

Xenomai RTDM skin API

2.4.5

Generated by Doxygen 1.5.5

Tue Aug 19 23:04:26 2008

Contents

1	Deprecated List	1
2	Module Index	3
2.1	Modules	3
3	Data Structure Index	5
3.1	Data Structures	5
4	File Index	7
4.1	File List	7
5	Module Documentation	9
5.1	CAN Devices	9
5.2	Real-Time Driver Model	32
5.3	User API	34
5.4	Serial Devices	46
5.5	Testing Devices	55
5.6	Inter-Driver API	57
5.7	Device Registration Services	66
5.8	Driver Development API	75
5.9	Clock Services	76
5.10	Task Services	78
5.11	Timer Services	86
5.12	Synchronisation Services	91
5.13	Interrupt Management Services	109
5.14	Non-Real-Time Signalling Services	114
5.15	Utility Services	117
5.16	Device Profiles	127
6	Data Structure Documentation	129

6.1	can_bittime Struct Reference	129
6.2	can_bittime_btr Struct Reference	130
6.3	can_bittime_std Struct Reference	131
6.4	can_filter Struct Reference	132
6.5	can_frame Struct Reference	133
6.6	rt dm_dev_context Struct Reference	134
6.7	rt dm_device Struct Reference	135
6.8	rt dm_device_info Struct Reference	137
6.9	rt dm_operations Struct Reference	138
6.10	rt ser_config Struct Reference	140
6.11	rt ser_event Struct Reference	141
6.12	rt ser_status Struct Reference	142
6.13	sockaddr_can Struct Reference	143
7	File Documentation	145
7.1	include/rt dm/rt can.h File Reference	145
7.2	include/rt dm/rt dm.h File Reference	154
7.3	include/rt dm/rt dm_driver.h File Reference	157
7.4	include/rt dm/rt serial.h File Reference	164
7.5	include/rt dm/rt testing.h File Reference	168
7.6	ksrc/skins/rt dm/device.c File Reference	170
7.7	ksrc/skins/rt dm/drvlib.c File Reference	171
7.8	ksrc/skins/rt dm/module.c File Reference	176
7.9	ksrc/skins/rt dm/core.c File Reference	177
8	Example Documentation	181
8.1	cross-link.c	181
8.2	rt can_rtt.c	187
8.3	rt canconfig.c	194
8.4	rt canrecv.c	198
8.5	rt cansend.c	203

Chapter 1

Deprecated List

Global [rtbm_task_sleep_until](#) Use rtbm_task_sleep_abs instead!

Chapter 2

Module Index

2.1 Modules

Here is a list of all modules:

Real-Time Driver Model	32
User API	34
Driver Development API	75
Inter-Driver API	57
Device Registration Services	66
Synchronisation Services	91
Clock Services	76
Task Services	78
Timer Services	86
Synchronisation Services	91
Interrupt Management Services	109
Non-Real-Time Signalling Services	114
Utility Services	117
Device Profiles	127
CAN Devices	9
Serial Devices	46
Testing Devices	55

Chapter 3

Data Structure Index

3.1 Data Structures

Here are the data structures with brief descriptions:

can_bittime (Custom CAN bit-time definition)	129
can_bittime_btr (Hardware-specific BTR bit-times)	130
can_bittime_std (Standard bit-time parameters according to Bosch)	131
can_filter (Filter for reception of CAN messages)	132
can_frame (Raw CAN frame)	133
rtdm_dev_context (Device context)	134
rtdm_device (RTDM device)	135
rtdm_device_info (Device information)	137
rtdm_operations (Device operations)	138
rtser_config (Serial device configuration)	140
rtser_event (Additional information about serial device events)	141
rtser_status (Serial device status)	142
sockaddr_can (Socket address structure for the CAN address family)	143

Chapter 4

File Index

4.1 File List

Here is a list of all documented files with brief descriptions:

include/rtdm/ rtcan.h (Real-Time Driver Model for RT-Socket-CAN, CAN device profile header)	145
include/rtdm/ rtdm.h (Real-Time Driver Model for Xenomai, user API header)	154
include/rtdm/ rtdm_driver.h (Real-Time Driver Model for Xenomai, driver API header)	157
include/rtdm/ rtserial.h (Real-Time Driver Model for Xenomai, serial device profile header)	164
include/rtdm/ rttesting.h (Real-Time Driver Model for Xenomai, testing device profile header)	168
include/rtdm/ syscall.h	??
ksrc/skins/rtdm/ core.c (Real-Time Driver Model for Xenomai, device operation multiplexing)	177
ksrc/skins/rtdm/ device.c (Real-Time Driver Model for Xenomai, device management)	170
ksrc/skins/rtdm/ drvlib.c (Real-Time Driver Model for Xenomai, driver library)	171
ksrc/skins/rtdm/ internal.h	??
ksrc/skins/rtdm/ module.c (Real-Time Driver Model for Xenomai)	176

Chapter 5

Module Documentation

5.1 CAN Devices

Collaboration diagram for CAN Devices:



5.1.1 Detailed Description

This is the common interface a RTDM-compliant CAN device has to provide. Feel free to report bugs and comments on this profile to the "Socketcan" mailing list (Socketcan-core@lists.berlios.de) or directly to the authors (wg@grandegger.com or Sebastian.Smolorz@stud.uni-hannover.de).

Profile Revision: 2

Device Characteristics

Device Flags: RTDM_PROTOCOL_DEVICE

Protocol Family: PF_CAN

Socket Type: SOCK_RAW

Device Class: RTDM_CLASS_CAN

Supported Operations

Socket

Environments: non-RT (RT optional)

Specific return values:

- -EPROTONOSUPPORT (Protocol is not supported by the driver. See [CAN protocols](#) for possible protocols.)

Close

Blocking calls to any of the [Send](#) or [Receive](#) functions will be unblocked when the socket is closed and return with an error.

Environments: non-RT (RT optional)

Specific return values: none

IOCTL

Mandatory Environments: see [below](#)

Specific return values: see [below](#)

Bind

Binds a socket to one or all CAN devices (see struct [sockaddr_can](#)). If a filter list has been defined with [setsockopt](#) (see [Sockopts](#)), it will be used upon reception of CAN frames to decide whether the bound socket will receive a frame. If no filter has been defined, the socket will receive **all** CAN frames on the specified interface(s).

Binding to special interface index 0 will make the socket receive CAN frames from all CAN interfaces.

Binding to an interface index is also relevant for the [Send](#) functions because they will transmit a message over the interface the socket is bound to when no socket address is given to them.

Environments: non-RT (RT optional)

Specific return values:

- -EFAULT (It was not possible to access user space memory area at the specified address.)
- -ENOMEM (Not enough memory to fulfill the operation)
- -EINVAL (Invalid address family, or invalid length of address structure)
- -ENODEV (Invalid CAN interface index)
- -ENOSPC (No enough space for filter list)
- -EBADF (Socket is about to be closed)
- -EAGAIN (Too many receivers. Old binding (if any) is still active. Close some sockets and try again.)

Setsockopt, Getsockopt

These functions allow to set and get various socket options. Currently, only CAN raw sockets are supported.

Supported Levels and Options:

- Level **SOL_CAN_RAW** : CAN RAW protocol (see [CAN_RAW](#))
 - Option [CAN_RAW_FILTER](#) : CAN filter list
 - Option [CAN_RAW_ERR_FILTER](#) : CAN error mask
 - Option [CAN_RAW_LOOPBACK](#) : CAN TX loopback to local sockets

Environments: non-RT (RT optional)

Specific return values: see links to options above.

Recv, Recvfrom, Recvmsg

These functions receive CAN messages from a socket. Only one message per call can be received, so only one buffer with the correct length must be passed. For **SOCK_RAW**, this is the size of struct [can_frame](#).

Unlike a call to one of the [Send](#) functions, a Recv function will not return with an error if an interface is down (due to bus-off or setting of stop mode) or in sleep mode. Moreover, in such a case there may still be some CAN messages in the socket buffer which could be read out successfully.

It is possible to receive a high precision timestamp with every CAN message. The condition is a former instruction to the socket via [RTCAN_RTIOC_TAKE_TIMESTAMP](#). The timestamp will be copied to the `msg_control` buffer of struct `msghdr` if it points to a valid memory location with size of [nanosecs_abs_t](#). If this is a NULL pointer the timestamp will be discarded silently.

Note: A `msg_controllen` of 0 upon completion of the function call indicates that no timestamp is available for that message.

Supported Flags [in]:

- **MSG_DONTWAIT** (By setting this flag the operation will only succeed if it would not block, i.e. if there is a message in the socket buffer. This flag takes precedence over a timeout specified by [RTCAN_RTIOC_RCV_TIMEOUT](#).)

- MSG_PEEK (Receive a message but leave it in the socket buffer. The next receive operation will get that message again.)

Supported Flags [out]: none

Environments: RT (non-RT optional)

Specific return values:

- Non-negative value (Indicating the successful reception of a CAN message. For SOCK_RAW, this is the size of struct [can_frame](#) regardless of the actual size of the payload.)
- -EFAULT (It was not possible to access user space memory area at one of the specified addresses.)
- -EINVAL (Unsupported flag detected, or invalid length of socket address buffer, or invalid length of message control buffer)
- -EMSGSIZE (Zero or more than one iovec buffer passed, or buffer too small)
- -EAGAIN (No data available in non-blocking mode)
- -EBADF (Socket was closed.)
- -EINTR (Operation was interrupted explicitly or by signal.)
- -ETIMEDOUT (Timeout)

Send, Sendto, Sendmsg

These functions send out CAN messages. Only one message per call can be transmitted, so only one buffer with the correct length must be passed. For SOCK_RAW, this is the size of struct [can_frame](#).

The following only applies to SOCK_RAW: If a socket address of struct [sockaddr_can](#) is given, only `can_ifindex` is used. It is also possible to omit the socket address. Then the interface the socket is bound to will be used for sending messages.

If an interface goes down (due to bus-off or setting of stop mode) all senders that were blocked on this interface will be woken up.

Supported Flags:

- MSG_DONTWAIT (By setting this flag the transmit operation will only succeed if it would not block. This flag takes precedence over a timeout specified by [RTCAN_RTIOC_SND_TIMEOUT](#).)

Environments: RT (non-RT optional)

Specific return values:

- Non-negative value equal to given buffer size (Indicating the successful completion of the function call. See also note.)
- -EOPNOTSUPP (MSG_OOB flag is not supported.)
- -EINVAL (Unsupported flag detected *or*: Invalid length of socket address *or*: Invalid address family *or*: Data length code of CAN frame not between 0 and 15 *or*: CAN standard frame has got an ID not between 0 and 2031)
- -EMSGSIZE (Zero or more than one buffer passed or invalid size of buffer)
- -EFAULT (It was not possible to access user space memory area at one of the specified addresses.)
- -ENXIO (Invalid CAN interface index - 0 is not allowed here - or socket not bound or rather bound to all interfaces.)
- -ENETDOWN (Controller is bus-off or in stopped state.)
- -ECOMM (Controller is sleeping)
- -EAGAIN (Cannot transmit without blocking but a non-blocking call was requested.)
- -EINTR (Operation was interrupted explicitly or by signal)
- -EBADF (Socket was closed.)

- -ETIMEDOUT (Timeout)

Note: A successful completion of the function call does not implicate a successful transmission of the message.

Files

- file [rtcan.h](#)
Real-Time Driver Model for RT-Socket-CAN, CAN device profile header.

Data Structures

- struct [can_bittime_std](#)
Standard bit-time parameters according to Bosch.
- struct [can_bittime_btr](#)
Hardware-specific BTR bit-times.
- struct [can_bittime](#)
Custom CAN bit-time definition.
- struct [can_filter](#)
Filter for reception of CAN messages.
- struct [sockaddr_can](#)
Socket address structure for the CAN address family.
- struct [can_frame](#)
Raw CAN frame.

CAN operation modes

Modes into which CAN controllers can be set

- enum [CAN_MODE](#) { [CAN_MODE_STOP](#) = 0, [CAN_MODE_START](#), [CAN_MODE_SLEEP](#) }

CAN controller states

States a CAN controller can be in.

- enum [CAN_STATE](#) {
 [CAN_STATE_ACTIVE](#) = 0, [CAN_STATE_BUS_WARNING](#), [CAN_STATE_BUS_PASSIVE](#),
 [CAN_STATE_BUS_OFF](#),
 [CAN_STATE_SCANNING_BAUDRATE](#), [CAN_STATE_STOPPED](#), [CAN_STATE_SLEEPING](#) }

CAN ID masks

Bit masks for masking CAN IDs

- #define `CAN_EFF_MASK` 0x1FFFFFFF
Bit mask for extended CAN IDs.
- #define `CAN_SFF_MASK` 0x000007FF
Bit mask for standard CAN IDs.

CAN ID flags

Flags within a CAN ID indicating special CAN frame attributes

- #define `CAN_EFF_FLAG` 0x80000000
Extended frame.
- #define `CAN_RTR_FLAG` 0x40000000
Remote transmission frame.
- #define `CAN_ERR_FLAG` 0x20000000
Error frame (see [Errors](#)), not valid in struct `can_filter`.
- #define `CAN_INV_FILTER` `CAN_ERR_FLAG`
Invert CAN filter definition, only valid in struct `can_filter`.

Particular CAN protocols

Possible protocols for the PF_CAN protocol family

Currently only the RAW protocol is supported.

- #define `CAN_RAW` 1
Raw protocol of PF_CAN, applicable to socket type `SOCK_RAW`.

CAN controller modes

Special CAN controllers modes, which can be or'ed together.

Note:

These modes are hardware-dependent. Please consult the hardware manual of the CAN controller for more detailed information.

- #define `CAN_CTRLMODE_LISTENONLY` 0x1
- #define `CAN_CTRLMODE_LOOPBACK` 0x2

Timestamp switches

Arguments to pass to [RTCAN_RTIOC_TAKE_TIMESTAMP](#)

- `#define RTCAN_TAKE_NO_TIMESTAMPS 0`
Switch off taking timestamps.
- `#define RTCAN_TAKE_TIMESTAMPS 1`
Do take timestamps.

RAW socket options

Setting and getting CAN RAW socket options.

- `#define CAN_RAW_FILTER 0x1`
CAN filter definition.
- `#define CAN_RAW_ERR_FILTER 0x2`
CAN error mask.
- `#define CAN_RAW_LOOPBACK 0x3`
CAN TX loopback.
- `#define CAN_RAW_RECV_OWN_MSGS 0x4`
CAN receive own messages.

IOCTLs

CAN device IOCTLs

- `#define SIOCGIFINDEX defined_by_kernel_header_file`
Get CAN interface index by name.
- `#define SIOCSCANBAUDRATE _IOW(RTIOC_TYPE_CAN, 0x01, struct ifreq)`
Set baud rate.
- `#define SIOCGCANBAUDRATE _IOWR(RTIOC_TYPE_CAN, 0x02, struct ifreq)`
Get baud rate.
- `#define SIOCSCANCUSTOMBITTIME _IOW(RTIOC_TYPE_CAN, 0x03, struct ifreq)`
Set custom bit time parameter.
- `#define SIOCGCANCUSTOMBITTIME _IOWR(RTIOC_TYPE_CAN, 0x04, struct ifreq)`
Get custom bit-time parameters.
- `#define SIOCSCANMODE _IOW(RTIOC_TYPE_CAN, 0x05, struct ifreq)`
Set operation mode of CAN controller.

- #define [SIOCGCANSTATE](#) _IOW(RTIOC_TYPE_CAN, 0x06, struct ifreq)
Get current state of CAN controller.
- #define [SIOCSCANCTRLMODE](#) _IOW(RTIOC_TYPE_CAN, 0x07, struct ifreq)
Set special controller modes.
- #define [SIOCGCANCTRLMODE](#) _IOW(RTIOC_TYPE_CAN, 0x08, struct ifreq)
Get special controller modes.
- #define [RTCAN_RTIOC_TAKE_TIMESTAMP](#) _IOW(RTIOC_TYPE_CAN, 0x09, int)
Enable or disable storing a high precision timestamp upon reception of a CAN frame.
- #define [RTCAN_RTIOC_RCV_TIMEOUT](#) _IOW(RTIOC_TYPE_CAN, 0x0A, nanosecs_rel_t)
Specify a reception timeout for a socket.
- #define [RTCAN_RTIOC_SND_TIMEOUT](#) _IOW(RTIOC_TYPE_CAN, 0x0B, nanosecs_rel_t)
Specify a transmission timeout for a socket.

Error mask

Error class (mask) in `can_id` field of struct [can_frame](#) to be used with [CAN_RAW_ERR_FILTER](#).

Note: Error reporting is hardware dependent and most CAN controllers report less detailed error conditions than the SJA1000.

Note: In case of a bus-off error condition ([CAN_ERR_BUSOFF](#)), the CAN controller is **not** restarted automatically. It is the application's responsibility to react appropriately, e.g. calling [CAN_MODE_START](#).

Note: Bus error interrupts ([CAN_ERR_BUSERROR](#)) are enabled when an application is calling a [Recv](#) function on a socket listening on bus errors (using [CAN_RAW_ERR_FILTER](#)). After one bus error has occurred, the interrupt will be disabled to allow the application time for error processing and to efficiently avoid bus error interrupt flooding.

- #define [CAN_ERR_TX_TIMEOUT](#) 0x00000001U
TX timeout (netdevice driver).
- #define [CAN_ERR_LOSTARB](#) 0x00000002U
Lost arbitration (see [data\[0\]](#)).
- #define [CAN_ERR_CRTL](#) 0x00000004U
Controller problems (see [data\[1\]](#)).
- #define [CAN_ERR_PROT](#) 0x00000008U
Protocol violations (see [data\[2\]](#), [data\[3\]](#)).
- #define [CAN_ERR_TRX](#) 0x00000010U
Transceiver status (see [data\[4\]](#)).

- #define [CAN_ERR_ACK](#) 0x00000020U
Received no ACK on transmission.
- #define [CAN_ERR_BUSOFF](#) 0x00000040U
Bus off.
- #define [CAN_ERR_BUSERROR](#) 0x00000080U
Bus error (may flood!).
- #define [CAN_ERR_RESTARTED](#) 0x00000100U
Controller restarted.
- #define [CAN_ERR_MASK](#) 0x1FFFFFFFU
Omit EFF, RTR, ERR flags.

Arbitration lost error

Error in the data[0] field of struct [can_frame](#).

- #define [CAN_ERR_LOSTARB_UNSPEC](#) 0x00
unspecified

Controller problems

Error in the data[1] field of struct [can_frame](#).

- #define [CAN_ERR_CRTL_UNSPEC](#) 0x00
unspecified
- #define [CAN_ERR_CRTL_RX_OVERFLOW](#) 0x01
RX buffer overflow.
- #define [CAN_ERR_CRTL_TX_OVERFLOW](#) 0x02
TX buffer overflow.
- #define [CAN_ERR_CRTL_RX_WARNING](#) 0x04
reached warning level for RX errors
- #define [CAN_ERR_CRTL_TX_WARNING](#) 0x08
reached warning level for TX errors
- #define [CAN_ERR_CRTL_RX_PASSIVE](#) 0x10
reached passive level for RX errors
- #define [CAN_ERR_CRTL_TX_PASSIVE](#) 0x20
reached passive level for TX errors

Protocol error type

Error in the data[2] field of struct `can_frame`.

- #define `CAN_ERR_PROT_UNSPEC` 0x00
unspecified
- #define `CAN_ERR_PROT_BIT` 0x01
single bit error
- #define `CAN_ERR_PROT_FORM` 0x02
frame format error
- #define `CAN_ERR_PROT_STUFF` 0x04
bit stuffing error
- #define `CAN_ERR_PROT_BIT0` 0x08
unable to send dominant bit
- #define `CAN_ERR_PROT_BIT1` 0x10
unable to send recessive bit
- #define `CAN_ERR_PROT_OVERLOAD` 0x20
bus overload
- #define `CAN_ERR_PROT_ACTIVE` 0x40
active error announcement
- #define `CAN_ERR_PROT_TX` 0x80
error occurred on transmission

Protocol error location

Error in the data[3] field of struct `can_frame`.

- #define `CAN_ERR_PROT_LOC_UNSPEC` 0x00
unspecified
- #define `CAN_ERR_PROT_LOC_SOF` 0x03
start of frame
- #define `CAN_ERR_PROT_LOC_ID28_21` 0x02
ID bits 28 - 21 (SFF: 10 - 3).
- #define `CAN_ERR_PROT_LOC_ID20_18` 0x06
ID bits 20 - 18 (SFF: 2 - 0).
- #define `CAN_ERR_PROT_LOC_SRTR` 0x04

substitute RTR (SFF: RTR)

- `#define CAN_ERR_PROT_LOC_IDE 0x05`
identifier extension
- `#define CAN_ERR_PROT_LOC_ID17_13 0x07`
ID bits 17-13.
- `#define CAN_ERR_PROT_LOC_ID12_05 0x0F`
ID bits 12-5.
- `#define CAN_ERR_PROT_LOC_ID04_00 0x0E`
ID bits 4-0.
- `#define CAN_ERR_PROT_LOC_RTR 0x0C`
RTR.
- `#define CAN_ERR_PROT_LOC_RES1 0x0D`
reserved bit 1
- `#define CAN_ERR_PROT_LOC_RES0 0x09`
reserved bit 0
- `#define CAN_ERR_PROT_LOC_DLC 0x0B`
data length code
- `#define CAN_ERR_PROT_LOC_DATA 0x0A`
data section
- `#define CAN_ERR_PROT_LOC_CRC_SEQ 0x08`
CRC sequence.
- `#define CAN_ERR_PROT_LOC_CRC_DEL 0x18`
CRC delimiter.
- `#define CAN_ERR_PROT_LOC_ACK 0x19`
ACK slot.
- `#define CAN_ERR_PROT_LOC_ACK_DEL 0x1B`
ACK delimiter.
- `#define CAN_ERR_PROT_LOC_EOF 0x1A`
end of frame
- `#define CAN_ERR_PROT_LOC_INTERM 0x12`
intermission

Protocol error location

Error in the data[4] field of struct `can_frame`.

- `#define CAN_ERR_TRX_UNSPEC 0x00`
`0000 0000`
- `#define CAN_ERR_TRX_CANH_NO_WIRE 0x04`
`0000 0100`
- `#define CAN_ERR_TRX_CANH_SHORT_TO_BAT 0x05`
`0000 0101`
- `#define CAN_ERR_TRX_CANH_SHORT_TO_VCC 0x06`
`0000 0110`
- `#define CAN_ERR_TRX_CANH_SHORT_TO_GND 0x07`
`0000 0111`
- `#define CAN_ERR_TRX_CANL_NO_WIRE 0x40`
`0100 0000`
- `#define CAN_ERR_TRX_CANL_SHORT_TO_BAT 0x50`
`0101 0000`
- `#define CAN_ERR_TRX_CANL_SHORT_TO_VCC 0x60`
`0110 0000`
- `#define CAN_ERR_TRX_CANL_SHORT_TO_GND 0x70`
`0111 0000`
- `#define CAN_ERR_TRX_CANL_SHORT_TO_CANH 0x80`
`1000 0000`

Defines

- `#define AF_CAN 29`
CAN address family.
- `#define PF_CAN AF_CAN`
CAN protocol family.
- `#define SOL_CAN_RAW 103`
CAN socket levels.

Typedefs

- typedef uint32_t [can_id_t](#)
Type of CAN id (see [CAN_xxx_MASK](#) and [CAN_xxx_FLAG](#)).
- typedef [can_id_t](#) [can_err_mask_t](#)
Type of CAN error mask.
- typedef uint32_t [can_baudrate_t](#)
Baudrate definition in bits per second.
- typedef enum [CAN_BITTIME_TYPE](#) [can_bittime_type_t](#)
See [CAN_BITTIME_TYPE](#).
- typedef enum [CAN_MODE](#) [can_mode_t](#)
See [CAN_MODE](#).
- typedef int [can_ctrlmode_t](#)
See [CAN_CTRLMODE](#).
- typedef enum [CAN_STATE](#) [can_state_t](#)
See [CAN_STATE](#).

Enumerations

- enum [CAN_BITTIME_TYPE](#) { [CAN_BITTIME_STD](#), [CAN_BITTIME_BTR](#) }
Supported CAN bit-time types.

5.1.2 Define Documentation

5.1.2.1 #define CAN_CTRLMODE_LISTENONLY 0x1

Listen-Only mode

In this mode the CAN controller would give no acknowledge to the CAN-bus, even if a message is received successfully and messages would not be transmitted. This mode might be useful for bus-monitoring, hot-plugging or throughput analysis.

Examples:

[rtcanconfig.c](#).

5.1.2.2 #define CAN_CTRLMODE_LOOPBACK 0x2

Loopback mode

In this mode the CAN controller does an internal loop-back, a message is transmitted and simultaneously received. That mode can be used for self test operation.

Examples:

[rtcanconfig.c](#).

5.1.2.3 #define CAN_ERR_LOSTARB_UNSPEC 0x00

unspecified

else bit number in bitstream

5.1.2.4 #define CAN_RAW_ERR_FILTER 0x2

CAN error mask.

A CAN error mask (see [Errors](#)) can be set with `setsockopt`. This mask is then used to decide if error frames are delivered to this socket in case of error conditions. The error frames are marked with the `CAN_ERR_FLAG` of `CAN_XXX_FLAG` and must be handled by the application properly. A detailed description of the errors can be found in the `can_id` and the `data` fields of struct `can_frame` (see [Errors](#) for further details).

Parameters:

- ← *level* `SOL_CAN_RAW`
- ← *optname* `CAN_RAW_ERR_FILTER`
- ← *optval* Pointer to error mask of type `can_err_mask_t`.
- ← *optlen* Size of error mask: `sizeof(can_err_mask_t)`.

Environments: non-RT (RT optional)

Specific return values:

- -EFAULT (It was not possible to access user space memory area at the specified address.)
- -EINVAL (Invalid length "optlen")

Examples:

[rtcanrecv.c](#).

5.1.2.5 #define CAN_RAW_FILTER 0x1

CAN filter definition.

A CAN raw filter list with elements of struct `can_filter` can be installed with `setsockopt`. This list is used upon reception of CAN frames to decide whether the bound socket will receive a frame. An empty filter list can also be defined using `optlen = 0`, which is recommended for write-only sockets.

If the socket was already bound with [Bind](#), the old filter list gets replaced with the new one. Be aware that already received, but not read out CAN frames may stay in the socket buffer.

Parameters:

- ← *level* `SOL_CAN_RAW`

← *optname* CAN_RAW_FILTER

← *optval* Pointer to array of struct [can_filter](#).

← *optlen* Size of filter list: count * sizeof(struct can_filter).

Environments: non-RT (RT optional)

Specific return values:

- -EFAULT (It was not possible to access user space memory area at the specified address.)
- -ENOMEM (Not enough memory to fulfill the operation)
- -EINVAL (Invalid length "optlen")
- -ENOSPC (No space to store filter list, check RT-Socket-CAN kernel parameters)

Examples:

[rtcan_rtt.c](#), [rtcanrecv.c](#), and [rtcansend.c](#).

5.1.2.6 #define CAN_RAW_LOOPBACK 0x3

CAN TX loopback.

The TX loopback to other local sockets can be selected with this `setsockopt`.

Note:

The TX loopback feature must be enabled in the kernel and then the loopback to other local TX sockets is enabled by default.

Parameters:

← *level* SOL_CAN_RAW

← *optname* CAN_RAW_LOOPBACK

← *optval* Pointer to integer value.

← *optlen* Size of int: sizeof(int).

Environments: non-RT (RT optional)

Specific return values:

- -EFAULT (It was not possible to access user space memory area at the specified address.)
- -EINVAL (Invalid length "optlen")
- -EOPNOTSUPP (not supported, check RT-Socket-CAN kernel parameters).

Examples:

[rtcansend.c](#).

5.1.2.7 #define CAN_RAW_RECV_OWN_MSGS 0x4

CAN receive own messages.

Not supported by RT-Socket-CAN, but defined for compatibility with Socket-CAN.

5.1.2.8 `#define RTCAN_RTIOC_RCV_TIMEOUT _IOW(RTIOC_TYPE_CAN, 0x0A, nanosecs_rel_t)`

Specify a reception timeout for a socket.

Defines a timeout for all receive operations via a socket which will take effect when one of the [receive functions](#) is called without the MSG_DONTWAIT flag set.

The default value for a newly created socket is an infinite timeout.

Note:

The setting of the timeout value is not done atomically to avoid locks. Please set the value before receiving messages from the socket.

Parameters:

← *arg* Pointer to [nanosecs_rel_t](#) variable. The value is interpreted as relative timeout in nanoseconds in case of a positive value. See [Timeouts](#) for special timeouts.

Returns:

0 on success, otherwise:

- -EFAULT: It was not possible to access user space memory area at the specified address.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

Examples:

[rtcanrecv.c](#).

5.1.2.9 `#define RTCAN_RTIOC_SND_TIMEOUT _IOW(RTIOC_TYPE_CAN, 0x0B, nanosecs_rel_t)`

Specify a transmission timeout for a socket.

Defines a timeout for all send operations via a socket which will take effect when one of the [send functions](#) is called without the MSG_DONTWAIT flag set.

The default value for a newly created socket is an infinite timeout.

Note:

The setting of the timeout value is not done atomically to avoid locks. Please set the value before sending messages to the socket.

Parameters:

← *arg* Pointer to [nanosecs_rel_t](#) variable. The value is interpreted as relative timeout in nanoseconds in case of a positive value. See [Timeouts](#) for special timeouts.

Returns:

0 on success, otherwise:

- -EFAULT: It was not possible to access user space memory area at the specified address.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

Examples:

[rtcansend.c](#).

5.1.2.10 #define RTCAN_RTIOC_TAKE_TIMESTAMP_IOW(RTIOC_TYPE_CAN, 0x09, int)

Enable or disable storing a high precision timestamp upon reception of a CAN frame.

A newly created socket takes no timestamps by default.

Parameters:

← *arg* int variable, see [Timestamp switches](#)

Returns:

0 on success.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Note:

Activating taking timestamps only has an effect on newly received CAN messages from the bus. Frames that already are in the socket buffer do not have timestamps if it was deactivated before. See [Receive](#) for more details.

Rescheduling: never.

Examples:

[rtcanrecv.c](#).

5.1.2.11 `#define SIOCGCANBAUDRATE _IOWR(RTIOC_TYPE_CAN, 0x02, struct ifreq)`

Get baud rate.

Parameters:

↔ *arg* Pointer to interface request structure buffer (`struct ifreq` from `linux/if.h`). `ifr_name` must hold a valid CAN interface name, `ifr_ifru` will be filled with an instance of `can_baudrate_t`.

Returns:

0 on success, otherwise:

- -EFAULT: It was not possible to access user space memory area at the specified address.
- -ENODEV: No device with specified name exists.
- -EINVAL: No baud rate was set yet.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.1.2.12 `#define SIOCGCANCTRLMODE _IOWR(RTIOC_TYPE_CAN, 0x08, struct ifreq)`

Get special controller modes.

Parameters:

↔ *arg* Pointer to interface request structure buffer (`struct ifreq` from `linux/if.h`). `ifr_name` must hold a valid CAN interface name, `ifr_ifru` must be filled with an instance of `can_ctrlmode_t`.

Returns:

0 on success, otherwise:

- -EFAULT: It was not possible to access user space memory area at the specified address.
- -ENODEV: No device with specified name exists.
- -EINVAL: No baud rate was set yet.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.1.2.13 `#define SIOCGCANCUSTOMBITTIME _IOWR(RTIOC_TYPE_CAN, 0x04, struct ifreq)`

Get custom bit-time parameters.

Parameters:

↔ *arg* Pointer to interface request structure buffer (`struct ifreq` from `linux/if.h`). `ifr_name` must hold a valid CAN interface name, `ifr_ifru` will be filled with an instance of `struct can_bittime`.

Returns:

0 on success, otherwise:

- -EFAULT: It was not possible to access user space memory area at the specified address.
- -ENODEV: No device with specified name exists.
- -EINVAL: No baud rate was set yet.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.1.2.14 `#define SIOCGCANSTATE _IOWR(RTIOC_TYPE_CAN, 0x06, struct ifreq)`

Get current state of CAN controller.

States are divided into main states and additional error indicators. A CAN controller is always in exactly one main state. CAN bus errors are registered by the CAN hardware and collected by the driver. There is one error indicator (bit) per error type. If this IOCTL is triggered the error types which occurred since the last call of this IOCTL are reported and thereafter the error indicators are cleared. See also [CAN controller states](#).

Parameters:

↔ *arg* Pointer to interface request structure buffer (`struct ifreq` from `linux/if.h`). `ifr_name` must hold a valid CAN interface name, `ifr_ifru` will be filled with an instance of `can_mode_t`.

Returns:

0 on success, otherwise:

- -EFAULT: It was not possible to access user space memory area at the specified address.
- -ENODEV: No device with specified name exists.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.1.2.15 #define SIOCGIFINDEX defined_by_kernel_header_file

Get CAN interface index by name.

Parameters:

↔ *arg* Pointer to interface request structure buffer (struct ifreq from linux/if.h). If ifr_name holds a valid CAN interface name ifr_index will be filled with the corresponding interface index.

Returns:

0 on success, otherwise:

- -EFAULT: It was not possible to access user space memory area at the specified address.
- -ENODEV: No device with specified name exists.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

Examples:

[rtcan_rtt.c](#), [rtcanconfig.c](#), [rtcanrecv.c](#), and [rtcansend.c](#).

5.1.2.16 #define SIOCSCANBAUDRATE_IOW(RTIOC_TYPE_CAN, 0x01, struct ifreq)

Set baud rate.

The baudrate must be specified in bits per second. The driver will try to calculate resonable CAN bit-timing parameters. You can use [SIOCSCANCUSTOMBITTIME](#) to set custom bit-timing.

Parameters:

↔ *arg* Pointer to interface request structure buffer (struct ifreq from linux/if.h). ifr_name must hold a valid CAN interface name, ifr_ifru must be filled with an instance of [can_baudrate_t](#).

Returns:

0 on success, otherwise:

- -EFAULT: It was not possible to access user space memory area at the specified address.
- -ENODEV: No device with specified name exists.
- -EINVAL: No valid baud rate, see [can_baudrate_t](#).
- -EDOM : Baud rate not possible.
- -EAGAIN: Request could not be successfully fulfilled. Try again.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Note:

Setting the baud rate is a configuration task. It should be done deliberately or otherwise CAN messages will likely be lost.

Rescheduling: possible.

Examples:

[rtcanconfig.c](#).

5.1.2.17 #define SIOCSCANCTRLMODE_IOW(RTIOC_TYPE_CAN, 0x07, struct ifreq)

Set special controller modes.

Various special controller modes could be or'ed together (see [CAN_CTRLMODE](#) for further information).

Parameters:

← *arg* Pointer to interface request structure buffer (struct ifreq from linux/if.h). ifr_name must hold a valid CAN interface name, ifr_ifru must be filled with an instance of [can_ctrlmode_t](#).

Returns:

0 on success, otherwise:

- -EFAULT: It was not possible to access user space memory area at the specified address.
- -ENODEV: No device with specified name exists.
- -EINVAL: No valid baud rate, see [can_baudrate_t](#).
- -EAGAIN: Request could not be successfully fulfilled. Try again.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Note:

Setting special controller modes is a configuration task. It should be done deliberately or otherwise CAN messages will likely be lost.

Rescheduling: possible.

Examples:

[rtcanconfig.c](#).

5.1.2.18 #define SIOCSCANCUSTOMBITTIME _IOW(RTIOC_TYPE_CAN, 0x03, struct ifreq)

Set custom bit time parameter.

Custom-bit time could be defined in various formats (see struct [can_bittime](#)).

Parameters:

← *arg* Pointer to interface request structure buffer (struct `ifreq` from `linux/if.h`). `ifr_name` must hold a valid CAN interface name, `ifr_ifru` must be filled with an instance of struct [can_bittime](#).

Returns:

0 on success, otherwise:

- -EFAULT: It was not possible to access user space memory area at the specified address.
- -ENODEV: No device with specified name exists.
- -EINVAL: No valid baud rate, see [can_baudrate_t](#).
- -EAGAIN: Request could not be successfully fulfilled. Try again.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Note:

Setting the bit-time is a configuration task. It should be done deliberately or otherwise CAN messages will likely be lost.

Rescheduling: possible.

Examples:

[rtcanconfig.c](#).

5.1.2.19 #define SIOCSCANMODE_IOW(RTIOC_TYPE_CAN, 0x05, struct ifreq)

Set operation mode of CAN controller.

See [CAN controller modes](#) for available modes.

Parameters:

← *arg* Pointer to interface request structure buffer (`struct ifreq` from `linux/if.h`). `ifr_name` must hold a valid CAN interface name, `ifr_ifru` must be filled with an instance of [can_mode_t](#).

Returns:

0 on success, otherwise:

- -EFAULT: It was not possible to access user space memory area at the specified address.
- -ENODEV: No device with specified name exists.
- -EAGAIN: ([CAN_MODE_START](#), [CAN_MODE_STOP](#)) Could not successfully set mode, hardware is busy. Try again.
- -EINVAL: ([CAN_MODE_START](#)) Cannot start controller, set baud rate first.
- -ENETDOWN: ([CAN_MODE_SLEEP](#)) Cannot go into sleep mode because controller is stopped or bus off.
- -EOPNOTSUPP: unknown mode

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Note:

Setting a CAN controller into normal operation after a bus-off can take some time (128 occurrences of 11 consecutive recessive bits). In such a case, although this IOCTL will return immediately with success and [SIOCGCANSTATE](#) will report [CAN_STATE_ACTIVE](#), bus-off recovery may still be in progress.

If a controller is bus-off, setting it into stop mode will return no error but the controller remains bus-off.

Rescheduling: possible.

Examples:

[rtcanconfig.c](#).

5.1.2.20 #define SOL_CAN_RAW 103

CAN socket levels.

Used for [Sockopts](#) for the particular protocols.

Examples:

[rtcan_rtt.c](#), [rtcanrecv.c](#), and [rtcansend.c](#).

5.1.3 Enumeration Type Documentation

5.1.3.1 enum CAN_BITTIME_TYPE

Supported CAN bit-time types.

Enumerator:

CAN_BITTIME_STD Standard bit-time definition according to Bosch.

CAN_BITTIME_BTR Hardware-specific BTR bit-time definition.

5.1.3.2 enum CAN_MODE

Enumerator:

CAN_MODE_STOP Set controller in Stop mode (no reception / transmission possible)

CAN_MODE_START Set controller into normal operation.

Coming from stopped mode or bus off, the controller begins with no errors in [CAN_STATE_ACTIVE](#).

CAN_MODE_SLEEP Set controller into Sleep mode.

This is only possible if the controller is not stopped or bus-off.

Notice that sleep mode will only be entered when there is no bus activity. If the controller detects bus activity while "sleeping" it will go into operating mode again.

To actively leave sleep mode again trigger *CAN_MODE_START*.

5.1.3.3 enum CAN_STATE

Enumerator:

CAN_STATE_ACTIVE CAN controller is error active.

CAN_STATE_BUS_WARNING CAN controller is error active, warning level is reached.

CAN_STATE_BUS_PASSIVE CAN controller is error passive.

CAN_STATE_BUS_OFF CAN controller went into Bus Off.

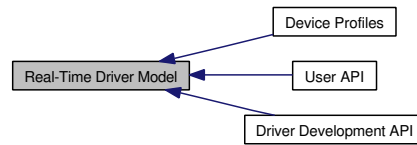
CAN_STATE_SCANNING_BAUDRATE CAN controller is scanning to get the baudrate.

CAN_STATE_STOPPED CAN controller is in stopped mode.

CAN_STATE_SLEEPING CAN controller is in Sleep mode.

5.2 Real-Time Driver Model

Collaboration diagram for Real-Time Driver Model:



5.2.1 Detailed Description

The Real-Time Driver Model (RTDM) provides a unified interface to both users and developers of real-time device drivers. Specifically, it addresses the constraints of mixed RT/non-RT systems like Xenomai. RTDM conforms to POSIX semantics (IEEE Std 1003.1) where available and applicable.

API Revision: 7

Modules

- [User API](#)
- [Driver Development API](#)
- [Device Profiles](#)

API Versioning

- `#define RTDM_API_VER 7`
Common user and driver API version.
- `#define RTDM_API_MIN_COMPAT_VER 6`
Minimum API revision compatible with the current release.

RTDM_TIMEOUT_XXX

Special timeout values

- `#define RTDM_TIMEOUT_INFINITE 0`
Block forever.
- `#define RTDM_TIMEOUT_NONE (-1)`
Any negative timeout means non-blocking.

Typedefs

- `typedef uint64_t nanosecs_abs_t`

RTDM type for representing absolute dates.

- `typedef int64_t nanosecs_rel_t`

RTDM type for representing relative intervals.

5.2.2 Define Documentation

5.2.2.1 `#define RTDM_TIMEOUT_INFINITE 0`

Block forever.

5.2.2.2 `#define RTDM_TIMEOUT_NONE (-1)`

Any negative timeout means non-blocking.

5.2.3 Typedef Documentation

5.2.3.1 `typedef uint64_t nanosecs_abs_t`

RTDM type for representing absolute dates.

Its base type is a 64 bit unsigned integer. The unit is 1 nanosecond.

Examples:

[rtcanrecv.c](#).

5.2.3.2 `typedef int64_t nanosecs_rel_t`

RTDM type for representing relative intervals.

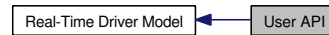
Its base type is a 64 bit signed integer. The unit is 1 nanosecond. Relative intervals can also encode the special timeouts "infinite" and "non-blocking", see [RTDM_TIMEOUT_xxx](#).

Examples:

[rtcanrecv.c](#), and [rtcansend.c](#).

5.3 User API

Collaboration diagram for User API:



5.3.1 Detailed Description

This is the upper interface of RTDM provided to application programs both in kernel and user space. Note that certain functions may not be implemented by every device. Refer to the [Device Profiles](#) for precise information.

Files

- file [rtdm.h](#)
Real-Time Driver Model for Xenomai, user API header.

Functions

- int [rt_dev_open](#) (const char *path, int oflag,...)
Open a device.
- int [rt_dev_socket](#) (int protocol_family, int socket_type, int protocol)
Create a socket.
- int [rt_dev_close](#) (int fd)
Close a device or socket.
- int [rt_dev_ioctl](#) (int fd, int request,...)
Issue an IOCTL.
- ssize_t [rt_dev_read](#) (int fd, void *buf, size_t nbyte)
Read from device.
- ssize_t [rt_dev_write](#) (int fd, const void *buf, size_t nbyte)
Write to device.
- ssize_t [rt_dev_recvmsg](#) (int fd, struct msghdr *msg, int flags)
Receive message from socket.
- ssize_t [rt_dev_recvfrom](#) (int fd, void *buf, size_t len, int flags, struct sockaddr *from, socklen_t *fromlen)
Receive message from socket.
- ssize_t [rt_dev_recv](#) (int fd, void *buf, size_t len, int flags)
Receive message from socket.

- `ssize_t rt_dev_sendmsg` (int fd, const struct msghdr *msg, int flags)
Transmit message to socket.
- `ssize_t rt_dev_sendto` (int fd, const void *buf, size_t len, int flags, const struct sockaddr *to, socklen_t tolen)
Transmit message to socket.
- `ssize_t rt_dev_send` (int fd, const void *buf, size_t len, int flags)
Transmit message to socket.
- `int rt_dev_bind` (int fd, const struct sockaddr *my_addr, socklen_t addrlen)
Bind to local address.
- `int rt_dev_connect` (int fd, const struct sockaddr *serv_addr, socklen_t addrlen)
Connect to remote address.
- `int rt_dev_listen` (int fd, int backlog)
Listen for incoming connection requests.
- `int rt_dev_accept` (int fd, struct sockaddr *addr, socklen_t *addrlen)
Accept a connection requests.
- `int rt_dev_shutdown` (int fd, int how)
Shut down parts of a connection.
- `int rt_dev_getsockopt` (int fd, int level, int optname, void *optval, socklen_t *optlen)
Get socket option.
- `int rt_dev_setsockopt` (int fd, int level, int optname, const void *optval, socklen_t optlen)
Set socket option.
- `int rt_dev_getsockname` (int fd, struct sockaddr *name, socklen_t *namelen)
Get local socket address.
- `int rt_dev_getpeername` (int fd, struct sockaddr *name, socklen_t *namelen)
Get socket destination address.

5.3.2 Function Documentation

5.3.2.1 `int rt_dev_accept (int fd, struct sockaddr * addr, socklen_t * addrlen)`

Accept a connection requests.

Parameters:

- ← *fd* File descriptor as returned by `rt_dev_socket()`
- *addr* Buffer for remote address
- ↔ *addrlen* Address buffer size

Returns:

0 on success, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`accept()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.2 `int rt_dev_bind (int fd, const struct sockaddr * my_addr, socklen_t addrlen)`

Bind to local address.

Parameters:

← *fd* File descriptor as returned by `rt_dev_socket()`

← *my_addr* Address buffer

← *addrlen* Address buffer size

Returns:

0 on success, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`bind()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.3 `int rt_dev_close (int fd)`

Close a device or socket.

Parameters:

← *fd* File descriptor as returned by `rt_dev_open()` or `rt_dev_socket()`

Returns:

0 on success, otherwise a negative error code.

Note:

If the matching `rt_dev_open()` or `rt_dev_socket()` call took place in non-real-time context, `rt_dev_close()` must be issued within non-real-time as well. Otherwise, the call will fail.

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`close()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.4 `int rt_dev_connect (int fd, const struct sockaddr * serv_addr, socklen_t addrlen)`

Connect to remote address.

Parameters:

← *fd* File descriptor as returned by `rt_dev_socket()`

← *serv_addr* Address buffer

← *addrlen* Address buffer size

Returns:

0 on success, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`connect()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.5 `int rt_dev_getpeername (int fd, struct sockaddr * name, socklen_t * namelen)`

Get socket destination address.

Parameters:

← *fd* File descriptor as returned by `rt_dev_socket()`

→ *name* Address buffer

↔ *namelen* Address buffer size

Returns:

0 on success, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`getpeername()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.6 `int rt_dev_getsockname (int fd, struct sockaddr * name, socklen_t * namelen)`

Get local socket address.

Parameters:

- ← *fd* File descriptor as returned by `rt_dev_socket()`
- *name* Address buffer
- ↔ *namelen* Address buffer size

Returns:

0 on success, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`getsockname()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.7 `int rt_dev_getsockopt (int fd, int level, int optname, void * optval, socklen_t * optlen)`

Get socket option.

Parameters:

- ← *fd* File descriptor as returned by `rt_dev_socket()`
- ← *level* Addressed stack level
- ← *optname* Option name ID
- *optval* Value buffer
- ↔ *optlen* Value buffer size

Returns:

0 on success, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`getsockopt()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.8 `int rt_dev_ioctl (int fd, int request, ...)`

Issue an IOCTL.

Parameters:

- ← *fd* File descriptor as returned by `rt_dev_open()` or `rt_dev_socket()`
- ← *request* IOCTL code
- ... Optional third argument, depending on IOCTL function (void * or unsigned long)

Returns:

Positiv value on success, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`ioctl()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.9 `int rt_dev_listen (int fd, int backlog)`

Listen for incomming connection requests.

Parameters:

- ← *fd* File descriptor as returned by `rt_dev_socket()`
- ← *backlog* Maximum queue length

Returns:

0 on success, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`listen()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.10 `int rt_dev_open (const char * path, int oflag, ...)`

Open a device.

Parameters:

- ← *path* Device name

← *oflag* Open flags
... Further parameters will be ignored.

Returns:

Positive file descriptor value on success, otherwise a negative error code.

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`open()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.11 `ssize_t rt_dev_read (int fd, void * buf, size_t nbyte)`

Read from device.

Parameters:

← *fd* File descriptor as returned by `rt_dev_open()`
→ *buf* Input buffer
← *nbyte* Number of bytes to read

Returns:

Number of bytes read, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`read()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.12 `ssize_t rt_dev_recv (int fd, void * buf, size_t len, int flags)`

Receive message from socket.

Parameters:

← *fd* File descriptor as returned by `rt_dev_socket()`
→ *buf* Message buffer
← *len* Message buffer size
← *flags* Message flags

Returns:

Number of bytes received, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

recv() in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.13 ssize_t rt_dev_recvfrom (int *fd*, void * *buf*, size_t *len*, int *flags*, struct sockaddr * *from*, socklen_t * *fromlen*)

Receive message from socket.

Parameters:

- ← *fd* File descriptor as returned by rt_dev_socket()
- *buf* Message buffer
- ← *len* Message buffer size
- ← *flags* Message flags
- *from* Buffer for message sender address
- ↔ *fromlen* Address buffer size

Returns:

Number of bytes received, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

recvfrom() in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

References rt_dev_recvfrom().

Referenced by rt_dev_recvfrom().

5.3.2.14 ssize_t rt_dev_recvmsg (int *fd*, struct msghdr * *msg*, int *flags*)

Receive message from socket.

Parameters:

- ← *fd* File descriptor as returned by rt_dev_socket()
- ↔ *msg* Message descriptor

← *flags* Message flags

Returns:

Number of bytes received, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

recvmsg() in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.15 ssize_t rt_dev_send (int *fd*, const void * *buf*, size_t *len*, int *flags*)

Transmit message to socket.

Parameters:

← *fd* File descriptor as returned by rt_dev_socket()

← *buf* Message buffer

← *len* Message buffer size

← *flags* Message flags

Returns:

Number of bytes sent, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

send() in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.16 ssize_t rt_dev_sendmsg (int *fd*, const struct msghdr * *msg*, int *flags*)

Transmit message to socket.

Parameters:

← *fd* File descriptor as returned by rt_dev_socket()

← *msg* Message descriptor

← *flags* Message flags

Returns:

Number of bytes sent, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`sendmsg()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.17 `ssize_t rt_dev_sendto (int fd, const void * buf, size_t len, int flags, const struct sockaddr * to, socklen_t tolen)`

Transmit message to socket.

Parameters:

- ← *fd* File descriptor as returned by `rt_dev_socket()`
- ← *buf* Message buffer
- ← *len* Message buffer size
- ← *flags* Message flags
- ← *to* Buffer for message destination address
- ← *tolen* Address buffer size

Returns:

Number of bytes sent, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`sendto()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.18 `int rt_dev_setsockopt (int fd, int level, int optname, const void * optval, socklen_t optlen)`

Set socket option.

Parameters:

- ← *fd* File descriptor as returned by `rt_dev_socket()`
- ← *level* Addressed stack level
- ← *optname* Option name ID
- ← *optval* Value buffer
- ← *optlen* Value buffer size

Returns:

0 on success, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`setsockopt()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.19 `int rt_dev_shutdown (int fd, int how)`

Shut down parts of a connection.

Parameters:

- ← *fd* File descriptor as returned by `rt_dev_socket()`
- ← *how* Specifies the part to be shut down (`SHUT_XXX`)

Returns:

0 on success, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`shutdown()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.20 `int rt_dev_socket (int protocol_family, int socket_type, int protocol)`

Create a socket.

Parameters:

- ← *protocol_family* Protocol family (`PF_XXX`)
- ← *socket_type* Socket type (`SOCK_XXX`)
- ← *protocol* Protocol ID, 0 for default

Returns:

Positive file descriptor value on success, otherwise a negative error code.

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`socket()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.3.2.21 `ssize_t rt_dev_write(int fd, const void * buf, size_t nbyte)`

Write to device.

Parameters:

- ← *fd* File descriptor as returned by `rt_dev_open()`
- ← *buf* Output buffer
- ← *nbyte* Number of bytes to write

Returns:

Number of bytes written, otherwise negative error code

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

See also:

`write()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.4 Serial Devices

Collaboration diagram for Serial Devices:



5.4.1 Detailed Description

This is the common interface a RTDM-compliant serial device has to provide. Feel free to comment on this profile via the Xenomai mailing list (Xenomai-core@gna.org) or directly to the author (jan.kiszka@web.de).

Profile Revision: 2

Device Characteristics

Device Flags: RTDM_NAMED_DEVICE, RTDM_EXCLUSIVE

Device Name: "rtser<N>", N >= 0

Device Class: RTDM_CLASS_SERIAL

Supported Operations

Open

Environments: non-RT (RT optional)

Specific return values: none

Close

Environments: non-RT (RT optional)

Specific return values: none

IOCTL

Mandatory Environments: see [below](#)

Specific return values: see [below](#)

Read

Environments: RT (non-RT optional)

Specific return values:

- -ETIMEDOUT
- -EINTR (interrupted explicitly or by signal)
- -EAGAIN (no data available in non-blocking mode)
- -EBADF (device has been closed while reading)
- -EIO (hardware error or broken bit stream)

Write

Environments: RT (non-RT optional)

Specific return values:

- -ETIMEDOUT
- -EINTR (interrupted explicitly or by signal)
- -EAGAIN (no data written in non-blocking mode)
- -EBADF (device has been closed while writing)

Files

- file [rtserial.h](#)

Real-Time Driver Model for Xenomai, serial device profile header.

Data Structures

- struct [rtser_config](#)

Serial device configuration.

- struct [rtser_status](#)

Serial device status.

- struct [rtser_event](#)

Additional information about serial device events.

RTSER_BREAK_xxx

Break control

- typedef struct [rtser_config](#) [rtser_config_t](#)
- typedef struct [rtser_status](#) [rtser_status_t](#)
- typedef struct [rtser_event](#) [rtser_event_t](#)
- #define **RTSER_BREAK_CLR** 0x00
- #define **RTSER_BREAK_SET** 0x01
- #define **RTIOC_TYPE_SERIAL** RTDM_CLASS_SERIAL

RTSER_DEF_BAUD

Default baud rate

- #define **RTSER_DEF_BAUD** 9600

RTSER_xxx_PARITY

Number of parity bits

- #define **RTSER_NO_PARITY** 0x00
- #define **RTSER_ODD_PARITY** 0x01
- #define **RTSER_EVEN_PARITY** 0x03
- #define **RTSER_DEF_PARITY** RTSER_NO_PARITY

RTSER_xxx_BITS

Number of data bits

- `#define RTSER_5_BITS 0x00`
- `#define RTSER_6_BITS 0x01`
- `#define RTSER_7_BITS 0x02`
- `#define RTSER_8_BITS 0x03`
- `#define RTSER_DEF_BITS RTSER_8_BITS`

RTSER_xxx_STOPB

Number of stop bits

- `#define RTSER_1_STOPB 0x00`
- `#define RTSER_1_5_STOPB 0x01`
valid only in combination with 5 data bits
- `#define RTSER_2_STOPB 0x01`
- `#define RTSER_DEF_STOPB RTSER_1_STOPB`

RTSER_xxx_HAND

Handshake mechanisms

- `#define RTSER_NO_HAND 0x00`
- `#define RTSER_RTSCTS_HAND 0x01`
- `#define RTSER_DEF_HAND RTSER_NO_HAND`

RTSER_FIFO_xxx

Reception FIFO interrupt threshold

- `#define RTSER_FIFO_DEPTH_1 0x00`
- `#define RTSER_FIFO_DEPTH_4 0x40`
- `#define RTSER_FIFO_DEPTH_8 0x80`
- `#define RTSER_FIFO_DEPTH_14 0xC0`
- `#define RTSER_DEF_FIFO_DEPTH RTSER_FIFO_DEPTH_1`

RTSER_TIMEOUT_xxx

Special timeout values, see also [RTDM_TIMEOUT_xxx](#)

- `#define RTSER_TIMEOUT_INFINITE RTDM_TIMEOUT_INFINITE`
- `#define RTSER_TIMEOUT_NONE RTDM_TIMEOUT_NONE`
- `#define RTSER_DEF_TIMEOUT RTDM_TIMEOUT_INFINITE`

RTSER_XXX_TIMESTAMP_HISTORY

Timestamp history control

- #define RTSER_RX_TIMESTAMP_HISTORY 0x01
- #define RTSER_DEF_TIMESTAMP_HISTORY 0x00

RTSER_EVENT_XXX

Events bits

- #define RTSER_EVENT_RXPEND 0x01
- #define RTSER_EVENT_ERRPEND 0x02
- #define RTSER_EVENT_MODEMHI 0x04
- #define RTSER_EVENT_MODEMLO 0x08
- #define RTSER_DEF_EVENT_MASK 0x00

RTSER_SET_XXX

Configuration mask bits

- #define RTSER_SET_BAUD 0x0001
- #define RTSER_SET_PARITY 0x0002
- #define RTSER_SET_DATA_BITS 0x0004
- #define RTSER_SET_STOP_BITS 0x0008
- #define RTSER_SET_HANDSHAKE 0x0010
- #define RTSER_SET_FIFO_DEPTH 0x0020
- #define RTSER_SET_TIMEOUT_RX 0x0100
- #define RTSER_SET_TIMEOUT_TX 0x0200
- #define RTSER_SET_TIMEOUT_EVENT 0x0400
- #define RTSER_SET_TIMESTAMP_HISTORY 0x0800
- #define RTSER_SET_EVENT_MASK 0x1000

RTSER_LSR_XXX

Line status bits

- #define RTSER_LSR_DATA 0x01
- #define RTSER_LSR_OVERRUN_ERR 0x02
- #define RTSER_LSR_PARITY_ERR 0x04
- #define RTSER_LSR_FRAMING_ERR 0x08
- #define RTSER_LSR_BREAK_IND 0x10
- #define RTSER_LSR_THR_EMPTY 0x20
- #define RTSER_LSR_TRANSM_EMPTY 0x40
- #define RTSER_LSR_FIFO_ERR 0x80
- #define RTSER_SOFT_OVERRUN_ERR 0x0100

RTSER_MSR_xxx

Modem status bits

- #define RTSER_MSR_DCTS 0x01
- #define RTSER_MSR_DDSD 0x02
- #define RTSER_MSR_TERI 0x04
- #define RTSER_MSR_DDSD 0x08
- #define RTSER_MSR_CTS 0x10
- #define RTSER_MSR_DSR 0x20
- #define RTSER_MSR_RI 0x40
- #define RTSER_MSR_DCD 0x80

RTSER_MCR_xxx

Modem control bits

- #define RTSER_MCR_DTR 0x01
- #define RTSER_MCR_RTS 0x02
- #define RTSER_MCR_OUT1 0x04
- #define RTSER_MCR_OUT2 0x08
- #define RTSER_MCR_LOOP 0x10

Sub-Classes of RTDM_CLASS_SERIAL

- #define RTDM_SUBCLASS_16550A 0

IOCTLs

Serial device IOCTLs

- #define [RTSER_RTIOC_GET_CONFIG](#) _IOR(RTIOC_TYPE_SERIAL, 0x00, struct rtser_config)
Get serial device configuration.
- #define [RTSER_RTIOC_SET_CONFIG](#) _IOW(RTIOC_TYPE_SERIAL, 0x01, struct rtser_config)
Set serial device configuration.
- #define [RTSER_RTIOC_GET_STATUS](#) _IOR(RTIOC_TYPE_SERIAL, 0x02, struct rtser_status)
Get serial device status.
- #define [RTSER_RTIOC_GET_CONTROL](#) _IOR(RTIOC_TYPE_SERIAL, 0x03, int)
Get serial device's modem control register.
- #define [RTSER_RTIOC_SET_CONTROL](#) _IOW(RTIOC_TYPE_SERIAL, 0x04, int)
Set serial device's modem control register.

- `#define RTSER_RTIOC_WAIT_EVENT _IOR(RTIOC_TYPE_SERIAL, 0x05, struct rtser_event)`

Wait on serial device events according to previously set mask.

Defines

- `#define RTSER_RTIOC_BREAK_CTL _IOR(RTIOC_TYPE_SERIAL, 0x06, int)`

Set or clear break on UART output line.

5.4.2 Define Documentation

5.4.2.1 `#define RTSER_RTIOC_BREAK_CTL _IOR(RTIOC_TYPE_SERIAL, 0x06, int)`

Set or clear break on UART output line.

Parameters:

← *arg* RTSER_BREAK_SET or RTSER_BREAK_CLR (int)

Returns:

0 on success, otherwise negative error code

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Note:

A set break condition may also be cleared on UART line reconfiguration.

Rescheduling: never.

5.4.2.2 `#define RTSER_RTIOC_GET_CONFIG _IOR(RTIOC_TYPE_SERIAL, 0x00, struct rtser_config)`

Get serial device configuration.

Parameters:

→ *arg* Pointer to configuration buffer (struct `rtser_config`)

Returns:

0 on success, otherwise negative error code

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.4.2.3 `#define RTSER_RTIOC_GET_CONTROL_IOR(RTIOC_TYPE_SERIAL, 0x03, int)`

Get serial device's modem control register.

Parameters:

→ *arg* Pointer to variable receiving the content (int, see [RTSER_MCR_xxx](#))

Returns:

0 on success, otherwise negative error code

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.4.2.4 `#define RTSER_RTIOC_GET_STATUS_IOR(RTIOC_TYPE_SERIAL, 0x02, struct rtser_status)`

Get serial device status.

Parameters:

→ *arg* Pointer to status buffer (struct [rtser_status](#))

Returns:

0 on success, otherwise negative error code

Environments:

This service can be called from:

- Kernel module initialization/cleanup code

- Kernel-based task
- User-space task (RT, non-RT)

Note:

The error states `RTSER_LSR_OVERRUN_ERR`, `RTSER_LSR_PARITY_ERR`, `RTSER_LSR_FRAMING_ERR`, and `RTSER_SOFT_OVERRUN_ERR` that may have occurred during previous read accesses to the device will be saved for being reported via this IOCTL. Upon return from `RTSER_RTIOC_GET_STATUS`, the saved state will be cleared.

Rescheduling: never.

5.4.2.5 `#define RTSER_RTIOC_SET_CONFIG _IOW(RTIOC_TYPE_SERIAL, 0x01, struct rtser_config)`

Set serial device configuration.

Parameters:

← *arg* Pointer to configuration buffer (struct [rtser_config](#))

Returns:

0 on success, otherwise:

- `-EPERM` is returned if the caller's context is invalid, see note below.
- `-ENOMEM` is returned if a new history buffer for timestamps cannot be allocated.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Note:

If [rtser_config](#) contains a valid `timestamp_history` and the addressed device has been opened in non-real-time context, this IOCTL must be issued in non-real-time context as well. Otherwise, this command will fail.

Rescheduling: never.

Examples:

[cross-link.c](#).

5.4.2.6 `#define RTSER_RTIOC_SET_CONTROL_IOW(RTIOC_TYPE_SERIAL, 0x04, int)`

Set serial device's modem control register.

Parameters:

← *arg* New control register content (int, see [RTSER_MCR_xxx](#))

Returns:

0 on success, otherwise negative error code

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.4.2.7 `#define RTSER_RTIOC_WAIT_EVENT_IOR(RTIOC_TYPE_SERIAL, 0x05, struct rtser_event)`

Wait on serial device events according to previously set mask.

Parameters:

→ *arg* Pointer to event information buffer (struct [rtser_event](#))

Returns:

0 on success, otherwise:

- -EBUSY is returned if another task is already waiting on events of this device.
- -EBADF is returned if the file descriptor is invalid or the device has just been closed.

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: possible.

Examples:

[cross-link.c](#).

5.5 Testing Devices

Collaboration diagram for Testing Devices:



5.5.1 Detailed Description

This group of devices is intended to provide in-kernel testing results. Feel free to comment on this profile via the Xenomai mailing list (xenomai-core@gna.org) or directly to the author (jan.kiszka@web.de).

Profile Revision: 1

Device Characteristics

Device Flags: RTDM_NAMED_DEVICE
Device Name: "rttest<N>", N >= 0
Device Class: RTDM_CLASS_TESTING

Supported Operations

Open

Environments: non-RT (RT optional)
 Specific return values: none

Close

Environments: non-RT (RT optional)
 Specific return values: none

IOCTL

Mandatory Environments: see [TSTIOCTLs](#) below
 Specific return values: see [TSTIOCTLs](#) below

Files

- file [rttesting.h](#)

Real-Time Driver Model for Xenomai, testing device profile header.

Sub-Classes of RTDM_CLASS_TESTING

- `#define RTDM_SUBCLASS_TIMERBENCH 0`
- `#define RTDM_SUBCLASS_IRQBENCH 1`
- `#define RTDM_SUBCLASS_SWITCHTEST 2`

IOCTLs

Testing device IOCTLs

- `#define RTTST_RTIOC_INTERM_BENCH_RES _IOWR(RTIOC_TYPE_TESTING, 0x00, struct rttst_interm_bench_res)`

- #define **RTTST_RTIOC_TMBENCH_START** _IOW(RTIOC_TYPE_TESTING, 0x10, struct rttst_tmbench_config)
- #define **RTTST_RTIOC_TMBENCH_STOP** _IOWR(RTIOC_TYPE_TESTING, 0x11, struct rttst_overall_bench_res)
- #define **RTTST_RTIOC_IRQBENCH_START** _IOW(RTIOC_TYPE_TESTING, 0x20, struct rttst_irqbench_config)
- #define **RTTST_RTIOC_IRQBENCH_STOP** _IO(RTIOC_TYPE_TESTING, 0x21)
- #define **RTTST_RTIOC_IRQBENCH_GET_STATS** _IOR(RTIOC_TYPE_TESTING, 0x22, struct rttst_irqbench_stats)
- #define **RTTST_RTIOC_IRQBENCH_WAIT_IRQ** _IO(RTIOC_TYPE_TESTING, 0x23)
- #define **RTTST_RTIOC_IRQBENCH_REPLY_IRQ** _IO(RTIOC_TYPE_TESTING, 0x24)
- #define **RTTST_RTIOC_SWTEST_SET_TASKS_COUNT** _IOW(RTIOC_TYPE_TESTING, 0x30, unsigned long)
- #define **RTTST_RTIOC_SWTEST_SET_CPU** _IOW(RTIOC_TYPE_TESTING, 0x31, unsigned long)
- #define **RTTST_RTIOC_SWTEST_REGISTER_UTASK** _IOW(RTIOC_TYPE_TESTING, 0x32, struct rttst_swtest_task)
- #define **RTTST_RTIOC_SWTEST_CREATE_KTASK** _IOWR(RTIOC_TYPE_TESTING, 0x33, struct rttst_swtest_task)
- #define **RTTST_RTIOC_SWTEST_PEND** _IOR(RTIOC_TYPE_TESTING, 0x34, struct rttst_swtest_task)
- #define **RTTST_RTIOC_SWTEST_SWITCH_TO** _IOR(RTIOC_TYPE_TESTING, 0x35, struct rttst_swtest_dir)
- #define **RTTST_RTIOC_SWTEST_GET_SWITCHES_COUNT** _IOR(RTIOC_TYPE_TESTING, 0x36, unsigned long)
- #define **RTTST_RTIOC_SWTEST_GET_LAST_ERROR** _IOR(RTIOC_TYPE_TESTING, 0x37, struct rttst_swtest_error)

5.6 Inter-Driver API

Collaboration diagram for Inter-Driver API:



Functions

- struct `rtdm_dev_context` * `rtdm_context_get` (int fd)
Resolve file descriptor to device context.
- int `rtdm_select_bind` (int fd, rtdm_selector_t *selector, enum `rtdm_selecttype` type, unsigned fd_index)
Bind a selector to specified event types of a given file descriptor.
- void `rtdm_context_lock` (struct `rtdm_dev_context` *context)
Increment context reference counter.
- void `rtdm_context_unlock` (struct `rtdm_dev_context` *context)
Decrement context reference counter.
- int `rtdm_open` (const char *path, int oflag,...)
Open a device.
- int `rtdm_socket` (int protocol_family, int socket_type, int protocol)
Create a socket.
- int `rtdm_close` (int fd)
Close a device or socket.
- int `rtdm_ioctl` (int fd, int request,...)
Issue an IOCTL.
- ssize_t `rtdm_read` (int fd, void *buf, size_t nbyte)
Read from device.
- ssize_t `rtdm_write` (int fd, const void *buf, size_t nbyte)
Write to device.
- ssize_t `rtdm_recvmmsg` (int fd, struct msghdr *msg, int flags)
Receive message from socket.
- ssize_t `rtdm_recvfrom` (int fd, void *buf, size_t len, int flags, struct sockaddr *from, socklen_t *fromlen)
Receive message from socket.
- ssize_t `rtdm_recv` (int fd, void *buf, size_t len, int flags)
Receive message from socket.

- `ssize_t rtdm_sendmsg` (int fd, const struct msghdr *msg, int flags)
Transmit message to socket.
- `ssize_t rtdm_sendto` (int fd, const void *buf, size_t len, int flags, const struct sockaddr *to, socklen_t tolen)
Transmit message to socket.
- `ssize_t rtdm_send` (int fd, const void *buf, size_t len, int flags)
Transmit message to socket.
- `int rtdm_bind` (int fd, const struct sockaddr *my_addr, socklen_t addrlen)
Bind to local address.
- `int rtdm_connect` (int fd, const struct sockaddr *serv_addr, socklen_t addrlen)
Connect to remote address.
- `int rtdm_listen` (int fd, int backlog)
Listen for incoming connection requests.
- `int rtdm_accept` (int fd, struct sockaddr *addr, socklen_t *addrlen)
Accept a connection requests.
- `int rtdm_shutdown` (int fd, int how)
Shut down parts of a connection.
- `int rtdm_getsockopt` (int fd, int level, int optname, void *optval, socklen_t *optlen)
Get socket option.
- `int rtdm_setsockopt` (int fd, int level, int optname, const void *optval, socklen_t optlen)
Set socket option.
- `int rtdm_getsockname` (int fd, struct sockaddr *name, socklen_t *namelen)
Get local socket address.
- `int rtdm_getpeername` (int fd, struct sockaddr *name, socklen_t *namelen)
Get socket destination address.

5.6.1 Function Documentation

5.6.1.1 `int rtdm_accept` (int fd, struct sockaddr * addr, socklen_t * addrlen)

Accept a connection requests.

Refer to `rt_dev_accept()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.2 int rtdm_bind (int *fd*, const struct sockaddr * *my_addr*, socklen_t *addrlen*)

Bind to local address.

Refer to `rt_dev_bind()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.3 int rtdm_close (int *fd*)

Close a device or socket.

Refer to `rt_dev_close()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.4 int rtdm_connect (int *fd*, const struct sockaddr * *serv_addr*, socklen_t *addrlen*)

Connect to remote address.

Refer to `rt_dev_connect()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.5 struct rtdm_dev_context* rtdm_context_get (int *fd*) [read]

Resolve file descriptor to device context.

Parameters:

← *fd* File descriptor

Returns:

Pointer to associated device context, or NULL on error

Note:

The device context has to be unlocked using [rtdm_context_unlock\(\)](#) when it is no longer referenced.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code

- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

References `rtdm_dev_context::context_flags`, `RTDM_CLOSING`, and `rtdm_context_lock()`.

Referenced by `rtdm_select_bind()`.

5.6.1.6 `void rtdm_context_lock (struct rtdm_dev_context * context)`

Increment context reference counter.

Parameters:

← *context* Device context

Note:

[rtdm_context_get\(\)](#) automatically increments the lock counter. You only need to call this function in special scenrios.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

Referenced by `rtdm_context_get()`.

5.6.1.7 `void rtdm_context_unlock (struct rtdm_dev_context * context)`

Decrement context reference counter.

Parameters:

← *context* Device context

Note:

Every successful call to [rtdm_context_get\(\)](#) must be matched by a [rtdm_context_unlock\(\)](#) invocation.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

Referenced by `rtdm_select_bind()`.

5.6.1.8 `int rtdm_getpeername(int fd, struct sockaddr * name, socklen_t * namelen)`

Get socket destination address.

Refer to `rt_dev_getpeername()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.9 `int rtdm_getsockname(int fd, struct sockaddr * name, socklen_t * namelen)`

Get local socket address.

Refer to `rt_dev_getsockname()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.10 `int rtdm_getsockopt(int fd, int level, int optname, void * optval, socklen_t * optlen)`

Get socket option.

Refer to `rt_dev_getsockopt()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.11 `int rtdm_ioctl(int fd, int request, ...)`

Issue an IOCTL.

Refer to `rt_dev_ioctl()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.12 `int rtdm_listen (int fd, int backlog)`

Listen for incoming connection requests.

Refer to `rt_dev_listen()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.13 `int rtdm_open (const char * path, int oflag, ...)`

Open a device.

Refer to `rt_dev_open()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.14 `ssize_t rtdm_read (int fd, void * buf, size_t nbyte)`

Read from device.

Refer to `rt_dev_read()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.15 `ssize_t rtdm_recv (int fd, void * buf, size_t len, int flags)`

Receive message from socket.

Refer to `rt_dev_recv()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.16 `ssize_t rtdm_recvfrom (int fd, void * buf, size_t len, int flags, struct sockaddr * from, socklen_t * fromlen)`

Receive message from socket.

Refer to `rt_dev_recvfrom()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.17 `ssize_t rtdm_recvmmsg (int fd, struct msghdr * msg, int flags)`

Receive message from socket.

Refer to `rt_dev_recvmmsg()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.18 `int rtdm_select_bind (int fd, rtdm_selector_t * selector, enum rtdm_selecttype type, unsigned fd_index)`

Bind a selector to specified event types of a given file descriptor.

For internal use only.

This function is invoked by higher RTOS layers implementing select-like services. It shall not be called directly by RTDM drivers.

Parameters:

- ← *fd* File descriptor to bind to
- ↔ *selector* Selector object that shall be bound to the given event
- ← *type* Event type the caller is interested in
- ← *fd_index* Index in the file descriptor set of the caller

Returns:

0 on success, otherwise:

- -EBADF is returned if the file descriptor *fd* cannot be resolved.
- -EINVAL is returned if *type* or *fd_index* are invalid.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

References `rtdm_dev_context::ops`, `rtdm_context_get()`, `rtdm_context_unlock()`, and `rtdm_operations::select_bind`.

5.6.1.19 `ssize_t rtdm_send (int fd, const void * buf, size_t len, int flags)`

Transmit message to socket.

Refer to `rt_dev_send()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.20 `ssize_t rtdm_sendmsg (int fd, const struct msghdr * msg, int flags)`

Transmit message to socket.

Refer to `rt_dev_sendmsg()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.21 `ssize_t rtdm_sendto (int fd, const void * buf, size_t len, int flags, const struct sockaddr * to, socklen_t tolen)`

Transmit message to socket.

Refer to `rt_dev_sendto()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.22 `int rtdm_setsockopt (int fd, int level, int optname, const void * optval, socklen_t optlen)`

Set socket option.

Refer to `rt_dev_setsockopt()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.23 `int rtdm_shutdown (int fd, int how)`

Shut down parts of a connection.

Refer to `rt_dev_shutdown()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.24 `int rtdm_socket (int protocol_family, int socket_type, int protocol)`

Create a socket.

Refer to `rt_dev_socket()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.6.1.25 `ssize_t rtdm_write (int fd, const void * buf, size_t nbyte)`

Write to device.

Refer to `rt_dev_write()` for parameters and return values

Environments:

Depends on driver implementation, see [Device Profiles](#).

Rescheduling: possible.

5.7 Device Registration Services

Collaboration diagram for Device Registration Services:



Modules

- [Synchronisation Services](#)

Data Structures

- struct [rtdm_operations](#)
Device operations.
- struct [rtdm_dev_context](#)
Device context.
- struct [rtdm_device](#)
RTDM device.

Operation Handler Prototypes

- typedef int(* [rtdm_open_handler_t](#))(struct [rtdm_dev_context](#) *context, rtdm_user_info_t *user_info, int oflag)
Named device open handler.
- typedef int(* [rtdm_socket_handler_t](#))(struct [rtdm_dev_context](#) *context, rtdm_user_info_t *user_info, int protocol)
Socket creation handler for protocol devices.
- typedef int(* [rtdm_close_handler_t](#))(struct [rtdm_dev_context](#) *context, rtdm_user_info_t *user_info)
Close handler.
- typedef int(* [rtdm_ioctl_handler_t](#))(struct [rtdm_dev_context](#) *context, rtdm_user_info_t *user_info, unsigned int request, void __user *arg)
IOCTL handler.
- typedef int(* [rtdm_select_bind_handler_t](#))(struct [rtdm_dev_context](#) *context, rtdm_selector_t *selector, enum [rtdm_selecttype](#) type, unsigned fd_index)
Select binding handler.
- typedef ssize_t(* [rtdm_read_handler_t](#))(struct [rtdm_dev_context](#) *context, rtdm_user_info_t *user_info, void *buf, size_t nbyte)
Read handler.

- typedef ssize_t(* [rtm_write_handler_t](#))(struct [rtm_dev_context](#) *context, rtm_user_info_t *user_info, const void *buf, size_t nbyte)
Write handler.
- typedef ssize_t(* [rtm_recvmmsg_handler_t](#))(struct [rtm_dev_context](#) *context, rtm_user_info_t *user_info, struct msghdr *msg, int flags)
Receive message handler.
- typedef ssize_t(* [rtm_sendmsg_handler_t](#))(struct [rtm_dev_context](#) *context, rtm_user_info_t *user_info, const struct msghdr *msg, int flags)
Transmit message handler.

Device Flags

Static flags describing a RTDM device

- #define [RTDM_EXCLUSIVE](#) 0x0001
If set, only a single instance of the device can be requested by an application.
- #define [RTDM_NAMED_DEVICE](#) 0x0010
If set, the device is addressed via a clear-text name.
- #define [RTDM_PROTOCOL_DEVICE](#) 0x0020
If set, the device is addressed via a combination of protocol ID and socket type.
- #define [RTDM_DEVICE_TYPE_MASK](#) 0x00F0
Mask selecting the device type.

Context Flags

Dynamic flags describing the state of an open RTDM device (bit numbers)

- #define [RTDM_CREATED_IN_NRT](#) 0
Set by RTDM if the device instance was created in non-real-time context.
- #define [RTDM_CLOSING](#) 1
Set by RTDM when the device is being closed.
- #define [RTDM_USER_CONTEXT_FLAG](#) 8
Lowest bit number the driver developer can use freely.

Driver Versioning

Current revisions of RTDM structures, encoding of driver versions. See [API Versioning](#) for the interface revision.

- `#define RTDM_DEVICE_STRUCT_VER 5`
Version of struct `rtdm_device`.
- `#define RTDM_CONTEXT_STRUCT_VER 3`
Version of struct `rtdm_dev_context`.
- `#define RTDM_SECURE_DEVICE 0x80000000`
Flag indicating a secure variant of RTDM (not supported here).
- `#define RTDM_DRIVER_VER(major, minor, patch) (((major & 0xFF) << 16) | ((minor & 0xFF) << 8) | (patch & 0xFF))`
Version code constructor for driver revisions.
- `#define RTDM_DRIVER_MAJOR_VER(ver) (((ver) >> 16) & 0xFF)`
Get major version number from driver revision code.
- `#define RTDM_DRIVER_MINOR_VER(ver) (((ver) >> 8) & 0xFF)`
Get minor version number from driver revision code.
- `#define RTDM_DRIVER_PATCH_VER(ver) ((ver) & 0xFF)`
Get patch version number from driver revision code.

Functions

- `int rtdm_dev_register (struct rtdm_device *device)`
Register a RTDM device.
- `int rtdm_dev_unregister (struct rtdm_device *device, unsigned int poll_delay)`
Unregisters a RTDM device.

5.7.1 Define Documentation

5.7.1.1 `#define RTDM_CLOSING 1`

Set by RTDM when the device is being closed.

Referenced by `rtdm_context_get()`.

5.7.1.2 `#define RTDM_CREATED_IN_NRT 0`

Set by RTDM if the device instance was created in non-real-time context.

5.7.1.3 `#define RTDM_DEVICE_TYPE_MASK 0x00F0`

Mask selecting the device type.

Referenced by `rtdm_dev_register()`, and `rtdm_dev_unregister()`.

5.7.1.4 `#define RTDM_EXCLUSIVE 0x0001`

If set, only a single instance of the device can be requested by an application.

Referenced by `rtdm_dev_register()`.

5.7.1.5 `#define RTDM_NAMED_DEVICE 0x0010`

If set, the device is addressed via a clear-text name.

Referenced by `rtdm_dev_register()`, and `rtdm_dev_unregister()`.

5.7.1.6 `#define RTDM_PROTOCOL_DEVICE 0x0020`

If set, the device is addressed via a combination of protocol ID and socket type.

Referenced by `rtdm_dev_register()`.

5.7.2 Typedef Documentation

5.7.2.1 `typedef int(* rtdm_close_handler_t)(struct rtdm_dev_context *context, rtdm_user_info_t *user_info)`

Close handler.

Parameters:

- ← *context* Context structure associated with opened device instance
- ← *user_info* Opaque pointer to information about user mode caller, NULL if kernel mode call

Returns:

0 on success, otherwise negative error code

See also:

`close()` in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.7.2.2 `typedef int(* rtdm_ioctl_handler_t)(struct rtdm_dev_context *context, rtdm_user_info_t *user_info, unsigned int request, void __user *arg)`

IOCTL handler.

Parameters:

- ← *context* Context structure associated with opened device instance
- ← *user_info* Opaque pointer to information about user mode caller, NULL if kernel mode call
- ← *request* Request number as passed by the user
- ↔ *arg* Request argument as passed by the user

Returns:

Positive value on success, otherwise negative error code

See also:

ioctl() in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.7.2.3 `typedef int(* rtdm_open_handler_t)(struct rtdm_dev_context *context,
rtdm_user_info_t *user_info, int oflag)`

Named device open handler.

Parameters:

- ← *context* Context structure associated with opened device instance
- ← *user_info* Opaque pointer to information about user mode caller, NULL if kernel mode call
- ← *oflag* Open flags as passed by the user

Returns:

0 on success, otherwise negative error code

See also:

open() in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.7.2.4 `typedef ssize_t(* rtdm_read_handler_t)(struct rtdm_dev_context *context,
rtdm_user_info_t *user_info, void *buf, size_t nbyte)`

Read handler.

Parameters:

- ← *context* Context structure associated with opened device instance
- ← *user_info* Opaque pointer to information about user mode caller, NULL if kernel mode call
- *buf* Input buffer as passed by the user
- ← *nbyte* Number of bytes the user requests to read

Returns:

On success, the number of bytes read, otherwise negative error code

See also:

read() in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.7.2.5 `typedef ssize_t(* rtdm_recvmmsg_handler_t)(struct rtdm_dev_context *context,
rtdm_user_info_t *user_info, struct msghdr *msg, int flags)`

Receive message handler.

Parameters:

- ← *context* Context structure associated with opened device instance
- ← *user_info* Opaque pointer to information about user mode caller, NULL if kernel mode call
- ↔ *msg* Message descriptor as passed by the user, automatically mirrored to safe kernel memory in case of user mode call
- ← *flags* Message flags as passed by the user

Returns:

On success, the number of bytes received, otherwise negative error code

See also:

recvmmsg() in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.7.2.6 `typedef int(* rtdm_select_bind_handler_t)(struct rtdm_dev_context *context,
rtdm_selector_t *selector, enum rtdm_selecttype type, unsigned fd_index)`

Select binding handler.

Parameters:

- ← *context* Context structure associated with opened device instance
- ↔ *selector* Object that shall be bound to the given event
- ← *type* Event type the selector is interested in
- ← *fd_index* Opaque value, to be passed to rtdm_event_select_bind or rtdm_sem_select_bind unmodified

Returns:

0 on success, otherwise negative error code

5.7.2.7 `typedef ssize_t(* rtdm_sendmsg_handler_t)(struct rtdm_dev_context *context,
rtdm_user_info_t *user_info, const struct msghdr *msg, int flags)`

Transmit message handler.

Parameters:

- ← *context* Context structure associated with opened device instance
- ← *user_info* Opaque pointer to information about user mode caller, NULL if kernel mode call
- ← *msg* Message descriptor as passed by the user, automatically mirrored to safe kernel memory in case of user mode call

← *flags* Message flags as passed by the user

Returns:

On success, the number of bytes transmitted, otherwise negative error code

See also:

sendmsg() in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.7.2.8 `typedef int(* rtdm_socket_handler_t)(struct rtdm_dev_context *context,
rtdm_user_info_t *user_info, int protocol)`

Socket creation handler for protocol devices.

Parameters:

- ← *context* Context structure associated with opened device instance
- ← *user_info* Opaque pointer to information about user mode caller, NULL if kernel mode call
- ← *protocol* Protocol number as passed by the user

Returns:

0 on success, otherwise negative error code

See also:

socket() in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.7.2.9 `typedef ssize_t(* rtdm_write_handler_t)(struct rtdm_dev_context *context,
rtdm_user_info_t *user_info, const void *buf, size_t nbyte)`

Write handler.

Parameters:

- ← *context* Context structure associated with opened device instance
- ← *user_info* Opaque pointer to information about user mode caller, NULL if kernel mode call
- ← *buf* Output buffer as passed by the user
- ← *nbyte* Number of bytes the user requests to write

Returns:

On success, the number of bytes written, otherwise negative error code

See also:

write() in IEEE Std 1003.1, <http://www.opengroup.org/onlinepubs/009695399>

5.7.3 Function Documentation

5.7.3.1 `int rtdm_dev_register (struct rtdm_device * device)`

Register a RTDM device.

Parameters:

← *device* Pointer to structure describing the new device.

Returns:

0 is returned upon success. Otherwise:

- -EINVAL is returned if the device structure contains invalid entries. Check kernel log in this case.
- -ENOMEM is returned if the context for an exclusive device cannot be allocated.
- -EEXIST is returned if the specified device name or protocol ID is already in use.
- -EAGAIN is returned if some /proc entry cannot be created.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code

Rescheduling: never.

References `rtdm_operations::close_nrt`, `rtdm_operations::close_rt`, `rtdm_device::context_size`, `rtdm_device::device_class`, `rtdm_device::device_flags`, `rtdm_device::device_name`, `rtdm_device::device_sub_class`, `rtdm_device::driver_version`, `rtdm_device::ops`, `rtdm_device::proc_name`, `rtdm_device::profile_version`, `rtdm_device::protocol_family`, `rtdm_device::reserved`, `RTDM_DEVICE_STRUCT_VER`, `RTDM_DEVICE_TYPE_MASK`, `RTDM_EXCLUSIVE`, `RTDM_NAMED_DEVICE`, `RTDM_PROTOCOL_DEVICE`, `rtdm_operations::select_bind`, `rtdm_device::socket_type`, and `rtdm_device::struct_version`.

5.7.3.2 `int rtdm_dev_unregister (struct rtdm_device * device, unsigned int poll_delay)`

Unregisters a RTDM device.

Parameters:

← *device* Pointer to structure describing the device to be unregistered.

← *poll_delay* Polling delay in milliseconds to check repeatedly for open instances of *device*, or 0 for non-blocking mode.

Returns:

0 is returned upon success. Otherwise:

- -ENODEV is returned if the device was not registered.
- -EAGAIN is returned if the device is busy with open instances and 0 has been passed for *poll_delay*.

Environments:

This service can be called from:

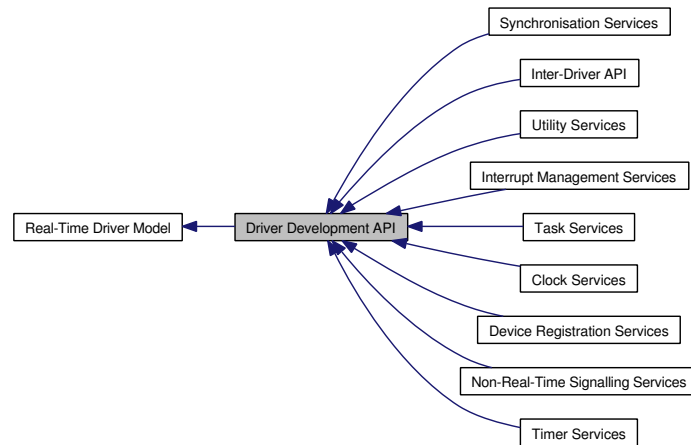
- Kernel module initialization/cleanup code

Rescheduling: never.

References `rtdm_device::device_flags`, `rtdm_device::device_name`, `rtdm_device::proc_entry`, `rtdm_device::proc_name`, `rtdm_device::protocol_family`, `rtdm_device::reserved`, `RTDM_DEVICE_TYPE_MASK`, `RTDM_NAMED_DEVICE`, and `rtdm_device::socket_type`.

5.8 Driver Development API

Collaboration diagram for Driver Development API:



5.8.1 Detailed Description

This is the lower interface of RTDM provided to device drivers, currently limited to kernel-space. Real-time drivers should only use functions of this interface in order to remain portable.

Files

- file [rtdm_driver.h](#)
Real-Time Driver Model for Xenomai, driver API header.

Modules

- [Inter-Driver API](#)
- [Device Registration Services](#)
- [Clock Services](#)
- [Task Services](#)
- [Timer Services](#)
- [Synchronisation Services](#)
- [Interrupt Management Services](#)
- [Non-Real-Time Signalling Services](#)
- [Utility Services](#)

5.9 Clock Services

Collaboration diagram for Clock Services:



Functions

- `nanosecs_abs_t rtdm_clock_read (void)`
Get system time.
- `nanosecs_abs_t rtdm_clock_read_monotonic (void)`
Get monotonic time.

5.9.1 Function Documentation

5.9.1.1 `nanosecs_abs_t rtdm_clock_read (void)`

Get system time.

Returns:

The system time in nanoseconds is returned

Note:

The resolution of this service depends on the system timer. In particular, if the system timer is running in periodic mode, the return value will be limited to multiples of the timer tick period.

The system timer may have to be started to obtain valid results. Whether this happens automatically (as on Xenomai) or is controlled by the application depends on the RTDM host environment.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.9.1.2 nanosecs_abs_t rtdm_clock_read_monotonic (void)

Get monotonic time.

Returns:

The monotonic time in nanoseconds is returned

Note:

The resolution of this service depends on the system timer. In particular, if the system timer is running in periodic mode, the return value will be limited to multiples of the timer tick period.

The system timer may have to be started to obtain valid results. Whether this happens automatically (as on Xenomai) or is controlled by the application depends on the RTDM host environment.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.10 Task Services

Collaboration diagram for Task Services:



Task Priority Range

Maximum and minimum task priorities

- `#define RTDM_TASK_LOWEST_PRIORITY XNCORE_LOW_PRIO`
- `#define RTDM_TASK_HIGHEST_PRIORITY XNCORE_HIGH_PRIO`

Task Priority Modification

Raise or lower task priorities by one level

- `#define RTDM_TASK_RAISE_PRIORITY (+1)`
- `#define RTDM_TASK_LOWER_PRIORITY (-1)`

Typedefs

- `typedef void(* rtdm_task_proc_t)(void *arg)`
Real-time task procedure.

Functions

- `int rtdm_task_init (rtdm_task_t *task, const char *name, rtdm_task_proc_t task_proc, void *arg, int priority, nanosecs_rel_t period)`
Intialise and start a real-time task.
- `void rtdm_task_destroy (rtdm_task_t *task)`
Destroy a real-time task.
- `void rtdm_task_set_priority (rtdm_task_t *task, int priority)`
Adjust real-time task priority.
- `int rtdm_task_set_period (rtdm_task_t *task, nanosecs_rel_t period)`
Adjust real-time task period.
- `int rtdm_task_wait_period (void)`
Wait on next real-time task period.
- `int rtdm_task_unblock (rtdm_task_t *task)`
Activate a blocked real-time task.

- `rtm_task_t * rtdm_task_current` (void)
Get current real-time task.
- `int rtdm_task_sleep` (`nanosecs_rel_t` delay)
Sleep a specified amount of time.
- `int rtdm_task_sleep_until` (`nanosecs_abs_t` wakeup_time)
Sleep until a specified absolute time.
- `int rtdm_task_sleep_abs` (`nanosecs_abs_t` wakeup_time, enum `rtdm_timer_mode` mode)
Sleep until a specified absolute time.
- `void rtdm_task_join_nrt` (`rtm_task_t *task`, unsigned int poll_delay)
Wait on a real-time task to terminate.
- `void rtdm_task_busy_sleep` (`nanosecs_rel_t` delay)
Busy-wait a specified amount of time.

5.10.1 Typedef Documentation

5.10.1.1 `typedef void(* rtdm_task_proc_t)(void *arg)`

Real-time task procedure.

Parameters:

↔ *arg* argument as passed to `rtdm_task_init()`

5.10.2 Function Documentation

5.10.2.1 `void rtdm_task_busy_sleep (nanosecs_rel_t delay)`

Busy-wait a specified amount of time.

Parameters:

← *delay* Delay in nanoseconds. Note that a zero delay does **not** have the meaning of `RTDM_TIMEOUT_INFINITE` here.

Note:

The caller must not be migratable to different CPUs while executing this service. Otherwise, the actual delay will be undefined.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code

- Interrupt service routine (should be avoided or kept short)
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never (except due to external interruptions).

5.10.2.2 `rtdm_task_t* rtdm_task_current (void)`

Get current real-time task.

Returns:

Pointer to task handle

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.10.2.3 `void rtdm_task_destroy (rtdm_task_t * task)`

Destroy a real-time task.

Parameters:

↔ *task* Task handle as returned by [rtdm_task_init\(\)](#)

Note:

Passing the same task handle to RTDM services after the completion of this function is not allowed.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.10.2.4 `int rtdm_task_init (rtdm_task_t * task, const char * name, rtdm_task_proc_t task_proc, void * arg, int priority, nanosecs_rel_t period)`

Initialise and start a real-time task.

After initialising a task, the task handle remains valid and can be passed to RTDM services until either `rtdm_task_destroy()` or `rtdm_task_join_nrt()` was invoked.

Parameters:

- ↔ *task* Task handle
- ← *name* Optional task name
- ← *task_proc* Procedure to be executed by the task
- ← *arg* Custom argument passed to `task_proc()` on entry
- ← *priority* Priority of the task, see also [Task Priority Range](#)
- ← *period* Period in nanoseconds of a cyclic task, 0 for non-cyclic mode

Returns:

0 on success, otherwise negative error code

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.10.2.5 `void rtdm_task_join_nrt (rtdm_task_t * task, unsigned int poll_delay)`

Wait on a real-time task to terminate.

Parameters:

- ↔ *task* Task handle as returned by `rtdm_task_init()`
- ← *poll_delay* Delay in milliseconds between periodic tests for the state of the real-time task.
This parameter is ignored if the termination is internally realised without polling.

Note:

Passing the same task handle to RTDM services after the completion of this function is not allowed.

This service does not trigger the termination of the targeted task. The user has to take of this, otherwise `rtdm_task_join_nrt()` will never return.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- User-space task (non-RT)

Rescheduling: possible.

5.10.2.6 `int rtdm_task_set_period (rtdm_task_t * task, nanosecs_rel_t period)`

Adjust real-time task period.

Parameters:

- ↔ *task* Task handle as returned by [rtdm_task_init\(\)](#)
- ← *period* New period in nanoseconds of a cyclic task, 0 for non-cyclic mode

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.10.2.7 `void rtdm_task_set_priority (rtdm_task_t * task, int priority)`

Adjust real-time task priority.

Parameters:

- ↔ *task* Task handle as returned by [rtdm_task_init\(\)](#)
- ← *priority* New priority of the task, see also [Task Priority Range](#)

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.10.2.8 `int rtdm_task_sleep (nanosecs_rel_t delay)`

Sleep a specified amount of time.

Parameters:

- ← *delay* Delay in nanoseconds, see [RTDM_TIMEOUT_XXX](#) for special values.

Returns:

0 on success, otherwise:

- -EINTR is returned if calling task has been unblock by a signal or explicitly via [rt dm_task_unblock\(\)](#).
- -EPERM *may* be returned if an illegal invocation environment is detected.

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: always.

5.10.2.9 int rtdm_task_sleep_abs (nanosecs_abs_t *wakeup_time*, enum rtdm_timer_mode *mode*)

Sleep until a specified absolute time.

Parameters:

← *wakeup_time* Absolute timeout in nanoseconds

← *mode* Selects the timer mode, see RTDM_TIMERMODE_XXX for details

Returns:

0 on success, otherwise:

- -EINTR is returned if calling task has been unblock by a signal or explicitly via [rt dm_task_unblock\(\)](#).
- -EPERM *may* be returned if an illegal invocation environment is detected.
- -EINVAL is returned if an invalid parameter was passed.

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: always, unless the specified time already passed.

5.10.2.10 `int rtdm_task_sleep_until (nanosecs_abs_t wakeup_time)`

Sleep until a specified absolute time.

Deprecated

Use `rtdm_task_sleep_abs` instead!

Parameters:

← *wakeup_time* Absolute timeout in nanoseconds

Returns:

0 on success, otherwise:

- -EINTR is returned if calling task has been unblock by a signal or explicitly via [rtdm_task_unblock\(\)](#).
- -EPERM *may* be returned if an illegal invocation environment is detected.

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: always, unless the specified time already passed.

5.10.2.11 `int rtdm_task_unblock (rtdm_task_t * task)`

Activate a blocked real-time task.

Returns:

Non-zero is returned if the task was actually unblocked from a pending wait state, 0 otherwise.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.10.2.12 `int rtdm_task_wait_period (void)`

Wait on next real-time task period.

Returns:

0 on success, otherwise:

- -EINVAL is returned if calling task is not in periodic mode.
- -ETIMEDOUT is returned if a timer overrun occurred, which indicates that a previous release point has been missed by the calling task.

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: always, unless a timer overrun occurred.

5.11 Timer Services

Collaboration diagram for Timer Services:



RTDM_TIMERMODE_XXX

Timer operation modes

- enum `rtdm_timer_mode` { `RTDM_TIMERMODE_RELATIVE` = `XN_RELATIVE`, `RTDM_TIMERMODE_ABSOLUTE` = `XN_ABSOLUTE`, `RTDM_TIMERMODE_REALTIME` = `XN_REALTIME` }

Typedefs

- typedef void(* `rtdm_timer_handler_t`)(`rtdm_timer_t` *timer)
Timer handler.

Functions

- int `rtdm_timer_init` (`rtdm_timer_t` *timer, `rtdm_timer_handler_t` handler, const char *name)
Initialise a timer.
- void `rtdm_timer_destroy` (`rtdm_timer_t` *timer)
Destroy a timer.
- int `rtdm_timer_start` (`rtdm_timer_t` *timer, `nanosecs_abs_t` expiry, `nanosecs_rel_t` interval, enum `rtdm_timer_mode` mode)
Start a timer.
- void `rtdm_timer_stop` (`rtdm_timer_t` *timer)
Stop a timer.
- int `rtdm_timer_start_in_handler` (`rtdm_timer_t` *timer, `nanosecs_abs_t` expiry, `nanosecs_rel_t` interval, enum `rtdm_timer_mode` mode)
Start a timer from inside a timer handler.
- void `rtdm_timer_stop_in_handler` (`rtdm_timer_t` *timer)
Stop a timer from inside a timer handler.

5.11.1 Typedef Documentation

5.11.1.1 typedef void(* rtdm_timer_handler_t)(rtdm_timer_t *timer)

Timer handler.

Parameters:

← *timer* Timer handle as returned by [rtdm_timer_init\(\)](#)

5.11.2 Enumeration Type Documentation

5.11.2.1 enum rtdm_timer_mode

Enumerator:

RTDM_TIMERMODE_RELATIVE Monotonic timer with relative timeout.

RTDM_TIMERMODE_ABSOLUTE Monotonic timer with absolute timeout.

RTDM_TIMERMODE_REALTIME Adjustable timer with absolute timeout.

5.11.3 Function Documentation

5.11.3.1 void rtdm_timer_destroy (rtdm_timer_t * timer)

Destroy a timer.

Parameters:

↔ *timer* Timer handle as returned by [rtdm_timer_init\(\)](#)

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.11.3.2 int rtdm_timer_init (rtdm_timer_t * timer, rtdm_timer_handler_t handler, const char * name)

Initialise a timer.

Parameters:

↔ *timer* Timer handle

← *handler* Handler to be called on timer expiry

← *name* Optional timer name

Returns:

0 on success, otherwise negative error code

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.11.3.3 `int rtdm_timer_start(rtdm_timer_t * timer, nanosecs_abs_t expiry, nanosecs_rel_t interval, enum rtdm_timer_mode mode)`

Start a timer.

Parameters:

- ↔ *timer* Timer handle as returned by [rtdm_timer_init\(\)](#)
- ← *expiry* Firing time of the timer, *mode* defines if relative or absolute
- ← *interval* Relative reload value, > 0 if the timer shall work in periodic mode with the specific interval, 0 for one-shot timers
- ← *mode* Defines the operation mode, see [RTDM_TIMERMODE_XXX](#) for possible values

Returns:

0 on success, otherwise:

- -ETIMEDOUT is returned if *expiry* describes an absolute date in the past.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.11.3.4 `int rtdm_timer_start_in_handler(rtdm_timer_t * timer, nanosecs_abs_t expiry, nanosecs_rel_t interval, enum rtdm_timer_mode mode)`

Start a timer from inside a timer handler.

Parameters:

- ↔ *timer* Timer handle as returned by [rtdm_timer_init\(\)](#)
- ← *expiry* Firing time of the timer, *mode* defines if relative or absolute
- ← *interval* Relative reload value, > 0 if the timer shall work in periodic mode with the specific interval, 0 for one-shot timers
- ← *mode* Defines the operation mode, see [RTDM_TIMERMODE_XXX](#) for possible values

Returns:

0 on success, otherwise:

- -ETIMEDOUT is returned if *expiry* describes an absolute date in the past.

Environments:

This service can be called from:

- Timer handler

Rescheduling: never.

5.11.3.5 `void rtdm_timer_stop(rtdm_timer_t * timer)`

Stop a timer.

Parameters:

- ↔ *timer* Timer handle as returned by [rtdm_timer_init\(\)](#)

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.11.3.6 void `rtdm_timer_stop_in_handler` (`rtdm_timer_t * timer`)

Stop a timer from inside a timer handler.

Parameters:

↔ *timer* Timer handle as returned by [rtdm_timer_init\(\)](#)

Environments:

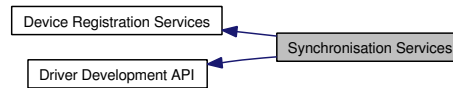
This service can be called from:

- Timer handler

Rescheduling: never.

5.12 Synchronisation Services

Collaboration diagram for Synchronisation Services:



RTDM_SELECTTYPE_xxx

Event types select can bind to

- enum `rtdm_selecttype` { `RTDM_SELECTTYPE_READ` = `XNSELECT_READ`, `RTDM_SELECTTYPE_WRITE` = `XNSELECT_WRITE`, `RTDM_SELECTTYPE_EXCEPT` = `XNSELECT_EXCEPT` }

Spinlock with Preemption Deactivation

- typedef `rthal_spinlock_t` `rtdm_lock_t`
Lock variable.
- typedef unsigned long `rtdm_lockctx_t`
Variable to save the context while holding a lock.
- #define `RTDM_LOCK_UNLOCKED` `RTHAL_SPIN_LOCK_UNLOCKED`
Static lock initialisation.
- #define `rtdm_lock_init(lock)` `rthal_spin_lock_init(lock)`
Dynamic lock initialisation.
- #define `rtdm_lock_get(lock)` `rthal_spin_lock(lock)`
Acquire lock from non-preemptible contexts.
- #define `rtdm_lock_put(lock)` `rthal_spin_unlock(lock)`
Release lock without preemption restoration.
- #define `rtdm_lock_get_irqsave(lock, context)` `rthal_spin_lock_irqsave(lock, context)`
Acquire lock and disable preemption.
- #define `rtdm_lock_put_irqrestore(lock, context)` `rthal_spin_unlock_irqrestore(lock, context)`
Release lock and restore preemption state.
- #define `rtdm_lock_irqsave(context)` `rthal_local_irq_save(context)`
Disable preemption locally.
- #define `rtdm_lock_irqrestore(context)` `rthal_local_irq_restore(context)`
Restore preemption state.

Timeout Sequence Management

- void [rt dm_toseq_init](#) (rt dm_toseq_t *timeout_seq, [nanosecs_rel_t](#) timeout)
Initialise a timeout sequence.

Event Services

- void [rt dm_event_init](#) (rt dm_event_t *event, unsigned long pending)
Initialise an event.
- void [rt dm_event_destroy](#) (rt dm_event_t *event)
Destroy an event.
- void [rt dm_event_pulse](#) (rt dm_event_t *event)
Signal an event occurrence to currently listening waiters.
- void [rt dm_event_signal](#) (rt dm_event_t *event)
Signal an event occurrence.
- int [rt dm_event_wait](#) (rt dm_event_t *event)
Wait on event occurrence.
- int [rt dm_event_timedwait](#) (rt dm_event_t *event, [nanosecs_rel_t](#) timeout, rt dm_toseq_t *timeout_seq)
Wait on event occurrence with timeout.
- void [rt dm_event_clear](#) (rt dm_event_t *event)
Clear event state.
- int [rt dm_event_select_bind](#) (rt dm_event_t *event, rt dm_selector_t *selector, enum [rt dm_selecttype](#) type, unsigned fd_index)
Bind a selector to an event.

Semaphore Services

- void [rt dm_sem_init](#) (rt dm_sem_t *sem, unsigned long value)
Initialise a semaphore.
- void [rt dm_sem_destroy](#) (rt dm_sem_t *sem)
Destroy a semaphore.
- int [rt dm_sem_down](#) (rt dm_sem_t *sem)
Decrement a semaphore.
- int [rt dm_sem_timeddown](#) (rt dm_sem_t *sem, [nanosecs_rel_t](#) timeout, rt dm_toseq_t *timeout_seq)
Decrement a semaphore with timeout.

- void `rt dm_sem_up` (rt dm_sem_t *sem)
Increment a semaphore.
- int `rt dm_sem_select_bind` (rt dm_sem_t *sem, rt dm_selector_t *selector, enum `rt dm_selecttype` type, unsigned fd_index)
Bind a selector to a semaphore.

Mutex Services

- void `rt dm_mutex_init` (rt dm_mutex_t *mutex)
Initialise a mutex.
- void `rt dm_mutex_destroy` (rt dm_mutex_t *mutex)
Destroy a mutex.
- void `rt dm_mutex_unlock` (rt dm_mutex_t *mutex)
Release a mutex.
- int `rt dm_mutex_lock` (rt dm_mutex_t *mutex)
Request a mutex.
- int `rt dm_mutex_timedlock` (rt dm_mutex_t *mutex, `nanosecs_rel_t` timeout, rt dm_toseq_t *timeout_seq)
Request a mutex with timeout.

Global Lock across Scheduler Invocation

- #define `RTDM_EXECUTE_ATOMICALY`(code_block)
Execute code block atomically.

Functions

- int `rt dm_select_bind` (int fd, rt dm_selector_t *selector, enum `rt dm_selecttype` type, unsigned fd_index)
Bind a selector to specified event types of a given file descriptor.

5.12.1 Define Documentation

5.12.1.1 #define RTDM_EXECUTE_ATOMICALY(code_block)

Value:

```

{
    <ENTER_ATOMIC_SECTION>          \
    code_block;                     \
    <LEAVE_ATOMIC_SECTION>         \
}

```

Execute code block atomically.

Generally, it is illegal to suspend the current task by calling [rtm_task_sleep\(\)](#), [rtm_event_wait\(\)](#), etc. while holding a spinlock. In contrast, this macro allows to combine several operations including a potentially rescheduling call to an atomic code block with respect to other [RTDM_EXECUTE_ATOMICALY\(\)](#) blocks. The macro is a light-weight alternative for protecting code blocks via mutexes, and it can even be used to synchronise real-time and non-real-time contexts.

Parameters:

code_block Commands to be executed atomically

Note:

It is not allowed to leave the code block explicitly by using `break`, `return`, `goto`, etc. This would leave the global lock held during the code block execution in an inconsistent state. Moreover, do not embed complex operations into the code block. Consider that they will be executed under preemption lock with interrupts switched-off. Also note that invocation of rescheduling calls may break the atomicity until the task gains the CPU again.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible, depends on functions called within *code_block*.

5.12.1.2 #define rtdm_lock_get(lock) rthal_spin_lock(lock)

Acquire lock from non-preemptible contexts.

Parameters:

lock Address of lock variable

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.12.1.3 #define rtdm_lock_get_irqsave(lock, context) rthal_spin_lock_irqsave(lock, context)

Acquire lock and disable preemption.

Parameters:

lock Address of lock variable

context name of local variable to store the context in

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.12.1.4 #define rtdm_lock_init(lock) rthal_spin_lock_init(lock)

Dynamic lock initialisation.

Parameters:

lock Address of lock variable

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.12.1.5 #define rtdm_lock_irqrestore(context) rthal_local_irq_restore(context)

Restore preemption state.

Parameters:

context name of local variable which stored the context

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.12.1.6 **#define rtdm_lock_irqsave(context) rthal_local_irq_save(context)**

Disable preemption locally.

Parameters:

context name of local variable to store the context in

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.12.1.7 **#define rtdm_lock_put(lock) rthal_spin_unlock(lock)**

Release lock without preemption restoration.

Parameters:

lock Address of lock variable

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.12.1.8 `#define rtdm_lock_put_irqrestore(lock, context) rthal_spin_unlock_irqrestore(lock, context)`

Release lock and restore preemption state.

Parameters:

lock Address of lock variable

context name of local variable which stored the context

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.12.2 Enumeration Type Documentation

5.12.2.1 `enum rtdm_selecttype`

Enumerator:

RTDM_SELECTTYPE_READ Select input data availability events.

RTDM_SELECTTYPE_WRITE Select output buffer availability events.

RTDM_SELECTTYPE_EXCEPT Select exceptional events.

5.12.3 Function Documentation

5.12.3.1 `void rtdm_event_clear (rtdm_event_t * event)`

Clear event state.

Parameters:

↔ *event* Event handle as returned by [rtdm_event_init\(\)](#)

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.12.3.2 void rtdm_event_destroy (rtdm_event_t * event)

Destroy an event.

Parameters:

↔ *event* Event handle as returned by [rtdm_event_init\(\)](#)

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.12.3.3 void rtdm_event_init (rtdm_event_t * event, unsigned long pending)

Initialise an event.

Parameters:

↔ *event* Event handle

← *pending* Non-zero if event shall be initialised as set, 0 otherwise

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.12.3.4 void rtdm_event_pulse (rtdm_event_t * event)

Signal an event occurrence to currently listening waiters.

This function wakes up all current waiters of the given event, but it does not change the event state. Subsequently callers of [rtdm_event_wait\(\)](#) or [rtdm_event_timedwait\(\)](#) will therefore be blocked first.

Parameters:

↔ *event* Event handle as returned by [rtdm_event_init\(\)](#)

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.12.3.5 `int rtdm_event_select_bind (rtdm_event_t * event, rtdm_selector_t * selector, enum rtdm_selecttype type, unsigned fd_index)`

Bind a selector to an event.

This functions binds the given selector to an event so that the former is notified when the event state changes. Typically the select binding handler will invoke this service.

Parameters:

- ↔ *event* Event handle as returned by `rtdm_event_init()`
- ↔ *selector* Selector as passed to the select binding handler
- ← *type* Type of the bound event as passed to the select binding handler
- ← *fd_index* File descriptor index as passed to the select binding handler

Returns:

0 on success, otherwise:

- -EIDRM is returned if *event* has been destroyed.
- -ENOMEM is returned if there is insufficient memory to establish the dynamic binding.
- -EINVAL is returned if *type* or *fd_index* are invalid.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.12.3.6 `void rtdm_event_signal (rtdm_event_t * event)`

Signal an event occurrence.

This function sets the given event and wakes up all current waiters. If no waiter is presently registered, the next call to `rtdm_event_wait()` or `rtdm_event_timedwait()` will return immediately.

Parameters:

↔ *event* Event handle as returned by [rt dm_event_init\(\)](#)

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.12.3.7 `int rtdm_event_timedwait (rtdm_event_t * event, nanosecs_rel_t timeout, rtdm_toseq_t * timeout_seq)`

Wait on event occurrence with timeout.

This function waits or tests for the occurrence of the given event, taking the provided timeout into account. On successful return, the event is reset.

Parameters:

↔ *event* Event handle as returned by [rt dm_event_init\(\)](#)

← *timeout* Relative timeout in nanoseconds, see [RTDM_TIMEOUT_xxx](#) for special values

↔ *timeout_seq* Handle of a timeout sequence as returned by [rt dm_toseq_init\(\)](#) or NULL

Returns:

0 on success, otherwise:

- -ETIMEDOUT is returned if the request has not been satisfied within the specified amount of time.
- -EINTR is returned if calling task has been unblock by a signal or explicitly via [rt dm_task_unblock\(\)](#).
- -EIDRM is returned if *event* has been destroyed.
- -EPERM *may* be returned if an illegal invocation environment is detected.

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: possible.

Referenced by [rt dm_event_wait\(\)](#).

5.12.3.8 `int rtdm_event_wait (rtdm_event_t * event)`

Wait on event occurrence.

This is the light-weight version of [rtdm_event_timedwait\(\)](#), implying an infinite timeout.

Parameters:

↔ *event* Event handle as returned by [rtdm_event_init\(\)](#)

Returns:

0 on success, otherwise:

- -EINTR is returned if calling task has been unblock by a signal or explicitly via [rtdm_task_unblock\(\)](#).
- -EIDRM is returned if *event* has been destroyed.
- -EPERM *may* be returned if an illegal invocation environment is detected.

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: possible.

References [rtdm_event_timedwait\(\)](#).

5.12.3.9 `void rtdm_mutex_destroy (rtdm_mutex_t * mutex)`

Destroy a mutex.

Parameters:

↔ *mutex* Mutex handle as returned by [rtdm_mutex_init\(\)](#)

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.12.3.10 void rtdm_mutex_init (rtdm_mutex_t * mutex)

Initialise a mutex.

This function initialises a basic mutex with priority inversion protection. "Basic", as it does not allow a mutex owner to recursively lock the same mutex again.

Parameters:

↔ *mutex* Mutex handle

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.12.3.11 int rtdm_mutex_lock (rtdm_mutex_t * mutex)

Request a mutex.

This is the light-weight version of [rtdm_mutex_timedlock\(\)](#), implying an infinite timeout.

Parameters:

↔ *mutex* Mutex handle as returned by [rtdm_mutex_init\(\)](#)

Returns:

0 on success, otherwise:

- -EIDRM is returned if *mutex* has been destroyed.
- -EPERM *may* be returned if an illegal invocation environment is detected.

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: possible.

References [rtdm_mutex_timedlock\(\)](#).

5.12.3.12 `int rtdm_mutex_timedlock (rtdm_mutex_t * mutex, nanosecs_rel_t timeout, rtdm_toseq_t * timeout_seq)`

Request a mutex with timeout.

This function tries to acquire the given mutex. If it is not available, the caller is blocked unless non-blocking operation was selected.

Parameters:

- ↔ *mutex* Mutex handle as returned by [rtdm_mutex_init\(\)](#)
- ← *timeout* Relative timeout in nanoseconds, see [RTDM_TIMEOUT_xxx](#) for special values
- ↔ *timeout_seq* Handle of a timeout sequence as returned by [rtdm_toseq_init\(\)](#) or NULL

Returns:

0 on success, otherwise:

- -ETIMEDOUT is returned if the request has not been satisfied within the specified amount of time.
- -EWOULDBLOCK is returned if *timeout* is negative and the semaphore value is currently not positive.
- -EIDRM is returned if *mutex* has been destroyed.
- -EPERM *may* be returned if an illegal invocation environment is detected.

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: possible.

Referenced by [rtdm_mutex_lock\(\)](#).

5.12.3.13 `void rtdm_mutex_unlock (rtdm_mutex_t * mutex)`

Release a mutex.

This function releases the given mutex, waking up a potential waiter which was blocked upon [rtdm_mutex_lock\(\)](#) or [rtdm_mutex_timedlock\(\)](#).

Parameters:

- ↔ *mutex* Mutex handle as returned by [rtdm_mutex_init\(\)](#)

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: possible.

5.12.3.14 `int rtdm_select_bind (int fd, rtdm_selector_t * selector, enum rtdm_selecttype type, unsigned fd_index)`

Bind a selector to specified event types of a given file descriptor.

For internal use only.

This function is invoked by higher RTOS layers implementing select-like services. It shall not be called directly by RTDM drivers.

Parameters:

- ← *fd* File descriptor to bind to
- ↔ *selector* Selector object that shall be bound to the given event
- ← *type* Event type the caller is interested in
- ← *fd_index* Index in the file descriptor set of the caller

Returns:

- 0 on success, otherwise:
- -EBADF is returned if the file descriptor *fd* cannot be resolved.
- -EINVAL is returned if *type* or *fd_index* are invalid.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

References `rtdm_dev_context::ops`, `rtdm_context_get()`, `rtdm_context_unlock()`, and `rtdm_operations::select_bind`.

5.12.3.15 `void rtdm_sem_destroy (rtdm_sem_t * sem)`

Destroy a semaphore.

Parameters:

- ↔ *sem* Semaphore handle as returned by [rtdm_sem_init\(\)](#)

Environments:

This service can be called from:

- Kernel module initialization/cleanup code

- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.12.3.16 `int rtdm_sem_down (rtdm_sem_t * sem)`

Decrement a semaphore.

This is the light-weight version of `rtdm_sem_timeddown()`, implying an infinite timeout.

Parameters:

↔ *sem* Semaphore handle as returned by `rtdm_sem_init()`

Returns:

0 on success, otherwise:

- -EINTR is returned if calling task has been unblock by a signal or explicitly via `rtdm_task_unblock()`.
- -EIDRM is returned if *sem* has been destroyed.
- -EPERM *may* be returned if an illegal invocation environment is detected.

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: possible.

References `rtdm_sem_timeddown()`.

5.12.3.17 `void rtdm_sem_init (rtdm_sem_t * sem, unsigned long value)`

Initialise a semaphore.

Parameters:

↔ *sem* Semaphore handle

← *value* Initial value of the semaphore

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.12.3.18 `int rtdm_sem_select_bind (rtdm_sem_t * sem, rtdm_selector_t * selector, enum rtdm_selecttype type, unsigned fd_index)`

Bind a selector to a semaphore.

This functions binds the given selector to the semaphore so that the former is notified when the semaphore state changes. Typically the select binding handler will invoke this service.

Parameters:

- ↔ *sem* Semaphore handle as returned by [rtdm_sem_init\(\)](#)
- ↔ *selector* Selector as passed to the select binding handler
- ← *type* Type of the bound event as passed to the select binding handler
- ← *fd_index* File descriptor index as passed to the select binding handler

Returns:

- 0 on success, otherwise:
- -EIDRM is returned if *sem* has been destroyed.
- -ENOMEM is returned if there is insufficient memory to establish the dynamic binding.
- -EINVAL is returned if *type* or *fd_index* are invalid.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.12.3.19 `int rtdm_sem_timeddown (rtdm_sem_t * sem, nanosecs_rel_t timeout, rtdm_toseq_t * timeout_seq)`

Decrement a semaphore with timeout.

This function tries to decrement the given semaphore's value if it is positive on entry. If not, the caller is blocked unless non-blocking operation was selected.

Parameters:

- ↔ *sem* Semaphore handle as returned by [rtdm_sem_init\(\)](#)
- ← *timeout* Relative timeout in nanoseconds, see [RTDM_TIMEOUT_xxx](#) for special values
- ↔ *timeout_seq* Handle of a timeout sequence as returned by [rtdm_toseq_init\(\)](#) or NULL

Returns:

- 0 on success, otherwise:

- -ETIMEDOUT is returned if the request has not been satisfied within the specified amount of time.
- -EWOULDBLOCK is returned if *timeout* is negative and the semaphore value is currently not positive.
- -EINTR is returned if calling task has been unblock by a signal or explicitly via [rt dm_task_unblock\(\)](#).
- -EIDRM is returned if *sem* has been destroyed.
- -EPERM *may* be returned if an illegal invocation environment is detected.

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: possible.

Referenced by [rt dm_sem_down\(\)](#).

5.12.3.20 void [rt dm_sem_up](#) ([rt dm_sem_t](#) * *sem*)

Increment a semaphore.

This function increments the given semaphore's value, waking up a potential waiter which was blocked upon [rt dm_sem_down\(\)](#).

Parameters:

↔ *sem* Semaphore handle as returned by [rt dm_sem_init\(\)](#)

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.12.3.21 void rtdm_toseq_init (rtdm_toseq_t * *timeout_seq*, nanosecs_rel_t *timeout*)

Initialise a timeout sequence.

This service initialises a timeout sequence handle according to the given timeout value. Timeout sequences allow to maintain a continuous *timeout* across multiple calls of blocking synchronisation services. A typical application scenario is given below.

Parameters:

- ↔ *timeout_seq* Timeout sequence handle
- ← *timeout* Relative timeout in nanoseconds, see [RTDM_TIMEOUT_xxx](#) for special values

Application Scenario:

```
int device_service_routine(...)
{
    rtdm_toseq_t timeout_seq;
    ...

    rtdm_toseq_init(&timeout_seq, timeout);
    ...
    while (received < requested) {
        ret = rtdm_event_timedwait(&data_available, timeout, &timeout_seq);
        if (ret < 0) // including -ETIMEDOUT
            break;

        // receive some data
        ...
    }
    ...
}
```

Using a timeout sequence in such a scenario avoids that the user-provided relative *timeout* is restarted on every call to [rtdm_event_timedwait\(\)](#), potentially causing an overall delay that is larger than specified by *timeout*. Moreover, all functions supporting timeout sequences also interpret special timeout values (infinite and non-blocking), disburdening the driver developer from handling them separately.

Environments:

This service can be called from:

- Kernel-based task
- User-space task (RT)

Rescheduling: never.

5.13 Interrupt Management Services

Collaboration diagram for Interrupt Management Services:



RTDM_IRQTYPE_xxx

Interrupt registrations flags

- #define `RTDM_IRQTYPE_SHARED` `XN_ISR_SHARED`
Enable IRQ-sharing with other real-time drivers.
- #define `RTDM_IRQTYPE_EDGE` `XN_ISR_EDGE`
Mark IRQ as edge-triggered, relevant for correct handling of shared edge-triggered IRQs.

RTDM_IRQ_xxx

Return flags of interrupt handlers

- #define `RTDM_IRQ_NONE` `XN_ISR_NONE`
Unhandled interrupt.
- #define `RTDM_IRQ_HANDLED` `XN_ISR_HANDLED`
Denote handled interrupt.

Defines

- #define `rtdm_irq_get_arg`(`irq_handle`, `type`) ((`type *`)`irq_handle` → `cookie`)
Retrieve IRQ handler argument.

Typedefs

- typedef int(* `rtdm_irq_handler_t`)(`rtdm_irq_t *``irq_handle`)
Interrupt handler.

Functions

- int `rtdm_irq_request`(`rtdm_irq_t *``irq_handle`, unsigned int `irq_no`, `rtdm_irq_handler_t` `handler`, unsigned long `flags`, const char *`device_name`, void *`arg`)
Register an interrupt handler.

- int [rt dm_irq_free](#) (rt dm_irq_t *irq_handle)
Release an interrupt handler.
- int [rt dm_irq_enable](#) (rt dm_irq_t *irq_handle)
Enable interrupt line.
- int [rt dm_irq_disable](#) (rt dm_irq_t *irq_handle)
Disable interrupt line.

5.13.1 Define Documentation

5.13.1.1 #define rt dm_irq_get_arg(irq_handle, type) ((type *)irq_handle → cookie)

Retrieve IRQ handler argument.

Parameters:

irq_handle IRQ handle
type Type of the pointer to return

Returns:

The argument pointer registered on [rt dm_irq_request\(\)](#) is returned, type-casted to the specified *type*.

Environments:

This service can be called from:

- Interrupt service routine

Rescheduling: never.

5.13.2 Typedef Documentation

5.13.2.1 typedef int(* rt dm_irq_handler_t)(rt dm_irq_t *irq_handle)

Interrupt handler.

Parameters:

← *irq_handle* IRQ handle as returned by [rt dm_irq_request\(\)](#)

Returns:

0 or a combination of [RTDM_IRQ_XXX](#) flags

5.13.3 Function Documentation

5.13.3.1 `int rtdm_irq_disable (rtdm_irq_t * irq_handle)`

Disable interrupt line.

Parameters:

↔ *irq_handle* IRQ handle as returned by `rtdm_irq_request()`

Returns:

0 on success, otherwise negative error code

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.13.3.2 `int rtdm_irq_enable (rtdm_irq_t * irq_handle)`

Enable interrupt line.

Parameters:

↔ *irq_handle* IRQ handle as returned by `rtdm_irq_request()`

Returns:

0 on success, otherwise negative error code

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: possible.

5.13.3.3 `int rtdm_irq_free (rtdm_irq_t * irq_handle)`

Release an interrupt handler.

Parameters:

↔ *irq_handle* IRQ handle as returned by [rtdm_irq_request\(\)](#)

Returns:

0 on success, otherwise negative error code

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.13.3.4 `int rtdm_irq_request (rtdm_irq_t * irq_handle, unsigned int irq_no, rtdm_irq_handler_t handler, unsigned long flags, const char * device_name, void * arg)`

Register an interrupt handler.

This function registers the provided handler with an IRQ line and enables the line.

Parameters:

↔ *irq_handle* IRQ handle
 ← *irq_no* Line number of the addressed IRQ
 ← *handler* Interrupt handler
 ← *flags* Registration flags, see [RTDM_IRQTYPE_xxx](#) for details
 ← *device_name* Device name to show up in real-time IRQ lists
 ← *arg* Pointer to be passed to the interrupt handler on invocation

Returns:

0 on success, otherwise:

- -EINVAL is returned if an invalid parameter was passed.
- -EBUSY is returned if the specified IRQ line is already in use.

Environments:

This service can be called from:

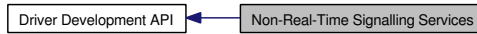
- Kernel module initialization/cleanup code

- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.14 Non-Real-Time Signalling Services

Collaboration diagram for Non-Real-Time Signalling Services:



5.14.1 Detailed Description

These services provide a mechanism to request the execution of a specified handler in non-real-time context. The triggering can safely be performed in real-time context without suffering from unknown delays. The handler execution will be deferred until the next time the real-time subsystem releases the CPU to the non-real-time part.

Typedefs

- typedef void(* [rt dm_nrtsig_handler_t](#))(rt dm_nrtsig_t nrt_sig, void *arg)
Non-real-time signal handler.

Functions

- int [rt dm_nrtsig_init](#) (rt dm_nrtsig_t *nrt_sig, [rt dm_nrtsig_handler_t](#) handler, void *arg)
Register a non-real-time signal handler.
- void [rt dm_nrtsig_destroy](#) (rt dm_nrtsig_t *nrt_sig)
Release a non-realtime signal handler.
- void [rt dm_nrtsig_pend](#) (rt dm_nrtsig_t *nrt_sig)
Trigger non-real-time signal.

5.14.2 Typedef Documentation

5.14.2.1 typedef void(* [rt dm_nrtsig_handler_t](#))(rt dm_nrtsig_t nrt_sig, void *arg)

Non-real-time signal handler.

Parameters:

- ← *nrt_sig* Signal handle as returned by [rt dm_nrtsig_init\(\)](#)
- ← *arg* Argument as passed to [rt dm_nrtsig_init\(\)](#)

Note:

The signal handler will run in soft-IRQ context of the non-real-time subsystem. Note the implications of this context, e.g. no invocation of blocking operations.

5.14.3 Function Documentation

5.14.3.1 `void rtdm_nrtsig_destroy (rtdm_nrtsig_t * nrt_sig)`

Release a non-realtime signal handler.

Parameters:

↔ *nrt_sig* Signal handle

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.14.3.2 `int rtdm_nrtsig_init (rtdm_nrtsig_t * nrt_sig, rtdm_nrtsig_handler_t handler, void * arg)`

Register a non-real-time signal handler.

Parameters:

↔ *nrt_sig* Signal handle

← *handler* Non-real-time signal handler

← *arg* Custom argument passed to `handler()` on each invocation

Returns:

0 on success, otherwise:

- -EAGAIN is returned if no free signal slot is available.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.14.3.3 void rtdm_nrtsig_pend (rtdm_nrtsig_t * *nrt_sig*)

Trigger non-real-time signal.

Parameters:

↔ *nrt_sig* Signal handle

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never in real-time context, possible in non-real-time environments.

5.15 Utility Services

Collaboration diagram for Utility Services:



Functions

- `int rtdm_mmap_to_user (rtdm_user_info_t *user_info, void *src_addr, size_t len, int prot, void **pptr, struct vm_operations_struct *vm_ops, void *vm_private_data)`
Map a kernel memory range into the address space of the user.
- `int rtdm_iomap_to_user (rtdm_user_info_t *user_info, unsigned long src_addr, size_t len, int prot, void **pptr, struct vm_operations_struct *vm_ops, void *vm_private_data)`
Map an I/O memory range into the address space of the user.
- `int rtdm_munmap (rtdm_user_info_t *user_info, void *ptr, size_t len)`
Unmap a user memory range.
- `void rtdm_printk (const char *format,...)`
Real-time safe message printing on kernel console.
- `void * rtdm_malloc (size_t size)`
Allocate memory block in real-time context.
- `void rtdm_free (void *ptr)`
Release real-time memory block.
- `int rtdm_read_user_ok (rtdm_user_info_t *user_info, const void __user *ptr, size_t size)`
Check if read access to user-space memory block is safe.
- `int rtdm_rw_user_ok (rtdm_user_info_t *user_info, const void __user *ptr, size_t size)`
Check if read/write access to user-space memory block is safe.
- `int rtdm_copy_from_user (rtdm_user_info_t *user_info, void *dst, const void __user *src, size_t size)`
Copy user-space memory block to specified buffer.
- `int rtdm_safe_copy_from_user (rtdm_user_info_t *user_info, void *dst, const void __user *src, size_t size)`
Check if read access to user-space memory block and copy it to specified buffer.
- `int rtdm_copy_to_user (rtdm_user_info_t *user_info, void __user *dst, const void *src, size_t size)`
Copy specified buffer to user-space memory block.
- `int rtdm_safe_copy_to_user (rtdm_user_info_t *user_info, void __user *dst, const void *src, size_t size)`

Check if read/write access to user-space memory block is safe and copy specified buffer to it.

- `int rtdm_strncpy_from_user` (`rtdm_user_info_t *user_info`, `char *dst`, `const char __user *src`, `size_t count`)

Copy user-space string to specified buffer.

- `int rtdm_in_rt_context` (`void`)

Test if running in a real-time task.

5.15.1 Function Documentation

5.15.1.1 `int rtdm_copy_from_user` (`rtdm_user_info_t * user_info`, `void * dst`, `const void __user * src`, `size_t size`)

Copy user-space memory block to specified buffer.

Parameters:

- ← *user_info* User information pointer as passed to the invoked device operation handler
- ← *dst* Destination buffer address
- ← *src* Address of the user-space memory block
- ← *size* Size of the memory block

Returns:

0 on success, otherwise:

- -EFAULT is returned if an invalid memory area was accessed.

Note:

Before invoking this service, verify via `rtdm_read_user_ok()` that the provided user-space address can securely be accessed.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.15.1.2 `int rtdm_copy_to_user` (`rtdm_user_info_t * user_info`, `void __user * dst`, `const void * src`, `size_t size`)

Copy specified buffer to user-space memory block.

Parameters:

- ← *user_info* User information pointer as passed to the invoked device operation handler
- ← *dst* Address of the user-space memory block
- ← *src* Source buffer address
- ← *size* Size of the memory block

Returns:

0 on success, otherwise:

- -EFAULT is returned if an invalid memory area was accessed.

Note:

Before invoking this service, verify via [rt dm_rw_user_ok\(\)](#) that the provided user-space address can securely be accessed.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.15.1.3 void rt dm_free (void * ptr)

Release real-time memory block.

Parameters:

- ← *ptr* Pointer to memory block as returned by [rt dm_malloc\(\)](#)

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine (consider the overhead!)
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.15.1.4 `int rtdm_in_rt_context (void)`

Test if running in a real-time task.

Returns:

Non-zero is returned if the caller resides in real-time context, 0 otherwise.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.15.1.5 `int rtdm_iomap_to_user (rtdm_user_info_t * user_info, unsigned long src_addr, size_t len, int prot, void ** pptr, struct vm_operations_struct * vm_ops, void * vm_private_data)`

Map an I/O memory range into the address space of the user.

Parameters:

- ← *user_info* User information pointer as passed to the invoked device operation handler
- ← *src_addr* physical I/O address to be mapped
- ← *len* Length of the memory range
- ← *prot* Protection flags for the user's memory range, typically either PROT_READ or PROT_READ|PROT_WRITE
- ↔ *pptr* Address of a pointer containing the desired user address or NULL on entry and the finally assigned address on return
- ← *vm_ops* vm_operations to be executed on the vma_area of the user memory range or NULL
- ← *vm_private_data* Private data to be stored in the vma_area, primarily useful for vm_-operation handlers

Returns:

0 on success, otherwise (most common values):

- -EINVAL is returned if an invalid start address, size, or destination address was passed.
- -ENOMEM is returned if there is insufficient free memory or the limit of memory mapping for the user process was reached.
- -EAGAIN is returned if too much memory has been already locked by the user process.
- -EPERM *may* be returned if an illegal invocation environment is detected.

Note:

RTDM supports two models for unmapping the user memory range again. One is explicit unmapping via `rtdm_munmap()`, either performed when the user requests it via an IOCTL etc. or when the related device is closed. The other is automatic unmapping, triggered by the user invoking standard `munmap()` or by the termination of the related process. To track release of the mapping and therefore relinquishment of the referenced physical memory, the caller of `rtdm_iomap_to_user()` can pass a `vm_operations_struct` on invocation, defining a close handler for the `vm_area`. See Linux documentaion (e.g. Linux Device Drivers book) on virtual memory management for details.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- User-space task (non-RT)

Rescheduling: possible.

5.15.1.6 void* rtdm_malloc (size_t size)

Allocate memory block in real-time context.

Parameters:

← *size* Requested size of the memory block

Returns:

The pointer to the allocated block is returned on success, NULL otherwise.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine (consider the overhead!)
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.15.1.7 int rtdm_mmap_to_user (rtdm_user_info_t * user_info, void * src_addr, size_t len, int prot, void ** pptr, struct vm_operations_struct * vm_ops, void * vm_private_data)

Map a kernel memory range into the address space of the user.

Parameters:

← *user_info* User information pointer as passed to the invoked device operation handler

- ← *src_addr* Kernel virtual address to be mapped
- ← *len* Length of the memory range
- ← *prot* Protection flags for the user's memory range, typically either PROT_READ or PROT_READ|PROT_WRITE
- ↔ *pptr* Address of a pointer containing the desired user address or NULL on entry and the finally assigned address on return
- ← *vm_ops* vm_operations to be executed on the vma_area of the user memory range or NULL
- ← *vm_private_data* Private data to be stored in the vma_area, primarily useful for vm_-operation handlers

Returns:

0 on success, otherwise (most common values):

- -EINVAL is returned if an invalid start address, size, or destination address was passed.
- -ENOMEM is returned if there is insufficient free memory or the limit of memory mapping for the user process was reached.
- -EAGAIN is returned if too much memory has been already locked by the user process.
- -EPERM *may* be returned if an illegal invocation environment is detected.

Note:

This service only works on memory regions allocated via kmalloc() or vmalloc(). To map physical I/O memory to user-space use [rtdm_iomap_to_user\(\)](#) instead.

RTDM supports two models for unmapping the user memory range again. One is explicit unmapping via [rtdm_munmap\(\)](#), either performed when the user requests it via an IOCTL etc. or when the related device is closed. The other is automatic unmapping, triggered by the user invoking standard munmap() or by the termination of the related process. To track release of the mapping and therefore relinquishment of the referenced physical memory, the caller of [rtdm_mmap_to_user\(\)](#) can pass a vm_operations_struct on invocation, defining a close handler for the vm_area. See Linux documentaion (e.g. Linux Device Drivers book) on virtual memory management for details.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- User-space task (non-RT)

Rescheduling: possible.

5.15.1.8 int rtdm_munmap (rtdm_user_info_t * user_info, void * ptr, size_t len)

Unmap a user memory range.

Parameters:

- ← *user_info* User information pointer as passed to `rtdm_mmap_to_user()` when requesting to map the memory range
- ← *ptr* User address or the memory range
- ← *len* Length of the memory range

Returns:

0 on success, otherwise:

- -EINVAL is returned if an invalid address or size was passed.
- -EPERM *may* be returned if an illegal invocation environment is detected.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- User-space task (non-RT)

Rescheduling: possible.

5.15.1.9 void rtdm_printk (const char * *format*, ...)

Real-time safe message printing on kernel console.

Parameters:

- ← *format* Format string (conforming standard `printf()`)
- ... Arguments referred by *format*

Returns:

On success, this service returns the number of characters printed. Otherwise, a negative error code is returned.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Interrupt service routine (consider the overhead!)
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never in real-time context, possible in non-real-time environments.

5.15.1.10 `int rtdm_read_user_ok (rtdm_user_info_t * user_info, const void __user * ptr, size_t size)`

Check if read access to user-space memory block is safe.

Parameters:

- ← *user_info* User information pointer as passed to the invoked device operation handler
- ← *ptr* Address of the user-provided memory block
- ← *size* Size of the memory block

Returns:

Non-zero is return when it is safe to read from the specified memory block, 0 otherwise.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.15.1.11 `int rtdm_rw_user_ok (rtdm_user_info_t * user_info, const void __user * ptr, size_t size)`

Check if read/write access to user-space memory block is safe.

Parameters:

- ← *user_info* User information pointer as passed to the invoked device operation handler
- ← *ptr* Address of the user-provided memory block
- ← *size* Size of the memory block

Returns:

Non-zero is return when it is safe to read from or write to the specified memory block, 0 otherwise.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.15.1.12 `int rtdm_safe_copy_from_user (rtdm_user_info_t * user_info, void * dst, const void __user * src, size_t size)`

Check if read access to user-space memory block and copy it to specified buffer.

Parameters:

- ← *user_info* User information pointer as passed to the invoked device operation handler
- ← *dst* Destination buffer address
- ← *src* Address of the user-space memory block
- ← *size* Size of the memory block

Returns:

0 on success, otherwise:

- -EFAULT is returned if an invalid memory area was accessed.

Note:

This service is a combination of `rtdm_read_user_ok` and `rtdm_copy_from_user`.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.15.1.13 `int rtdm_safe_copy_to_user (rtdm_user_info_t * user_info, void __user * dst, const void * src, size_t size)`

Check if read/write access to user-space memory block is safe and copy specified buffer to it.

Parameters:

- ← *user_info* User information pointer as passed to the invoked device operation handler
- ← *dst* Address of the user-space memory block
- ← *src* Source buffer address
- ← *size* Size of the memory block

Returns:

0 on success, otherwise:

- -EFAULT is returned if an invalid memory area was accessed.

Note:

This service is a combination of `rtdm_rw_user_ok` and `rtdm_copy_to_user`.

Environments:

This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.15.1.14 `int rtdm_strncpy_from_user (rtdm_user_info_t * user_info, char * dst, const char __user * src, size_t count)`

Copy user-space string to specified buffer.

Parameters:

- ← *user_info* User information pointer as passed to the invoked device operation handler
- ← *dst* Destination buffer address
- ← *src* Address of the user-space string
- ← *count* Maximum number of bytes to copy, including the trailing '0'

Returns:

Length of the string on success (not including the trailing '0'), otherwise:

- -EFAULT is returned if an invalid memory area was accessed.

Note:

This services already includes a check of the source address, calling `rtdm_read_user_ok()` for *src* explicitly is not required.

Environments:

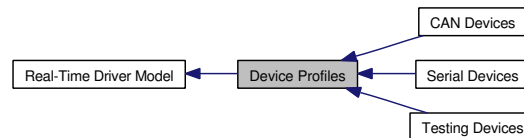
This service can be called from:

- Kernel module initialization/cleanup code
- Kernel-based task
- User-space task (RT, non-RT)

Rescheduling: never.

5.16 Device Profiles

Collaboration diagram for Device Profiles:



5.16.1 Detailed Description

Device profiles define which operation handlers a driver of a certain class has to implement, which name or protocol it has to register, which IOCTLs it has to provide, and further details. Sub-classes can be defined in order to extend a device profile with more hardware-specific functions.

Modules

- [CAN Devices](#)
- [Serial Devices](#)
- [Testing Devices](#)

Data Structures

- struct `rtdm_device_info`
Device information.

RTDM_CLASS_XXX

Device classes

- `#define RTDM_CLASS_PARPORT 1`
- `#define RTDM_CLASS_SERIAL 2`
- `#define RTDM_CLASS_CAN 3`
- `#define RTDM_CLASS_NETWORK 4`
- `#define RTDM_CLASS_RTMAC 5`
- `#define RTDM_CLASS_TESTING 6`
- `#define RTDM_CLASS_EXPERIMENTAL 224`
- `#define RTDM_CLASS_MAX 255`

Device Naming

Maximum length of device names (excluding the final null character)

- `#define RTDM_MAX_DEVNAME_LEN 31`

RTDM_PURGE_XXX_BUFFER

Flags selecting buffers to be purged

- `#define RTDM_PURGE_RX_BUFFER 0x0001`
- `#define RTDM_PURGE_TX_BUFFER 0x0002`

Common IOCTLs

The following IOCTLs are common to all device profiles.

- `#define RTIOC_DEVICE_INFO _IOR(RTIOC_TYPE_COMMON, 0x00, struct rtdm_device_info)`
Retrieve information about a device or socket.
- `#define RTIOC_PURGE _IOW(RTIOC_TYPE_COMMON, 0x10, int)`
Purge internal device or socket buffers.

5.16.2 Define Documentation

5.16.2.1 `#define RTIOC_DEVICE_INFO _IOR(RTIOC_TYPE_COMMON, 0x00, struct rtdm_device_info)`

Retrieve information about a device or socket.

Parameters:

→ *arg* Pointer to information buffer (struct [rtdm_device_info](#))

5.16.2.2 `#define RTIOC_PURGE _IOW(RTIOC_TYPE_COMMON, 0x10, int)`

Purge internal device or socket buffers.

Parameters:

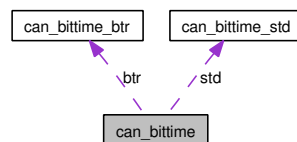
← *arg* Purge mask, see [RTDM_PURGE_XXX_BUFFER](#)

Chapter 6

Data Structure Documentation

6.1 `can_bittime` Struct Reference

Collaboration diagram for `can_bittime`:



6.1.1 Detailed Description

Custom CAN bit-time definition.

Examples:

[rtcanconfig.c](#).

Data Fields

- [can_bittime_type_t](#) `type`
Type of bit-time definition.
- struct [can_bittime_std](#) `std`
Standard bit-time.
- struct [can_bittime_btr](#) `btr`
Hardware-specific BTR bit-time.

The documentation for this struct was generated from the following file:

- `include/rtdm/rtcan.h`

6.2 can_bittime_btr Struct Reference

6.2.1 Detailed Description

Hardware-specific BTR bit-times.

Data Fields

- `uint8_t btr0`
Bus timing register 0.
- `uint8_t btr1`
Bus timing register 1.

The documentation for this struct was generated from the following file:

- `include/rtdm/rtcan.h`

6.3 can_bittime_std Struct Reference

6.3.1 Detailed Description

Standard bit-time parameters according to Bosch.

Data Fields

- uint32_t [brp](#)
Baud rate prescaler.
- uint8_t [prop_seg](#)
from 1 to 8
- uint8_t [phase_seg1](#)
from 1 to 8
- uint8_t [phase_seg2](#)
from 1 to 8
- uint8_t [sjw](#):7
from 1 to 4
- uint8_t [sam](#):1
1 - enable triple sampling

The documentation for this struct was generated from the following file:

- [include/rtdm/rtcan.h](#)

6.4 can_filter Struct Reference

6.4.1 Detailed Description

Filter for reception of CAN messages.

This filter works as follows: A received CAN ID is AND'ed bitwise with `can_mask` and then compared to `can_id`. This also includes the [CAN_EFF_FLAG](#) and [CAN_RTR_FLAG](#) of [CAN_XXX_FLAG](#). If this comparison is true, the message will be received by the socket. The logic can be inverted with the `can_id` flag [CAN_INV_FILTER](#) :

```
if (can_id & CAN_INV_FILTER) {
    if ((received_can_id & can_mask) != (can_id & ~CAN_INV_FILTER))
        accept-message;
} else {
    if ((received_can_id & can_mask) == can_id)
        accept-message;
}
```

Multiple filters can be arranged in a filter list and set with [Sockopts](#). If one of these filters matches a CAN ID upon reception of a CAN frame, this frame is accepted.

Examples:

[rtcan_rtt.c](#), and [rtcanrecv.c](#).

Data Fields

- `uint32_t` [can_id](#)
CAN ID which must match with incoming IDs after passing the mask.
- `uint32_t` [can_mask](#)
Mask which is applied to incoming IDs.

6.4.2 Field Documentation

6.4.2.1 `uint32_t can_filter::can_id`

CAN ID which must match with incoming IDs after passing the mask.

The filter logic can be inverted with the flag [CAN_INV_FILTER](#).

6.4.2.2 `uint32_t can_filter::can_mask`

Mask which is applied to incoming IDs.

See [CAN ID masks](#) if exactly one CAN ID should come through.

The documentation for this struct was generated from the following file:

- `include/rtm/rtdm/rtcan.h`

6.5 can_frame Struct Reference

6.5.1 Detailed Description

Raw CAN frame.

Central structure for receiving and sending CAN frames.

Examples:

[rtcan_rtt.c](#), [rtcanrecv.c](#), and [rtcansend.c](#).

Public Member Functions

- `uint8_t data[8] __attribute__\(\(aligned\(8\)\)\)`
Payload data bytes.

Data Fields

- `can_id_t can_id`
CAN ID of the frame.
- `uint8_t can_dlc`
Size of the payload in bytes.

6.5.2 Field Documentation

6.5.2.1 `can_id_t can_frame::can_id`

CAN ID of the frame.

See [CAN ID flags](#) for special bits.

Examples:

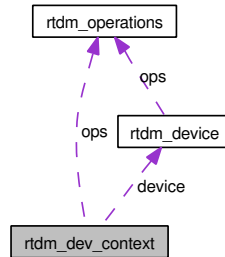
[rtcan_rtt.c](#).

The documentation for this struct was generated from the following file:

- `include/rtdm/rtcan.h`

6.6 rtdm_dev_context Struct Reference

Collaboration diagram for rtdm_dev_context:



6.6.1 Detailed Description

Device context.

A device context structure is associated with every open device instance. RTDM takes care of its creation and destruction and passes it to the operation handlers when being invoked.

Drivers can attach arbitrary data immediately after the official structure. The size of this data is provided via [rtdm_device.context_size](#) during device registration.

Data Fields

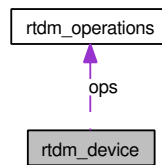
- unsigned long [context_flags](#)
Context flags, see [Context Flags](#) for details.
- int [fd](#)
Associated file descriptor.
- atomic_t [close_lock_count](#)
Lock counter of context, held while structure is referenced by an operation handler.
- struct [rtdm_operations](#) * [ops](#)
Set of active device operation handlers.
- struct [rtdm_device](#) * [device](#)
Reference to owning device.
- struct rtdm_devctx_reserved [reserved](#)
Data stored by RTDM inside a device context (internal use only).
- char [dev_private](#) [0]
Begin of driver defined context data structure.

The documentation for this struct was generated from the following file:

- [include/rtdm/rtdm_driver.h](#)

6.7 rtdm_device Struct Reference

Collaboration diagram for rtdm_device:



6.7.1 Detailed Description

RTDM device.

This structure specifies a RTDM device. As some fields, especially the reserved area, will be modified by RTDM during runtime, the structure must not reside in write-protected memory.

Data Fields

- `int struct_version`
Revision number of this structure, see [Driver Versioning](#) defines.
- `int device_flags`
Device flags, see [Device Flags](#) for details.
- `size_t context_size`
Size of driver defined appendix to struct `rtdm_dev_context`.
- `char device_name [RTDM_MAX_DEVNAME_LEN+1]`
Named device identification (orthogonal to Linux device name space).
- `int protocol_family`
Protocol device identification: protocol family (PF_XXX).
- `int socket_type`
Protocol device identification: socket type (SOCK_XXX).
- `rtdm_open_handler_t open_rt`
Named device instance creation for real-time contexts, optional if `open_nrt` is non-NULL, ignored for protocol devices.
- `rtdm_open_handler_t open_nrt`
Named device instance creation for non-real-time contexts, optional if `open_rt` is non-NULL, ignored for protocol devices.
- `rtdm_socket_handler_t socket_rt`
Protocol socket creation for real-time contexts, optional if `socket_nrt` is non-NULL, ignored for named devices.

- [rt dm_socket_handler_t socket_nrt](#)
Protocol socket creation for non-real-time contexts, optional if socket_rt is non-NULL, ignored for named devices.
- struct [rt dm_operations ops](#)
Default operations on newly opened device instance.
- int [device_class](#)
Device class ID, see [RTDM_CLASS_xxx](#).
- int [device_sub_class](#)
Device sub-class, see [RTDM_SUBCLASS_xxx](#) definition in the [Device Profiles](#).
- int [profile_version](#)
Supported device profile version.
- const char * [driver_name](#)
Informational driver name (reported via /proc).
- int [driver_version](#)
Driver version, see [Driver Versioning](#) defines.
- const char * [peripheral_name](#)
Informational peripheral name the device is attached to (reported via /proc).
- const char * [provider_name](#)
Informational driver provider name (reported via /proc).
- const char * [proc_name](#)
Name of /proc entry for the device, must not be NULL.
- struct proc_dir_entry * [proc_entry](#)
Set to device's /proc root entry after registration, do not modify.
- int [device_id](#)
Driver definable device ID.
- void * [device_data](#)
Driver definable device data.
- struct rt dm_dev_reserved [reserved](#)
Data stored by RTDM inside a registered device (internal use only).

The documentation for this struct was generated from the following file:

- [include/rt dm/rt dm_driver.h](#)

6.8 rtdm_device_info Struct Reference

6.8.1 Detailed Description

Device information.

Data Fields

- int [device_flags](#)
Device flags, see [Device Flags](#) for details.
- int [device_class](#)
Device class ID, see [RTDM_CLASS_xxx](#).
- int [device_sub_class](#)
Device sub-class, either [RTDM_SUBCLASS_GENERIC](#) or a [RTDM_SUBCLASS_xxx](#) definition of the related [Device Profile](#).
- int [profile_version](#)
Supported device profile version.

The documentation for this struct was generated from the following file:

- [include/rtdm/rtdm.h](#)

6.9 rtdm_operations Struct Reference

6.9.1 Detailed Description

Device operations.

Data Fields

Common Operations

- [rtdm_close_handler_t close_rt](#)
Close handler for real-time contexts (optional).
- [rtdm_close_handler_t close_nrt](#)
Close handler for non-real-time contexts (required).
- [rtdm_ioctl_handler_t ioctl_rt](#)
IOCTL from real-time context (optional).
- [rtdm_ioctl_handler_t ioctl_nrt](#)
IOCTL from non-real-time context (optional).
- [rtdm_select_bind_handler_t select_bind](#)
Select binding handler for any context (optional).

Stream-Oriented Device Operations

- [rtdm_read_handler_t read_rt](#)
Read handler for real-time context (optional).
- [rtdm_read_handler_t read_nrt](#)
Read handler for non-real-time context (optional).
- [rtdm_write_handler_t write_rt](#)
Write handler for real-time context (optional).
- [rtdm_write_handler_t write_nrt](#)
Write handler for non-real-time context (optional).

Message-Oriented Device Operations

- [rtdm_recvmsg_handler_t recvmsg_rt](#)
Receive message handler for real-time context (optional).
- [rtdm_recvmsg_handler_t recvmsg_nrt](#)
Receive message handler for non-real-time context (optional).
- [rtdm_sendmsg_handler_t sendmsg_rt](#)
Transmit message handler for real-time context (optional).

- [rtdm_sendmsg_handler_t sendmsg_nrt](#)

Transmit message handler for non-real-time context (optional).

The documentation for this struct was generated from the following file:

- [include/rtdm/rtdm_driver.h](#)

6.10 rtser_config Struct Reference

6.10.1 Detailed Description

Serial device configuration.

Examples:

[cross-link.c](#).

Data Fields

- int [config_mask](#)
mask specifying valid fields, see [RTSER_SET_xxx](#)
- int [baud_rate](#)
baud rate, default [RTSER_DEF_BAUD](#)
- int [parity](#)
number of parity bits, see [RTSER_xxx_PARITY](#)
- int [data_bits](#)
number of data bits, see [RTSER_xxx_BITS](#)
- int [stop_bits](#)
number of stop bits, see [RTSER_xxx_STOPB](#)
- int [handshake](#)
handshake mechanisms, see [RTSER_xxx_HAND](#)
- int [fifo_depth](#)
reception FIFO interrupt threshold, see [RTSER_FIFO_xxx](#)
- [nanosecs_rel_t rx_timeout](#)
reception timeout, see [RTSER_TIMEOUT_xxx](#) for special values
- [nanosecs_rel_t tx_timeout](#)
transmission timeout, see [RTSER_TIMEOUT_xxx](#) for special values
- [nanosecs_rel_t event_timeout](#)
event timeout, see [RTSER_TIMEOUT_xxx](#) for special values
- int [timestamp_history](#)
enable timestamp history, see [RTSER_xxx_TIMESTAMP_HISTORY](#)
- int [event_mask](#)
event mask to be used with [RTSER_RTIOC_WAIT_EVENT](#), see [RTSER_EVENT_xxx](#)

The documentation for this struct was generated from the following file:

- [include/rtdm/rtserial.h](#)

6.11 rtser_event Struct Reference

6.11.1 Detailed Description

Additional information about serial device events.

Examples:

[cross-link.c](#).

Data Fields

- int [events](#)
signalled events, see [RTSER_EVENT_xxx](#)
- int [rx_pending](#)
number of pending input characters
- [nanosecs_abs_t last_timestamp](#)
last interrupt timestamp
- [nanosecs_abs_t rxpend_timestamp](#)
reception timestamp of oldest character in input queue

The documentation for this struct was generated from the following file:

- [include/rtdm/rtserial.h](#)

6.12 rtser_status Struct Reference

6.12.1 Detailed Description

Serial device status.

Data Fields

- int [line_status](#)
line status register, see [RTSER_LSR_xxx](#)
- int [modem_status](#)
modem status register, see [RTSER_MSR_xxx](#)

The documentation for this struct was generated from the following file:

- [include/rtdm/rtserial.h](#)

6.13 sockaddr_can Struct Reference

6.13.1 Detailed Description

Socket address structure for the CAN address family.

Examples:

[rtcan_rtt.c](#), [rtcanrecv.c](#), and [rtcansend.c](#).

Data Fields

- `sa_family_t can_family`
CAN address family, must be AF_CAN.
- `int can_ifindex`
Interface index of CAN controller.

6.13.2 Field Documentation

6.13.2.1 `int sockaddr_can::can_ifindex`

Interface index of CAN controller.

See [SIOCGIFINDEX](#).

The documentation for this struct was generated from the following file:

- `include/rtdm/rtcan.h`

Chapter 7

File Documentation

7.1 `include/rtdm/rtdmcan.h` File Reference

7.1.1 Detailed Description

Real-Time Driver Model for RT-Socket-CAN, CAN device profile header.

Note:

Copyright (C) 2006 Wolfgang Grandegger <wg@grandegger.com>

Copyright (C) 2005, 2006 Sebastian Smolorz <Sebastian.Smolorz@stud.uni-hannover.de>

This RTDM CAN device profile header is based on:

`include/linux/can.h`, `include/linux/socket.h`, `net/can/pf_can.h` in `linux-can.patch`, a CAN socket framework for Linux

Copyright (C) 2004, 2005, Robert Schwebel, Benedikt Spranger, Marc Kleine-Budde, Pengutronix

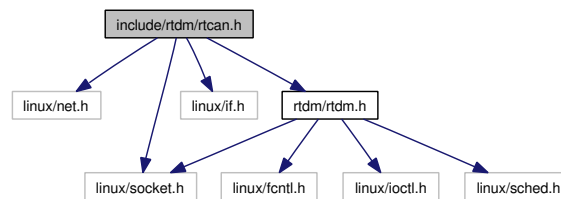
This program is free software; you can redistribute it and/or modify it under the terms of the GNU General Public License as published by the Free Software Foundation; either version 2 of the License, or (at your option) any later version.

This program is distributed in the hope that it will be useful, but WITHOUT ANY WARRANTY; without even the implied warranty of MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE. See the GNU

General Public License for more details.

You should have received a copy of the GNU General Public License along with this program; if not, write to the Free Software Foundation, Inc., 59 Temple Place - Suite 330, Boston, MA 02111-1307, USA.

Include dependency graph for `rtcan.h`:



Data Structures

- struct [can_bittime_std](#)
Standard bit-time parameters according to Bosch.
- struct [can_bittime_btr](#)
Hardware-specific BTR bit-times.
- struct [can_bittime](#)
Custom CAN bit-time definition.
- struct [can_filter](#)
Filter for reception of CAN messages.
- struct [sockaddr_can](#)
Socket address structure for the CAN address family.
- struct [can_frame](#)
Raw CAN frame.

Defines

- `#define` [AF_CAN](#) 29
CAN address family.
- `#define` [PF_CAN](#) `AF_CAN`
CAN protocol family.
- `#define` [SOL_CAN_RAW](#) 103
CAN socket levels.

CAN ID masks

Bit masks for masking CAN IDs

- `#define` [CAN_EFF_MASK](#) `0x1FFFFFFF`
Bit mask for extended CAN IDs.

- #define [CAN_SFF_MASK](#) 0x000007FF
Bit mask for standard CAN IDs.

CAN ID flags

Flags within a CAN ID indicating special CAN frame attributes

- #define [CAN_EFF_FLAG](#) 0x80000000
Extended frame.
- #define [CAN_RTR_FLAG](#) 0x40000000
Remote transmission frame.
- #define [CAN_ERR_FLAG](#) 0x20000000
Error frame (see [Errors](#)), not valid in struct [can_filter](#).
- #define [CAN_INV_FILTER](#) [CAN_ERR_FLAG](#)
Invert CAN filter definition, only valid in struct [can_filter](#).

Particular CAN protocols

Possible protocols for the PF_CAN protocol family

Currently only the RAW protocol is supported.

- #define [CAN_RAW](#) 1
Raw protocol of PF_CAN, applicable to socket type SOCK_RAW.

CAN controller modes

Special CAN controllers modes, which can be or'ed together.

Note:

These modes are hardware-dependent. Please consult the hardware manual of the CAN controller for more detailed information.

- #define [CAN_CTRLMODE_LISTENONLY](#) 0x1
- #define [CAN_CTRLMODE_LOOPBACK](#) 0x2

Timestamp switches

Arguments to pass to [RTCAN_RTIOC_TAKE_TIMESTAMP](#)

- #define [RTCAN_TAKE_NO_TIMESTAMPS](#) 0
Switch off taking timestamps.
- #define [RTCAN_TAKE_TIMESTAMPS](#) 1
Do take timestamps.

RAW socket options

Setting and getting CAN RAW socket options.

- #define [CAN_RAW_FILTER](#) 0x1

CAN filter definition.

- #define [CAN_RAW_ERR_FILTER](#) 0x2
CAN error mask.
- #define [CAN_RAW_LOOPBACK](#) 0x3
CAN TX loopback.
- #define [CAN_RAW_RECV_OWN_MSGS](#) 0x4
CAN receive own messages.

IOCTLs

CAN device IOCTLs

- #define [SIOCGIFINDEX](#) defined_by_kernel_header_file
Get CAN interface index by name.
- #define [SIOCSCANBAUDRATE](#) _IOW(RTIOC_TYPE_CAN, 0x01, struct ifreq)
Set baud rate.
- #define [SIOCGCANBAUDRATE](#) _IOWR(RTIOC_TYPE_CAN, 0x02, struct ifreq)
Get baud rate.
- #define [SIOCSCANCUSTOMBITTIME](#) _IOW(RTIOC_TYPE_CAN, 0x03, struct ifreq)
Set custom bit time parameter.
- #define [SIOCGCANCUSTOMBITTIME](#) _IOWR(RTIOC_TYPE_CAN, 0x04, struct ifreq)
Get custom bit-time parameters.
- #define [SIOCSCANMODE](#) _IOW(RTIOC_TYPE_CAN, 0x05, struct ifreq)
Set operation mode of CAN controller.
- #define [SIOCGCANSTATE](#) _IOWR(RTIOC_TYPE_CAN, 0x06, struct ifreq)
Get current state of CAN controller.
- #define [SIOCSCANCTRLMODE](#) _IOW(RTIOC_TYPE_CAN, 0x07, struct ifreq)
Set special controller modes.
- #define [SIOCGCANCTRLMODE](#) _IOWR(RTIOC_TYPE_CAN, 0x08, struct ifreq)
Get special controller modes.
- #define [RTCAN_RTIOC_TAKE_TIMESTAMP](#) _IOW(RTIOC_TYPE_CAN, 0x09, int)
Enable or disable storing a high precision timestamp upon reception of a CAN frame.
- #define [RTCAN_RTIOC_RCV_TIMEOUT](#) _IOW(RTIOC_TYPE_CAN, 0x0A, nanosecs_rel_t)
Specify a reception timeout for a socket.
- #define [RTCAN_RTIOC_SND_TIMEOUT](#) _IOW(RTIOC_TYPE_CAN, 0x0B, nanosecs_rel_t)
Specify a transmission timeout for a socket.

Error mask

Error class (mask) in `can_id` field of struct `can_frame` to be used with `CAN_RAW_ERR_FILTER`.

Note: Error reporting is hardware dependent and most CAN controllers report less detailed error conditions than the SJA1000.

Note: In case of a bus-off error condition (`CAN_ERR_BUSOFF`), the CAN controller is **not** restarted automatically. It is the application's responsibility to react appropriately, e.g. calling `CAN_MODE_START`.

Note: Bus error interrupts (`CAN_ERR_BUSERROR`) are enabled when an application is calling a `Recv` function on a socket listening on bus errors (using `CAN_RAW_ERR_FILTER`). After one bus error has occurred, the interrupt will be disabled to allow the application time for error processing and to efficiently avoid bus error interrupt flooding.

- `#define CAN_ERR_TX_TIMEOUT 0x00000001U`
TX timeout (netdevice driver).
- `#define CAN_ERR_LOSTARB 0x00000002U`
Lost arbitration (see `data[0]`).
- `#define CAN_ERR_CRTL 0x00000004U`
Controller problems (see `data[1]`).
- `#define CAN_ERR_PROT 0x00000008U`
Protocol violations (see `data[2]`, `data[3]`).
- `#define CAN_ERR_TRX 0x00000010U`
Transceiver status (see `data[4]`).
- `#define CAN_ERR_ACK 0x00000020U`
Received no ACK on transmission.
- `#define CAN_ERR_BUSOFF 0x00000040U`
Bus off.
- `#define CAN_ERR_BUSERROR 0x00000080U`
Bus error (may flood!).
- `#define CAN_ERR_RESTARTED 0x00000100U`
Controller restarted.
- `#define CAN_ERR_MASK 0x1FFFFFFFU`
Omit EFF, RTR, ERR flags.

Arbitration lost error

Error in the `data[0]` field of struct `can_frame`.

- `#define CAN_ERR_LOSTARB_UNSPEC 0x00`
unspecified

Controller problems

Error in the `data[1]` field of struct `can_frame`.

- #define [CAN_ERR_CTRL_UNSPEC](#) 0x00
unspecified
- #define [CAN_ERR_CTRL_RX_OVERFLOW](#) 0x01
RX buffer overflow.
- #define [CAN_ERR_CTRL_TX_OVERFLOW](#) 0x02
TX buffer overflow.
- #define [CAN_ERR_CTRL_RX_WARNING](#) 0x04
reached warning level for RX errors
- #define [CAN_ERR_CTRL_TX_WARNING](#) 0x08
reached warning level for TX errors
- #define [CAN_ERR_CTRL_RX_PASSIVE](#) 0x10
reached passive level for RX errors
- #define [CAN_ERR_CTRL_TX_PASSIVE](#) 0x20
reached passive level for TX errors

Protocol error type

Error in the `data[2]` field of struct [can_frame](#).

- #define [CAN_ERR_PROT_UNSPEC](#) 0x00
unspecified
- #define [CAN_ERR_PROT_BIT](#) 0x01
single bit error
- #define [CAN_ERR_PROT_FORM](#) 0x02
frame format error
- #define [CAN_ERR_PROT_STUFF](#) 0x04
bit stuffing error
- #define [CAN_ERR_PROT_BIT0](#) 0x08
unable to send dominant bit
- #define [CAN_ERR_PROT_BIT1](#) 0x10
unable to send recessive bit
- #define [CAN_ERR_PROT_OVERLOAD](#) 0x20
bus overload
- #define [CAN_ERR_PROT_ACTIVE](#) 0x40
active error announcement
- #define [CAN_ERR_PROT_TX](#) 0x80
error occurred on transmission

Protocol error location

Error in the `data[3]` field of struct `can_frame`.

- #define `CAN_ERR_PROT_LOC_UNSPEC` 0x00
unspecified
- #define `CAN_ERR_PROT_LOC_SOF` 0x03
start of frame
- #define `CAN_ERR_PROT_LOC_ID28_21` 0x02
ID bits 28 - 21 (SFF: 10 - 3).
- #define `CAN_ERR_PROT_LOC_ID20_18` 0x06
ID bits 20 - 18 (SFF: 2 - 0).
- #define `CAN_ERR_PROT_LOC_SRTR` 0x04
substitute RTR (SFF: RTR)
- #define `CAN_ERR_PROT_LOC_IDE` 0x05
identifier extension
- #define `CAN_ERR_PROT_LOC_ID17_13` 0x07
ID bits 17-13.
- #define `CAN_ERR_PROT_LOC_ID12_05` 0x0F
ID bits 12-5.
- #define `CAN_ERR_PROT_LOC_ID04_00` 0x0E
ID bits 4-0.
- #define `CAN_ERR_PROT_LOC_RTR` 0x0C
RTR.
- #define `CAN_ERR_PROT_LOC_RES1` 0x0D
reserved bit 1
- #define `CAN_ERR_PROT_LOC_RES0` 0x09
reserved bit 0
- #define `CAN_ERR_PROT_LOC_DLC` 0x0B
data length code
- #define `CAN_ERR_PROT_LOC_DATA` 0x0A
data section
- #define `CAN_ERR_PROT_LOC_CRC_SEQ` 0x08
CRC sequence.
- #define `CAN_ERR_PROT_LOC_CRC_DEL` 0x18
CRC delimiter.
- #define `CAN_ERR_PROT_LOC_ACK` 0x19
ACK slot.

- #define [CAN_ERR_PROT_LOC_ACK_DEL](#) 0x1B
ACK delimiter.
- #define [CAN_ERR_PROT_LOC_EOF](#) 0x1A
end of frame
- #define [CAN_ERR_PROT_LOC_INTERM](#) 0x12
intermission

Protocol error location

Error in the `data[4]` field of struct [can_frame](#).

- #define [CAN_ERR_TRX_UNSPEC](#) 0x00
0000 0000
- #define [CAN_ERR_TRX_CANH_NO_WIRE](#) 0x04
0000 0100
- #define [CAN_ERR_TRX_CANH_SHORT_TO_BAT](#) 0x05
0000 0101
- #define [CAN_ERR_TRX_CANH_SHORT_TO_VCC](#) 0x06
0000 0110
- #define [CAN_ERR_TRX_CANH_SHORT_TO_GND](#) 0x07
0000 0111
- #define [CAN_ERR_TRX_CANL_NO_WIRE](#) 0x40
0100 0000
- #define [CAN_ERR_TRX_CANL_SHORT_TO_BAT](#) 0x50
0101 0000
- #define [CAN_ERR_TRX_CANL_SHORT_TO_VCC](#) 0x60
0110 0000
- #define [CAN_ERR_TRX_CANL_SHORT_TO_GND](#) 0x70
0111 0000
- #define [CAN_ERR_TRX_CANL_SHORT_TO_CANH](#) 0x80
1000 0000

Typedefs

- typedef uint32_t [can_id_t](#)
Type of CAN id (see [CAN_xxx_MASK](#) and [CAN_xxx_FLAG](#)).
- typedef [can_id_t](#) [can_err_mask_t](#)
Type of CAN error mask.

- typedef uint32_t [can_baudrate_t](#)
Baudrate definition in bits per second.
- typedef enum [CAN_BITTIME_TYPE](#) [can_bittime_type_t](#)
See [CAN_BITTIME_TYPE](#).
- typedef enum [CAN_MODE](#) [can_mode_t](#)
See [CAN_MODE](#).
- typedef int [can_ctrlmode_t](#)
See [CAN_CTRLMODE](#).
- typedef enum [CAN_STATE](#) [can_state_t](#)
See [CAN_STATE](#).

Enumerations

- enum [CAN_BITTIME_TYPE](#) { [CAN_BITTIME_STD](#), [CAN_BITTIME_BTR](#) }
Supported CAN bit-time types.

CAN operation modes

Modes into which CAN controllers can be set

- enum [CAN_MODE](#) { [CAN_MODE_STOP](#) = 0, [CAN_MODE_START](#), [CAN_MODE_SLEEP](#) }

CAN controller states

States a CAN controller can be in.

- enum [CAN_STATE](#) {
 [CAN_STATE_ACTIVE](#) = 0, [CAN_STATE_BUS_WARNING](#), [CAN_STATE_BUS_PASSIVE](#), [CAN_STATE_BUS_OFF](#),
 [CAN_STATE_SCANNING_BAUDRATE](#), [CAN_STATE_STOPPED](#), [CAN_STATE_SLEEPING](#) }

7.2 include/rtdm/rtdm.h File Reference

7.2.1 Detailed Description

Real-Time Driver Model for Xenomai, user API header.

Note:

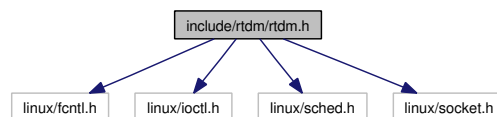
Copyright (C) 2005, 2006 Jan Kiszka <jan.kiszka@web.de>
 Copyright (C) 2005 Joerg Langenberg <joerg.langenberg@gmx.net>

Xenomai is free software; you can redistribute it and/or modify it under the terms of the GNU General Public License as published by the Free Software Foundation; either version 2 of the License, or (at your option) any later version.

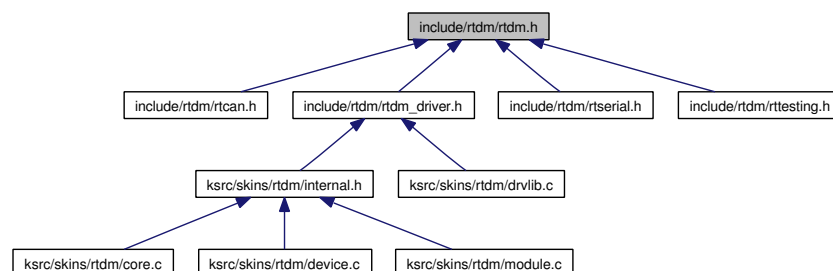
Xenomai is distributed in the hope that it will be useful, but WITHOUT ANY WARRANTY; without even the implied warranty of MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE. See the GNU General Public License for more details.

You should have received a copy of the GNU General Public License along with Xenomai; if not, write to the Free Software Foundation, Inc., 59 Temple Place - Suite 330, Boston, MA 02111-1307, USA.

Include dependency graph for rtdm.h:



This graph shows which files directly or indirectly include this file:



Data Structures

- struct [rtdm_device_info](#)
Device information.

Defines

API Versioning

- #define **RTDM_API_VER** 7
Common user and driver API version.
- #define **RTDM_API_MIN_COMPAT_VER** 6
Minimum API revision compatible with the current release.

RTDM_TIMEOUT_XXX

Special timeout values

- #define **RTDM_TIMEOUT_INFINITE** 0
Block forever.
- #define **RTDM_TIMEOUT_NONE** (-1)
Any negative timeout means non-blocking.

RTDM_CLASS_XXX

Device classes

- #define **RTDM_CLASS_PARPORT** 1
- #define **RTDM_CLASS_SERIAL** 2
- #define **RTDM_CLASS_CAN** 3
- #define **RTDM_CLASS_NETWORK** 4
- #define **RTDM_CLASS_RTMAC** 5
- #define **RTDM_CLASS_TESTING** 6
- #define **RTDM_CLASS_EXPERIMENTAL** 224
- #define **RTDM_CLASS_MAX** 255

Device Naming

Maximum length of device names (excluding the final null character)

- #define **RTDM_MAX_DEVNAME_LEN** 31

RTDM_PURGE_XXX_BUFFER

Flags selecting buffers to be purged

- #define **RTDM_PURGE_RX_BUFFER** 0x0001
- #define **RTDM_PURGE_TX_BUFFER** 0x0002

Common IOCTLs

The following IOCTLs are common to all device profiles.

- #define **RTIOC_DEVICE_INFO** _IOR(RTIOC_TYPE_COMMON, 0x00, struct rtdm_device_info)
Retrieve information about a device or socket.
- #define **RTIOC_PURGE** _IOW(RTIOC_TYPE_COMMON, 0x10, int)
Purge internal device or socket buffers.

Typedefs

- typedef uint64_t [nanosecs_abs_t](#)
RTDM type for representing absolute dates.
- typedef int64_t [nanosecs_rel_t](#)
RTDM type for representing relative intervals.

7.3 include/rtdm/rtdm_driver.h File Reference

7.3.1 Detailed Description

Real-Time Driver Model for Xenomai, driver API header.

Note:

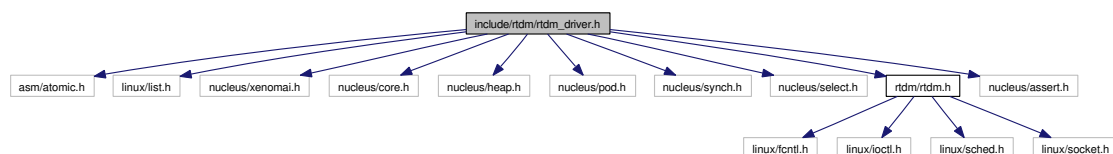
Copyright (C) 2005-2007 Jan Kiszka <jan.kiszka@web.de>
 Copyright (C) 2005 Joerg Langenberg <joerg.langenberg@gmx.net>
 Copyright (C) 2008 Gilles Chanteperdrix <gilles.chanteperdrix@gmail.com>

Xenomai is free software; you can redistribute it and/or modify it under the terms of the GNU General Public License as published by the Free Software Foundation; either version 2 of the License, or (at your option) any later version.

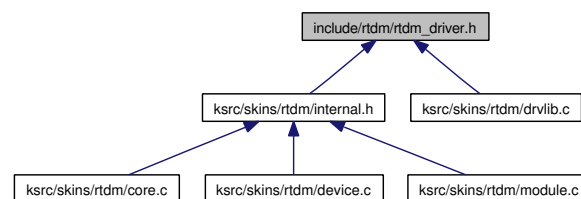
Xenomai is distributed in the hope that it will be useful, but WITHOUT ANY WARRANTY; without even the implied warranty of MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE. See the GNU General Public License for more details.

You should have received a copy of the GNU General Public License along with Xenomai; if not, write to the Free Software Foundation, Inc., 59 Temple Place - Suite 330, Boston, MA 02111-1307, USA.

Include dependency graph for rtdm_driver.h:



This graph shows which files directly or indirectly include this file:



Data Structures

- struct [rtdm_operations](#)
Device operations.
- struct [rtdm_dev_context](#)
Device context.
- struct [rtdm_device](#)
RTDM device.

Spinlock with Preemption Deactivation

- #define `RTDM_LOCK_UNLOCKED` `RTHAL_SPIN_LOCK_UNLOCKED`
Static lock initialisation.
- #define `rtdm_lock_init(lock)` `rthal_spin_lock_init(lock)`
Dynamic lock initialisation.
- #define `rtdm_lock_get(lock)` `rthal_spin_lock(lock)`
Acquire lock from non-preemptible contexts.
- #define `rtdm_lock_put(lock)` `rthal_spin_unlock(lock)`
Release lock without preemption restoration.
- #define `rtdm_lock_get_irqsave(lock, context)` `rthal_spin_lock_irqsave(lock, context)`
Acquire lock and disable preemption.
- #define `rtdm_lock_put_irqrestore(lock, context)` `rthal_spin_unlock_irqrestore(lock, context)`
Release lock and restore preemption state.
- #define `rtdm_lock_irqsave(context)` `rthal_local_irq_save(context)`
Disable preemption locally.
- #define `rtdm_lock_irqrestore(context)` `rthal_local_irq_restore(context)`
Restore preemption state.
- typedef `rthal_spinlock_t` `rtdm_lock_t`
Lock variable.
- typedef unsigned long `rtdm_lockctx_t`
Variable to save the context while holding a lock.

Defines

- #define `rtdm_irq_get_arg(irq_handle, type)` `((type *)irq_handle → cookie)`
Retrieve IRQ handler argument.

Device Flags

Static flags describing a RTDM device

- #define `RTDM_EXCLUSIVE` `0x0001`
If set, only a single instance of the device can be requested by an application.
- #define `RTDM_NAMED_DEVICE` `0x0010`
If set, the device is addressed via a clear-text name.
- #define `RTDM_PROTOCOL_DEVICE` `0x0020`

If set, the device is addressed via a combination of protocol ID and socket type.

- #define [RTDM_DEVICE_TYPE_MASK](#) 0x00F0
Mask selecting the device type.

Context Flags

Dynamic flags describing the state of an open RTDM device (bit numbers)

- #define [RTDM_CREATED_IN_NRT](#) 0
Set by RTDM if the device instance was created in non-real-time context.
- #define [RTDM_CLOSING](#) 1
Set by RTDM when the device is being closed.
- #define [RTDM_USER_CONTEXT_FLAG](#) 8
Lowest bit number the driver developer can use freely.

Driver Versioning

Current revisions of RTDM structures, encoding of driver versions. See [API Versioning](#) for the interface revision.

- #define [RTDM_DEVICE_STRUCT_VER](#) 5
Version of struct [rtdm_device](#).
- #define [RTDM_CONTEXT_STRUCT_VER](#) 3
Version of struct [rtdm_dev_context](#).
- #define [RTDM_SECURE_DEVICE](#) 0x80000000
Flag indicating a secure variant of RTDM (not supported here).
- #define [RTDM_DRIVER_VER](#)(major, minor, patch) (((major & 0xFF) << 16) | ((minor & 0xFF) << 8) | (patch & 0xFF))
Version code constructor for driver revisions.
- #define [RTDM_DRIVER_MAJOR_VER](#)(ver) (((ver) >> 16) & 0xFF)
Get major version number from driver revision code.
- #define [RTDM_DRIVER_MINOR_VER](#)(ver) (((ver) >> 8) & 0xFF)
Get minor version number from driver revision code.
- #define [RTDM_DRIVER_PATCH_VER](#)(ver) ((ver) & 0xFF)
Get patch version number from driver revision code.

Global Lock across Scheduler Invocation

- #define [RTDM_EXECUTE_ATOMICALY](#)(code_block)
Execute code block atomically.

RTDM_IRQTYPE_xxx

Interrupt registrations flags

- `#define RTDM_IRQTYPE_SHARED XN_ISR_SHARED`
Enable IRQ-sharing with other real-time drivers.
- `#define RTDM_IRQTYPE_EDGE XN_ISR_EDGE`
Mark IRQ as edge-triggered, relevant for correct handling of shared edge-triggered IRQs.

RTDM_IRQ_XXX

Return flags of interrupt handlers

- `#define RTDM_IRQ_NONE XN_ISR_NONE`
Unhandled interrupt.
- `#define RTDM_IRQ_HANDLED XN_ISR_HANDLED`
Denote handled interrupt.

Task Priority Range

Maximum and minimum task priorities

- `#define RTDM_TASK_LOWEST_PRIORITY XNCORE_LOW_PRIO`
- `#define RTDM_TASK_HIGHEST_PRIORITY XNCORE_HIGH_PRIO`

Task Priority Modification

Raise or lower task priorities by one level

- `#define RTDM_TASK_RAISE_PRIORITY (+1)`
- `#define RTDM_TASK_LOWER_PRIORITY (-1)`

Typedefs

- `typedef int(* rtdm_irq_handler_t)(rtdm_irq_t *irq_handle)`
Interrupt handler.
- `typedef void(* rtdm_nrtsig_handler_t)(rtdm_nrtsig_t nrt_sig, void *arg)`
Non-real-time signal handler.
- `typedef void(* rtdm_timer_handler_t)(rtdm_timer_t *timer)`
Timer handler.
- `typedef void(* rtdm_task_proc_t)(void *arg)`
Real-time task procedure.

Operation Handler Prototypes

- `typedef int(* rtdm_open_handler_t)(struct rtdm_dev_context *context, rtdm_user_info_t *user_info, int oflag)`
Named device open handler.
- `typedef int(* rtdm_socket_handler_t)(struct rtdm_dev_context *context, rtdm_user_info_t *user_info, int protocol)`

Socket creation handler for protocol devices.

- typedef int(* [rtdm_close_handler_t](#))(struct [rtdm_dev_context](#) *context, [rtdm_user_info_t](#) *user_info)
Close handler.
- typedef int(* [rtdm_ioctl_handler_t](#))(struct [rtdm_dev_context](#) *context, [rtdm_user_info_t](#) *user_info, unsigned int request, void __user *arg)
IOCTL handler.
- typedef int(* [rtdm_select_bind_handler_t](#))(struct [rtdm_dev_context](#) *context, [rtdm_selector_t](#) *selector, enum [rtdm_selecttype](#) type, unsigned fd_index)
Select binding handler.
- typedef ssize_t(* [rtdm_read_handler_t](#))(struct [rtdm_dev_context](#) *context, [rtdm_user_info_t](#) *user_info, void *buf, size_t nbyte)
Read handler.
- typedef ssize_t(* [rtdm_write_handler_t](#))(struct [rtdm_dev_context](#) *context, [rtdm_user_info_t](#) *user_info, const void *buf, size_t nbyte)
Write handler.
- typedef ssize_t(* [rtdm_recvmmsg_handler_t](#))(struct [rtdm_dev_context](#) *context, [rtdm_user_info_t](#) *user_info, struct msghdr *msg, int flags)
Receive message handler.
- typedef ssize_t(* [rtdm_sendmmsg_handler_t](#))(struct [rtdm_dev_context](#) *context, [rtdm_user_info_t](#) *user_info, const struct msghdr *msg, int flags)
Transmit message handler.

Enumerations

RTDM_SELECTTYPE_xxx

Event types select can bind to

- enum [rtdm_selecttype](#) { [RTDM_SELECTTYPE_READ](#) = XNSELECT_READ, [RTDM_SELECTTYPE_WRITE](#) = XNSELECT_WRITE, [RTDM_SELECTTYPE_EXCEPT](#) = XNSELECT_EXCEPT }

RTDM_TIMERMODE_xxx

Timer operation modes

- enum [rtdm_timer_mode](#) { [RTDM_TIMERMODE_RELATIVE](#) = XN_RELATIVE, [RTDM_TIMERMODE_ABSOLUTE](#) = XN_ABSOLUTE, [RTDM_TIMERMODE_REALTIME](#) = XN_REALTIME }

Functions

- int [rtdm_dev_register](#) (struct [rtdm_device](#) *device)
Register a RTDM device.

- int [rt dm_dev_unregister](#) (struct [rt dm_device](#) *device, unsigned int poll_delay)
Unregisters a RTDM device.
- struct [rt dm_dev_context](#) * [rt dm_context_get](#) (int fd)
Resolve file descriptor to device context.
- int [rt dm_select_bind](#) (int fd, [rt dm_selector_t](#) *selector, enum [rt dm_selecttype](#) type, unsigned fd_index)
Bind a selector to specified event types of a given file descriptor.
- int [rt dm_irq_request](#) ([rt dm_irq_t](#) *irq_handle, unsigned int irq_no, [rt dm_irq_handler_t](#) handler, unsigned long flags, const char *device_name, void *arg)
Register an interrupt handler.
- void [rt dm_timer_destroy](#) ([rt dm_timer_t](#) *timer)
Destroy a timer.
- int [rt dm_timer_start](#) ([rt dm_timer_t](#) *timer, [nanosecs_abs_t](#) expiry, [nanosecs_rel_t](#) interval, enum [rt dm_timer_mode](#) mode)
Start a timer.
- void [rt dm_timer_stop](#) ([rt dm_timer_t](#) *timer)
Stop a timer.
- int [rt dm_task_init](#) ([rt dm_task_t](#) *task, const char *name, [rt dm_task_proc_t](#) task_proc, void *arg, int priority, [nanosecs_rel_t](#) period)
Initialise and start a real-time task.
- void [rt dm_task_busy_sleep](#) ([nanosecs_rel_t](#) delay)
Busy-wait a specified amount of time.
- void [rt dm_toseq_init](#) ([rt dm_toseq_t](#) *timeout_seq, [nanosecs_rel_t](#) timeout)
Initialise a timeout sequence.
- void [rt dm_event_init](#) ([rt dm_event_t](#) *event, unsigned long pending)
Initialise an event.
- int [rt dm_event_select_bind](#) ([rt dm_event_t](#) *event, [rt dm_selector_t](#) *selector, enum [rt dm_selecttype](#) type, unsigned fd_index)
Bind a selector to an event.
- int [rt dm_event_wait](#) ([rt dm_event_t](#) *event)
Wait on event occurrence.
- int [rt dm_event_timedwait](#) ([rt dm_event_t](#) *event, [nanosecs_rel_t](#) timeout, [rt dm_toseq_t](#) *timeout_seq)
Wait on event occurrence with timeout.
- void [rt dm_event_signal](#) ([rt dm_event_t](#) *event)
Signal an event occurrence.

- void [rtdm_event_clear](#) (rtdm_event_t *event)
Clear event state.
- void [rtdm_sem_init](#) (rtdm_sem_t *sem, unsigned long value)
Initialise a semaphore.
- int [rtdm_sem_select_bind](#) (rtdm_sem_t *sem, rtdm_selector_t *selector, enum [rtdm_selecttype](#) type, unsigned fd_index)
Bind a selector to a semaphore.
- int [rtdm_sem_down](#) (rtdm_sem_t *sem)
Decrement a semaphore.
- int [rtdm_sem_timeddown](#) (rtdm_sem_t *sem, [nanosecs_rel_t](#) timeout, rtdm_toseq_t *timeout_seq)
Decrement a semaphore with timeout.
- void [rtdm_sem_up](#) (rtdm_sem_t *sem)
Increment a semaphore.
- void [rtdm_mutex_init](#) (rtdm_mutex_t *mutex)
Initialise a mutex.
- int [rtdm_mutex_lock](#) (rtdm_mutex_t *mutex)
Request a mutex.
- int [rtdm_mutex_timedlock](#) (rtdm_mutex_t *mutex, [nanosecs_rel_t](#) timeout, rtdm_toseq_t *timeout_seq)
Request a mutex with timeout.

7.4 include/rtm/rtserial.h File Reference

7.4.1 Detailed Description

Real-Time Driver Model for Xenomai, serial device profile header.

Note:

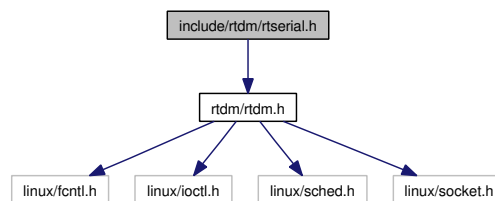
Copyright (C) 2005-2007 Jan Kiszka <jan.kiszka@web.de>

Xenomai is free software; you can redistribute it and/or modify it under the terms of the GNU General Public License as published by the Free Software Foundation; either version 2 of the License, or (at your option) any later version.

Xenomai is distributed in the hope that it will be useful, but WITHOUT ANY WARRANTY; without even the implied warranty of MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE. See the GNU General Public License for more details.

You should have received a copy of the GNU General Public License along with Xenomai; if not, write to the Free Software Foundation, Inc., 59 Temple Place - Suite 330, Boston, MA 02111-1307, USA.

Include dependency graph for rtserial.h:



Data Structures

- struct [rtser_config](#)
Serial device configuration.
- struct [rtser_status](#)
Serial device status.
- struct [rtser_event](#)
Additional information about serial device events.

RTSER_BREAK_xxx

Break control

- `#define RTSER_BREAK_CLR 0x00`
- `#define RTSER_BREAK_SET 0x01`
- `#define RTIOC_TYPE_SERIAL RTDM_CLASS_SERIAL`
- `typedef struct rtser_config rtser_config_t`

- typedef struct [rtser_status](#) **rtser_status_t**
- typedef struct [rtser_event](#) **rtser_event_t**

Defines

- #define [RTSER_RTIOC_BREAK_CTL](#) _IOR(RTIOC_TYPE_SERIAL, 0x06, int)
Set or clear break on UART output line.

RTSER_DEF_BAUD

Default baud rate

- #define **RTSER_DEF_BAUD** 9600

RTSER_xxx_PARITY

Number of parity bits

- #define **RTSER_NO_PARITY** 0x00
- #define **RTSER_ODD_PARITY** 0x01
- #define **RTSER_EVEN_PARITY** 0x03
- #define **RTSER_DEF_PARITY** **RTSER_NO_PARITY**

RTSER_xxx_BITS

Number of data bits

- #define **RTSER_5_BITS** 0x00
- #define **RTSER_6_BITS** 0x01
- #define **RTSER_7_BITS** 0x02
- #define **RTSER_8_BITS** 0x03
- #define **RTSER_DEF_BITS** **RTSER_8_BITS**

RTSER_xxx_STOPB

Number of stop bits

- #define **RTSER_1_STOPB** 0x00
- #define [RTSER_1_5_STOPB](#) 0x01
valid only in combination with 5 data bits
- #define **RTSER_2_STOPB** 0x01
- #define **RTSER_DEF_STOPB** **RTSER_1_STOPB**

RTSER_xxx_HAND

Handshake mechanisms

- #define **RTSER_NO_HAND** 0x00
- #define **RTSER_RTCTS_HAND** 0x01
- #define **RTSER_DEF_HAND** **RTSER_NO_HAND**

RTSER_FIFO_xxx

Reception FIFO interrupt threshold

- #define **RTSER_FIFO_DEPTH_1** 0x00

- #define **RTSER_FIFO_DEPTH_4** 0x40
- #define **RTSER_FIFO_DEPTH_8** 0x80
- #define **RTSER_FIFO_DEPTH_14** 0xC0
- #define **RTSER_DEF_FIFO_DEPTH** RTSER_FIFO_DEPTH_1

RTSER_TIMEOUT_xxx

Special timeout values, see also [RTDM_TIMEOUT_xxx](#)

- #define **RTSER_TIMEOUT_INFINITE** RTDM_TIMEOUT_INFINITE
- #define **RTSER_TIMEOUT_NONE** RTDM_TIMEOUT_NONE
- #define **RTSER_DEF_TIMEOUT** RTDM_TIMEOUT_INFINITE

RTSER_xxx_TIMESTAMP_HISTORY

Timestamp history control

- #define **RTSER_RX_TIMESTAMP_HISTORY** 0x01
- #define **RTSER_DEF_TIMESTAMP_HISTORY** 0x00

RTSER_EVENT_xxx

Events bits

- #define **RTSER_EVENT_RXPEND** 0x01
- #define **RTSER_EVENT_ERRPEND** 0x02
- #define **RTSER_EVENT_MODEMHI** 0x04
- #define **RTSER_EVENT_MODEMLO** 0x08
- #define **RTSER_DEF_EVENT_MASK** 0x00

RTSER_SET_xxx

Configuration mask bits

- #define **RTSER_SET_BAUD** 0x0001
- #define **RTSER_SET_PARITY** 0x0002
- #define **RTSER_SET_DATA_BITS** 0x0004
- #define **RTSER_SET_STOP_BITS** 0x0008
- #define **RTSER_SET_HANDSHAKE** 0x0010
- #define **RTSER_SET_FIFO_DEPTH** 0x0020
- #define **RTSER_SET_TIMEOUT_RX** 0x0100
- #define **RTSER_SET_TIMEOUT_TX** 0x0200
- #define **RTSER_SET_TIMEOUT_EVENT** 0x0400
- #define **RTSER_SET_TIMESTAMP_HISTORY** 0x0800
- #define **RTSER_SET_EVENT_MASK** 0x1000

RTSER_LSR_xxx

Line status bits

- #define **RTSER_LSR_DATA** 0x01
- #define **RTSER_LSR_OVERRUN_ERR** 0x02
- #define **RTSER_LSR_PARITY_ERR** 0x04
- #define **RTSER_LSR_FRAMING_ERR** 0x08
- #define **RTSER_LSR_BREAK_IND** 0x10
- #define **RTSER_LSR_THR_EMPTY** 0x20
- #define **RTSER_LSR_TRANSM_EMPTY** 0x40
- #define **RTSER_LSR_FIFO_ERR** 0x80
- #define **RTSER_SOFT_OVERRUN_ERR** 0x0100

RTSER_MSR_xxx*Modem status bits*

- #define **RTSER_MSR_DCTS** 0x01
- #define **RTSER_MSR_DDSR** 0x02
- #define **RTSER_MSR_TERI** 0x04
- #define **RTSER_MSR_DDCD** 0x08
- #define **RTSER_MSR_CTS** 0x10
- #define **RTSER_MSR_DSR** 0x20
- #define **RTSER_MSR_RI** 0x40
- #define **RTSER_MSR_DCD** 0x80

RTSER_MCR_xxx*Modem control bits*

- #define **RTSER_MCR_DTR** 0x01
- #define **RTSER_MCR_RTS** 0x02
- #define **RTSER_MCR_OUT1** 0x04
- #define **RTSER_MCR_OUT2** 0x08
- #define **RTSER_MCR_LOOP** 0x10

Sub-Classes of RTDM_CLASS_SERIAL

- #define **RTDM_SUBCLASS_16550A** 0

IOCTLs*Serial device IOCTLs*

- #define **RTSER_RTIOC_GET_CONFIG** _IOR(RTIOC_TYPE_SERIAL, 0x00, struct rtser_config)
Get serial device configuration.
- #define **RTSER_RTIOC_SET_CONFIG** _IOW(RTIOC_TYPE_SERIAL, 0x01, struct rtser_config)
Set serial device configuration.
- #define **RTSER_RTIOC_GET_STATUS** _IOR(RTIOC_TYPE_SERIAL, 0x02, struct rtser_status)
Get serial device status.
- #define **RTSER_RTIOC_GET_CONTROL** _IOR(RTIOC_TYPE_SERIAL, 0x03, int)
Get serial device's modem control register.
- #define **RTSER_RTIOC_SET_CONTROL** _IOW(RTIOC_TYPE_SERIAL, 0x04, int)
Set serial device's modem control register.
- #define **RTSER_RTIOC_WAIT_EVENT** _IOR(RTIOC_TYPE_SERIAL, 0x05, struct rtser_event)
Wait on serial device events according to previously set mask.

7.5 include/rtdm/rtesting.h File Reference

7.5.1 Detailed Description

Real-Time Driver Model for Xenomai, testing device profile header.

Note:

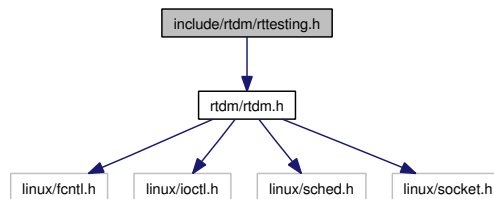
Copyright (C) 2005 Jan Kiszka <jan.kiszka@web.de>

Xenomai is free software; you can redistribute it and/or modify it under the terms of the GNU General Public License as published by the Free Software Foundation; either version 2 of the License, or (at your option) any later version.

Xenomai is distributed in the hope that it will be useful, but WITHOUT ANY WARRANTY; without even the implied warranty of MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE. See the GNU General Public License for more details.

You should have received a copy of the GNU General Public License along with Xenomai; if not, write to the Free Software Foundation, Inc., 59 Temple Place - Suite 330, Boston, MA 02111-1307, USA.

Include dependency graph for rtesting.h:



Defines

Sub-Classes of RTDM_CLASS_TESTING

- `#define RTDM_SUBCLASS_TIMERBENCH 0`
- `#define RTDM_SUBCLASS_IRQBENCH 1`
- `#define RTDM_SUBCLASS_SWITCHTEST 2`

IOCTLs

Testing device IOCTLs

- `#define RTTST_RTIOC_INTERM_BENCH_RES _IOWR(RTIOC_TYPE_TESTING, 0x00, struct rttst_interm_bench_res)`
- `#define RTTST_RTIOC_TMBENCH_START _IOW(RTIOC_TYPE_TESTING, 0x10, struct rttst_tmbench_config)`
- `#define RTTST_RTIOC_TMBENCH_STOP _IOWR(RTIOC_TYPE_TESTING, 0x11, struct rttst_overall_bench_res)`
- `#define RTTST_RTIOC_IRQBENCH_START _IOW(RTIOC_TYPE_TESTING, 0x20, struct rttst_irqbench_config)`
- `#define RTTST_RTIOC_IRQBENCH_STOP _IO(RTIOC_TYPE_TESTING, 0x21)`
- `#define RTTST_RTIOC_IRQBENCH_GET_STATS _IOR(RTIOC_TYPE_TESTING, 0x22, struct rttst_irqbench_stats)`

- #define **RTTST_RTIOC_IRQBENCH_WAIT_IRQ** _IO(RTIOC_TYPE_TESTING, 0x23)
- #define **RTTST_RTIOC_IRQBENCH_REPLY_IRQ** _IO(RTIOC_TYPE_TESTING, 0x24)
- #define **RTTST_RTIOC_SWTEST_SET_TASKS_COUNT** _IOW(RTIOC_TYPE_TESTING, 0x30, unsigned long)
- #define **RTTST_RTIOC_SWTEST_SET_CPU** _IOW(RTIOC_TYPE_TESTING, 0x31, unsigned long)
- #define **RTTST_RTIOC_SWTEST_REGISTER_UTASK** _IOW(RTIOC_TYPE_TESTING, 0x32, struct rttst_swtest_task)
- #define **RTTST_RTIOC_SWTEST_CREATE_KTASK** _IOWR(RTIOC_TYPE_TESTING, 0x33, struct rttst_swtest_task)
- #define **RTTST_RTIOC_SWTEST_PEND** _IOR(RTIOC_TYPE_TESTING, 0x34, struct rttst_swtest_task)
- #define **RTTST_RTIOC_SWTEST_SWITCH_TO** _IOR(RTIOC_TYPE_TESTING, 0x35, struct rttst_swtest_dir)
- #define **RTTST_RTIOC_SWTEST_GET_SWITCHES_COUNT** _IOR(RTIOC_TYPE_TESTING, 0x36, unsigned long)
- #define **RTTST_RTIOC_SWTEST_GET_LAST_ERROR** _IOR(RTIOC_TYPE_TESTING, 0x37, struct rttst_swtest_error)

7.6 ksrc/skins/rtdm/device.c File Reference

7.6.1 Detailed Description

Real-Time Driver Model for Xenomai, device management.

Note:

Copyright (C) 2005 Jan Kiszka <jan.kiszka@web.de>

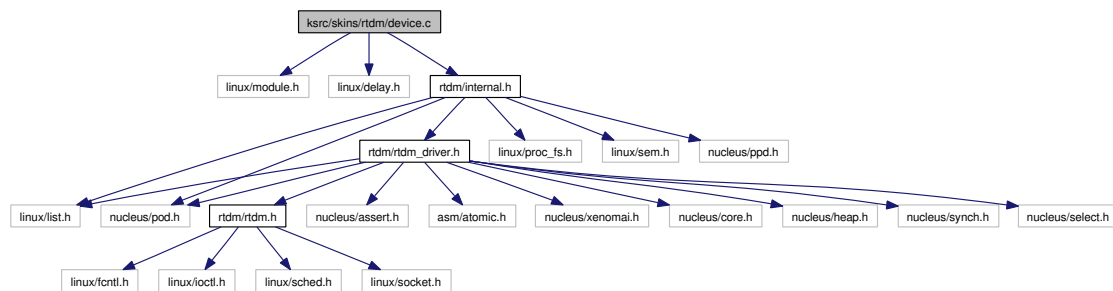
Copyright (C) 2005 Joerg Langenberg <joerg.langenberg@gmx.net>

Xenomai is free software; you can redistribute it and/or modify it under the terms of the GNU General Public License as published by the Free Software Foundation; either version 2 of the License, or (at your option) any later version.

Xenomai is distributed in the hope that it will be useful, but WITHOUT ANY WARRANTY; without even the implied warranty of MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE. See the GNU General Public License for more details.

You should have received a copy of the GNU General Public License along with Xenomai; if not, write to the Free Software Foundation, Inc., 59 Temple Place - Suite 330, Boston, MA 02111-1307, USA.

Include dependency graph for device.c:



Functions

- `int rtdm_dev_register` (struct `rtdm_device` *device)
Register a RTDM device.
- `int rtdm_dev_unregister` (struct `rtdm_device` *device, unsigned int poll_delay)
Unregisters a RTDM device.

7.7 ksrc/skins/rtdm/drvlib.c File Reference

7.7.1 Detailed Description

Real-Time Driver Model for Xenomai, driver library.

Note:

Copyright (C) 2005-2007 Jan Kiszka <jan.kiszka@web.de>

Copyright (C) 2005 Joerg Langenberg <joerg.langenberg@gmx.net>

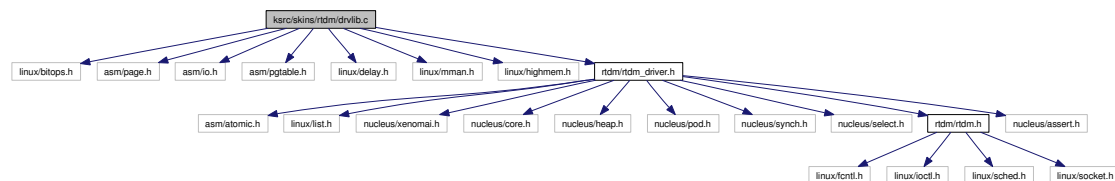
Copyright (C) 2008 Gilles Chanteperdrix <gilles.chanteperdrix@gmail.com>

Xenomai is free software; you can redistribute it and/or modify it under the terms of the GNU General Public License as published by the Free Software Foundation; either version 2 of the License, or (at your option) any later version.

Xenomai is distributed in the hope that it will be useful, but WITHOUT ANY WARRANTY; without even the implied warranty of MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE. See the GNU General Public License for more details.

You should have received a copy of the GNU General Public License along with Xenomai; if not, write to the Free Software Foundation, Inc., 59 Temple Place - Suite 330, Boston, MA 02111-1307, USA.

Include dependency graph for drvlib.c:



Functions

- [nanosecs_abs_t rtdm_clock_read](#) (void)
Get system time.
- [nanosecs_abs_t rtdm_clock_read_monotonic](#) (void)
Get monotonic time.
- [int rtdm_task_init](#) (rtdm_task_t *task, const char *name, [rtdm_task_proc_t](#) task_proc, void *arg, int priority, [nanosecs_rel_t](#) period)
Intialise and start a real-time task.
- [void rtdm_task_destroy](#) (rtdm_task_t *task)
Destroy a real-time task.
- [void rtdm_task_set_priority](#) (rtdm_task_t *task, int priority)
Adjust real-time task priority.
- [int rtdm_task_set_period](#) (rtdm_task_t *task, [nanosecs_rel_t](#) period)

Adjust real-time task period.

- int [rt dm_task_wait_period](#) (void)
Wait on next real-time task period.
- int [rt dm_task_unblock](#) (rt dm_task_t *task)
Activate a blocked real-time task.
- rt dm_task_t * [rt dm_task_current](#) (void)
Get current real-time task.
- int [rt dm_task_sleep](#) (nanosecs_rel_t delay)
Sleep a specified amount of time.
- int [rt dm_task_sleep_until](#) (nanosecs_abs_t wakeup_time)
Sleep until a specified absolute time.
- int [rt dm_task_sleep_abs](#) (nanosecs_abs_t wakeup_time, enum [rt dm_timer_mode](#) mode)
Sleep until a specified absolute time.
- void [rt dm_task_join_nrt](#) (rt dm_task_t *task, unsigned int poll_delay)
Wait on a real-time task to terminate.
- void [rt dm_task_busy_sleep](#) (nanosecs_rel_t delay)
Busy-wait a specified amount of time.
- int [rt dm_timer_init](#) (rt dm_timer_t *timer, [rt dm_timer_handler_t](#) handler, const char *name)
Initialise a timer.
- void [rt dm_timer_destroy](#) (rt dm_timer_t *timer)
Destroy a timer.
- int [rt dm_timer_start](#) (rt dm_timer_t *timer, nanosecs_abs_t expiry, nanosecs_rel_t interval, enum [rt dm_timer_mode](#) mode)
Start a timer.
- void [rt dm_timer_stop](#) (rt dm_timer_t *timer)
Stop a timer.
- int [rt dm_timer_start_in_handler](#) (rt dm_timer_t *timer, nanosecs_abs_t expiry, nanosecs_rel_t interval, enum [rt dm_timer_mode](#) mode)
Start a timer from inside a timer handler.
- void [rt dm_timer_stop_in_handler](#) (rt dm_timer_t *timer)
Stop a timer from inside a timer handler.
- int [rt dm_irq_request](#) (rt dm_irq_t *irq_handle, unsigned int irq_no, [rt dm_irq_handler_t](#) handler, unsigned long flags, const char *device_name, void *arg)
Register an interrupt handler.

- int [rtdm_irq_free](#) (rtdm_irq_t *irq_handle)
Release an interrupt handler.
- int [rtdm_irq_enable](#) (rtdm_irq_t *irq_handle)
Enable interrupt line.
- int [rtdm_irq_disable](#) (rtdm_irq_t *irq_handle)
Disable interrupt line.
- int [rtdm_nrtsig_init](#) (rtdm_nrtsig_t *nrt_sig, [rtdm_nrtsig_handler_t](#) handler, void *arg)
Register a non-real-time signal handler.
- void [rtdm_nrtsig_destroy](#) (rtdm_nrtsig_t *nrt_sig)
Release a non-realtime signal handler.
- void [rtdm_nrtsig_pend](#) (rtdm_nrtsig_t *nrt_sig)
Trigger non-real-time signal.
- int [rtdm_mmap_to_user](#) (rtdm_user_info_t *user_info, void *src_addr, size_t len, int prot, void **pptr, struct vm_operations_struct *vm_ops, void *vm_private_data)
Map a kernel memory range into the address space of the user.
- int [rtdm_iomap_to_user](#) (rtdm_user_info_t *user_info, unsigned long src_addr, size_t len, int prot, void **pptr, struct vm_operations_struct *vm_ops, void *vm_private_data)
Map an I/O memory range into the address space of the user.
- int [rtdm_munmap](#) (rtdm_user_info_t *user_info, void *ptr, size_t len)
Unmap a user memory range.
- void [rtdm_printk](#) (const char *format,...)
Real-time safe message printing on kernel console.
- void * [rtdm_malloc](#) (size_t size)
Allocate memory block in real-time context.
- void [rtdm_free](#) (void *ptr)
Release real-time memory block.
- int [rtdm_read_user_ok](#) (rtdm_user_info_t *user_info, const void __user *ptr, size_t size)
Check if read access to user-space memory block is safe.
- int [rtdm_rw_user_ok](#) (rtdm_user_info_t *user_info, const void __user *ptr, size_t size)
Check if read/write access to user-space memory block is safe.
- int [rtdm_copy_from_user](#) (rtdm_user_info_t *user_info, void *dst, const void __user *src, size_t size)
Copy user-space memory block to specified buffer.

- `int rtdm_safe_copy_from_user` (`rtdm_user_info_t *user_info`, `void *dst`, `const void __user *src`, `size_t size`)
Check if read access to user-space memory block and copy it to specified buffer.
- `int rtdm_copy_to_user` (`rtdm_user_info_t *user_info`, `void __user *dst`, `const void *src`, `size_t size`)
Copy specified buffer to user-space memory block.
- `int rtdm_safe_copy_to_user` (`rtdm_user_info_t *user_info`, `void __user *dst`, `const void *src`, `size_t size`)
Check if read/write access to user-space memory block is safe and copy specified buffer to it.
- `int rtdm_strncpy_from_user` (`rtdm_user_info_t *user_info`, `char *dst`, `const char __user *src`, `size_t count`)
Copy user-space string to specified buffer.
- `int rtdm_in_rt_context` (`void`)
Test if running in a real-time task.

Timeout Sequence Management

- `void rtdm_toseq_init` (`rtdm_toseq_t *timeout_seq`, `nanosecs_rel_t timeout`)
Initialise a timeout sequence.

Event Services

- `void rtdm_event_init` (`rtdm_event_t *event`, unsigned long pending)
Initialise an event.
- `void rtdm_event_destroy` (`rtdm_event_t *event`)
Destroy an event.
- `void rtdm_event_pulse` (`rtdm_event_t *event`)
Signal an event occurrence to currently listening waiters.
- `void rtdm_event_signal` (`rtdm_event_t *event`)
Signal an event occurrence.
- `int rtdm_event_wait` (`rtdm_event_t *event`)
Wait on event occurrence.
- `int rtdm_event_timedwait` (`rtdm_event_t *event`, `nanosecs_rel_t timeout`, `rtdm_toseq_t *timeout_seq`)
Wait on event occurrence with timeout.
- `void rtdm_event_clear` (`rtdm_event_t *event`)
Clear event state.
- `int rtdm_event_select_bind` (`rtdm_event_t *event`, `rtdm_selector_t *selector`, `enum rtdm_selecttype type`, unsigned `fd_index`)
Bind a selector to an event.

Semaphore Services

- void [rtdm_sem_init](#) (rtdm_sem_t *sem, unsigned long value)
Initialise a semaphore.
- void [rtdm_sem_destroy](#) (rtdm_sem_t *sem)
Destroy a semaphore.
- int [rtdm_sem_down](#) (rtdm_sem_t *sem)
Decrement a semaphore.
- int [rtdm_sem_timeddown](#) (rtdm_sem_t *sem, [nanosecs_rel_t](#) timeout, rtdm_toseq_t *timeout_seq)
Decrement a semaphore with timeout.
- void [rtdm_sem_up](#) (rtdm_sem_t *sem)
Increment a semaphore.
- int [rtdm_sem_select_bind](#) (rtdm_sem_t *sem, rtdm_selector_t *selector, enum [rtdm_selecttype](#) type, unsigned fd_index)
Bind a selector to a semaphore.

Mutex Services

- void [rtdm_mutex_init](#) (rtdm_mutex_t *mutex)
Initialise a mutex.
- void [rtdm_mutex_destroy](#) (rtdm_mutex_t *mutex)
Destroy a mutex.
- void [rtdm_mutex_unlock](#) (rtdm_mutex_t *mutex)
Release a mutex.
- int [rtdm_mutex_lock](#) (rtdm_mutex_t *mutex)
Request a mutex.
- int [rtdm_mutex_timedlock](#) (rtdm_mutex_t *mutex, [nanosecs_rel_t](#) timeout, rtdm_toseq_t *timeout_seq)
Request a mutex with timeout.

7.8 ksrc/skins/rtdm/module.c File Reference

7.8.1 Detailed Description

Real-Time Driver Model for Xenomai.

Note:

Copyright (C) 2005, 2006 Jan Kiszka <jan.kiszka@web.de>

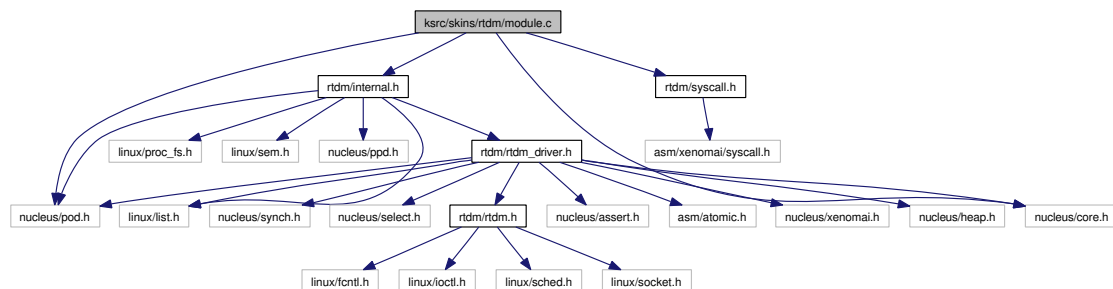
Copyright (C) 2005 Joerg Langenberg <joerg.langenberg@gmx.net>

Xenomai is free software; you can redistribute it and/or modify it under the terms of the GNU General Public License as published by the Free Software Foundation; either version 2 of the License, or (at your option) any later version.

Xenomai is distributed in the hope that it will be useful, but WITHOUT ANY WARRANTY; without even the implied warranty of MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE. See the GNU General Public License for more details.

You should have received a copy of the GNU General Public License along with Xenomai; if not, write to the Free Software Foundation, Inc., 59 Temple Place - Suite 330, Boston, MA 02111-1307, USA.

Include dependency graph for module.c:



- `int rtdm_socket` (int protocol_family, int socket_type, int protocol)
Create a socket.
- `int rtdm_close` (int fd)
Close a device or socket.
- `int rtdm_ioctl` (int fd, int request,...)
Issue an IOCTL.
- `ssize_t rtdm_read` (int fd, void *buf, size_t nbyte)
Read from device.
- `ssize_t rtdm_write` (int fd, const void *buf, size_t nbyte)
Write to device.
- `ssize_t rtdm_recvmmsg` (int fd, struct msghdr *msg, int flags)
Receive message from socket.
- `ssize_t rtdm_recvfrom` (int fd, void *buf, size_t len, int flags, struct sockaddr *from, socklen_t *fromlen)
Receive message from socket.
- `ssize_t rtdm_recv` (int fd, void *buf, size_t len, int flags)
Receive message from socket.
- `ssize_t rtdm_sendmsg` (int fd, const struct msghdr *msg, int flags)
Transmit message to socket.
- `ssize_t rtdm_sendto` (int fd, const void *buf, size_t len, int flags, const struct sockaddr *to, socklen_t tolen)
Transmit message to socket.
- `ssize_t rtdm_send` (int fd, const void *buf, size_t len, int flags)
Transmit message to socket.
- `int rtdm_bind` (int fd, const struct sockaddr *my_addr, socklen_t addrlen)
Bind to local address.
- `int rtdm_connect` (int fd, const struct sockaddr *serv_addr, socklen_t addrlen)
Connect to remote address.
- `int rtdm_listen` (int fd, int backlog)
Listen for incoming connection requests.
- `int rtdm_accept` (int fd, struct sockaddr *addr, socklen_t *addrlen)
Accept a connection requests.
- `int rtdm_shutdown` (int fd, int how)
Shut down parts of a connection.

- int [rtdm_getsockopt](#) (int fd, int level, int optname, void *optval, socklen_t *optlen)
Get socket option.
- int [rtdm_setsockopt](#) (int fd, int level, int optname, const void *optval, socklen_t optlen)
Set socket option.
- int [rtdm_getsockname](#) (int fd, struct sockaddr *name, socklen_t *namelen)
Get local socket address.
- int [rtdm_getpeername](#) (int fd, struct sockaddr *name, socklen_t *namelen)
Get socket destination address.
- int [rt_dev_open](#) (const char *path, int oflag,...)
Open a device.
- int [rt_dev_socket](#) (int protocol_family, int socket_type, int protocol)
Create a socket.
- int [rt_dev_close](#) (int fd)
Close a device or socket.
- int [rt_dev_ioctl](#) (int fd, int request,...)
Issue an IOCTL.
- ssize_t [rt_dev_read](#) (int fd, void *buf, size_t nbyte)
Read from device.
- ssize_t [rt_dev_write](#) (int fd, const void *buf, size_t nbyte)
Write to device.
- ssize_t [rt_dev_recvmmsg](#) (int fd, struct mshdr *msg, int flags)
Receive message from socket.
- ssize_t [rt_dev_recvfrom](#) (int fd, void *buf, size_t len, int flags, struct sockaddr *from, socklen_t *fromlen)
Receive message from socket.
- ssize_t [rt_dev_recv](#) (int fd, void *buf, size_t len, int flags)
Receive message from socket.
- ssize_t [rt_dev_sendmsg](#) (int fd, const struct mshdr *msg, int flags)
Transmit message to socket.
- ssize_t [rt_dev_sendto](#) (int fd, const void *buf, size_t len, int flags, const struct sockaddr *to, socklen_t tolen)
Transmit message to socket.
- ssize_t [rt_dev_send](#) (int fd, const void *buf, size_t len, int flags)
Transmit message to socket.

- `int rt_dev_bind (int fd, const struct sockaddr *my_addr, socklen_t addrlen)`
Bind to local address.
- `int rt_dev_connect (int fd, const struct sockaddr *serv_addr, socklen_t addrlen)`
Connect to remote address.
- `int rt_dev_listen (int fd, int backlog)`
Listen for incoming connection requests.
- `int rt_dev_accept (int fd, struct sockaddr *addr, socklen_t *addrlen)`
Accept a connection requests.
- `int rt_dev_shutdown (int fd, int how)`
Shut down parts of a connection.
- `int rt_dev_getsockopt (int fd, int level, int optname, void *optval, socklen_t *optlen)`
Get socket option.
- `int rt_dev_setsockopt (int fd, int level, int optname, const void *optval, socklen_t optlen)`
Set socket option.
- `int rt_dev_getsockname (int fd, struct sockaddr *name, socklen_t *namelen)`
Get local socket address.
- `int rt_dev_getpeername (int fd, struct sockaddr *name, socklen_t *namelen)`
Get socket destination address.

Chapter 8

Example Documentation

8.1 cross-link.c

```
/*
 * cross-link.c
 *
 * Userspace test program (Xenomai native skin) for RTDM-based UART drivers
 * Copyright 2005 by Joerg Langenberg <joergel75@gmx.net>
 *
 * Updates by Jan Kiszka <jan.kiszka@web.de>
 *
 * This program is free software; you can redistribute it and/or modify
 * it under the terms of the GNU General Public License as published by
 * the Free Software Foundation; either version 2 of the License, or
 * (at your option) any later version.
 *
 * This program is distributed in the hope that it will be useful,
 * but WITHOUT ANY WARRANTY; without even the implied warranty of
 * MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE. See the
 * GNU General Public License for more details.
 *
 * You should have received a copy of the GNU General Public License
 * along with this program; if not, write to the Free Software
 * Foundation, Inc., 675 Mass Ave, Cambridge, MA 02139, USA.
 */
#include <stdio.h>
#include <signal.h>
#include <unistd.h>
#include <sys/mman.h>

#include <native/task.h>
#include <native/timer.h>

#include <rtdm/rtserial.h>

#define MAIN_PREFIX    "main : "
#define WTASK_PREFIX   "write_task: "
#define RTASK_PREFIX   "read_task: "

#define WRITE_FILE      "rtser0"
#define READ_FILE       "rtser1"

int read_fd  = -1;
int write_fd = -1;

#define STATE_FILE_OPENED      1
#define STATE_TASK_CREATED    2
```

```

unsigned int read_state = 0;
unsigned int write_state = 0;

/*          --s-ms-us-ns */
RTIME write_task_period_ns = 100000000llu;
RT_TASK write_task;
RT_TASK read_task;

static const struct rtser_config read_config = {
    .config_mask      = 0xFFFF,
    .baud_rate        = 115200,
    .parity           = RTSER_DEF_PARITY,
    .data_bits        = RTSER_DEF_BITS,
    .stop_bits        = RTSER_DEF_STOPB,
    .handshake        = RTSER_DEF_HAND,
    .fifo_depth       = RTSER_DEF_FIFO_DEPTH,
    .rx_timeout       = RTSER_DEF_TIMEOUT,
    .tx_timeout       = RTSER_DEF_TIMEOUT,
    .event_timeout    = 1000000000, /* 1 s */
    .timestamp_history = RTSER_RX_TIMESTAMP_HISTORY,
    .event_mask       = RTSER_EVENT_RXPEND,
};

static const struct rtser_config write_config = {
    .config_mask      = RTSER_SET_BAUD | RTSER_SET_TIMESTAMP_HISTORY,
    .baud_rate        = 115200,
    .timestamp_history = RTSER_DEF_TIMESTAMP_HISTORY,
    /* the rest implicitly remains default */
};

static int close_file( int fd, char *name)
{
    int err, i=0;

    do {
        i++;
        err = rt_dev_close(fd);
        switch (err) {
            case -EAGAIN:
                printf(MAIN_PREFIX "%s -> EAGAIN (%d times)\n",
                    name, i);
                rt_task_sleep(50000); /* wait 50us */
                break;
            case 0:
                printf(MAIN_PREFIX "%s -> closed\n", name);
                break;
            default:
                printf(MAIN_PREFIX "%s -> %s\n", name,
                    strerror(-err));
                break;
        }
    } while (err == -EAGAIN && i < 10);

    return err;
}

void cleanup_all(void)
{
    if (read_state & STATE_FILE_OPENED) {
        close_file(read_fd, READ_FILE " (read)");
        read_state &= ~STATE_FILE_OPENED;
    }

    if (write_state & STATE_FILE_OPENED) {
        close_file(write_fd, WRITE_FILE " (write)");
        write_state &= ~STATE_FILE_OPENED;
    }
}

```

```

    }

    if (write_state & STATE_TASK_CREATED) {
        printf(MAIN_PREFIX "delete write_task\n");
        rt_task_delete(&write_task);
        write_state &= ~STATE_TASK_CREATED;
    }

    if (read_state & STATE_TASK_CREATED) {
        printf(MAIN_PREFIX "delete read_task\n");
        rt_task_delete(&read_task);
        read_state &= ~STATE_TASK_CREATED;
    }
}

void catch_signal(int sig)
{
    cleanup_all();
    printf(MAIN_PREFIX "exit\n");
    return;
}

void write_task_proc(void *arg)
{
    int err;
    RTIME write_time;
    ssize_t sz = sizeof(RTIME);
    ssize_t written = 0;

    err = rt_task_set_periodic(NULL, TM_NOW,
                               rt_timer_ns2ticks(write_task_period_ns));
    if (err) {
        printf(WTASK_PREFIX "error on set periodic, %s\n",
               strerror(-err));
        goto exit_write_task;
    }

    while (1) {
        err = rt_task_wait_period(NULL);
        if (err) {
            printf(WTASK_PREFIX
                  "error on rt_task_wait_period, %s\n",
                  strerror(-err));
            break;
        }

        write_time = rt_timer_read();

        written = rt_dev_write(write_fd, &write_time, sz);
        if (written < 0) {
            printf(WTASK_PREFIX "error on rt_dev_write, %s\n",
                   strerror(-err));
            break;
        } else if (written != sz) {
            printf(WTASK_PREFIX "only %d / %d byte transmitted\n",
                   written, sz);
            break;
        }
    }

    exit_write_task:
    if ((write_state & STATE_FILE_OPENED) &&
        close_file(write_fd, WRITE_FILE " (write)") == 0)
        write_state &= ~STATE_FILE_OPENED;

    printf(WTASK_PREFIX "exit\n");
}

```

```

void read_task_proc(void *arg)
{
    int err;
    int nr = 0;
    RTIME read_time = 0;
    RTIME write_time = 0;
    RTIME irq_time = 0;
    ssize_t sz = sizeof(RTIME);
    ssize_t read = 0;
    struct rtser_event rx_event;

    printf(" Nr |   write->irq   |   irq->read   |   write->read   |\n");
    printf("-----\n");

    /*
     * We are in secondary mode now due to printf, the next
     * blocking Xenomai or driver call will switch us back
     * (here: RTSER_RTIOC_WAIT_EVENT).
     */

    while (1) {
        /* waiting for event */
        err = rt_dev_ioctl(read_fd, RTSER_RTIOC_WAIT_EVENT, &rx_event);
        if (err) {
            printf(RTASK_PREFIX
                   "error on RTSER_RTIOC_WAIT_EVENT, %s\n",
                   strerror(-err));
            if (err == -ETIMEDOUT)
                continue;
            break;
        }

        irq_time = rx_event.rxpnd_timestamp;
        read = rt_dev_read(read_fd, &write_time, sz);
        if (read == sz) {
            read_time = rt_timer_read();
            printf("%3d |%16llu |%16llu |%16llu\n", nr,
                   irq_time - write_time,
                   read_time - irq_time,
                   read_time - write_time);
            nr++;
        } else if (read < 0) {
            printf(RTASK_PREFIX "error on rt_dev_read, code %s\n",
                   strerror(-err));
            break;
        } else {
            printf(RTASK_PREFIX "only %d / %d byte received \n",
                   read, sz);
            break;
        }
    }

    if ((read_state & STATE_FILE_OPENED) &&
        close_file(read_fd, READ_FILE " (read)") == 0)
        read_state &= ~STATE_FILE_OPENED;

    printf(RTASK_PREFIX "exit\n");
}

int main(int argc, char* argv[])
{
    int err = 0;

    signal(SIGTERM, catch_signal);
    signal(SIGINT, catch_signal);

```

```

/* no memory-swapping for this program */
mlockall(MCL_CURRENT | MCL_FUTURE);

/* open rtser0 */
write_fd = rt_dev_open( WRITE_FILE, 0);
if (write_fd < 0) {
    printf(MAIN_PREFIX "can't open %s (write), %s\n", WRITE_FILE,
           strerror(-write_fd));
    goto error;
}
write_state |= STATE_FILE_OPENED;
printf(MAIN_PREFIX "write-file opened\n");

/* writing write-config */
err = rt_dev_ioctl(write_fd, RTSER_RTIOC_SET_CONFIG, &write_config);
if (err) {
    printf(MAIN_PREFIX "error while RTSER_RTIOC_SET_CONFIG, %s\n",
           strerror(-err));
    goto error;
}
printf(MAIN_PREFIX "write-config written\n");

/* open rtser1 */
read_fd = rt_dev_open( READ_FILE, 0 );
if (read_fd < 0) {
    printf(MAIN_PREFIX "can't open %s (read), %s\n", READ_FILE,
           strerror(-read_fd));
    goto error;
}
read_state |= STATE_FILE_OPENED;
printf(MAIN_PREFIX "read-file opened\n");

/* writing read-config */
err = rt_dev_ioctl(read_fd, RTSER_RTIOC_SET_CONFIG, &read_config);
if (err) {
    printf(MAIN_PREFIX "error while rt_dev_ioctl, %s\n",
           strerror(-err));
    goto error;
}
printf(MAIN_PREFIX "read-config written\n");

/* create write_task */
err = rt_task_create(&write_task, "write_task", 0, 50, 0);
if (err) {
    printf(MAIN_PREFIX "failed to create write_task, %s\n",
           strerror(-err));
    goto error;
}
write_state |= STATE_TASK_CREATED;
printf(MAIN_PREFIX "write-task created\n");

/* create read_task */
err = rt_task_create(&read_task, "read_task", 0, 51, 0);
if (err) {
    printf(MAIN_PREFIX "failed to create read_task, %s\n",
           strerror(-err));
    goto error;
}
read_state |= STATE_TASK_CREATED;
printf(MAIN_PREFIX "read-task created\n");

/* start write_task */
printf(MAIN_PREFIX "starting write-task\n");
err = rt_task_start(&write_task, &write_task_proc, NULL);
if (err) {
    printf(MAIN_PREFIX "failed to start write_task, %s\n",
           strerror(-err));
}

```

```
        goto error;
    }

    /* start read_task */
    printf(MAIN_PREFIX "starting read-task\n");
    err = rt_task_start(&read_task,&read_task_proc,NULL);
    if (err) {
        printf(MAIN_PREFIX "failed to start read_task, %s\n",
               strerror(-err));
        goto error;
    }

    pause();
    return 0;

error:
    cleanup_all();
    return err;
}
```

8.2 rtcan_rtt.c

```

/*
 * Round-Trip-Time Test - sends and receives messages and measures the
 *                        time in between.
 *
 * Copyright (C) 2006 Wolfgang Grandegger <wg@grandegger.com>
 *
 * Based on RTnet's examples/xenomai/posix/rtt-sender.c.
 *
 * Copyright (C) 2002 Ulrich Marx <marx@kammer.uni-hannover.de>
 *                2002 Marc Kleine-Budde <kleine-budde@gmx.de>
 *                2006 Jan Kiszka <jan.kiszka@web.de>
 *
 * This program is free software; you can redistribute it and/or modify
 * it under the terms of the GNU General Public License as published by
 * the Free Software Foundation; either version 2 of the License, or
 * (at your option) any later version.
 *
 * This program is distributed in the hope that it will be useful,
 * but WITHOUT ANY WARRANTY; without even the implied warranty of
 * MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE. See the
 * GNU General Public License for more details.
 *
 * You should have received a copy of the GNU General Public License
 * along with this program; if not, write to the Free Software
 * Foundation, Inc., 675 Mass Ave, Cambridge, MA 02139, USA.
 *
 * The program sends out CAN messages periodically and copies the current
 * time-stamp to the payload. At reception, that time-stamp is compared
 * with the current time to determine the round-trip time. The jitter
 * values are printed out regularly. Concurrent tests can be carried out
 * by starting the program with different message identifiers. It is also
 * possible to use this program on a remote system as simple repeater to
 * loopback messages.
 */

#include <errno.h>
#include <mqueue.h>
#include <signal.h>
#include <pthread.h>
#include <stdio.h>
#include <stdlib.h>
#include <string.h>
#include <unistd.h>
#include <limits.h>
#include <getopt.h>
#include <netinet/in.h>
#include <sys/mman.h>

#include <rtcm/rtdm.h>

#define NSEC_PER_SEC 1000000000

static unsigned int cycle = 10000; /* 10 ms */
static can_id_t can_id = 0x1;

static pthread_t txthread, rxthread;
static int txsock, rxsock;
static mqd_t mq;
static int txcount, rxcount;
static int overruns;
static int repeater;

struct rtt_stat {
    long long rtt;

```

```

    long long rtt_min;
    long long rtt_max;
    long long rtt_sum;
    long long rtt_sum_last;
    int counts_per_sec;
};

static void print_usage(char *prg)
{
    fprintf(stderr,
        "Usage: %s [Options] <tx-can-interface> <rx-can-interface>\n"
        "Options:\n"
        "  -h, --help      This help\n"
        "  -r, --repeater  Repeater, send back received messages\n"
        "  -i, --id=ID     CAN Identifier (default = 0x1)\n"
        "  -c, --cycle     Cycle time in us (default = 10000us)\n",
        prg);
}

void *transmitter(void *arg)
{
    struct sched_param param = { .sched_priority = 80 };
    struct timespec next_period;
    struct timespec time;
    struct can_frame frame;
    long long *rtt_time = (long long *)&frame.data;

    /* Pre-fill CAN frame */
    frame.can_id = can_id;
    frame.can_dlc = sizeof(*rtt_time);

    pthread_setschedparam(pthread_self(), SCHED_FIFO, &param);

    clock_gettime(CLOCK_MONOTONIC, &next_period);

    while(1) {
        next_period.tv_nsec += cycle * 1000;
        while (next_period.tv_nsec >= NSEC_PER_SEC) {
            next_period.tv_nsec -= NSEC_PER_SEC;
            next_period.tv_sec++;
        }

        clock_nanosleep(CLOCK_MONOTONIC, TIMER_ABSTIME, &next_period, NULL);

        if (rxcount != txcount) {
            overruns++;
            continue;
        }

        clock_gettime(CLOCK_MONOTONIC, &time);
        *rtt_time = time.tv_sec * NSEC_PER_SEC + time.tv_nsec;

        /* Transmit the message containing the local time */
        if (send(txsock, (void *)&frame, sizeof(can_frame_t), 0) < 0) {
            if (errno == EBADF)
                printf("terminating transmitter thread\n");
            else
                perror("send failed");
            return NULL;
        }
        txcount++;
    }
}

void *receiver(void *arg)
{

```



```

struct sched_param param = { .sched_priority = 82 };
struct timespec time;
struct can_frame frame;
long long *rtt_time = (long long *)frame.data;
struct rtt_stat rtt_stat = {0, 1000000000000000LL, -1000000000000000LL,
                          0, 0, 0};
pthread_setschedparam(pthread_self(), SCHED_FIFO, &param);

rtt_stat.counts_per_sec = 1000000 / cycle;

while (1) {
    if (recv(rxsock, (void *)&frame, sizeof(can_frame_t), 0) < 0) {
        if (errno == EBADF)
            printf("terminating receiver thread\n");
        else
            perror("recv failed");
        return NULL;
    }
    if (repeater) {
        /* Transmit the message back as is */
        if (send(txsock, (void *)&frame, sizeof(can_frame_t), 0) < 0) {
            if (errno == EBADF)
                printf("terminating transmitter thread\n");
            else
                perror("send failed");
            return NULL;
        }
        txcount++;
    } else {
        clock_gettime(CLOCK_MONOTONIC, &time);
        if (rxcount > 0) {
            rtt_stat.rtt = (time.tv_sec * 1000000000LL +
                          time.tv_nsec - *rtt_time);
            rtt_stat.rtt_sum += rtt_stat.rtt;
            if (rtt_stat.rtt < rtt_stat.rtt_min)
                rtt_stat.rtt_min = rtt_stat.rtt;
            if (rtt_stat.rtt > rtt_stat.rtt_max)
                rtt_stat.rtt_max = rtt_stat.rtt;
        }
        rxcount++;

        if ((rxcount % rtt_stat.counts_per_sec) == 0) {
            mq_send(mq, (char *)&rtt_stat, sizeof(rtt_stat), 0);
            rtt_stat.rtt_sum_last = rtt_stat.rtt_sum;
        }
    }
}

void catch_signal(int sig)
{
    mq_close(mq);
}

int main(int argc, char *argv[])
{
    struct sched_param param = { .sched_priority = 1 };
    pthread_attr_t thattr;
    struct mq_attr mqattr;
    struct sockaddr_can rxaddr, txaddr;
    struct can_filter rxfilter[1];
    struct rtt_stat rtt_stat;
    char mqname[32];
    char *txdev, *rxdev;
    struct ifreq ifr;
    int ret, opt;

```

```

struct option long_options[] = {
    { "id", required_argument, 0, 'i'},
    { "cycle", required_argument, 0, 'c'},
    { "repeater", required_argument, 0, 'r'},
    { "help", no_argument, 0, 'h'},
    { 0, 0, 0, 0},
};

while ((opt = getopt_long(argc, argv, "hri:c:",
                          long_options, NULL)) != -1) {
    switch (opt) {
    case 'c':
        cycle = atoi(optarg);
        break;

    case 'i':
        can_id = strtoul(optarg, NULL, 0);
        break;

    case 'r':
        repeater = 1;
        break;

    default:
        fprintf(stderr, "Unknown option %c\n", opt);
    case 'h':
        print_usage(argv[0]);
        exit(-1);
    }
}

printf("%d %d\n", optind, argc);
if (optind + 2 != argc) {
    print_usage(argv[0]);
    exit(0);
}

txdev = argv[optind];
rxdev = argv[optind + 1];

/* Create and configure RX socket */
if ((rxsock = socket(PF_CAN, SOCK_RAW, CAN_RAW)) < 0) {
    perror("RX socket failed");
    return -1;
}

strncpy(ifr.ifr_name, rxdev, IFNAMSIZ);
printf("RX rxsock=%d, ifr_name=%s\n", rxsock, ifr.ifr_name);

if (ioctl(rxsock, SIOCGIFINDEX, &ifr) < 0) {
    perror("RX ioctl SIOCGIFINDEX failed");
    goto failure1;
}

/* We only want to receive our own messages */
rxfilter[0].can_id = can_id;
rxfilter[0].can_mask = 0x3ff;
if (setsockopt(rxsock, SOL_CAN_RAW, CAN_RAW_FILTER,
              &rxfilter, sizeof(struct can_filter)) < 0) {
    perror("RX setsockopt CAN_RAW_FILTER failed");
    goto failure1;
}
memset(&rxaddr, 0, sizeof(rxaddr));
rxaddr.can_ifindex = ifr.ifr_ifindex;
rxaddr.can_family = AF_CAN;
if (bind(rxsock, (struct sockaddr *)&rxaddr, sizeof(rxaddr)) < 0) {

```

```

        perror("RX bind failed\n");
        goto failure1;
    }

    /* Create and configure TX socket */

    if (strcmp(rxdev, txdev) == 0) {
        txsock = rxsock;
    } else {
        if ((txsock = socket(PF_CAN, SOCK_RAW, 0)) < 0) {
            perror("TX socket failed");
            goto failure1;
        }

        strncpy(ifr.ifr_name, txdev, IFNAMSIZ);
        printf("TX txsock=%d, ifr_name=%s\n", txsock, ifr.ifr_name);

        if (ioctl(txsock, SIOCGIFINDEX, &ifr) < 0) {
            perror("TX ioctl SIOCGIFINDEX failed");
            goto failure2;
        }

        /* Suppress definition of a default receive filter list */
        if (setsockopt(txsock, SOL_CAN_RAW, CAN_RAW_FILTER, NULL, 0) < 0) {
            perror("TX setsockopt CAN_RAW_FILTER failed");
            goto failure2;
        }

        memset(&txaddr, 0, sizeof(txaddr));
        txaddr.can_ifindex = ifr.ifr_ifindex;
        txaddr.can_family = AF_CAN;

        if (bind(txsock, (struct sockaddr *)&txaddr, sizeof(txaddr)) < 0) {
            perror("TX bind failed\n");
            goto failure2;
        }
    }

    signal(SIGTERM, catch_signal);
    signal(SIGINT, catch_signal);
    signal(SIGHUP, catch_signal);
    mlockall(MCL_CURRENT|MCL_FUTURE);

    printf("Round-Trip-Time test %s -> %s with CAN ID 0x%x\n",
          argv[optind], argv[optind + 1], can_id);
    printf("Cycle time: %d us\n", cycle);
    printf("All RTT timing figures are in us.\n");

    /* Create statistics message queue */
    snprintf(mqname, sizeof(mqname), "/rtcan_rtt-%d", getpid());
    mqattr.mq_flags = 0;
    mqattr.mq_maxmsg = 100;
    mqattr.mq_msgsize = sizeof(struct rtt_stat);
    mq = mq_open(mqname, O_RDWR | O_CREAT | O_EXCL, 0600, &mqattr);
    if (mq == (mqd_t)-1) {
        perror("opening mqueue failed");
        goto failure2;
    }

    /* Create receiver RT-thread */
    pthread_attr_init(&thattr);
    pthread_attr_setdetachstate(&thattr, PTHREAD_CREATE_JOINABLE);
    pthread_attr_setstacksize(&thattr, PTHREAD_STACK_MIN);
    ret = pthread_create(&rxthread, &thattr, &receiver, NULL);
    if (ret) {
        fprintf(stderr, "%s: pthread_create(receiver) failed\n",
              strerror(-ret));
    }

```

```

    goto failure3;
}

if (!repeater) {
    /* Create transitter RT-thread */
    ret = pthread_create(&txthread, &thattr, &transmitter, NULL);
    if (ret) {
        fprintf(stderr, "%s: pthread_create(transmitter) failed\n",
                strerror(-ret));
        goto failure4;
    }
}

pthread_setschedparam(pthread_self(), SCHED_FIFO, &param);

if (repeater)
    printf("Messages\n");
else
    printf("Messages RTTlast RTT_avg RTT_min RTT_max Overruns\n");

while (1) {
    long long rtt_avg;

    ret = mq_receive(mq, (char *)&rtt_stat, sizeof(rtt_stat), NULL);
    if (ret != sizeof(rtt_stat)) {
        if (ret < 0) {
            if (errno == EBADF)
                printf("terminating mq_receive\n");
            else
                perror("mq_receive failed");
        } else
            fprintf(stderr,
                    "mq_receive returned invalid length %d\n", ret);
        break;
    }

    if (repeater) {
        printf("%8d\n", rxcount);
    } else {
        rtt_avg = ((rtt_stat.rtt_sum - rtt_stat.rtt_sum_last) /
                  rtt_stat.counts_per_sec);
        printf("%8d %7ld %7ld %7ld %7ld %8d\n", rxcount,
              (long)(rtt_stat.rtt / 1000), (long)(rtt_avg / 1000),
              (long)(rtt_stat.rtt_min / 1000),
              (long)(rtt_stat.rtt_max / 1000),
              overruns);
    }
}

/* This call also leaves primary mode, required for socket cleanup. */
printf("shutting down\n");

/* Important: First close the sockets! */
while ((close(rxsock) < 0) && (errno == EAGAIN)) {
    printf("RX socket busy - waiting...\n");
    sleep(1);
}
while ((close(txsock) < 0) && (errno == EAGAIN)) {
    printf("TX socket busy - waiting...\n");
    sleep(1);
}

pthread_join(txthread, NULL);
pthread_kill(rxthread, SIGHUP);
pthread_join(rxthread, NULL);

return 0;

```

```
failure4:
    pthread_kill(rxthread, SIGHUP);
    pthread_join(rxthread, NULL);
failure3:
    mq_close(mq);
failure2:
    close(txsock);
failure1:
    close(rxsock);

    return 1;
}
```

8.3 rtcanconfig.c

```

/*
 * Program to configuring the CAN controller
 *
 * Copyright (C) 2006 Wolfgang Grandegger <wg@grandegger.com>
 *
 * Copyright (C) 2005, 2006 Sebastian Smolorz
 *                               <Sebastian.Smolorz@stud.uni-hannover.de>
 *
 *
 * This program is free software; you can redistribute it and/or modify
 * it under the terms of the GNU General Public License as published by
 * the Free Software Foundation; either version 2 of the License, or
 * (at your option) any later version.
 *
 * This program is distributed in the hope that it will be useful,
 * but WITHOUT ANY WARRANTY; without even the implied warranty of
 * MERCHANTABILITY or FITNESS FOR A PARTICULAR PURPOSE. See the
 * GNU General Public License for more details.
 *
 * You should have received a copy of the GNU General Public License
 * along with this program; if not, write to the Free Software
 * Foundation, Inc., 675 Mass Ave, Cambridge, MA 02139, USA.
 */

#include <stdio.h>
#include <stdlib.h>
#include <signal.h>
#include <unistd.h>
#include <string.h>
#include <time.h>
#include <errno.h>
#include <getopt.h>
#include <sys/mman.h>

#include <rtcm/rtcan.h>

static void print_usage(char *prg)
{
    fprintf(stderr,
        "Usage: %s <can-interface> [Options] [up|down|start|stop|sleep]\n"
        "Options:\n"
        "  -v, --verbose           be verbose\n"
        "  -h, --help             this help\n"
        "  -c, --ctrlmode=CTRLMODE listenonly, loopback or none\n"
        "  -b, --baudrate=BPS      baudrate in bits/sec\n"
        "  -B, --bittime=BTR0:BTR1 BTR or standard bit-time\n"
        "  -B, --bittime=BRP:PROP_SEG:PHASE_SEG1:PHASE_SEG2:SJW:SAM\n",
        prg);
}

can_baudrate_t string_to_baudrate(char *str)
{
    can_baudrate_t baudrate;
    if (sscanf(str, "%i", &baudrate) != 1)
        return -1;
    return baudrate;
}

int string_to_mode(char *str)
{
    if ( !strcmp(str, "up") || !strcmp(str, "start") )
        return CAN_MODE_START;
    else if ( !strcmp(str, "down") || !strcmp(str, "stop") )
        return CAN_MODE_STOP;
    else if ( !strcmp(str, "sleep") )

```

```

        return CAN_MODE_SLEEP;
    return -EINVAL;
}

int string_to_ctrlmode(char *str)
{
    if ( !strcmp(str, "listenonly") )
        return CAN_CTRLMODE_LISTENONLY;
    else if ( !strcmp(str, "loopback") )
        return CAN_CTRLMODE_LOOPBACK;
    else if ( !strcmp(str, "none") )
        return 0;

    return -1;
}

int main(int argc, char *argv[])
{
    char    ifname[16];
    int     can_fd = -1;
    int     new_baudrate = -1;
    int     new_mode = -1;
    int     new_ctrlmode = 0, set_ctrlmode = 0;
    int     verbose = 0;
    int     bittime_count = 0, bittime_data[6];
    struct  ifreq ifr;
    can_baudrate_t *baudrate;
    can_ctrlmode_t *ctrlmode;
    can_mode_t *mode;
    struct  can_bittime *bittime;
    int opt, ret;
    char* ptr;

    struct option long_options[] = {
        { "help", no_argument, 0, 'h' },
        { "verbose", no_argument, 0, 'v' },
        { "baudrate", required_argument, 0, 'b' },
        { "bittime", required_argument, 0, 'B' },
        { "ctrlmode", required_argument, 0, 'c' },
        { 0, 0, 0, 0 },
    };

    while ((opt = getopt_long(argc, argv, "hvb:B:c:",
                             long_options, NULL)) != -1) {
        switch (opt) {
            case 'h':
                print_usage(argv[0]);
                exit(0);

            case 'v':
                verbose = 1;
                break;

            case 'b':
                new_baudrate = string_to_baudrate(optarg);
                if (new_baudrate == -1) {
                    print_usage(argv[0]);
                    exit(0);
                }
                break;

            case 'B':
                ptr = optarg;
                while (1) {
                    bittime_data[bittime_count++] = strtoul(ptr, NULL, 0);
                    if (!(ptr = strchr(ptr, ':')))
                        break;
                }
                break;
        }
    }

```

```

        ptr++;
    }
    if (bittime_count != 2 && bittime_count != 6) {
        print_usage(argv[0]);
        exit(0);
    }
    break;

case 'c':
    ret = string_to_ctrlmode(optarg);
    if (ret == -1) {
        print_usage(argv[0]);
        exit(0);
    }
    new_ctrlmode |= ret;
    set_ctrlmode = 1;
    break;

    break;

default:
    fprintf(stderr, "Unknown option %c\n", opt);
    break;
}
}

/* Get CAN interface name */
if (optind != argc - 1 && optind != argc - 2) {
    print_usage(argv[0]);
    return 0;
}

strncpy(iframe, argv[optind], IFNAMSIZ);
strncpy(ifr.ifr_name, iframe, IFNAMSIZ);

if (optind == argc - 2) { /* Get mode setting */
    new_mode = string_to_mode(argv[optind + 1]);
    if (verbose)
        printf("mode: %s (%#x)\n", argv[optind + 1], new_mode);
    if (new_mode < 0) {
        print_usage(argv[0]);
        return 0;
    }
}

can_fd = rt_dev_socket(PF_CAN, SOCK_RAW, CAN_RAW);
if (can_fd < 0) {
    fprintf(stderr, "Cannot open RTDM CAN socket. Maybe driver not loaded? \n");
    return can_fd;
}

ret = rt_dev_ioctl(can_fd, SIOCGIFINDEX, &ifr);
if (ret) {
    fprintf(stderr, "Can't get interface index for %s, code = %d\n", iframe, ret);
    return ret;
}

if (new_baudrate != -1) {
    if (verbose)
        printf("baudrate: %d\n", new_baudrate);
    baudrate = (can_baudrate_t *)&ifr.ifr_ifru;
    *baudrate = new_baudrate;
    ret = rt_dev_ioctl(can_fd, SIOCSCANBAUDRATE, &ifr);
    if (ret) {
        goto abort;
    }
}

```



```

    }

    if (bittime_count) {
        bittime = (struct can_bittime *)&ifr.ifr_ifru;
        if (bittime_count == 2) {
            bittime->type = CAN_BITTIME_BTR;
            bittime->btr.btr0 = bittime_data[0];
            bittime->btr.btr1 = bittime_data[1];
            if (verbose)
                printf("bit-time: btr0=0x%02x btr1=0x%02x\n",
                       bittime->btr.btr0, bittime->btr.btr1);
        } else {
            bittime->type = CAN_BITTIME_STD;
            bittime->std.brp = bittime_data[0];
            bittime->std.prop_seg = bittime_data[1];
            bittime->std.phase_seg1 = bittime_data[2];
            bittime->std.phase_seg2 = bittime_data[3];
            bittime->std.sjw = bittime_data[4];
            bittime->std.sam = bittime_data[5];
            if (verbose)
                printf("bit-time: brp=%d prop_seg=%d phase_seg1=%d "
                       "phase_seg2=%d sjw=%d sam=%d\n",
                       bittime->std.brp,
                       bittime->std.prop_seg,
                       bittime->std.phase_seg1,
                       bittime->std.phase_seg2,
                       bittime->std.sjw,
                       bittime->std.sam);
        }

        ret = rt_dev_ioctl(can_fd, SIOCSCANCUSTOMBITTIME, &ifr);
        if (ret) {
            goto abort;
        }
    }

    if (set_ctrlmode != 0) {
        ctrlmode = (can_ctrlmode_t *)&ifr.ifr_ifru;
        *ctrlmode = new_ctrlmode;
        if (verbose)
            printf("ctrlmode: %#x\n", new_ctrlmode);
        ret = rt_dev_ioctl(can_fd, SIOCSCANCTRLMODE, &ifr);
        if (ret) {
            goto abort;
        }
    }

    if (new_mode != -1) {
        mode = (can_mode_t *)&ifr.ifr_ifru;
        *mode = new_mode;
        ret = rt_dev_ioctl(can_fd, SIOCSCANMODE, &ifr);
        if (ret) {
            goto abort;
        }
    }

    rt_dev_close(can_fd);
    return 0;

abort:
    rt_dev_close(can_fd);
    return ret;
}

```

8.4 rtcanrecv.c

```
#include <stdio.h>
#include <stdlib.h>
#include <signal.h>
#include <unistd.h>
#include <time.h>
#include <errno.h>
#include <getopt.h>
#include <sys/mman.h>

#include <native/task.h>
#include <native/pipe.h>

#include <rtcm/rtdm.h>

static void print_usage(char *prg)
{
    fprintf(stderr,
        "Usage: %s [<can-interface>] [Options]\n"
        "Options:\n"
        " -f --filter=id:mask[:id:mask]... apply filter\n"
        " -e --error=mask      receive error messages\n"
        " -t, --timeout=MS      timeout in ms\n"
        " -T, --timestamp      with absolute timestamp\n"
        " -R, --timestamp-rel   with relative timestamp\n"
        " -v, --verbose         be verbose\n"
        " -p, --print=MODULO    print every MODULO message\n"
        " -h, --help           this help\n",
        prg);
}

extern int optind, opterr, optopt;

static int s = -1, verbose = 0, print = 1;
static nanosecs_rel_t timeout = 0, with_timestamp = 0, timestamp_rel = 0;

RT_TASK rt_task_desc;

#define BUF_SIZ 255
#define MAX_FILTER 16

struct sockaddr_can recv_addr;
struct can_filter recv_filter[MAX_FILTER];
static int filter_count = 0;

int add_filter(u_int32_t id, u_int32_t mask)
{
    if (filter_count >= MAX_FILTER)
        return -1;
    recv_filter[filter_count].can_id = id;
    recv_filter[filter_count].can_mask = mask;
    printf("Filter #%d: id=0x%08x mask=0x%08x\n", filter_count, id, mask);
    filter_count++;
    return 0;
}

void cleanup(void)
{
    int ret;

    if (verbose)
        printf("Cleaning up...\n");

    if (s >= 0) {
        ret = rt_dev_close(s);
    }
}
```

```

        s = -1;
        if (ret) {
            fprintf(stderr, "rt_dev_close: %s\n", strerror(-ret));
        }
        rt_task_delete(&rt_task_desc);
    }
}

void cleanup_and_exit(int sig)
{
    if (verbose)
        printf("Signal %d received\n", sig);
    cleanup();
    exit(0);
}

void rt_task(void)
{
    int i, ret, count = 0;
    struct can_frame frame;
    struct sockaddr_can addr;
    socklen_t addrlen = sizeof(addr);
    struct msghdr msg;
    struct iovec iov;
    nanosecs_abs_t timestamp, timestamp_prev = 0;

    if (with_timestamp) {
        msg.msg_iov = &iov;
        msg.msg_iovlen = 1;
        msg.msg_name = (void *)&addr;
        msg.msg_namelen = sizeof(struct sockaddr_can);
        msg.msg_control = (void *)&timestamp;
        msg.msg_controllen = sizeof(nanosecs_abs_t);
    }

    while (1) {
        if (with_timestamp) {
            iov.iov_base = (void *)&frame;
            iov.iov_len = sizeof(can_frame_t);
            ret = rt_dev_recvmsg(s, &msg, 0);
        } else
            ret = rt_dev_recvfrom(s, (void *)&frame, sizeof(can_frame_t), 0,
                                (struct sockaddr *)&addr, &addrlen);

        if (ret < 0) {
            switch (ret) {
                case -ETIMEDOUT:
                    if (verbose)
                        printf("rt_dev_recv: timed out");
                    continue;
                case -EBADF:
                    if (verbose)
                        printf("rt_dev_recv: aborted because socket was closed");
                    break;
                default:
                    fprintf(stderr, "rt_dev_recv: %s\n", strerror(-ret));
            }
            break;
        }

        if (print && (count % print) == 0) {
            printf("#%d: (%d) ", count, addr.can_ifindex);
            if (with_timestamp && msg.msg_controllen) {
                if (timestamp_rel) {
                    printf("%lldns ", (long long)(timestamp - timestamp_prev));
                    timestamp_prev = timestamp;
                } else
                    printf("%lldns ", (long long)timestamp);
            }
        }
    }
}

```

```

    }
    if (frame.can_id & CAN_ERR_FLAG)
        printf("!0x%08x!", frame.can_id & CAN_ERR_MASK);
    else if (frame.can_id & CAN EFF_FLAG)
        printf("<0x%08x>", frame.can_id & CAN EFF_MASK);
    else
        printf("<0x%03x>", frame.can_id & CAN_SFF_MASK);

    printf(" [%d]", frame.can_dlc);
    if (!(frame.can_id & CAN_RTR_FLAG))
        for (i = 0; i < frame.can_dlc; i++) {
            printf(" %02x", frame.data[i]);
        }
    if (frame.can_id & CAN_ERR_FLAG) {
        printf(" ERROR ");
        if (frame.can_id & CAN_ERR_BUSOFF)
            printf("bus-off");
        if (frame.can_id & CAN_ERR_CRTL)
            printf("controller problem");
    } else if (frame.can_id & CAN_RTR_FLAG)
        printf(" remote request");
    printf("\n");
}
count++;
}
}

int main(int argc, char **argv)
{
    int opt, ret;
    u_int32_t id, mask;
    u_int32_t err_mask = 0;
    struct ifreq ifr;
    char *ptr;
    char name[32];

    struct option long_options[] = {
        { "help", no_argument, 0, 'h' },
        { "verbose", no_argument, 0, 'v' },
        { "filter", required_argument, 0, 'f' },
        { "error", required_argument, 0, 'e' },
        { "timeout", required_argument, 0, 't' },
        { "timestamp", no_argument, 0, 'T' },
        { "timestamp-rel", no_argument, 0, 'R' },
        { 0, 0, 0, 0 },
    };

    mlockall(MCL_CURRENT | MCL_FUTURE);

    signal(SIGTERM, cleanup_and_exit);
    signal(SIGINT, cleanup_and_exit);

    while ((opt = getopt_long(argc, argv, "hve:f:t:p:RT",
                             long_options, NULL)) != -1) {
        switch (opt) {
            case 'h':
                print_usage(argv[0]);
                exit(0);

            case 'p':
                print = strtoul(optarg, NULL, 0);
                break;

            case 'v':
                verbose = 1;
                break;
        }
    }

```

```

    case 'e':
        err_mask = strtoul(optarg, NULL, 0);
        break;

    case 'f':
        ptr = optarg;
        while (1) {
            id = strtoul(ptr, NULL, 0);
            ptr = strchr(ptr, ':');
            if (!ptr) {
                fprintf(stderr, "filter must be applied in the form id:mask[:id:mask]...\n");
                exit(1);
            }
            ptr++;
            mask = strtoul(ptr, NULL, 0);
            ptr = strchr(ptr, ':');
            add_filter(id, mask);
            if (!ptr)
                break;
            ptr++;
        }
        break;

    case 't':
        timeout = (nanosecs_rel_t)strtoul(optarg, NULL, 0) * 1000000;
        break;

    case 'R':
        timestamp_rel = 1;
    case 'T':
        with_timestamp = 1;
        break;

    default:
        fprintf(stderr, "Unknown option %c\n", opt);
        break;
}

ret = rt_dev_socket(PF_CAN, SOCK_RAW, CAN_RAW);
if (ret < 0) {
    fprintf(stderr, "rt_dev_socket: %s\n", strerror(-ret));
    return -1;
}
s = ret;

if (argv[optind] == NULL) {
    if (verbose)
        printf("interface all\n");

    ifr.ifr_ifindex = 0;
} else {
    if (verbose)
        printf("interface %s\n", argv[optind]);

    strncpy(ifr.ifr_name, argv[optind], IFNAMSIZ);
    if (verbose)
        printf("s=%d, ifr_name=%s\n", s, ifr.ifr_name);

    ret = rt_dev_ioctl(s, SIOCGIFINDEX, &ifr);
    if (ret < 0) {
        fprintf(stderr, "rt_dev_ioctl GET_IFINDEX: %s\n", strerror(-ret));
        goto failure;
    }
}

if (err_mask) {

```

```

    ret = rt_dev_setsockopt(s, SOL_CAN_RAW, CAN_RAW_ERR_FILTER,
                           &err_mask, sizeof(err_mask));
    if (ret < 0) {
        fprintf(stderr, "rt_dev_setsockopt: %s\n", strerror(-ret));
        goto failure;
    }
    if (verbose)
        printf("Using err_mask=0x%x\n", err_mask);
}

if (filter_count) {
    ret = rt_dev_setsockopt(s, SOL_CAN_RAW, CAN_RAW_FILTER,
                           &recv_filter, filter_count *
                           sizeof(struct can_filter));

    if (ret < 0) {
        fprintf(stderr, "rt_dev_setsockopt: %s\n", strerror(-ret));
        goto failure;
    }
}

recv_addr.can_family = AF_CAN;
recv_addr.can_ifindex = ifr.ifr_ifindex;
ret = rt_dev_bind(s, (struct sockaddr *)&recv_addr,
                  sizeof(struct sockaddr_can));
if (ret < 0) {
    fprintf(stderr, "rt_dev_bind: %s\n", strerror(-ret));
    goto failure;
}

if (timeout) {
    if (verbose)
        printf("Timeout: %lld ns\n", (long long)timeout);
    ret = rt_dev_ioctl(s, RTCAN_RTIOC_RCV_TIMEOUT, &timeout);
    if (ret) {
        fprintf(stderr, "rt_dev_ioctl RCV_TIMEOUT: %s\n", strerror(-ret));
        goto failure;
    }
}

if (with_timestamp) {
    ret = rt_dev_ioctl(s, RTCAN_RTIOC_TAKE_TIMESTAMP, RTCAN_TAKE_TIMESTAMPS);
    if (ret) {
        fprintf(stderr, "rt_dev_ioctl TAKE_TIMESTAMP: %s\n", strerror(-ret));
        goto failure;
    }
}

snprintf(name, sizeof(name), "rtcanrecv-%d", getpid());
ret = rt_task_shadow(&rt_task_desc, name, 0, 0);
if (ret) {
    fprintf(stderr, "rt_task_shadow: %s\n", strerror(-ret));
    goto failure;
}

rt_task();
/* never returns */

failure:
    cleanup();
    return -1;
}

```

8.5 rtcanseend.c

```

#include <stdio.h>
#include <stdlib.h>
#include <signal.h>
#include <unistd.h>
#include <time.h>
#include <errno.h>
#include <getopt.h>
#include <sys/mman.h>

#include <native/task.h>
#include <native/timer.h>
#include <native/pipe.h>

#include <rtcm/rtcan.h>

extern int optind, opterr, optopt;

static void print_usage(char *prg)
{
    fprintf(stderr,
        "Usage: %s <can-interface> [Options] <can-msg>\n"
        "<can-msg> can consist of up to 8 bytes given as a space separated list\n"
        "Options:\n"
        " -i, --identifier=ID    CAN Identifier (default = 1)\n"
        " -r --rtr              send remote request\n"
        " -e --extended          send extended frame\n"
        " -l --loop=COUNT      send message COUNT times\n"
        " -c, --count            message count in data[0-3]\n"
        " -d, --delay=MS         delay in ms (default = 1ms)\n"
        " -s, --send             use send instead of sendto\n"
        " -t, --timeout=MS       timeout in ms\n"
        " -L, --loopback=0|1     switch local loopback off or on\n"
        " -v, --verbose          be verbose\n"
        " -p, --print=MODULO     print every MODULO message\n"
        " -h, --help             this help",
        prg);
}

RT_TASK rt_task_desc;

static int s=-1, dlc=0, rtr=0, extended=0, verbose=0, loops=1;
static SRTIME delay=1000000;
static int count=0, print=1, use_send=0, loopback=-1;
static nanosecs_rel_t timeout = 0;
static struct can_frame frame;
static struct sockaddr_can to_addr;

void cleanup(void)
{
    int ret;

    if (verbose)
        printf("Cleaning up...\n");

    usleep(100000);

    if (s >= 0) {
        ret = rt_dev_close(s);
        s = -1;
        if (ret) {
            fprintf(stderr, "rt_dev_close: %s\n", strerror(-ret));
        }
        rt_task_delete(&rt_task_desc);
    }
}

```

```

    }
}

void cleanup_and_exit(int sig)
{
    if (verbose)
        printf("Signal %d received\n", sig);
    cleanup();
    exit(0);
}

void rt_task(void)
{
    int i, j, ret;

    for (i = 0; i < loops; i++) {
        rt_task_sleep(rt_timer_ns2ticks(delay));
        if (count)
            memcpy(&frame.data[0], &i, sizeof(i));
        /* Note: sendto avoids the definition of a receive filter list */
        if (use_send)
            ret = rt_dev_send(s, (void *)&frame, sizeof(can_frame_t), 0);
        else
            ret = rt_dev_sendto(s, (void *)&frame, sizeof(can_frame_t), 0,
                                (struct sockaddr *)&to_addr, sizeof(to_addr));

        if (ret < 0) {
            switch (ret) {
                case -ETIMEDOUT:
                    if (verbose)
                        printf("rt_dev_send(to): timed out");
                    break;
                case -EBADF:
                    if (verbose)
                        printf("rt_dev_send(to): aborted because socket was closed");
                    break;
                default:
                    fprintf(stderr, "rt_dev_send: %s\n", strerror(-ret));
                    break;
            }
            i = loops;          /* abort */
            break;
        }
        if (verbose && (i % print) == 0) {
            if (frame.can_id & CAN_EFF_FLAG)
                printf("<0x%08x>", frame.can_id & CAN_EFF_MASK);
            else
                printf("<0x%03x>", frame.can_id & CAN_SFF_MASK);
            printf(" [%d]", frame.can_dlc);
            for (j = 0; j < frame.can_dlc; j++) {
                printf(" %02x", frame.data[j]);
            }
            printf("\n");
        }
    }
}

int main(int argc, char **argv)
{
    int i, opt, ret;
    struct ifreq ifr;
    char name[32];

    struct option long_options[] = {
        { "help", no_argument, 0, 'h' },
        { "identifier", required_argument, 0, 'i' },
        { "rtr", no_argument, 0, 'r' },
        { "extended", no_argument, 0, 'e' },
    };

```



```

    { "verbose", no_argument, 0, 'v'},
    { "count", no_argument, 0, 'c'},
    { "print", required_argument, 0, 'p'},
    { "loop", required_argument, 0, 'l'},
    { "delay", required_argument, 0, 'd'},
    { "send", no_argument, 0, 's'},
    { "timeout", required_argument, 0, 't'},
    { "loopback", required_argument, 0, 'L'},
    { 0, 0, 0, 0},
};

mlockall(MCL_CURRENT | MCL_FUTURE);

signal(SIGTERM, cleanup_and_exit);
signal(SIGINT, cleanup_and_exit);

frame.can_id = 1;

while ((opt = getopt_long(argc, argv, "hvi:l:red:t:cp:sL:",
                           long_options, NULL)) != -1) {
    switch (opt) {
        case 'h':
            print_usage(argv[0]);
            exit(0);

        case 'p':
            print = strtoul(optarg, NULL, 0);

        case 'v':
            verbose = 1;
            break;

        case 'c':
            count = 1;
            break;

        case 'l':
            loops = strtoul(optarg, NULL, 0);
            break;

        case 'i':
            frame.can_id = strtoul(optarg, NULL, 0);
            break;

        case 'r':
            rtr = 1;
            break;

        case 'e':
            extended = 1;
            break;

        case 'd':
            delay = strtoul(optarg, NULL, 0) * 1000000LL;
            break;

        case 's':
            use_send = 1;
            break;

        case 't':
            timeout = strtoul(optarg, NULL, 0) * 1000000LL;
            break;

        case 'L':
            loopback = strtoul(optarg, NULL, 0);
            break;
    }
}

```

```

        default:
            fprintf(stderr, "Unknown option %c\n", opt);
            break;
    }
}

if (optind == argc) {
    print_usage(argv[0]);
    exit(0);
}

if (argv[optind] == NULL) {
    fprintf(stderr, "No Interface supplied\n");
    exit(-1);
}

if (verbose)
    printf("interface %s\n", argv[optind]);

ret = rt_dev_socket(PF_CAN, SOCK_RAW, CAN_RAW);
if (ret < 0) {
    fprintf(stderr, "rt_dev_socket: %s\n", strerror(-ret));
    return -1;
}
s = ret;

if (loopback >= 0) {
    ret = rt_dev_setsockopt(s, SOL_CAN_RAW, CAN_RAW_LOOPBACK,
                           &loopback, sizeof(loopback));

    if (ret < 0) {
        fprintf(stderr, "rt_dev_setsockopt: %s\n", strerror(-ret));
        goto failure;
    }
    if (verbose)
        printf("Using loopback=%d\n", loopback);
}

strncpy(ifr.ifr_name, argv[optind], IFNAMSIZ);
if (verbose)
    printf("s=%d, ifr_name=%s\n", s, ifr.ifr_name);

ret = rt_dev_ioctl(s, SIOCGIFINDEX, &ifr);
if (ret < 0) {
    fprintf(stderr, "rt_dev_ioctl: %s\n", strerror(-ret));
    goto failure;
}

memset(&to_addr, 0, sizeof(to_addr));
to_addr.can_ifindex = ifr.ifr_ifindex;
to_addr.can_family = AF_CAN;
if (use_send) {
    /* Suppress definition of a default receive filter list */
    ret = rt_dev_setsockopt(s, SOL_CAN_RAW, CAN_RAW_FILTER, NULL, 0);
    if (ret < 0) {
        fprintf(stderr, "rt_dev_setsockopt: %s\n", strerror(-ret));
        goto failure;
    }
}

ret = rt_dev_bind(s, (struct sockaddr *)&to_addr, sizeof(to_addr));
if (ret < 0) {
    fprintf(stderr, "rt_dev_bind: %s\n", strerror(-ret));
    goto failure;
}
}

if (count)

```

```
    frame.can_dlc = sizeof(int);
else {
    for (i = optind + 1; i < argc; i++) {
        frame.data[dlc] = strtoul(argv[i], NULL, 0);
        dlc++;
        if( dlc == 8 )
            break;
    }
    frame.can_dlc = dlc;
}

if (rtr)
    frame.can_id |= CAN_RTR_FLAG;

if (extended)
    frame.can_id |= CAN_EFF_FLAG;

if (timeout) {
    if (verbose)
        printf("Timeout: %lld ns\n", (long long)timeout);
    ret = rt_dev_ioctl(s, RTCAN_RTIOC_SND_TIMEOUT, &timeout);
    if (ret) {
        fprintf(stderr, "rt_dev_ioctl SND_TIMEOUT: %s\n", strerror(-ret));
        goto failure;
    }
}

snprintf(name, sizeof(name), "rtcansend-%d", getpid());
ret = rt_task_shadow(&rt_task_desc, name, 1, 0);
if (ret) {
    fprintf(stderr, "rt_task_shadow: %s\n", strerror(-ret));
    goto failure;
}

rt_task();

cleanup();
return 0;

failure:
    cleanup();
    return -1;
}
```

Index

- CAN Devices, [9](#)
- CAN_BITTIME_BTR
 - [rtcan, 31](#)
- CAN_BITTIME_STD
 - [rtcan, 31](#)
- CAN_MODE_SLEEP
 - [rtcan, 31](#)
- CAN_MODE_START
 - [rtcan, 31](#)
- CAN_MODE_STOP
 - [rtcan, 31](#)
- CAN_STATE_ACTIVE
 - [rtcan, 31](#)
- CAN_STATE_BUS_OFF
 - [rtcan, 31](#)
- CAN_STATE_BUS_PASSIVE
 - [rtcan, 31](#)
- CAN_STATE_BUS_WARNING
 - [rtcan, 31](#)
- CAN_STATE_SCANNING_BAUDRATE
 - [rtcan, 31](#)
- CAN_STATE_SLEEPING
 - [rtcan, 31](#)
- CAN_STATE_STOPPED
 - [rtcan, 31](#)
- [can_bittime, 129](#)
- [can_bittime_btr, 130](#)
- [can_bittime_std, 131](#)
- CAN_BITTIME_TYPE
 - [rtcan, 31](#)
- CAN_CTRLMODE_LISTENONLY
 - [rtcan, 20](#)
- CAN_CTRLMODE_LOOPBACK
 - [rtcan, 20](#)
- CAN_ERR_LOSTARB_UNSPEC
 - [rtcan, 21](#)
- [can_filter, 132](#)
 - [can_id, 132](#)
 - [can_mask, 132](#)
- [can_frame, 133](#)
 - [can_id, 133](#)
- [can_id](#)
 - [can_filter, 132](#)
 - [can_frame, 133](#)
- [can_ifindex](#)
 - [sockaddr_can, 143](#)
- [can_mask](#)
 - [can_filter, 132](#)
- CAN_MODE
 - [rtcan, 31](#)
- CAN_RAW_ERR_FILTER
 - [rtcan, 21](#)
- CAN_RAW_FILTER
 - [rtcan, 21](#)
- CAN_RAW_LOOPBACK
 - [rtcan, 22](#)
- CAN_RAW_RECV_OWN_MSGS
 - [rtcan, 22](#)
- CAN_STATE
 - [rtcan, 31](#)
- [clock](#)
 - [rtdm_clock_read, 76](#)
 - [rtdm_clock_read_monotonic, 76](#)
- [Clock Services, 76](#)
- [Device Profiles, 127](#)
- [Device Registration Services, 66](#)
- [devregister](#)
 - [rtdm_close_handler_t, 69](#)
 - [RTDM_CLOSING, 68](#)
 - [RTDM_CREATED_IN_NRT, 68](#)
 - [rtdm_dev_register, 73](#)
 - [rtdm_dev_unregister, 73](#)
 - [RTDM_DEVICE_TYPE_MASK, 68](#)
 - [RTDM_EXCLUSIVE, 68](#)
 - [rtdm_ioctl_handler_t, 69](#)
 - [RTDM_NAMED_DEVICE, 69](#)
 - [rtdm_open_handler_t, 70](#)
 - [RTDM_PROTOCOL_DEVICE, 69](#)
 - [rtdm_read_handler_t, 70](#)
 - [rtdm_recvmsg_handler_t, 70](#)
 - [rtdm_select_bind_handler_t, 71](#)
 - [rtdm_sendmsg_handler_t, 71](#)
 - [rtdm_socket_handler_t, 72](#)
 - [rtdm_write_handler_t, 72](#)
- [Driver Development API, 75](#)
- [include/rtdm/rtcan.h, 145](#)
- [include/rtdm/rtdm.h, 154](#)

- include/rtdm/rtdm_driver.h, 157
- include/rtdm/rtserial.h, 164
- include/rtdm/rttesting.h, 168
- Inter-Driver API, 57
- interdrv
 - rtdm_accept, 58
 - rtdm_bind, 58
 - rtdm_close, 59
 - rtdm_connect, 59
 - rtdm_context_get, 59
 - rtdm_context_lock, 60
 - rtdm_context_unlock, 60
 - rtdm_getpeername, 61
 - rtdm_getsockname, 61
 - rtdm_getsockopt, 61
 - rtdm_ioctl, 61
 - rtdm_listen, 61
 - rtdm_open, 62
 - rtdm_read, 62
 - rtdm_recv, 62
 - rtdm_recvfrom, 62
 - rtdm_recvmsg, 62
 - rtdm_select_bind, 63
 - rtdm_send, 63
 - rtdm_sendmsg, 63
 - rtdm_sendto, 64
 - rtdm_setsockopt, 64
 - rtdm_shutdown, 64
 - rtdm_socket, 64
 - rtdm_write, 64
- Interrupt Management Services, 109
- ksrc/skins/rtdm/core.c, 177
- ksrc/skins/rtdm/device.c, 170
- ksrc/skins/rtdm/drvlib.c, 171
- ksrc/skins/rtdm/module.c, 176
- nanosecs_abs_t
 - rtdm, 33
- nanosecs_rel_t
 - rtdm, 33
- Non-Real-Time Signalling Services, 114
- nrtsignal
 - rtdm_nrtsig_destroy, 115
 - rtdm_nrtsig_handler_t, 114
 - rtdm_nrtsig_init, 115
 - rtdm_nrtsig_pend, 115
- profiles
 - RTIOC_DEVICE_INFO, 128
 - RTIOC_PURGE, 128
- Real-Time Driver Model, 32
- rt_dev_accept
 - userapi, 35
- rt_dev_bind
 - userapi, 36
- rt_dev_close
 - userapi, 36
- rt_dev_connect
 - userapi, 37
- rt_dev_getpeername
 - userapi, 37
- rt_dev_getsockname
 - userapi, 37
- rt_dev_getsockopt
 - userapi, 38
- rt_dev_ioctl
 - userapi, 38
- rt_dev_listen
 - userapi, 39
- rt_dev_open
 - userapi, 39
- rt_dev_read
 - userapi, 40
- rt_dev_recv
 - userapi, 40
- rt_dev_recvfrom
 - userapi, 41
- rt_dev_recvmsg
 - userapi, 41
- rt_dev_send
 - userapi, 42
- rt_dev_sendmsg
 - userapi, 42
- rt_dev_sendto
 - userapi, 43
- rt_dev_setsockopt
 - userapi, 43
- rt_dev_shutdown
 - userapi, 44
- rt_dev_socket
 - userapi, 44
- rt_dev_write
 - userapi, 44
- rtcan
 - CAN_BITTIME_BTR, 31
 - CAN_BITTIME_STD, 31
 - CAN_MODE_SLEEP, 31
 - CAN_MODE_START, 31
 - CAN_MODE_STOP, 31
 - CAN_STATE_ACTIVE, 31
 - CAN_STATE_BUS_OFF, 31
 - CAN_STATE_BUS_PASSIVE, 31
 - CAN_STATE_BUS_WARNING, 31
 - CAN_STATE_SCANNING_BAUDRATE, 31
 - CAN_STATE_SLEEPING, 31

- CAN_STATE_STOPPED, 31
- CAN_BITTIME_TYPE, 31
- CAN_CTRLMODE_LISTENONLY, 20
- CAN_CTRLMODE_LOOPBACK, 20
- CAN_ERR_LOSTARB_UNSPEC, 21
- CAN_MODE, 31
- CAN_RAW_ERR_FILTER, 21
- CAN_RAW_FILTER, 21
- CAN_RAW_LOOPBACK, 22
- CAN_RAW_RECV_OWN_MSGS, 22
- CAN_STATE, 31
- RTCAN_RTIOC_RCV_TIMEOUT, 22
- RTCAN_RTIOC_SND_TIMEOUT, 23
- RTCAN_RTIOC_TAKE_TIMESTAMP, 24
- SIOCGCANBAUDRATE, 24
- SIOCGCANCTRLMODE, 25
- SIOCGCANCUSTOMBITTIME, 25
- SIOCGCANSTATE, 26
- SIOCGIFINDEX, 27
- SIOCSCANBAUDRATE, 27
- SIOCSCANCTRLMODE, 28
- SIOCSCANCUSTOMBITTIME, 29
- SIOCSCANMODE, 29
- SOL_CAN_RAW, 30
- RTCAN_RTIOC_RCV_TIMEOUT
 - rtcan, 22
- RTCAN_RTIOC_SND_TIMEOUT
 - rtcan, 23
- RTCAN_RTIOC_TAKE_TIMESTAMP
 - rtcan, 24
- rtdm
 - nanosecs_abs_t, 33
 - nanosecs_rel_t, 33
 - RTDM_TIMEOUT_INFINITE, 33
 - RTDM_TIMEOUT_NONE, 33
- RTDM_SELECTTYPE_EXCEPT
 - rtdmsync, 97
- RTDM_SELECTTYPE_READ
 - rtdmsync, 97
- RTDM_SELECTTYPE_WRITE
 - rtdmsync, 97
- RTDM_TIMERMODE_ABSOLUTE
 - rtdmtimer, 87
- RTDM_TIMERMODE_REALTIME
 - rtdmtimer, 87
- RTDM_TIMERMODE_RELATIVE
 - rtdmtimer, 87
- rtdm_accept
 - interdrv, 58
- rtdm_bind
 - interdrv, 58
- rtdm_clock_read
 - clock, 76
- rtdm_clock_read_monotonic
 - clock, 76
- rtdm_close
 - interdrv, 59
- rtdm_close_handler_t
 - devregister, 69
- RTDM_CLOSING
 - devregister, 68
- rtdm_connect
 - interdrv, 59
- rtdm_context_get
 - interdrv, 59
- rtdm_context_lock
 - interdrv, 60
- rtdm_context_unlock
 - interdrv, 60
- rtdm_copy_from_user
 - util, 118
- rtdm_copy_to_user
 - util, 118
- RTDM_CREATED_IN_NRT
 - devregister, 68
- rtdm_dev_context, 134
- rtdm_dev_register
 - devregister, 73
- rtdm_dev_unregister
 - devregister, 73
- rtdm_device, 135
- rtdm_device_info, 137
- RTDM_DEVICE_TYPE_MASK
 - devregister, 68
- rtdm_event_clear
 - rtdmsync, 97
- rtdm_event_destroy
 - rtdmsync, 97
- rtdm_event_init
 - rtdmsync, 98
- rtdm_event_pulse
 - rtdmsync, 98
- rtdm_event_select_bind
 - rtdmsync, 99
- rtdm_event_signal
 - rtdmsync, 99
- rtdm_event_timedwait
 - rtdmsync, 100
- rtdm_event_wait
 - rtdmsync, 100
- RTDM_EXCLUSIVE
 - devregister, 68
- RTDM_EXECUTE_ATOMICALLY
 - rtdmsync, 93
- rtdm_free
 - util, 119
- rtdm_getpeername
 - interdrv, 61

- rt dm_getsockname
 - interdrv, [61](#)
- rt dm_getsockopt
 - interdrv, [61](#)
- rt dm_in_rt_context
 - util, [119](#)
- rt dm_ioctl
 - interdrv, [61](#)
- rt dm_ioctl_handler_t
 - devregister, [69](#)
- rt dm_iomap_to_user
 - util, [120](#)
- rt dm_irq_disable
 - rt dmirq, [111](#)
- rt dm_irq_enable
 - rt dmirq, [111](#)
- rt dm_irq_free
 - rt dmirq, [111](#)
- rt dm_irq_get_arg
 - rt dmirq, [110](#)
- rt dm_irq_handler_t
 - rt dmirq, [110](#)
- rt dm_irq_request
 - rt dmirq, [112](#)
- rt dm_listen
 - interdrv, [61](#)
- rt dm_lock_get
 - rt dmsync, [94](#)
- rt dm_lock_get_irqsave
 - rt dmsync, [94](#)
- rt dm_lock_init
 - rt dmsync, [95](#)
- rt dm_lock_irqrestore
 - rt dmsync, [95](#)
- rt dm_lock_irqsave
 - rt dmsync, [96](#)
- rt dm_lock_put
 - rt dmsync, [96](#)
- rt dm_lock_put_irqrestore
 - rt dmsync, [96](#)
- rt dm_malloc
 - util, [121](#)
- rt dm_mmap_to_user
 - util, [121](#)
- rt dm_munmap
 - util, [122](#)
- rt dm_mutex_destroy
 - rt dmsync, [101](#)
- rt dm_mutex_init
 - rt dmsync, [101](#)
- rt dm_mutex_lock
 - rt dmsync, [102](#)
- rt dm_mutex_timedlock
 - rt dmsync, [102](#)
- rt dm_mutex_unlock
 - rt dmsync, [103](#)
- RTDM_NAMED_DEVICE
 - devregister, [69](#)
- rt dm_nrtsig_destroy
 - nrtsignal, [115](#)
- rt dm_nrtsig_handler_t
 - nrtsignal, [114](#)
- rt dm_nrtsig_init
 - nrtsignal, [115](#)
- rt dm_nrtsig_pend
 - nrtsignal, [115](#)
- rt dm_open
 - interdrv, [62](#)
- rt dm_open_handler_t
 - devregister, [70](#)
- rt dm_operations, [138](#)
- rt dm_printk
 - util, [123](#)
- RTDM_PROTOCOL_DEVICE
 - devregister, [69](#)
- rt dm_read
 - interdrv, [62](#)
- rt dm_read_handler_t
 - devregister, [70](#)
- rt dm_read_user_ok
 - util, [123](#)
- rt dm_recv
 - interdrv, [62](#)
- rt dm_recvfrom
 - interdrv, [62](#)
- rt dm_recvmsg
 - interdrv, [62](#)
- rt dm_recvmsg_handler_t
 - devregister, [70](#)
- rt dm_rw_user_ok
 - util, [124](#)
- rt dm_safe_copy_from_user
 - util, [124](#)
- rt dm_safe_copy_to_user
 - util, [125](#)
- rt dm_select_bind
 - interdrv, [63](#)
 - rt dmsync, [104](#)
- rt dm_select_bind_handler_t
 - devregister, [71](#)
- rt dm_selecttype
 - rt dmsync, [97](#)
- rt dm_sem_destroy
 - rt dmsync, [104](#)
- rt dm_sem_down
 - rt dmsync, [105](#)
- rt dm_sem_init
 - rt dmsync, [105](#)

- rt dm_sem_select_bind
 - rt dmsync, 105
- rt dm_sem_timeddown
 - rt dmsync, 106
- rt dm_sem_up
 - rt dmsync, 107
- rt dm_send
 - interdrv, 63
- rt dm_sendmsg
 - interdrv, 63
- rt dm_sendmsg_handler_t
 - devregister, 71
- rt dm_sendto
 - interdrv, 64
- rt dm_setsockopt
 - interdrv, 64
- rt dm_shutdown
 - interdrv, 64
- rt dm_socket
 - interdrv, 64
- rt dm_socket_handler_t
 - devregister, 72
- rt dm_strncpy_from_user
 - util, 126
- rt dm_task_busy_sleep
 - rt dmtask, 79
- rt dm_task_current
 - rt dmtask, 80
- rt dm_task_destroy
 - rt dmtask, 80
- rt dm_task_init
 - rt dmtask, 80
- rt dm_task_join_nrt
 - rt dmtask, 81
- rt dm_task_proc_t
 - rt dmtask, 79
- rt dm_task_set_period
 - rt dmtask, 81
- rt dm_task_set_priority
 - rt dmtask, 82
- rt dm_task_sleep
 - rt dmtask, 82
- rt dm_task_sleep_abs
 - rt dmtask, 83
- rt dm_task_sleep_until
 - rt dmtask, 83
- rt dm_task_unblock
 - rt dmtask, 84
- rt dm_task_wait_period
 - rt dmtask, 84
- RTDM_TIMEOUT_INFINITE
 - rt dm, 33
- RTDM_TIMEOUT_NONE
 - rt dm, 33
- rt dm_timer_destroy
 - rt dmtimer, 87
- rt dm_timer_handler_t
 - rt dmtimer, 87
- rt dm_timer_init
 - rt dmtimer, 87
- rt dm_timer_mode
 - rt dmtimer, 87
- rt dm_timer_start
 - rt dmtimer, 88
- rt dm_timer_start_in_handler
 - rt dmtimer, 88
- rt dm_timer_stop
 - rt dmtimer, 89
- rt dm_timer_stop_in_handler
 - rt dmtimer, 89
- rt dm_toseq_init
 - rt dmsync, 107
- rt dm_write
 - interdrv, 64
- rt dm_write_handler_t
 - devregister, 72
- rt dmirq
 - rt dm_irq_disable, 111
 - rt dm_irq_enable, 111
 - rt dm_irq_free, 111
 - rt dm_irq_get_arg, 110
 - rt dm_irq_handler_t, 110
 - rt dm_irq_request, 112
- rt dmsync
 - RTDM_SELECTTYPE_EXCEPT, 97
 - RTDM_SELECTTYPE_READ, 97
 - RTDM_SELECTTYPE_WRITE, 97
 - rt dm_event_clear, 97
 - rt dm_event_destroy, 97
 - rt dm_event_init, 98
 - rt dm_event_pulse, 98
 - rt dm_event_select_bind, 99
 - rt dm_event_signal, 99
 - rt dm_event_timedwait, 100
 - rt dm_event_wait, 100
 - RTDM_EXECUTE_ATOMICALLY, 93
 - rt dm_lock_get, 94
 - rt dm_lock_get_irqsave, 94
 - rt dm_lock_init, 95
 - rt dm_lock_irqrestore, 95
 - rt dm_lock_irqsave, 96
 - rt dm_lock_put, 96
 - rt dm_lock_put_irqrestore, 96
 - rt dm_mutex_destroy, 101
 - rt dm_mutex_init, 101
 - rt dm_mutex_lock, 102
 - rt dm_mutex_timedlock, 102
 - rt dm_mutex_unlock, 103

- rt dm_select_bind, 104
- rt dm_selecttype, 97
- rt dm_sem_destroy, 104
- rt dm_sem_down, 105
- rt dm_sem_init, 105
- rt dm_sem_select_bind, 105
- rt dm_sem_timeddown, 106
- rt dm_sem_up, 107
- rt dm_toseq_init, 107
- rt dmtask
 - rt dm_task_busy_sleep, 79
 - rt dm_task_current, 80
 - rt dm_task_destroy, 80
 - rt dm_task_init, 80
 - rt dm_task_join_nrt, 81
 - rt dm_task_proc_t, 79
 - rt dm_task_set_period, 81
 - rt dm_task_set_priority, 82
 - rt dm_task_sleep, 82
 - rt dm_task_sleep_abs, 83
 - rt dm_task_sleep_until, 83
 - rt dm_task_unblock, 84
 - rt dm_task_wait_period, 84
- rt dmtimer
 - RTDM_TIMERMODE_ABSOLUTE, 87
 - RTDM_TIMERMODE_REALTIME, 87
 - RTDM_TIMERMODE_RELATIVE, 87
 - rt dm_timer_destroy, 87
 - rt dm_timer_handler_t, 87
 - rt dm_timer_init, 87
 - rt dm_timer_mode, 87
 - rt dm_timer_start, 88
 - rt dm_timer_start_in_handler, 88
 - rt dm_timer_stop, 89
 - rt dm_timer_stop_in_handler, 89
- RTIOC_DEVICE_INFO
 - profiles, 128
- RTIOC_PURGE
 - profiles, 128
- rt ser_config, 140
- rt ser_event, 141
- RTSER_RTIOC_BREAK_CTL
 - rt serial, 51
- RTSER_RTIOC_GET_CONFIG
 - rt serial, 51
- RTSER_RTIOC_GET_CONTROL
 - rt serial, 52
- RTSER_RTIOC_GET_STATUS
 - rt serial, 52
- RTSER_RTIOC_SET_CONFIG
 - rt serial, 53
- RTSER_RTIOC_SET_CONTROL
 - rt serial, 53
- RTSER_RTIOC_WAIT_EVENT
 - rt serial, 54
- rt ser_status, 142
- rt serial
 - RTSER_RTIOC_BREAK_CTL, 51
 - RTSER_RTIOC_GET_CONFIG, 51
 - RTSER_RTIOC_GET_CONTROL, 52
 - RTSER_RTIOC_GET_STATUS, 52
 - RTSER_RTIOC_SET_CONFIG, 53
 - RTSER_RTIOC_SET_CONTROL, 53
 - RTSER_RTIOC_WAIT_EVENT, 54
- Serial Devices, 46
- SIOCGCANBAUDRATE
 - rt can, 24
- SIOCGCANCTRLMODE
 - rt can, 25
- SIOCGCANCUSTOMBITTIME
 - rt can, 25
- SIOCGCANSTATE
 - rt can, 26
- SIOCGIFINDEX
 - rt can, 27
- SIOCSCANBAUDRATE
 - rt can, 27
- SIOCSCANCTRLMODE
 - rt can, 28
- SIOCSCANCUSTOMBITTIME
 - rt can, 29
- SIOCSCANMODE
 - rt can, 29
- sockaddr_can, 143
 - can_ifindex, 143
- SOL_CAN_RAW
 - rt can, 30
- Synchronisation Services, 91
- Task Services, 78
- Testing Devices, 55
- Timer Services, 86
- User API, 34
- userapi
 - rt_dev_accept, 35
 - rt_dev_bind, 36
 - rt_dev_close, 36
 - rt_dev_connect, 37
 - rt_dev_getpeername, 37
 - rt_dev_getsockname, 37
 - rt_dev_getsockopt, 38
 - rt_dev_ioctl, 38
 - rt_dev_listen, 39
 - rt_dev_open, 39
 - rt_dev_read, 40
 - rt_dev_recv, 40

- [rt_dev_recvfrom, 41](#)
 - [rt_dev_recvmsg, 41](#)
 - [rt_dev_send, 42](#)
 - [rt_dev_sendmsg, 42](#)
 - [rt_dev_sendto, 43](#)
 - [rt_dev_setsockopt, 43](#)
 - [rt_dev_shutdown, 44](#)
 - [rt_dev_socket, 44](#)
 - [rt_dev_write, 44](#)
- [util](#)
 - [rtdm_copy_from_user, 118](#)
 - [rtdm_copy_to_user, 118](#)
 - [rtdm_free, 119](#)
 - [rtdm_in_rt_context, 119](#)
 - [rtdm_iomap_to_user, 120](#)
 - [rtdm_malloc, 121](#)
 - [rtdm_mmap_to_user, 121](#)
 - [rtdm_munmap, 122](#)
 - [rtdm_printk, 123](#)
 - [rtdm_read_user_ok, 123](#)
 - [rtdm_rw_user_ok, 124](#)
 - [rtdm_safe_copy_from_user, 124](#)
 - [rtdm_safe_copy_to_user, 125](#)
 - [rtdm_strncpy_from_user, 126](#)
- [Utility Services, 117](#)