AND PHYSICAL INJURY TO YOURSELF AND OTHERS. A POTENTIALLY HAZARDOUS OPERATING CONDITION IS PRESENT WHEN THE FOLLOWING TWO CONDITIONS ARE CONCURRENTLY TRUE: THE PRODUCT IS PHYSICALLY INTERCONNECTED TO A REAL DISTRIBUTED EMBEDDED SYSTEM; AND THE FUNCTIONS AND OPERATIONS OF THE REAL DISTRIBUTED EMBEDDED SYSTEM ARE CONTROLLABLE OR INFLUENCED BY THE USE OF THE CAN NETWORK. A POTENTIALLY HAZARDOUS OPERATING CONDITION MAY RESULT FROM THE ACTIVITY OR NON-ACTIVITY OF SOME DISTRIBUTED EMBEDDED SYSTEM FUNCTIONS AND OPERATIONS, WHICH MAY RESULT IN SERIOUS PHYSICAL HARM OR DEATH OR CAUSE DAMAGE TO EQUIPMENT, DEVICES, OR THE SURROUNDING ENVIRONMENT.
WITH THIS DEVICE, YOU MAY POTENTIALLY:

- CAUSE A CHANGE IN THE OPERATION OF THE SYSTEM, MODULE, DEVICE, CIRCUIT, OR OUTPUT.
- TURN ON OR ACTIVATE A MODULE, DEVICE, CIRCUIT, OUTPUT, OR FUNCTION.
- TURN OFF OR DEACTIVATE A MODULE, DEVICE, CIRCUIT, OUTPUT, OR FUNCTION.
- INHIBIT, TURN OFF, OR DEACTIVATE NORMAL OPERATION.
- MODIFY THE BEHAVIOR OF A DISTRIBUTED PRODUCT.
- ACTIVATE AN UNINTENDED OPERATION.
- PLACE THE SYSTEM, MODULE, DEVICE, CIRCUIT, OR OUTPUT INTO AN UNINTENDED MODE.

ONLY THOSE PERSONS WHO:
(A) ARE PROPERLY TRAINED AND QUALIFIED WITH RESPECT TO THE USE OF THE DEVICE,
(B) UNDERSTAND THE WARNINGS ABOVE, AND
(C) UNDERSTAND HOW THIS DEVICE INTERACTS WITH AND IMPACTS THE FUNCTION AND SAFETY OF OTHER PRODUCTS IN A DISTRIBUTED SYSTEM AND THE APPLICATION FOR WHICH THIS DEVICE WILL BE APPLIED, MAY USE THE DEVICE.
PLEASE NOTE THAT YOU CAN INTEGRATE THIS PRODUCT AS A SUBSYSTEM INTO HIGHER-LEVEL SYSTEMS. IN CASE YOU DO SO, KVASER AB HEREBY DECLARES THAT KVASER AB'S WARRANTY SHALL BE LIMITED TO THE CORRECTION OF DEFECTS, AND KVASER AB HEREBY EXPRESSLY DISCLAIMS ANY LIABILITY OVER AND ABOVE THE REFUNDING OF THE PRICE PAID FOR THIS DEVICE, SINCE KVASER AB DOES NOT HAVE ANY INFLUENCE ON THE IMPLEMENTATIONS OF THE HIGHER-LEVEL SYSTEM, WHICH MAY BE DEFECTIVE.

6 Disposal and Recycling Information



When this product reaches its end of life, please dispose of it according to your local environmental laws and guidelines.

For information about Kvaser's recycling programs, visit:
https://www.kvaser.com/en/kvaser/recycling-policy.html

7 Legal acknowledgements

7.1 EU Regulatory Compliance

KVASER **EU Declaration of Conformity (DoC)**

We

Company Name:	Kvaser AB	City:	Mölndal
Postal address:	Aminogatan 25	Telephone number:	+46 31 886344
Postcode:	431 53	E-mail address:	sales@kvaser.com

declare that the DoC is issued under our sole responsibility and belongs to the following product:

Product: Kvaser Hybrid Pro 2xCAN/LIN

Object of the declaration (identification of apparatus allowing traceability):
Product: Kvaser Hybrid Pro 2xCAN/LIN
Type: 73-30130-01042-0

The object of the declaration described above is in conformity with the relevant Union harmonisation legislation:
Electromagnetic Compatibility (EMC) Directive 2014/30/EU (Art. 6)

RoHS recast Directive 2011/65/EU (Art. 4.1)

The following harmonised standards and technical specifications have been applied
(title, date of standard/specification):

EN 55032 (2015 + A11:2020) EN 55035 (2017 + A11:2020)

EN IEC 63000 (2018)

Signed for and on behalf of:

Mölndal	2025-01-10	
Place of issue	Date of issue	Kent Lennartsson, Research Manager

7.2 FCC Regulatory Compliance

KVASER

Federal Communications Commission (FCC) Compliance Information Statement

IDENTIFICATION OBJECT:
Product: Kvaser Hybrid Pro 2xCAN/LIN
Type: 73-30130-01042-0

APPLICABLE COMPLIANCE STATEMENTS:
CFR Title 47 Part 15 §15.107, §15.109
This device complies with part 15 of the FCC Rules.
Operation is subject to the following two conditions:
(1) This device may not cause harmful interference, and
(2) this device must accept any interference received,
including interference that may cause undesired operation.

RESPONSIBLE PARTY (IN USA) NAME:
Kvaser Inc.
23881 Via Fabricante, Suite 503
Mission Viejo, CA 92691

Internet contact: support@kvaser.com

7.3 Patents, Copyrights and Trademarks

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DeviceNet is a trademark of Open DeviceNet Vendor Association, Inc.

NMEA 2000 is the registered trademark of the National Marine Electronics Association, Inc.

For information about Kvaser related CAN patents, see www.kvaser.com/patent.

8 Document Revision History

Version history for document UG_98202_hybrid_pro_2xcan_lin:

Revision	Date	Changes
1.0	2018-02-15	Initial version.
1.0	2018-05-03	Minor textual changes.
1.1	2018-05-07	Minor textual changes.
1.2	2018-08-28	Minor textual changes.
2.0	2018-11-12	Updated EU Regulatory Compliance, updated restrictions in t.
2.1	2019-02-11	Minor textual changes.
2.2	2019-08-09	Url protocol updated.
2.3	2020-01-27	Added sdoc.
2.4	2020-08-27	Updated supported OS.
2.5	2021-09-09	Dropped mention of Hi-Speed CAN.
2.6	2021-10-25	Minor textual changes.
2.7	2022-04-01	Minor textual changes, added galvanic isolation info to Technical data table.
2.8	2023-02-13	Updated the Technical data table and tables with firmware and driver information. Added section about intended use.
2.9	2024-03-15	Updated Kvaser logo.
2.10	2025-01-14	Updated EU Declaration of Conformity. Updated the USB connector description. Minor textual changes.
2.11	2026-02-05	Added paragraph about reference voltage.