

EK-LM3S3748 Firmware Development Package

USER'S GUIDE



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1 Introduction

The Texas Instruments® Stellaris® EK-LM3S3748 evaluation board is a platform that can be used for software development and to prototype a hardware design. It contains a Stellaris ARM® Cortex™-M3-based microcontroller, along with an color STN display, a navigation switch, a small speaker, and USB host and device ports (shared via a USB mux) that can be used to exercise the peripherals on the microcontroller. Additionally, all of the microcontroller's pins are brought to unpopulated stake headers, allowing for easy connection to other hardware for the purposes of prototyping (after the stake headers have been populated by the customer).

This document describes the board-specific drivers and example applications that are provided for this development board.

2 Example Applications

The example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is an IAR workspace file (`ek-lm3s3748.eww`) that contains the peripheral driver library project, graphics library project, USB library project, and all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench version 5.

There is a Keil multi-project workspace file (`ek-lm3s3748.mpw`) that contains the peripheral driver library project, graphics library project, USB library project, and all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/ek-lm3s3748` subdirectory of the firmware development package source distribution.

2.1 Audio Playback (audio)

This example application plays audio via the Class-D amplifier and speaker. The same source audio clip is provided in both PCM and ADPCM format so that the audio quality can be compared.

2.2 Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

2.3 Blinky (blinky)

A very simple example that blinks the on-board LED.

2.4 Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the ROM-based boot loader. At startup, the application will configure the UART and branch to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

The `boot_demo2` application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

2.5 Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the ROM-based boot loader. At startup, the application will configure the UART, wait for the select button to be pressed, and then branch to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

2.6 USB Boot Loader Example (boot_demo_usb)

This example application is used in conjunction with the USB boot loader (boot_usb) and turns the evaluation board into a composite device supporting the Human Interface Device mouse and Device Firmware Upgrade classes. Presses on the navigation control on the evaluation board are translated into mouse movement and button press messages in HID reports sent to the USB host allowing the evaluation board to control the mouse pointer on the host system.

Since the device also publishes a DFU interface, host software such as the dfuprog tool can determine that the device is capable of receiving software updates over USB. The runtime DFU protocol allows such tools to signal the device to switch into DFU mode and prepare to receive a new software image.

Runtime DFU functionality requires only that the device listen for a particular request (DETACH) from the host and, when this is received, transfer control to the USB boot loader via the normal means to reenumerate as a pure DFU device capable of uploading and downloading firmware images.

Windows device drivers for both the runtime and DFU mode of operation can be found in C:/StellarisWare/windows_drivers assuming you installed StellarisWare in the default directory.

To illustrate runtime DFU capability, use the dfuprog tool which is part of the Stellaris Windows USB Examples package (SW-USB-win-xxxx.msi). Assuming this package is installed in the default location, the dfuprog executable can be found in the C:/Program Files/Texas Instruments/Stellaris/usb_examples directory.

With the device connected to your PC and the device driver installed, enter the following command to enumerate DFU devices:

```
dfuprog -e
```

This will list all DFU-capable devices found and you should see that you have one device available which is in "Runtime" mode. Entering the following command will switch this device into DFU mode and leave it ready to receive a new firmware image:

```
dfuprog -m
```

After entering this command, you should notice that the device disconnects from the USB bus and reconnects again. Running "dfuprog -e" a second time will show that the device is now in DFU mode and ready to receive downloads. At this point, either LM Flash Programmer or dfuprog may be used to send a new application binary to the device.

2.7 USB Boot Loader (boot_usb)

The boot loader is a small piece of code that can be programmed at the beginning of flash to act as an application loader as well as an update mechanism for an application running on a Stellaris microcontroller, utilizing either UART0, I2C0, SSI0, Ethernet or USB. The capabilities of the boot loader are configured via the `bl_config.h` include file. For this example, the boot loader uses the USB Device Firmware Upgrade (DFU) class to download an application.

Applications intended for use with this version of the boot loader should be linked to run from address 0x1800 in flash (rather than the default run address of 0). This address is chosen to ensure that boot loader images built with all supported compilers may be used without modifying the application start address. Depending upon the compiler and optimization level you are using, however, you may find that you can reclaim some space by lowering this address and rebuilding both the application and boot loader. To do this, modify the makefile or project you use to build the application to show the new run address and also change the `APP_START_ADDRESS` value defined in `bl_config.h` before rebuilding the boot loader.

The USB boot loader may be demonstrated using the `usb_boot_demo1` and `usb_boot_demo2` example applications in addition to the `boot_usb` boot loader binary itself. Note that these are the only two example applications currently configured to run alongside the USB boot loader but making any of the other applications boot loader compatible is simply a matter of relinking them with the new start address.

The boot loader configuration used here enables a GPIO check on boot. If the "Navigate" button on the EK board is pressed down when power is applied, the USB boot loader will run and prepare to receive download or upload commands from the USB host. If the button is not pressed, control will immediately transfer to the main application if one is present at 0x1800.

The Windows device driver required to communicate with the USB boot loader can be found on the software and documentation CD from the evaluation kit package. It can also be found in the Windows driver package which can be downloaded via a link from <http://www.ti.com/stellaris>.

A Windows command-line application, `dfuprog`, is also provided which illustrates how to perform uploads and downloads via the USB DFU protocol. The source for this application can be found in the "C:/StellarisWare/tools" directory and the prebuilt executable is available in the package "Windows-side examples for USB kits" available for download via a link from <http://www.ti.com/stellarisware>.

2.8 GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the select push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, four pins (PC0, PC1, PC2, and PC3) are switched.

2.9 Graphics Library Demonstration (grlib_demo)

This application provides a demonstration of the capabilities of the Stellaris Graphics Library. The display will be configured to demonstrate the available drawing primitives: lines, circles, rectangles, strings, and images.

2.10 Hello World (hello)

A very simple “hello world” example. It simply displays “Hello World!” on the display and is a starting point for more complicated applications.

2.11 Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, pre-emption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the display; GPIO pins D0, D1 and D2 will be asserted upon interrupt handler entry and de-asserted before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

2.12 MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

2.13 PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 20% duty cycle PWM signal and a 80% duty cycle PWM signal, both at 8000 Hz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

2.14 Quickstart Oscilloscope (qs-scope)

A two channel oscilloscope implemented using the Stellaris microcontroller’s analog-to-digital converter (ADC). The oscilloscope supports sample rates of up to 1M sample per second and will show the captured waveforms on the color STN display. On-screen menus provide user control over timebase, channel voltage scale and position, trigger type, trigger level and trigger position. Other features include the ability to save captured data as comma-separated-value files suitable for

use with spreadsheet applications or bitmap images on either an installed microSD card or a USB flash drive. The board may also be connected to a WindowsXP or Vista host system and controlled remotely using a Windows application.

Oscilloscope User Interface

All oscilloscope controls and settings are accessed using the navigation control on the board. This control offers up, down, left, right and select functions in a single unit. Rocking the control in the desired direction sends "up", "down", "left" or "right" messages to the application and pressing on the center sends a "select" message.

Controls and settings are arranged into groups by function such as display settings, trigger settings, file operations and setup choices. These groups are accessed by pressing "select" to display the main menu. With the menu displayed, use "up" and "down" to select between the available groups. When the desired group is highlighted, press "select" once again to dismiss the menu.

Controls from the currently selected group are shown in the bottom portion of the application display. Use "up" and "down" to cycle through the controls in the group and "left" and "right" to change the value of, or select the action associated with the control which is currently displayed.

The control groups and the individual controls offered by each are outlined below:

Group	Control	Setting
-----	-----	-----
Display	Channel 2	ON or OFF.
	Timebase	Select values from 2uS to 50mS per division.
	Ch1 Scale	Select values from 100mV to 10V per division.
	Ch2 Scale	Select values from 100mV to 10V per division.
	Ch1 Offset	Press and hold "left" or "right" to move the waveform up or down in 100mV increments.
	Ch2 Offset	Press and hold "left" or "right" to move the waveform up or down in 100mV increments.
Trigger	Trigger	The trigger type - Always, Rising, Falling or Level.
	Trig Channel	1 or 2 to select the channel used for triggering.
	Trig Level	Press and hold "left" or "right" to change the trigger level in 100mV increments.
	Trig Pos	Press and hold "left" or "right" to move the trigger position on the display.
	Mode	Running or Stopped.
	One Shot	If the current mode is "Stopped", pressing "left" or "right" initiates capture and display of a single waveform.
Setup	Captions	Select ON to show the timebase and scale captions or OFF to remove them from the display.
	Voltages	Select ON to show the measured voltages for each channel or OFF to remove them from the display.
	Grid	Select ON to show the graticule lines or OFF to remove them from the display.
	Ground	Select ON to show dotted lines corresponding to the ground levels for each channel or OFF to remove them from the display.
	Trig Level	Select ON to show a solid horizontal line corresponding to the trigger level for the trigger channel or OFF to remove this line from the display.
	Trig Pos	Select ON to show a solid vertical line at the trigger position or OFF to remove this line from the display.
	Clicks	Select ON to enable sounds on button presses or

	USB Mode	OFF to disable them. Select Host to operate in USB host mode and allow use of flash memory sticks, or Device to operate as a USB device and allow connection to a host PC system.
File	CSV on SD	Save the current waveform data as a text file on an installed microSD card.
	CSV on USB	Save the current waveform data as a text file on an installed USB flash stick (if in USB host mode - see the Setup group above).
	BMP on SD	Save the current waveform display as a bitmap on an installed microSD card.
	BMP on USB	Save the current waveform display as a bitmap on an installed USB flash stick (if in USB host mode - see the Setup group above).
Help	Help	Pressing "left" or "right" will show or hide the screen showing oscilloscope connection help.
	Channel 1	Pressing "left" or "right" will cause the scale and position for the channel 1 waveform to be set such that the waveform is visible on the display.
	Channel 2	Pressing "left" or "right" will cause the scale and position for the channel 2 waveform to be set such that the waveform is visible on the display.

Oscilloscope Connections

The 8 pins immediately above the color STN display panel offer connections for both channels of the oscilloscope and also two test signals that can be used to provide input in the absence of any other suitable signals. Each channel input must lie in the range -16.5V to +16.5V relative to the board ground allowing differences of up to 33V to be measured.

The connections are as follow where pin 1 is the leftmost pin, nearest the microSD card socket:

1	Test 1	A test signal connected to one side of the speaker on the board.
2	Channel 1+	This is the positive connection for channel 1 of the oscilloscope.
3	Channel 1-	This is the negative connection for channel 1 of the oscilloscope.
4	Ground	This is connected to board ground.
5	Test 2	A test signal connected to the board Status LED which is driven from PWM0. This signal is configured to provide a 1KHz square wave.
6	Channel 2+	This is the positive connection for channel 2 of the oscilloscope.
7	Channel 2-	This is the negative connection for channel 2 of the oscilloscope.
8	Ground	This is connected to board ground.

Triggering and Sample Rate Notes

The oscilloscope can sample at a maximum combined rate of 1M samples per second. When both channels are enabled, therefore, the maximum sample rate on each channel is 500K samples per second. For maximum resolution at the lowest timebases (maximum samples rates), disable channel 2 if it is not required. These sample rates give usable waveform capture for signals up to around 100KHz.

Trigger detection is performed in software during ADC interrupt handling. At the highest sampling rates, this interrupt service routine consumes almost all the available CPU cycles when searching for trigger conditions. At these sample rates, if a trigger level is set which does not correspond to

a voltage that is ever seen in the trigger channel signal, the user interface response can become sluggish. To combat this, the oscilloscope will abort any pending waveform capture operation if a key is pressed before the capture cycle is completed. This prevents the user interface from being locked out and allows the trigger level or type to be changed to values more appropriate for the signal being measured.

File Operations

Comma-separated-value or bitmap files representing the last waveform captured may be saved to either a microSD card or a USB flash drive. In each case, the files are written to the root directory of the microSD card or flash drive with file names of the form "scopeXXX.csv" or "scopeXXX.bmp" where "XXX" represents the lowest, three digit, decimal number which offers a file name which does not already exist on the device.

Companion Application

A companion application, LMScope, which runs on WindowsXP and Vista PCs and the required device driver installer are available on the software CD and via download from the TI Stellaris web site at <http://focus.ti.com/mcu/docs/mcuorphan.tsp?contentId=87903>. This application offers full control of the oscilloscope from the PC and allows waveform display and save to local hard disk.

Note that the USB device drivers for the oscilloscope device must be installed prior to running the LMScope application. If the drivers are not installed when LMScope is run, the application will report that various required DLLs including Imusb.dll and winusb.dll are missing. To install the drivers, make sure that the USB mode is set to "Device" in the Setup menu then connect the ek-lm3s3748 board to a PC via the "USB Device" connector. This will cause Windows to prompt for device driver installation. The required driver can be found on the kit installation CD or in the "SW-USB-windrivers-xxxx" package downloadable from the software update web site.

2.15 SD card using FAT file system (sd_card)

This example application demonstrates reading a file system from an SD card. It makes use of FatFs, a FAT file system driver. It provides a simple command console via a serial port for issuing commands to view and navigate the file system on the SD card.

The first UART, which is connected to the FTDI virtual serial port on the evaluation board, is configured for 115,200 bits per second, and 8-N-1 mode. When the program is started a message will be printed to the terminal. Type "help" for command help.

For additional details about FatFs, see the following site:
http://elm-chan.org/fsw/ff/00index_e.html

2.16 Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own indicator on the display.

2.17 UART Echo (uart_echo)

This example application utilizes the UART to echo text. The first UART (connected to the FTDI virtual serial port on the evaluation board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

2.18 uDMA (udma_demo)

This example application demonstrates the use of the uDMA controller to transfer data between memory buffers, and to transfer data to and from a UART.

2.19 USB Boot Loader Demo 1 (usb_boot_demo1)

An example to demonstrate the use of the flash-based USB boot loader. At startup, the application displays a message then branches to the USB boot loader to await the start of an update. The boot loader presents a Device Firmware Upgrade interface to the host allowing new applications to be downloaded to flash via USB.

The usb_boot_demo2 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

The application dfuwrap, found in the boards directory, can be used to prepare binary images for download to a particular position in device flash. This application adds a Stellaris-specific prefix and a DFU standard suffix to the binary. A sample Windows command line application, dfuprog, is also provided which allows either binary images or DFU-wrapped files to be downloaded to the board or uploaded from it.

The usb_boot_demo1 and usb_boot_demo2 applications are essentially identical to boot_demo1 and boot_demo2 with the exception that they are linked to run at address 0x1800 rather than 0x0. This is due to the fact that the USB boot loader is not currently included in the Stellaris ROM and therefore has to be stored in the bottom few KB of flash with the main application stored above it.

2.20 USB Boot Loader Demo 2 (usb_boot_demo2)

An example to demonstrate the use of the flash-based USB boot loader. At startup, the application displays a message then waits for the user to press the select button before branching to the USB boot loader to await the start of an update. The boot loader presents a Device Firmware Upgrade interface to the host allowing new applications to be downloaded to flash via USB.

The usb_boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

The application dfuwrap, found in the boards directory, can be used to prepare binary images for download to a particular position in device flash. This application adds a Stellaris-specific prefix and a DFU standard suffix to the binary. A sample Windows command line application, dfuprog, is also provided which allows either binary images or DFU-wrapped files to be downloaded to the board or uploaded from it.

The `usb_boot_demo1` and `usb_boot_demo2` applications are essentially identical to `boot_demo1` and `boot_demo2` with the exception that they are linked to run at address 0x1800 rather than 0x0. This is due to the fact that the USB boot loader is not currently included in the Stellaris ROM and therefore has to be stored in the bottom few KB of flash with the main application stored above it.

2.21 USB Generic Bulk Device (`usb_dev_bulk`)

This example provides a generic USB device offering simple bulk data transfer to and from the host. The device uses a vendor-specific class ID and supports a single bulk IN endpoint and a single bulk OUT endpoint. Data received from the host is assumed to be ASCII text and it is echoed back with the case of all alphabetic characters swapped.

A Windows INF file for the device is provided on the installation CD and in the `C:/StellarisWare/windows_drivers` directory of StellarisWare releases. This INF contains information required to install the WinUSB subsystem on WindowsXP and Vista PCs. WinUSB is a Windows subsystem allowing user mode applications to access the USB device without the need for a vendor-specific kernel mode driver.

A sample Windows command-line application, `usb_bulk_example`, illustrating how to connect to and communicate with the bulk device is also provided. The application binary is installed as part of the “Windows-side examples for USB kits” package (SW-USB-win) on the installation CD or via download from <http://www.ti.com/stellarisware>. Project files are included to allow the examples to be built using Microsoft VisualStudio 2008. Source code for this application can be found in directory `StellarisWare/tools/usb_bulk_example`.

2.22 USB Composite Serial Device (`usb_dev_cserial`)

This example application turns the evaluation kit into a multiple virtual serial ports when connected to the USB host system. The application supports the USB Communication Device Class, Abstract Control Model to redirect UART0 traffic to and from the USB host system. The first virtual serial port will echo data to the physical UART0 port on the device which is connected to the virtual serial port on the FTDI device on this board. The physical UART0 will also echo onto the first virtual serial device provided by the Stellaris controller. The second Stellaris virtual serial port will provide a console that can echo data to both the FTDI virtual serial port and the first Stellaris virtual serial port. It will also allow turning on, off or toggling the boards led status. Typing a “?” and pressing return should echo a list of commands to the terminal, since this board can show up as possibly three individual virtual serial devices.

Assuming you installed StellarisWare in the default directory, a driver information (INF) file for use with Windows XP, Windows Vista and Windows7 can be found in `C:/StellarisWare/windows_drivers`. For Windows 2000, the required INF file is in `C:/StellarisWare/windows_drivers/win2K`.

2.23 USB HID Keyboard Device (`usb_dev_keyboard`)

This example application turns the evaluation board into a USB keyboard supporting the Human Interface Device class. The color STN display shows a virtual keyboard which can be navigated using the direction control button on the board. Pressing down on the button presses the highlighted

key, sending its usage code and, if necessary, a shift modifier, to the USB host. The board status LED is used to indicate the current Caps Lock state and is updated in response to pressing the “Caps” key on the virtual keyboard or any other keyboard attached to the same USB host system.

The device implemented by this application also supports USB remote wakeup allowing it to request the host to reactivate a suspended bus. If the bus is suspended (as indicated on the application display), pressing the Select key will request a remote wakeup assuming the host has not specifically disabled such requests.

2.24 USB HID Mouse Device (usb_dev_mouse)

This example application turns the evaluation board into a USB mouse supporting the Human Interface Device class. Presses on the navigation control on the evaluation board are translated into mouse movement and button press messages in HID reports sent to the USB host allowing the evaluation board to control the mouse pointer on the host system.

2.25 USB MSC Device (usb_dev_msc)

This example application turns the evaluation board into a USB mass storage class device. The application will use the microSD card for the storage media for the mass storage device. The screen will display the current action occurring on the device ranging from disconnected, no media, reading, writing and idle.

2.26 USB Serial Device (usb_dev_serial)

This example application turns the evaluation kit into a virtual serial port when connected to the USB host system. The application supports the USB Communication Device Class, Abstract Control Model to redirect UART0 traffic to and from the USB host system.

Assuming you installed StellarisWare in the default directory, a driver information (INF) file for use with Windows XP, Windows Vista and Windows7 can be found in C:/StellarisWare/windows_drivers. For Windows 2000, the required INF file is in C:/StellarisWare/windows_drivers/win2K.

2.27 USB HID Keyboard Host (usb_host_keyboard)

This example application demonstrates how to support a USB keyboard attached to the evaluation kit board. The display will show if a keyboard is currently connected and the current state of the Caps Lock key on the keyboard that is connected on the bottom status area of the screen. Pressing any keys on the keyboard will cause them to be printed on the screen and to be sent out the UART at 115200 baud with no parity, 8 bits and 1 stop bit. Any keyboard that supports the USB HID bios protocol should work with this demo application.

2.28 USB HID Mouse Host (usb_host_mouse)

This example application demonstrates how to support a USB mouse attached to the evaluation kit board. The display will show if a mouse is currently connected and the current state of the buttons on the on the bottom status area of the screen. The main drawing area will show a mouse cursor that can be moved around in the main area of the screen. If the left mouse button is held while moving the mouse, the cursor will draw on the screen. A side effect of the application not being able to read the current state of the screen is that the cursor will erase anything it moves over while the left mouse button is not pressed.

2.29 USB Mass Storage Class Host (usb_host_msc)

This example application demonstrates how to connect a USB mass storage class device to the evaluation kit. When a device is detected, the application displays the contents of the file system and allows browsing using the buttons.

2.30 USB Stick Update Demo (usb_stick_demo)

An example to demonstrate the use of the flash-based USB stick update program. This example is meant to be loaded into flash memory from a USB memory stick, using the USB stick update program (usb_stick_update), running on the microcontroller.

After this program is built, the binary file (usb_stick_demo.bin), should be renamed to the filename expected by usb_stick_update ("FIRMWARE.BIN" by default) and copied to the root directory of a USB memory stick. Then, when the memory stick is plugged into the eval board that is running the usb_stick_update program, this example program will be loaded into flash and then run on the microcontroller.

This program simply displays a message on the screen and prompts the user to press the select button. Once the button is pressed, control is passed back to the usb_stick_update program which is still in flash, and it will attempt to load another program from the memory stick. This shows how a user application can force a new firmware update from the memory stick.

2.31 USB Memory Stick Updater (usb_stick_update)

This example application behaves the same way as a boot loader. It resides at the beginning of flash, and will read a binary file from a USB memory stick and program it into another location in flash. Once the user application has been programmed into flash, this program will always start the user application until requested to load a new application.

When this application starts, if there is a user application already in flash (at **APP_START_ADDRESS**), then it will just run the user application. It will attempt to load a new application from a USB memory stick under the following conditions:

- no user application is present at **APP_START_ADDRESS**
- the user application has requested an update by transferring control to the updater

- the user holds down the eval board push button when the board is reset

When this application is attempting to perform an update, it will wait forever for a USB memory stick to be plugged in. Once a USB memory stick is found, it will search the root directory for a specific file name, which is *FIRMWARE.BIN* by default. This file must be a binary image of the program you want to load (the .bin file), linked to run from the correct address, at **APP_START_ADDRESS**.

The USB memory stick must be formatted as a FAT16 or FAT32 file system (the normal case), and the binary file must be located in the root directory. Other files can exist on the memory stick but they will be ignored.

2.32 Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED is inverted so that it is easy to see that it is being fed, which occurs once every second.

3 Development System Utilities

These are tools that run on the development system, not on the embedded target. They are provided to assist in the development of firmware for Stellaris microcontrollers.

These tools reside in the `tools` subdirectory of the firmware development package source distribution.

AES Key Expansion Utility

Usage:

```
aes_gen_key [OPTIONS] --keysize=[SIZE] --key=[KEYSTRING] [FILE]
```

Description:

Generates pre-expanded keys for AES encryption and decryption. It is designed to work in conjunction with the AES library code found in the StellarisWare directory `third_party/aes`. When using an AES key to perform encryption or decryption, the key must first be expanded into a larger table of values before the key can be used. This operation can be performed at run-time but takes time and uses space in RAM.

If the keys are fixed and known in advance, then it is possible to perform the expansion operation at build-time and the pre-expanded table can be built into the code. The advantages of doing this are that it saves time when the keys are used, and the expanded table is stored in non-volatile program memory (flash), which is usually less precious in a typical microcontroller application.

By default, the pre-expanded key is generated as a data array that can be used by reference in the application. It is also possible to generate the pre-expanded key as a code sequence. A function is generated that will copy the pre-expanded key to a caller supplied buffer. This does not save RAM space, but it makes the expanded key more secure. By making the key into pure code (versus data in flash), the Texas Instruments Stellaris OTP feature can be used to make the code execute only (no read). This means that the expanded key cannot be read from flash. It is only loaded into RAM during an encrypt or decrypt operation.

The length of a pre-set key is 44 words for 128-bit keys, 54 words for 192-bit keys, and 68 words for 256-bit keys; instruction-based versions are about two to four times as large in flash and require as much RAM as run-time expansion.

The source code for this utility is contained in `tools/aes_gen_key`, with a pre-built binary contained in `tools/bin`.

Arguments:

- a, **--data** generates expanded key as an array of data.
- x, **--code** generates expanded key as executable code.
- e, **--encrypt** generate expanded key for encryption.
- d, **--decrypt** generate expanded key for decryption.
- s, **--keysize** **KEYSIZE** size of the key in bits (128, 192, or 256).
- k, **--key** **KEY** key value in hexadecimal.
- v, **--version** show program version.
- h, **--help** display usage information.

The **--keysize** and **--key** arguments are mandatory. Only one each of **--data** or **--code**, and **--encrypt** or **--decrypt** should be used. If not specified otherwise then the default is **--data --encrypt**.

FILE is the name of the file that will be created containing the expanded key. This file will be in the form of a C header file and should be included in your application.

Example:

The following will generate an expanded 128-bit key for encryption, encoded as data and create a C header file named `enc_key.h`:

```
aes_gen_key --data --encrypt --keysize=128
            --key=112233445566778899AABBCCDDEEFF00 enc_key.h
```

The following will generate an expanded 128-bit key for decryption, encoded as a code function and create a C header file named `dec_key.h`:

```
aes_gen_key --code --decrypt --keysize=128
            --key=112233445566778899AABBCCDDEEFF00 dec_key.h
```

Audio Converter

Usage:

```
converter [OPTION]... [INPUT FILE]
```

Description:

Converts a file containing raw 16-bit mono PCM data into an C array. The input data is assumed to be 16-bit, signed, mono PCM data at the desired sample rate and with no header (in other words, raw PCM data). This utility can encode it as either 8-bit PCM or 4-bit IMA ADPCM data, resulting in a 50% or 75% reduction in size (respectively).

In 8-bit unsigned PCM format, each byte represents a single sample. This format provides 8 bits of resolution in the output stream. In IMA ADPCM format, each byte represents two encoded samples. After the decoding process, the output stream has approximately 14 bits of resolution. There will generally be little to no degradation of audio quality when using IMA ADPCM, though it varies based on the audio clip.

The output is a C array definition that can be placed into a source or header file and passed to a compiler. The contents of the array can be passed to the audio playback function of a board's class-D audio driver in order to playback the audio file. The sample rate of the input file must match the sample rate expected by the class-D audio driver in use.

In order to produce a raw 16-bit mono PCM file, some pre-processing is likely required. Since most audio files have headers, they must be stripped as well. There are numerous open source and commercial audio editors that are capable of performing these conversions, with `sox` (<http://sox.sourceforge.net>) being an open source tool that is powerful and easy to use. The following `sox` command will take an input audio file and convert it into the correct format (assuming that an 8 KHz sample rate is required):

```
sox foo.wav -t raw -r 8000 -c 1 -s 2 foo.raw polyphase
```

`sox` will sample rate convert the audio (`polyphase` selects a higher quality sample rate conversion algorithm), mix a stereo channel pair to get to mono, and convert the sample size to 16 bits (each step only if the input file is not already in the specified format). It may be helpful (and/or necessary) to also include `vol {factor}` before `polyphase` in order to increase or

decrease the volume of the waveform. If `sox` reports that clipping has occurred, the volume needs to be reduced to prevent the clipping.

The same steps can be performed using other audio editor software.

The source code for this utility is contained in `tools/converter`, with a pre-built binary contained in `tools/bin`.

Arguments:

- a** specifies that the audio should be encoded using ADPCM.
- c COUNT** specifies the number of audio samples to place into the output file.
- h** displays usage information.
- n NAME** specifies the name of the C array in the output file.
- o FILENAME** specifies the name of the output file.
- p** specifies that the audio should be encoded using PCM.
- s SKIP** specifies the number of audio samples at the beginning of the file to skip.
- INPUT FILE** specifies the name of the input PCM file. If no input file is specified, the input PCM is read from standard input.

Example:

The following will encode a 16-bit mono PCM file into IMA ADPCM and place the result into a C array called `g_pucFoo`:

```
converter -a -n g_pucFoo -o foo.h foo.raw
```

USB DFU Programmer

Usage:

```
dfuprog [OPTION]...
```

Description:

Downloads images to a Texas Instruments Stellaris microcontroller running the USB Device Firmware Upgrade boot loader. Additionally, this utility may be used to read back the existing application image or a subsection of flash and store it either as raw binary data or as a DFU-downloadable image file.

The source code for this utility is contained in `tools/dfuprog`. The binary for this utility is installed as part of the “Windows-side examples for USB kits” package (SW-USB-win) shipped on the release CD and downloadable from http://www.luminarymicro.com/products/software_updates.html. A Microsoft Visual Studio project file is provided to allow the application to be built.

Arguments:

- e** specifies the address of the binary.
- u** specifies that an image is to be uploaded from the board into the target file. If absent, the file will be downloaded to the board.
- c** specifies that a section of flash memory is to be cleared. The address and size of the block may be specified using the `-a` and `-l` parameters. If these are absent, the entire writable area of flash is erased.
- f FILE** specifies the name of the file to download or, if `-u` is given, to upload.
- b** specifies that an uploaded file is to be stored as raw binary data without the DFU file wrapper. This option is only valid if used alongside `-u`.

- d** specifies that the VID and PID in the DFU file wrapper should be ignored for a download operation.
- s** specifies that image verification should be skipped following a download operation.
- a ADDR** specifies the address at which the binary file will be downloaded or from which an uploaded file will be read. If a download operation is taking place and the source file provided is DFU-wrapped, this parameter will be ignored.
- l SIZE** specifies the number of bytes to be uploaded when used in conjunction with -i or the number of bytes of flash to erase if used in conjunction with -c.
- i NUM** specifies the zero-based index of the USB DFU device to access if more than one is currently attached to the system. If absent, the first device found is used.
- x** specifies that destination file for an upload operation should be overwritten without prompting if it already exists.
- w** specifies that the utility should wait for the user to press a key before it exits.
- v** displays verbose output during the requested operation.
- h** displays this help information.
- ?** displays this help information.

Example:

The following example writes binary file `program.bin` to the device flash memory at address `0x1800`:

```
dfuprog -f program.bin -a 0x1800
```

The following example writes DFU-wrapped file `program.dfu` to the flash memory of the second connected USB DFU device at the address found in the DFU file prefix:

```
dfuprog -i 1 -f program.dfu
```

The following example uploads (reads) the current application image into a DFU-formatted file `appimage.dfu`:

```
dfuprog -u -f appimage.dfu
```

USB DFU Wrapper

Usage:

```
dfuwrap [OPTION]...
```

Description:

Prepares binary images for download to a particular position in device flash via the USB device firmware upgrade protocol. A Stellaris-specific prefix and a DFU standard suffix are added to the binary.

The source code for this utility is contained in `tools/dfuwrap`, with a pre-built binary contained in `tools/bin`.

Arguments:

- a ADDR** specifies the address of the binary.
- c** specifies that the validity of the DFU wrapper on the input file should be checked.
- d ID** specifies the USB device ID to place into the DFU wrapper. If not specified, the default of `0x0000` will be used.

- e enables verbose output.
- f specifies that a DFU wrapper should be added to the file even if one already exists.
- h displays usage information.
- i **FILE** specifies the name of the input file.
- o **FILE** specifies the name of the output file. If not specified, the default of image.dfu will be used.
- p **ID** specifies the USB product ID to place into the DFU wrapper. If not specified, the default of 0x00ff will be used.
- q specifies that only error information should be output.
- r specifies that the DFU header should be removed from the input file.
- v **ID** specifies the USB vendor ID to place into the DFU wrapper. if not specified, the default of 0x1cbe will be used.
- x specifies that the output file should be overwritten without prompting.

Example:

The following example adds a DFU wrapper which will cause the image to be programmed to address 0x1800:

```
dfuwrap -i program.bin -o program.dfu -a 0x1800
```

FreeType Rasterizer

Usage:

```
ftrasterize [OPTION]... [INPUT FILE]
```

Description:

Uses the FreeType font rendering package to convert a font into the format that is recognized by the graphics library. Any font that is recognized by FreeType can be used, which includes TrueType®, OpenType®, PostScript® Type 1, and Windows® FNT fonts. A complete list of supported font formats can be found on the FreeType web site at <http://www.freetype.org>.

FreeType is used to render the glyphs of a font at a specific size in monochrome, using the result as the bitmap images for the font. These bitmaps are compressed and the results are written as a C source file that provides a tFont structure describing the font.

The source code for this utility is contained in `tools/ftrasterize`, with a pre-built binary contained in `tools/bin`.

Arguments:

- a specifies the index of the font character map to use in the conversion. If absent, Unicode is assumed when “-r” or “-u” is present. Without either of these switches, the Adobe Custom character map is used if such a map exists in the font, otherwise Unicode is used. This ensures backwards compatibility. To determine which character maps a font supports, call ftrasterize with the “-d” option to show font information.
- b specifies that this is a bold font. This does not affect the rendering of the font, it only changes the name of the file and the name of the font structure that are produced.
- c **FILENAME** specifies the name of a file containing a list of character codes whose glyphs should be encoded into the output font. Each line of the file contains either a single decimal or hex character code in the chosen codepage (Unicode unless “-a” is provided), or two character codes separated by a comma and a space to indicate all characters in the

inclusive range. Additionally, if the first non-comment line of the file is "REMAP", the output font is generated to use a custom codepage with character codes starting at 1 and incrementing with every character in the character map file. This switch is only valid with "-r" and overrides "-p" and "-e" which are ignored if present.

- d displays details about the first font whose name is supplied at the end of the command line. When "-d" is used, all other switches are ignored. When used without "-v", font header information and properties are shown along with the total number of characters encoded by the font and the number of contiguous blocks these characters are found in. With "-v", detailed information on the character blocks is also displayed.
- f **FILENAME** specifies the base name for this font, which is used as a base for the output file names and the name of the font structure. The default value is "font" if not specified.
- h shows command line help information.
- i specifies that this is an italic font. This does not affect the rendering of the font, it only changes the name of the file and the name of the font structure that are produced.
- m specifies that this is a monospaced font. This causes the glyphs to be horizontally centered in a box whose width is the width of the widest glyph. For best visual results, this option should only be used for font faces that are designed to be monospaced (such as Computer Modern TeleType).
- s **SIZE** specifies the size of this font, in points. The default value is 20 if not specified. If the size provided starts with "F", it is assumed that the following number is an index into the font's fixed size table. For example "-s F3" would select the fourth fixed size offered by the font. To determine whether a given font supports a fixed size table, use ftrasterize with the "-d" switch.
- p **NUM** specifies the index of the first character in the font that is to be encoded. If the value is not provided, it defaults to 32 which is typically the space character. This switch is ignored if "-c" is provided.
- e **NUM** specifies the index of the last character in the font that is to be encoded. If the value is not provided, it defaults to 126 which, in ISO8859-1 is tilde. This switch is ignored if "-c" is provided.
- v specifies that verbose output should be generated.
- w **NUM** encodes the specified character index as a space regardless of the character which may be present in the font at that location. This is helpful in allowing a space to be included in a font which only encodes a subset of the characters which would not normally include the space character (for example, numeric digits only). If absent, this value defaults to 32, ensuring that character 32 is always the space. Ignored if "-r" is specified.
- n overrides -w and causes no character to be encoded as a space unless the source font already contains a space.
- u causes ftrasterize to use Unicode character mapping when extracting glyphs from the source font. If absent, the Adobe Custom character map is used if it exists or Unicode otherwise.
- r specifies that the output should be a relocatable, wide character set font described using the tFontWide structure. Such fonts are suitable for encoding character sets described using Unicode or when multiple contiguous blocks of characters are to be stored in a single font file. This switch may be used in conjunction with "-y" to create a binary font file suitable for use from a file system.
- y writes the output in binary rather than text format. This switch is only valid if used in conjunction with "-r" and is ignored otherwise. Fonts generated in binary format may be accessed by the graphics library from a file system or other indirect storage assuming that simple wrapper software is provided.
- o **NUM** specifies the codepoint for the first character in the source font which is to be translated to a new position in the output font. If this switch is not provided, no remapping takes

place. If specified, this switch must be used in conjunction with `-t` which specifies where remapped characters are placed in the output font. Ignored if `-r` is specified.

-t NUM specifies the output font character index for the first character remapped from a higher codepoint in the source font. This should be used in conjunction with `-o`. The default value is 0. Ignored if `-r` is specified.

-z NUM specifies the codepage identifier for the output font. This switch is only valid if used with `-r` and is primarily intended for use when performing codepage remapping and custom string tables. The number provided when performing remapping must be in the region between `CODEPAGE_CUSTOM_BASE` (0x8000) and 0xFFFF.

INPUT FILE specifies the name of the input font file. When used with `-r`, up to four font filenames may be provided in order of priority. Characters missing from the first font are searched for in the remaining fonts. This allows the output font to contain characters from multiple different fonts and is helpful when generating multi-language string tables containing different alphabets which do not all exist in a single input font file.

Examples:

The following example produces a 24-point font called test and containing ASCII characters in the range 0x20 to 0x7F from test.ttf:

```
ftrasterize -f test -s 24 test.ttf
```

The result will be written to `fonttest24.c`, and will contain a structure called `g_sFontTest24` that describes the font.

The following would render a Computer Modern small-caps font at 44 points and generate an output font containing only characters 47 through 58 (the numeric digits). Additionally, the first character in the encoded font (which is displayed if an attempt is made to render a character which is not included in the font) is forced to be a space:

```
ftrasterize -f cmscdigits -s 44 -w 47 -p 47 -e 58 cmcsc10.pfb
```

The output will be written to `fontcmscdigits44.c` and contain a definition for `g_sFontCmscdigits44` that describes the font.

To generate some ISO8859 variant fonts, a block of characters from a source Unicode font must be moved downwards into the [0-255] codepoint range of the output font. This can be achieved by making use of the `-t` and `-o` switches. For example, the following will generate a font containing characters 32 to 255 of the ISO8859-5 character mapping. This contains the basic western European alphanumerics and the Cyrillic alphabet. The Cyrillic characters are found starting at Unicode character 1024 (0x400) but these must be placed starting at ISO8859-5 character number 160 (0xA0) so we encode characters 160 and above in the output from the Unicode block starting at 1024 to translate the Cyrillic glyphs into the correct position in the output:

```
ftrasterize -f cyrillic -s 18 -p 32 -e 255 -t 160 -o 1024 -u unicode.ttf
```

When encoding wide character sets for multiple alphabets (Roman, Arabic, Cyrillic, Hebrew, etc.) or to deal with ideograph-based writing systems (Hangul, Traditional or Simplified Chinese, Hiragana, Katakana, etc.), a character block map file is required to define which sections of the source font's codespace to encode into the destination font. The following example character map could be used to encode a font containing ASCII plus the Japanese Katakana alphabets:

```
#####
```

```
#
# katakana.txt - Unicode block definitions for ASCII and Katakana.
#
#####

# ASCII characters
0x20, 0x7E

# Katakana alphabet
0x30A0, 0x30FF
0x31F0, 0x32FF
0xFF00, 0xFFEF
```

Assuming the font “unicode.ttf” contains these glyphs and that it includes fixed size character renderings, the fifth of which uses an 8x12 character cell size, the following `ftrasterize` command line could then be used to generate a binary font file called `fontkatakana8x12.bin` containing this subset of characters:

```
ftrasterize -f katakana -s F4 -c katakana.txt -y -r -u unicode.ttf
```

In this case, the output file will be `fontkatakana8x12.bin` and it will contain a binary version of the font suitable for use from external memory (SDCard, a file system, serial flash memory, etc.) via a `tFontWrapper` and a suitable font wrapper module.

USB DFU Library

Description:

LMDFU is a Windows dynamic link library offering a high level interface to the USB Device Firmware Upgrade functionality provided by the Stellaris USB boot loader (`boot_usb`). This DLL is used by the `dfuprog` utility and also by the `LMFlash` application to allow download and upload of application images to or from a Stellaris-based board via USB.

The source code for this DLL is contained in `tools/lmdfu`. The DLL binary is installed as part of the “Stellaris embedded USB drivers” package (SW-USB-windrivers) shipped on the release CD and downloadable from http://www.ti.com/software_updates.html. A Microsoft Visual Studio 2008 project file is provided to allow the application to be built.

GIMP Script For Texas Instruments Stellaris Button

Description:

This is a script-fu plugin for GIMP (<http://www.gimp.org>) that produces push button images that can be used by the push button widget. When installed into `${HOME}/.gimp-2.4/scripts`, this will be available under `Xtns->Buttons->LMI Button`. When run, a dialog will be displayed allowing the width and height of the button, the radius of the corners, the thickness of the 3D effect, the color of the button, and the pressed state of the button to be selected. Once the desired configuration is selected, pressing OK will create the push button image in a new GIMP image. The image should be saved as a raw PPM file so that it can be converted to a C array by `pnmtoc`.

This script is provided as a convenience to easily produce a particular push button appearance; the push button images can be of any desired appearance.

This script is located in `tools/lmi-button/lmi-button.scm`.

Oscilloscope Application

Description:

LMScope is a Windows front end for the qs-scope example shipped with ek-lm3s3748 kits. The application communicates with the board via USB and allows control of various oscilloscope parameters and display of captured data.

Detailed documentation for this example is provided in a help file which is installed alongside the example binary.

The source code for this application is contained in `tools/lmscope`. The binary is installed as part of the “Windows-side examples for USB kits” package (SW-EK-USB-win) shipped on the release CD and downloadable from http://www.luminarymicro.com/products/software_updates.html. A Microsoft Visual Studio project file is provided to allow the application to be built.

USB Dynamic Link Library

Description:

LMUSBDLL is a simple Windows dynamic link library offering low level packet read and write functions for some USB-connected Stellaris example applications. The DLL is written above the Microsoft WinUSB interface and is intended solely to ensure that various Windows-side example applications can be built without having to use WinUSB header files. These header files are not included in the Visual Studio tools and are only shipped in the Windows Device Driver Kit (DDK). By providing this simple mapping DLL which links to WinUSB, the user avoids the need for a multi-gigabyte download to build the examples.

The source code for this DLL is contained in `tools/lmusbdll`. The DLL binary is installed as part of the “Stellaris embedded USB drivers” package (SW-USB-windrivers) shipped on the release CD and downloadable from http://www.ti.com/software_updates.html. A Microsoft Visual Studio 2008 project file is provided to allow the DLL to be built on a PC which has the Windows Device Driver Kit installed.

String Table Generator

Usage:

```
mkstringtable [INPUT FILE] [OUTPUT FILE]
```

Description:

Converts a comma separated file (.csv) to a table of strings that can be used by the Stellaris Graphics Library. The source .csv file has a simple fixed format that supports multiple strings in multiple languages. A .c and .h file will be created that can be compiled in with an application and used with the graphics library's string table handling functions. If encoding purely ASCII strings, the strings will also be compressed in order to reduce the space required to store them. If the CSV file contains strings encoded in other codepages, for example UTF8, the “-s”

command line option must be used to specify the encoding used for the string and “-u” must also be used to ensure that the strings are stored correctly.

The format of the input .csv file is simple and easily edited in any plain text editor or a spreadsheet editor capable of reading and editing a .csv file. The .csv file format has a header row where the first entry in the row can be any string as it is ignored. The remaining entries in the row must be one of the GrLang* language definitions defined by the graphics library in `grlib.h` or they must have a `#define` definition that is valid for the application as this text is used directly in the C output file that is produced. Adding additional languages only requires that the value is unique in the table and that the name used is defined by the application.

The strings are specified one per line in the .csv file. The first entry in any line is the value that is used as the actual text for the definition for the given string. The remaining entries should be the strings for each language specified in the header. Single words with no special characters do not require quotations, however any strings with a “,” character must be quoted as the “,” character is the delimiter for each item in the line. If the string has a quote character “” it must be preceded by another quote character.

The following is an example .csv file containing string in English (US), German, Spanish (SP), and Italian:

```
LanguageIDs,GrLangEnUS,GrLangDE,GrLangEsSP,GrLangIt
STR_CONFIG,Configuration,Konfigurieren,Configuracion,Configurazione
STR_INTRO,Introduction,Einfuhrung,Introduccion,Introduzione
STR_QUOTE,Introduction in "English","Einfuhrung, in Deutsch",Prueba,Verifica
...
```

In this example, `STR_QUOTE` would result in the following strings in the various languages:

- GrLangEnUs – Introduction in "English"
- GrLangDE – Einfuhrung, in Deutsch
- GrLangEsSP – Prueba
- GrLangIt – Verifica

The resulting .c file contains the string table that must be included with the application that is using the string table and two helper structure definitions, one a `tCodepointMap` array containing a single entry that is suitable for use with `GrCodepageMapTableSet()` and the other a `tGrLibDefaults` structure which can be used with `GrLibInit()` to initialize the graphics library to use the correct codepage for the string table.

While the contents of this .c file are readable, the string table itself may be unintelligible due to the compression or remapping used on the strings themselves. The .h file that is created has the definition for the string table as well as an enumerated type `enum SCOMP_STR_INDEX` that contains all of the string indexes that were present in the original .csv file and external definitions for the `tCodepointMap` and `tGrLibDefaults` structures defined in the .c file.

The code that uses the string table produced by this utility must refer to the strings by their identifier in the original .csv file. In the example above, this means that the value `STR_CONFIG` would refer to the “Configuration” string in English (GrLangEnUS) or “Konfigurieren” in German (GrLangDE).

This utility is contained in `tools/bin`.

Arguments:

- u indicates that the input .csv file contains strings encoded with UTF8 or some other non-ASCII codepage. If absent, `mkstringtable` assumes ASCII text and uses this knowledge to apply higher compression to the string table.

- c NUM** specifies the custom codepage identifier to use when remapping the string table for use with a custom font. Applications using the string table must set this value as the text codepage in use via a call to `GrStringCodepageSet()` and must ensure that they include an entry in their codepage mapping table specifying this value as both the source and font codepage. A macro, `GRLIB_CUSTOM_MAP_XXX`, containing the required `tCodePointMap` structure is written to the output header file to make this easier. A structure, `g_GrLibDefaultXXXX`, is also exported and a pointer to this may be passed to `GrLibInit()` to allow widgets to make use of the string table's custom codepage. Valid values to pass as `NUM` are in the `0x8000` to `0xFFFF` range set aside by the graphics library for application-specific or custom text codepages.
- r** indicates that the output string table should be constructed for use with a custom font and codepage. Character values in the string are remapped into a custom codepage intended to minimize the size of both the string table and the custom font used to display its strings. If `"-r"` is specified, an additional `.txt` output file is generated containing information that may be passed to the `ftrasterize` tool to create a compatible custom font containing only the characters required by the string table contents.
- s STR** specifies the codepage used in the input `.csv` file. If this switch is absent, ASCII is assumed. Valid values of `STR` are `"ASCII"`, `"utf8"` and `"iso8859-n"` where `"n"` indicates the ISO8859 variant in use and can have values from 1 to 11 or 13 to 16. Care must be taken to ensure that the `.csv` file is correctly encoded and makes use of the encoding specified using `"-s"` since a mismatch will cause the output strings to be incorrect. Note, also, that support for UTF-8 and ISO8859 varies from text editor to text editor so it is important to ensure that your editor supports the desired codepage to prevent string corruption.
- t** indicates that a character map file with a `.txt` extension should be generated in addition to the usual `.c` and `.h` output files. This output file may be passed to `ftrasterize` to generate a custom font containing only the glyphs required to display the strings in the table. Unlike the character map file generated when using `"-r"`, the version generated by `"-t"` will not remap the codepage of the strings in the table. This has the advantage of leaving them readable in a debugger (which typically understands ASCII and common codepages) but will generate a font that is rather larger than the font that would have been generated using a remapped codepage due to the additional overhead of encoding many small blocks of discontinuous characters.

INPUT FILE specifies the input `.csv` file to use to create a string table.

OUTPUT FILE specifies the root name of the output files as `<OUTPUT FILE>.c` and `<OUTPUT FILE>.h`. The value is also used in the naming of the string table variable.

Example:

The following will create a string table in `str.c`, with prototypes in `str.h`, based on the ASCII input file `str.csv`:

```
mkstringtable str.csv str
```

In the produced `str.c`, there will be a string table in `g_pucTablestr`.

The following will create a string table in `widestr.c`, with prototypes in `widestr.h`, based on the UTF8 input file `widestr.csv`. This form of the call should be used to encode string tables containing accented characters or non-Western character sets:

```
mkstringtable -u widestr.csv widestr
```

In the produced `widestr.c`, there will be a string table in `g_pucTablewidestr`.

NetPNM Converter

Usage:

```
pnmtoc [OPTION]... [INPUT FILE]
```

Description:

Converts a NetPBM image file into the format that is recognized by the Stellaris Graphics Library. The input image must be in the raw PPM format (in other words, with the P4, P5 or P6 tags). The NetPBM image format can be produced using GIMP, NetPBM (<http://netpbm.sourceforge.net>), ImageMagick (<http://www.imagemagick.org>), or numerous other open source and proprietary image manipulation packages.

The resulting C image array definition is written to standard output; this follows the convention of the NetPBM toolkit after which the application was modeled (both in behavior and naming). The output should be redirected into a file so that it can then be used by the application.

To take a JPEG and convert it for use by the graphics library (using GIMP; a similar technique would be used in other graphics programs):

1. Load the file (File->Open).
2. Convert the image to indexed mode (Image->Mode->Indexed). Select “Generate optimum palette” and select either 2, 16, or 256 as the maximum number of colors (for a 1 BPP, 4 BPP, or 8 BPP image respectively). If the image is already in indexed mode, it can be converted to RGB mode (Image->Mode->RGB) and then back to indexed mode.
3. Save the file as a PNM image (File->Save As). Select raw format when prompted.
4. Use `pnmtoc` to convert the PNM image into a C array.

This sequence will be the same for any source image type (GIF, BMP, TIFF, and so on); once loaded into GIMP, it will treat all image types equally. For some source images, such as a GIF which is naturally an indexed format with 256 colors, the second step could be skipped if an 8 BPP image is desired in the application.

The source code for this utility is contained in `tools/pnmtoc`, with a pre-built binary contained in `tools/bin`.

Arguments:

- `-c` specifies that the image should be compressed. Compression is bypassed if it would result in a larger C array.

Example:

The following will produce a compressed image in `foo.c` from `foo.ppm`:

```
pnmtoc -c foo.ppm > foo.c
```

This will result in an array called `g_pucImage` that contains the image data from `foo.ppm`.

Serial Flash Downloader

Usage:

```
sflash [OPTION]... [INPUT FILE]
```


Description:

Downloads a firmware image to a Stellaris board using a UART connection to the Stellaris Serial Flash Loader or the Stellaris Boot Loader. This has the same capabilities as the serial download portion of the Stellaris Flash Programmer.

The source code for this utility is contained in `tools/sflash`, with a pre-built binary contained in `tools/bin`.

Arguments:

- b **BAUD** specifies the baud rate. If not specified, the default of 115,200 will be used.
- c **PORT** specifies the COM port. If not specified, the default of COM1 will be used.
- d disables auto-baud.
- h displays usage information.
- i **FILENAME** specifies the name of the boot loader image file.
- p **ADDR** specifies the address at which to program the firmware. If not specified, the default of 0 will be used.
- r **ADDR** specifies the address at which to start processor execution after the firmware has been downloaded. If not specified, the processor will be reset after the firmware has been downloaded.
- s **SIZE** specifies the size of the data packets used to download the firmware data. This must be a multiple of four between 8 and 252, inclusive. If using the Serial Flash Loader, the maximum value that can be used is 76. If using the Boot Loader, the maximum value that can be used is dependent upon the configuration of the Boot Loader. If not specified, the default of 8 will be used.

INPUT FILE specifies the name of the firmware image file.

Example:

The following will download a firmware image to the board over COM2 without auto-baud support:

```
sflash -c 2 -d image.bin
```

USB Bulk Data Transfer Example

Description:

`usb_bulk_example` is a Windows command line application which communicates with the StellarisWare `usb_dev_bulk` example. The application finds the Stellaris device on the USB bus then, if found, prompts the user to enter strings which are sent to the application running on the Stellaris board. This application then inverts the case of the alphabetic characters in the string and returns the data back to the USB host where it is displayed.

The source code for this application is contained in `tools/usb_bulk_example`. The binary is installed as part of the "Windows-side examples for USB kits" package (SW-USB-win) shipped on the release CD and downloadable from http://www.luminarymicro.com/products/software_updates.html. A Microsoft Visual Studio project file is provided to allow the application to be built.

4 Buttons Driver

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4.1 Introduction

The board has a navigation switch that has a button for up, down, left, right, and select. The button driver handles sampling those buttons, performing software debouncing, and implementing an auto-repeat feature.

Debouncing the buttons is performed via the periodic sampling of the button states. If a button is in the opposite state from its debounced state for three consecutive samples, the debounced state is toggled. By choosing an appropriate button sampling rate, any button bounce will appear as a single sampled state in the opposite state and will therefore not affect the debounced state.

The choice of button sampling rate is a trade-off between the quality of debouncing and the latency introduced by the debouncing of the buttons (in other words, the amount of time between the button being pressed and the recognition of the button press). If the sample rate is too high, button bounce may not be properly filtered, and an excessive amount of processor time will be dedicated to button debouncing. If the sample rate is too low, it will take too long to recognize a button press, which will be noticeable to the user. A sampling rate between 1 ms and 10 ms typically provide a good balance of these two factors.

After the buttons have been debounced, the amount of time they are held is tracked in order to provide an auto-repeat function (if desired). There are two parameters that affect the auto-repeat; *ucInitialTicks* and *ucRepeatTicks*. *ucInitialTicks* is the number of samples that the button must be pressed before auto-repeat commences. After auto-repeat has started, *ucRepeatTicks* is the number of samples between repeated “presses” of the button.

Macros are provided to simplify the detection of button press, release, and auto-repeat events.

This driver is located in `boards/ek-lm3s3748/drivers`, with `buttons.c` containing the source code and `buttons.h` containing the API definitions for use by applications.

4.2 API Functions

Functions

- void `ButtonsInit` (void)
- unsigned char `ButtonsPoll` (unsigned char *pucDelta, unsigned char *pucRepeat)
- void `ButtonsSetAutoRepeat` (unsigned char ucButtonIDs, unsigned char ucInitialTicks, unsigned char ucRepeatTicks)

4.2.1 Function Documentation

4.2.1.1 ButtonsInit

Initializes the GPIO pins used by the board pushbuttons.

Prototype:

```
void  
ButtonsInit(void)
```

Description:

This function must be called during application initialization to configure the GPIO pins to which the pushbuttons are attached. It enables the port used by the buttons and configures each button GPIO as an input with a weak pull-up.

Returns:

None.

4.2.1.2 ButtonsPoll

Polls the current state of the buttons and determines which have changed.

Prototype:

```
unsigned char  
ButtonsPoll(unsigned char *pucDelta,  
            unsigned char *pucRepeat)
```

Parameters:

pucDelta points to a character that will be written to indicate which button states changed since the last time this function was called. This value is derived from the debounced state of the buttons.

pucRepeat points to a character that will be written to indicate which buttons are signaling an auto-repeat as a result of this call.

Description:

This function should be called periodically by the application to poll the pushbuttons. It determines both which buttons have changed state since the last call and also signals auto-repeats based on the button state and the number of [ButtonsPoll\(\)](#) calls made since the button was last pressed.

Auto-repeats are signaled at an application-specified rate if a key has been held down for longer than an initial delay period. To ensure that auto-repeats are generated at the desired rate, the application should ensure that this function is called at a regular period since all auto-repeat timing is calculated in terms of calls to [ButtonsPoll\(\)](#).

Returns:

Returns the current debounced state of the buttons where a 1 in the button ID's position indicates that the button is released and a 0 indicates that it is pressed.

4.2.1.3 ButtonsSetAutoRepeat

Sets the auto-repeat parameters for one or more buttons.

Prototype:

```
void
ButtonsSetAutoRepeat(unsigned char ucButtonIDs,
                    unsigned char ucInitialTicks,
                    unsigned char ucRepeatTicks)
```

Parameters:

ucButtonIDs is a bitmask containing the OR-ed IDs of the buttons whose auto-repeat parameters are to be set.

ucInitialTicks is the number of ticks (calls to [ButtonsPoll\(\)](#)) before the first auto-repeat is reported for the key if it is pressed for an extended period.

ucRepeatTicks is the number of ticks that must elapse after the initial period (*ucInitialTicks*) has expired between each subsequent auto-repeat is reported for the key.

Description:

This function may be called to change the auto-repeat delay and repeat period for one or more keys. Auto-Repeat allows an application to be signaled periodically if any key is held down for an extended period of time. After an initial delay following the original button press, a repeat signal flag is generated at a period determined by *ucRepeatTicks* and the interval between calls to [ButtonsPoll\(\)](#).

For example, to configure a button such that it starts auto-repeating 500mS after it is initially pressed and signals an auto-repeat every 100mS until it is released, and assuming that [ButtonsPoll\(\)](#) is called every 50mS, the following parameters would be used:

```
ucInitialTicks = 10
ucRepeatTicks = 2
```

Returns:

None.

4.3 Programming Example

The following example shows how to use the button API.

```
unsigned char ucButtons, ucChanged, ucRepeat;

//
// Initialize the buttons.
//
ButtonsInit();

//
// Loop forever sampling the buttons.
//
while(1)
{
    //
    // Sleep for some amount of time.
    //
}
```

```
    SysCtlDelay(1000);

    //
    // Sample the buttons.
    //
    ucButtons = ButtonsPoll(&ucChanged, &ucRepeat);

    //
    // See if the select button was pressed.
    //
    if(BUTTON_PRESSED(SELECT_BUTTON, ucButtons, ucChanged))
    {
        //
        // Do something in response to the select button press.
        //
    }
}
```

5 Class-D Audio Driver

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5.1 Introduction

The board has a Class-D audio amplifier connected to a small magnetic speaker that can be used to playback digital audio waveforms. The audio driver uses a carrier frequency of 64 KHz to playback 8 KHz digital audio waveforms, which can be in either 8-bit unsigned PCM format or IMA ADPCM format.

When running the processor at 50 MHz, the 64 KHz carrier frequency results in approximately 9.5 bits of resolution in the PWM output. Running the processor at slower rates will reduce the PWM resolution, and therefore the audio quality, so for best audio quality it is recommended that the processor be run at 50 MHz.

In 8-bit unsigned PCM format, each byte represents a single sample. This format provides 8 bits of resolution in the output stream and it takes 8000 bytes per second of audio.

In IMA ADPCM format, each byte represents two encoded samples. After the decoding process, the output stream has approximately 14 bits of resolution and it takes 4000 bytes per second of audio. There will generally be little to no degradation of audio quality when using IMA ADPCM.

The `converter` utility can be used to prepare audio files for playback by this audio driver.

This driver is located in `boards/ek-lm3s3748/drivers`, with `class-d.c` containing the source code and `class-d.h` containing the API definitions for use by applications.

5.2 API Functions

Functions

- tBoolean `ClassDBusy` (void)
- void `ClassDInit` (unsigned long ulPWMClock)
- void `ClassDPlayADPCM` (const unsigned char *pucBuffer, unsigned long ulLength)
- void `ClassDPlayPCM` (const unsigned char *pucBuffer, unsigned long ulLength)
- void `ClassDPWMHandler` (void)
- void `ClassDStop` (void)
- void `ClassDVolumeDown` (unsigned long ulVolume)
- void `ClassDVolumeSet` (unsigned long ulVolume)
- void `ClassDVolumeUp` (unsigned long ulVolume)

5.2.1 Function Documentation

5.2.1.1 ClassDBusy

Determines if the Class-D audio driver is busy.

Prototype:

```
tBoolean  
ClassDBusy(void)
```

Description:

This function determines if the Class-D audio driver is busy, either performing the startup or shutdown ramp for the speaker or playing an audio stream.

Returns:

Returns **true** if the Class-D audio driver is busy and **false** otherwise.

5.2.1.2 ClassDInit

Initializes the Class-D audio driver.

Prototype:

```
void  
ClassDInit(unsigned long ulPWMClock)
```

Parameters:

ulPWMClock is the rate of the clock supplied to the PWM module.

Description:

This function initializes the Class-D audio driver, preparing it to output audio data to the speaker.

The PWM module clock should be as high as possible; lower clock rates reduces the quality of the produced audio. For the best quality audio, the PWM module should be clocked at 50 MHz.

Note:

In order for the Class-D audio driver to function properly, the Class-D audio driver interrupt handler ([ClassDPWMHandler\(\)](#)) must be installed into the vector table for the PWM1 interrupt.

Returns:

None.

5.2.1.3 ClassDPlayADPCM

Plays a buffer of 8 KHz IMA ADPCM data.

Prototype:

```
void  
ClassDPlayADPCM(const unsigned char *pucBuffer,  
                unsigned long ulLength)
```


Parameters:

pucBuffer is a pointer to the buffer containing the IMA ADPCM encoded data.

ulLength is the number of bytes in the buffer.

Description:

This function starts playback of a stream of IMA ADPCM encoded data. The data is decoded as needed and therefore does not require a large buffer in SRAM. This provides a 2:1 compression ratio relative to raw 8-bit PCM with little to no loss in audio quality.

Returns:

None.

5.2.1.4 ClassDPlayPCM

Plays a buffer of 8 KHz, 8-bit, unsigned PCM data.

Prototype:

```
void  
ClassDPlayPCM(const unsigned char *pucBuffer,  
              unsigned long ulLength)
```

Parameters:

pucBuffer is a pointer to the buffer containing 8-bit, unsigned PCM data.

ulLength is the number of bytes in the buffer.

Description:

This function starts playback of a stream of 8-bit, unsigned PCM data. Since the data is unsigned, a value of 128 represents the mid-point of the speaker's travel (that is, corresponds to no DC offset).

Returns:

None.

5.2.1.5 ClassDPWMHandler

Handles the PWM1 interrupt.

Prototype:

```
void  
ClassDPWMHandler(void)
```

Description:

This function responds to the PWM1 interrupt, updating the duty cycle of the output waveform in order to produce sound. It is the application's responsibility to ensure that this function is called in response to the PWM1 interrupt, typically by installing it in the vector table as the handler for the PWM1 interrupt.

Returns:

None.

5.2.1.6 ClassDStop

Stops playback of the current audio stream.

Prototype:

```
void  
ClassDStop(void)
```

Description:

This function immediately stops playback of the current audio stream. As a result, the output is changed directly to the mid-point, possibly resulting in a pop or click. It is then ramped down to no output, eliminating the current draw through the Class-D amplifier and speaker.

Returns:

None.

5.2.1.7 ClassDVolumeDown

Decreases the volume of the audio playback.

Prototype:

```
void  
ClassDVolumeDown(unsigned long ulVolume)
```

Parameters:

ulVolume is the amount by which to decrease the volume of the audio playback, specified as a value between 0 (for no adjustment) and 256 maximum adjustment).

Description:

This function decreases the volume of the audio playback relative to the current volume.

Returns:

None.

5.2.1.8 ClassDVolumeSet

Sets the volume of the audio playback.

Prototype:

```
void  
ClassDVolumeSet(unsigned long ulVolume)
```

Parameters:

ulVolume is the volume of the audio playback, specified as a value between 0 (for silence) and 256 (for full volume).

Description:

This function sets the volume of the audio playback. Setting the volume to 0 will mute the output, while setting the volume to 256 will play the audio stream without any volume adjustment (that is, full volume).

Returns:

None.

5.2.1.9 ClassDVolumeUp

Increases the volume of the audio playback.

Prototype:

```
void  
ClassDVolumeUp(unsigned long ulVolume)
```

Parameters:

ulVolume is the amount by which to increase the volume of the audio playback, specified as a value between 0 (for no adjustment) and 256 maximum adjustment).

Description:

This function increases the volume of the audio playback relative to the current volume.

Returns:

None.

5.3 Programming Example

The following example shows how to use the Class-D audio driver. This assumes that the vector table in the startup code has [ClassDPWMHandler\(\)](#) listed as the handler for the PWM1 interrupt.

```
unsigned char pucBuffer[256];  
  
//  
// Initialize the Class-D driver.  
//  
ClassDInit(SysCtlClockGet());  
  
//  
// Fill pucBuffer with PCM audio data.  
//  
...  
  
//  
// Play the audio data.  
//  
ClassDPlayPCM(pucBuffer, sizeof(pucBuffer));
```


6 Display Driver

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6.1 Introduction

In addition to providing the `tDisplay` structure required by the graphics library, the display driver also provides APIs for initializing the display, turning on the backlight, and turning off the backlight.

This driver is located in `boards/ek-lm3s3748/drivers`, with `formike128x128x16.c` containing the source code and `formike128x128x16.h` containing the API definitions for use by applications.

6.2 API Functions

Functions

- void `Formike128x128x16BacklightOff` (void)
- void `Formike128x128x16BacklightOn` (void)
- void `Formike128x128x16Init` (void)

Variables

- const `tDisplay` `g_sFormike128x128x16`

6.2.1 Function Documentation

6.2.1.1 `Formike128x128x16BacklightOff`

Turns off the backlight.

Prototype:

```
void  
Formike128x128x16BacklightOff(void)
```

Description:

This function turns off the backlight on the display.

Returns:

None.

6.2.1.2 Formike128x128x16BacklightOn

Turns on the backlight.

Prototype:

```
void  
Formike128x128x16BacklightOn(void)
```

Description:

This function turns on the backlight on the display.

Returns:

None.

6.2.1.3 Formike128x128x16Init

Initializes the display driver.

Prototype:

```
void  
Formike128x128x16Init(void)
```

Description:

This function initializes the ST7637 display controller on the panel, preparing it to display data.

Returns:

None.

6.2.2 Variable Documentation

6.2.2.1 g_sFormike128x128x16

Definition:

```
const tDisplay g_sFormike128x128x16
```

Description:

The graphics library display structure that describes the driver for the Formike Electronic KWH015C04-F01 color STN panel with an ST7637 controller.

6.3 Programming Example

The following example shows how to initialize the display and prepare to draw on it using the graphics library.

```
tContext sContext;  
  
//  
// Initialize the display.  
//
```

```
Formike128x128x16Init();

//
// Turn on the backlight.
//
Formike128x128x16BacklightOn();

//
// Initialize a graphics library drawing context.
//
GrContextInit(&sContext, &g_sFormike128x128x16);
```


7 Command Line Processing Module

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7.1 Introduction

The command line processor allows a simple command line interface to be made available in an application, for example via a UART. It takes a buffer containing a string (which must be obtained by the application) and breaks it up into a command and arguments (in traditional C “argc, argv” format). The command is then found in a command table and the corresponding function in the table is called to process the command.

This module is contained in `utils/cmdline.c`, with `utils/cmdline.h` containing the API definitions for use by applications.

7.2 API Functions

Data Structures

- `tCmdLineEntry`

Defines

- `CMDLINE_BAD_CMD`
- `CMDLINE_INVALID_ARG`
- `CMDLINE_TOO_FEW_ARGS`
- `CMDLINE_TOO_MANY_ARGS`

Functions

- `int CmdLineProcess (char *pcCmdLine)`

Variables

- `tCmdLineEntry g_sCmdTable[]`

7.2.1 Data Structure Documentation

7.2.1.1 tCmdLineEntry

Definition:

```
typedef struct
{
    const char *pcCmd;
    pfnCmdLine pfnCmd;
    const char *pcHelp;
}
tCmdLineEntry
```

Members:

pcCmd A pointer to a string containing the name of the command.

pfnCmd A function pointer to the implementation of the command.

pcHelp A pointer to a string of brief help text for the command.

Description:

Structure for an entry in the command list table.

7.2.2 Define Documentation

7.2.2.1 CMDLINE_BAD_CMD

Definition:

```
#define CMDLINE_BAD_CMD
```

Description:

Defines the value that is returned if the command is not found.

7.2.2.2 CMDLINE_INVALID_ARG

Definition:

```
#define CMDLINE_INVALID_ARG
```

Description:

Defines the value that is returned if an argument is invalid.

7.2.2.3 CMDLINE_TOO_FEW_ARGS

Definition:

```
#define CMDLINE_TOO_FEW_ARGS
```

Description:

Defines the value that is returned if there are too few arguments.

7.2.2.4 CMDLINE_TOO_MANY_ARGS

Definition:

```
#define CMDLINE_TOO_MANY_ARGS
```

Description:

Defines the value that is returned if there are too many arguments.

7.2.3 Function Documentation

7.2.3.1 CmdLineProcess

Process a command line string into arguments and execute the command.

Prototype:

```
int  
CmdLineProcess(char *pcCmdLine)
```

Parameters:

pcCmdLine points to a string that contains a command line that was obtained by an application by some means.

Description:

This function will take the supplied command line string and break it up into individual arguments. The first argument is treated as a command and is searched for in the command table. If the command is found, then the command function is called and all of the command line arguments are passed in the normal argc, argv form.

The command table is contained in an array named `g_sCmdTable` which must be provided by the application.

Returns:

Returns **CMDLINE_BAD_CMD** if the command is not found, **CMDLINE_TOO_MANY_ARGS** if there are more arguments than can be parsed. Otherwise it returns the code that was returned by the command function.

7.2.4 Variable Documentation

7.2.4.1 g_sCmdTable

Definition:

```
tCmdLineEntry g_sCmdTable[ ]
```

Description:

This is the command table that must be provided by the application.

7.3 Programming Example

The following example shows how to process a command line.

```
//
// Code for the "foo" command.
//
int
ProcessFoo(int argc, char *argv[])
{
    //
    // Do something, using argc and argv if the command takes arguments.
    //
}

//
// Code for the "bar" command.
//
int
ProcessBar(int argc, char *argv[])
{
    //
    // Do something, using argc and argv if the command takes arguments.
    //
}

//
// Code for the "help" command.
//
int
ProcessHelp(int argc, char *argv[])
{
    //
    // Provide help.
    //
}

//
// The table of commands supported by this application.
//
tCmdLineEntry g_sCmdTable[] =
{
    { "foo", ProcessFoo, "The first command." },
    { "bar", ProcessBar, "The second command." },
    { "help", ProcessHelp, "Application help." }
};

//
// Read a process a command.
//
int
Test(void)
{
    unsigned char pucCmd[256];

    //
    // Retrieve a command from the user into pucCmd.
    //
    ...

    //
    // Process the command line.
    //
    return(CmdLineProcess(pucCmd));
}
```

8 CPU Usage Module

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8.1 Introduction

The CPU utilization module uses one of the system timers and peripheral clock gating to determine the percentage of the time that the processor is being clocked. For the most part, the processor is executing code whenever it is being clocked (exceptions occur when the clocking is being configured, which only happens at startup, and when entering/exiting an interrupt handler, when the processor is performing stacking operations on behalf of the application).

The specified timer is configured to run when the processor is in run mode and to not run when the processor is in sleep mode. Therefore, the timer will only count when the processor is being clocked. Comparing the number of clocks the timer counted during a fixed period to the number of clocks in the fixed period provides the percentage utilization.

In order for this to be effective, the application must put the processor to sleep when it has no work to do (instead of busy waiting). If the processor never goes to sleep (either because of a continual stream of work to do or a busy loop), the processor utilization will be reported as 100%.

Since deep-sleep mode changes the clocking of the system, the computed processor usage may be incorrect if deep-sleep mode is utilized. The number of clocks the processor spends in run mode will be properly counted, but the timing period may not be accurate (unless extraordinary measures are taken to ensure timing period accuracy).

The accuracy of the computed CPU utilization depends upon the regularity with which `CPUUsageTick()` is called by the application. If the CPU usage is constant, but `CPUUsageTick()` is called sporadically, the reported CPU usage will fluctuate as well despite the fact that the CPU usage is actually constant.

This module is contained in `utils/cpu_usage.c`, with `utils/cpu_usage.h` containing the API definitions for use by applications.

8.2 API Functions

Functions

- void `CPUUsageInit` (unsigned long ulClockRate, unsigned long ulRate, unsigned long ulTimer)
- unsigned long `CPUUsageTick` (void)

8.2.1 Function Documentation

8.2.1.1 CPUUsageInit

Initializes the CPU usage measurement module.

Prototype:

```
void  
CPUUsageInit(unsigned long ulClockRate,  
              unsigned long ulRate,  
              unsigned long ulTimer)
```

Parameters:

ulClockRate is the rate of the clock supplied to the timer module.

ulRate is the number of times per second that [CPUUsageTick\(\)](#) is called.

ulTimer is the index of the timer module to use.

Description:

This function prepares the CPU usage measurement module for measuring the CPU usage of the application.

Returns:

None.

8.2.1.2 CPUUsageTick

Updates the CPU usage for the new timing period.

Prototype:

```
unsigned long  
CPUUsageTick(void)
```

Description:

This function, when called at the end of a timing period, will update the CPU usage.

Returns:

Returns the CPU usage percentage as a 16.16 fixed-point value.

8.3 Programming Example

The following example shows how to use the CPU usage module to measure the CPU usage where the foreground simply burns some cycles.

```
//  
// The CPU usage for the most recent time period.  
//  
unsigned long g_ulCPUUsage;  
  
//  
// Handles the SysTick interrupt.
```

```
//
void
SysTickIntHandler(void)
{
    //
    // Compute the CPU usage for the last time period.
    //
    g_ulCPUUsage = CPUUsageTick();
}

//
// The main application.
//
int
main(void)
{
    //
    // Initialize the CPU usage module, using timer 0.
    //
    CPUUsageInit(8000000, 100, 0);

    //
    // Initialize SysTick to interrupt at 100 Hz.
    //
    SysTickPeriodSet(8000000 / 100);
    SysTickIntEnable();
    SysTickEnable();

    //
    // Loop forever.
    //
    while(1)
    {
        //
        // Delay for a little bit so that CPU usage is not zero.
        //
        SysCtlDelay(100);

        //
        // Put the processor to sleep.
        //
        SysCtlSleep();
    }
}
```


9 CRC Module

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9.1 Introduction

The CRC module provides functions to compute the CRC-8-CCITT and CRC-16 of a buffer of data. Support is provided for computing a running CRC, where a partial CRC is computed on one portion of the data, and then continued at a later time on another portion of the data. This is useful when computing the CRC on a stream of data that is coming in via a serial link (for example).

A CRC is useful for detecting errors that occur during the transmission of data over a communications channel or during storage in a memory (such as flash). However, a CRC does not provide protection against an intentional modification or tampering of the data.

This module is contained in `utils/crc.c`, with `utils/crc.h` containing the API definitions for use by applications.

9.2 API Functions

Functions

- unsigned short [Crc16](#) (unsigned short usCrc, const unsigned char *pucData, unsigned long ulCount)
- unsigned short [Crc16Array](#) (unsigned long ulWordLen, const unsigned long *pulData)
- void [Crc16Array3](#) (unsigned long ulWordLen, const unsigned long *pulData, unsigned short *pusCrc3)
- unsigned long [Crc32](#) (unsigned long ulCrc, const unsigned char *pucData, unsigned long ulCount)
- unsigned char [Crc8CCITT](#) (unsigned char ucCrc, const unsigned char *pucData, unsigned long ulCount)

9.2.1 Function Documentation

9.2.1.1 Crc16

Calculates the CRC-16 of an array of bytes.

Prototype:

```
unsigned short
Crc16(unsigned short usCrc,
      const unsigned char *pucData,
      unsigned long ulCount)
```

Parameters:

usCrc is the starting CRC-16 value.

pucData is a pointer to the data buffer.

ulCount is the number of bytes in the data buffer.

Description:

This function is used to calculate the CRC-16 of the input buffer. The CRC-16 is computed in a running fashion, meaning that the entire data block that is to have its CRC-16 computed does not need to be supplied all at once. If the input buffer contains the entire block of data, then **usCrc** should be set to 0. If, however, the entire block of data is not available, then **usCrc** should be set to 0 for the first portion of the data, and then the returned value should be passed back in as **usCrc** for the next portion of the data.

For example, to compute the CRC-16 of a block that has been split into three pieces, use the following:

```
usCrc = Crc16(0, pucData1, ulLen1);
usCrc = Crc16(usCrc, pucData2, ulLen2);
usCrc = Crc16(usCrc, pucData3, ulLen3);
```

Computing a CRC-16 in a running fashion is useful in cases where the data is arriving via a serial link (for example) and is therefore not all available at one time.

Returns:

The CRC-16 of the input data.

9.2.1.2 Crc16Array

Calculates the CRC-16 of an array of words.

Prototype:

```
unsigned short
Crc16Array(unsigned long ulWordLen,
           const unsigned long *pulData)
```

Parameters:

ulWordLen is the length of the array in words (the number of bytes divided by 4).

pulData is a pointer to the data buffer.

Description:

This function is a wrapper around the running CRC-16 function, providing the CRC-16 for a single block of data.

Returns:

The CRC-16 of the input data.

9.2.1.3 Crc16Array3

Calculates three CRC-16s of an array of words.

Prototype:

```
void
Crc16Array3(unsigned long ulWordLen,
            const unsigned long *pulData,
            unsigned short *pusCrc3)
```

Parameters:

ulWordLen is the length of the array in words (the number of bytes divided by 4).

pulData is a pointer to the data buffer.

pusCrc3 is a pointer to an array in which to place the three CRC-16 values.

Description:

This function is used to calculate three CRC-16s of the input buffer; the first uses every byte from the array, the second uses only the even-index bytes from the array (in other words, bytes 0, 2, 4, etc.), and the third uses only the odd-index bytes from the array (in other words, bytes 1, 3, 5, etc.).

Returns:

None

9.2.1.4 Crc32

Calculates the CRC-32 of an array of bytes.

Prototype:

```
unsigned long
Crc32(unsigned long ulCrc,
      const unsigned char *pucData,
      unsigned long ulCount)
```

Parameters:

ulCrc is the starting CRC-32 value.

pucData is a pointer to the data buffer.

ulCount is the number of bytes in the data buffer.

Description:

This function is used to calculate the CRC-32 of the input buffer. The CRC-32 is computed in a running fashion, meaning that the entire data block that is to have its CRC-32 computed does not need to be supplied all at once. If the input buffer contains the entire block of data, then **ulCrc** should be set to 0xFFFFFFFF. If, however, the entire block of data is not available, then **ulCrc** should be set to 0xFFFFFFFF for the first portion of the data, and then the returned value should be passed back in as **ulCrc** for the next portion of the data. Once all data has been passed to the function, the final CRC-32 can be obtained by inverting the last returned value.

For example, to compute the CRC-32 of a block that has been split into three pieces, use the following:

```
ulCrc = Crc32(0xFFFFFFFF, pucData1, ulLen1);
ulCrc = Crc32(ulCrc, pucData2, ulLen2);
ulCrc = Crc32(ulCrc, pucData3, ulLen3);
ulCrc ^= 0xFFFFFFFF;
```

Computing a CRC-32 in a running fashion is useful in cases where the data is arriving via a serial link (for example) and is therefore not all available at one time.

Returns:

The accumulated CRC-32 of the input data.

9.2.1.5 Crc8CCITT

Calculates the CRC-8-CCITT of an array of bytes.

Prototype:

```
unsigned char
Crc8CCITT(unsigned char ucCrc,
          const unsigned char *pucData,
          unsigned long ulCount)
```

Parameters:

ucCrc is the starting CRC-8-CCITT value.

pucData is a pointer to the data buffer.

ulCount is the number of bytes in the data buffer.

Description:

This function is used to calculate the CRC-8-CCITT of the input buffer. The CRC-8-CCITT is computed in a running fashion, meaning that the entire data block that is to have its CRC-8-CCITT computed does not need to be supplied all at once. If the input buffer contains the entire block of data, then **ucCrc** should be set to 0. If, however, the entire block of data is not available, then **ucCrc** should be set to 0 for the first portion of the data, and then the returned value should be passed back in as **ucCrc** for the next portion of the data.

For example, to compute the CRC-8-CCITT of a block that has been split into three pieces, use the following:

```
ucCrc = Crc8CCITT(0, pucData1, ulLen1);
ucCrc = Crc8CCITT(ucCrc, pucData2, ulLen2);
ucCrc = Crc8CCITT(ucCrc, pucData3, ulLen3);
```

Computing a CRC-8-CCITT in a running fashion is useful in cases where the data is arriving via a serial link (for example) and is therefore not all available at one time.

Returns:

The CRC-8-CCITT of the input data.

9.3 Programming Example

The following example shows how to compute the CRC-16 of a buffer of data.

```
unsigned long ulIdx, ulValue;
unsigned char pucData[256];

//
// Fill pucData with some data.
```

```
//  
for(ulIdx = 0; ulIdx < 256; ulIdx++)  
{  
    pucData[ulIdx] = ulIdx;  
}  
  
//  
// Compute the CRC-16 of the data.  
//  
ulValue = Crc16(0, pucData, 256);
```


10 Flash Parameter Block Module

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10.1 Introduction

The flash parameter block module provides a simple, fault-tolerant, persistent storage mechanism for storing parameter information for an application.

The [FlashPBlockInit\(\)](#) function is used to initialize a parameter block. The primary conditions for the parameter block are that flash region used to store the parameter blocks must contain at least two erase blocks of flash to ensure fault tolerance, and the size of the parameter block must be an integral divisor of the the size of an erase block. [FlashPBlockGet\(\)](#) and [FlashPBlockSave\(\)](#) are used to read and write parameter block data into the parameter region. The only constraints on the content of the parameter block are that the first two bytes of the block are reserved for use by the read/write functions as a sequence number and checksum, respectively.

This module is contained in `utils/flash_pb.c`, with `utils/flash_pb.h` containing the API definitions for use by applications.

10.2 API Functions

Functions

- unsigned char * [FlashPBlockGet](#) (void)
- void [FlashPBlockInit](#) (unsigned long ulStart, unsigned long ulEnd, unsigned long ulSize)
- void [FlashPBlockSave](#) (unsigned char *pucBuffer)

10.2.1 Function Documentation

10.2.1.1 FlashPBlockGet

Gets the address of the most recent parameter block.

Prototype:

```
unsigned char *  
FlashPBlockGet (void)
```

Description:

This function returns the address of the most recent parameter block that is stored in flash.

Returns:

Returns the address of the most recent parameter block, or NULL if there are no valid parameter blocks in flash.

10.2.1.2 FlashPBInit

Initializes the flash parameter block.

Prototype:

```
void  
FlashPBInit(unsigned long ulStart,  
             unsigned long ulEnd,  
             unsigned long ulSize)
```

Parameters:

ulStart is the address of the flash memory to be used for storing flash parameter blocks; this must be the start of an erase block in the flash.

ulEnd is the address of the end of flash memory to be used for storing flash parameter blocks; this must be the start of an erase block in the flash (the first block that is NOT part of the flash memory to be used), or the address of the first word after the flash array if the last block of flash is to be used.

ulSize is the size of the parameter block when stored in flash; this must be a power of two less than or equal to the flash erase block size (typically 1024).

Description:

This function initializes a fault-tolerant, persistent storage mechanism for a parameter block for an application. The last several erase blocks of flash (as specified by *ulStart* and *ulEnd*) are used for the storage; more than one erase block is required in order to be fault-tolerant.

A parameter block is an array of bytes that contain the persistent parameters for the application. The only special requirement for the parameter block is that the first byte is a sequence number (explained in [FlashPBSave\(\)](#)) and the second byte is a checksum used to validate the correctness of the data (the checksum byte is the byte such that the sum of all bytes in the parameter block is zero).

The portion of flash for parameter block storage is split into N equal-sized regions, where each region is the size of a parameter block (*ulSize*). Each region is scanned to find the most recent valid parameter block. The region that has a valid checksum and has the highest sequence number (with special consideration given to wrapping back to zero) is considered to be the current parameter block.

In order to make this efficient and effective, three conditions must be met. The first is *ulStart* and *ulEnd* must be specified such that at least two erase blocks of flash are dedicated to parameter block storage. If not, fault tolerance can not be guaranteed since an erase of a single block will leave a window where there are no valid parameter blocks in flash. The second condition is that the size (*ulSize*) of the parameter block must be an integral divisor of the size of an erase block of flash. If not, a parameter block will end up spanning between two erase blocks of flash, making it more difficult to manage. The final condition is that the size of the flash dedicated to parameter blocks (*ulEnd* - *ulStart*) divided by the parameter block size (*ulSize*) must be less than or equal to 128. If not, it will not be possible in all cases to determine which parameter block is the most recent (specifically when dealing with the sequence number wrapping back to zero).

When the microcontroller is initially programmed, the flash blocks used for parameter block storage are left in an erased state.

This function must be called before any other flash parameter block functions are called.

Returns:

None.

10.2.1.3 FlashPBSave

Writes a new parameter block to flash.

Prototype:

```
void  
FlashPBSave(unsigned char *pucBuffer)
```

Parameters:

pucBuffer is the address of the parameter block to be written to flash.

Description:

This function will write a parameter block to flash. Saving the new parameter blocks involves three steps:

- Setting the sequence number such that it is one greater than the sequence number of the latest parameter block in flash.
- Computing the checksum of the parameter block.
- Writing the parameter block into the storage immediately following the latest parameter block in flash; if that storage is at the start of an erase block, that block is erased first.

By this process, there is always a valid parameter block in flash. If power is lost while writing a new parameter block, the checksum will not match and the partially written parameter block will be ignored. This is what makes this fault-tolerant.

Another benefit of this scheme is that it provides wear leveling on the flash. Since multiple parameter blocks fit into each erase block of flash, and multiple erase blocks are used for parameter block storage, it takes quite a few parameter block saves before flash is re-written.

Returns:

None.

10.3 Programming Example

The following example shows how to use the flash parameter block module to read the contents of a flash parameter block.

```
unsigned char pucBuffer[16], *pucPB;  
  
//  
// Initialize the flash parameter block module, using the last two pages of  
// a 64 KB device as the parameter block.  
//  
FlashPBInit(0xf800, 0x10000, 16);  
  
//  
// Read the current parameter block.  
//  
pucPB = FlashPBGet();  
if(pucPB)  
{  
    memcpy(pucBuffer, pucPB);  
}
```


11 Integer Square Root Module

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11.1 Introduction

The integer square root module provides an integer version of the square root operation that can be used instead of the floating point version provided in the C library. The algorithm used is a derivative of the manual pencil-and-paper method that used to be taught in school, and is closely related to the pencil-and-paper division method that is likely still taught in school.

For full details of the algorithm, see the article by Jack W. Crenshaw in the February 1998 issue of Embedded System Programming. It can be found online at <http://www.embedded.com/98/9802fe2.htm>.

This module is contained in `utils/isqrt.c`, with `utils/isqrt.h` containing the API definitions for use by applications.

11.2 API Functions

Functions

- unsigned long `isqrt` (unsigned long `ulValue`)

11.2.1 Function Documentation

11.2.1.1 `isqrt`

Compute the integer square root of an integer.

Prototype:

```
unsigned long  
isqrt(unsigned long ulValue)
```

Parameters:

ulValue is the value whose square root is desired.

Description:

This function will compute the integer square root of the given input value. Since the value returned is also an integer, it is actually better defined as the largest integer whose square is less than or equal to the input value.

Returns:

Returns the square root of the input value.

11.3 Programming Example

The following example shows how to compute the square root of a number.

```
unsigned long ulValue;  
  
//  
// Get the square root of 52378. The result returned will be 228, which is  
// the largest integer less than or equal to the square root of 52378.  
//  
ulValue = isqrt(52378);
```

12 Ring Buffer Module

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12.1 Introduction

The ring buffer module provides a set of functions allowing management of a block of memory as a ring buffer. This is typically used in buffering transmit or receive data for a communication channel but has many other uses including implementing queues and FIFOs.

This module is contained in `utils/ringbuf.c`, with `utils/ringbuf.h` containing the API definitions for use by applications.

12.2 API Functions

Functions

- void [RingBufAdvanceRead](#) (tRingBufObject *ptRingBuf, unsigned long ulNumBytes)
- void [RingBufAdvanceWrite](#) (tRingBufObject *ptRingBuf, unsigned long ulNumBytes)
- unsigned long [RingBufContigFree](#) (tRingBufObject *ptRingBuf)
- unsigned long [RingBufContigUsed](#) (tRingBufObject *ptRingBuf)
- tBoolean [RingBufEmpty](#) (tRingBufObject *ptRingBuf)
- void [RingBufFlush](#) (tRingBufObject *ptRingBuf)
- unsigned long [RingBufFree](#) (tRingBufObject *ptRingBuf)
- tBoolean [RingBufFull](#) (tRingBufObject *ptRingBuf)
- void [RingBufInit](#) (tRingBufObject *ptRingBuf, unsigned char *pucBuf, unsigned long ulSize)
- void [RingBufRead](#) (tRingBufObject *ptRingBuf, unsigned char *pucData, unsigned long ulLength)
- unsigned char [RingBufReadOne](#) (tRingBufObject *ptRingBuf)
- unsigned long [RingBufSize](#) (tRingBufObject *ptRingBuf)
- unsigned long [RingBufUsed](#) (tRingBufObject *ptRingBuf)
- void [RingBufWrite](#) (tRingBufObject *ptRingBuf, unsigned char *pucData, unsigned long ulLength)
- void [RingBufWriteOne](#) (tRingBufObject *ptRingBuf, unsigned char ucData)

12.2.1 Function Documentation

12.2.1.1 RingBufAdvanceRead

Remove bytes from the ring buffer by advancing the read index.

Prototype:

```
void  
RingBufAdvanceRead(tRingBufObject *ptRingBuf,  
                   unsigned long ulNumBytes)
```

Parameters:

ptRingBuf points to the ring buffer from which bytes are to be removed.
ulNumBytes is the number of bytes to be removed from the buffer.

Description:

This function advances the ring buffer read index by a given number of bytes, removing that number of bytes of data from the buffer. If *ulNumBytes* is larger than the number of bytes currently in the buffer, the buffer is emptied.

Returns:

None.

12.2.1.2 RingBufAdvanceWrite

Add bytes to the ring buffer by advancing the write index.

Prototype:

```
void  
RingBufAdvanceWrite(tRingBufObject *ptRingBuf,  
                   unsigned long ulNumBytes)
```

Parameters:

ptRingBuf points to the ring buffer to which bytes have been added.
ulNumBytes is the number of bytes added to the buffer.

Description:

This function should be used by clients who wish to add data to the buffer directly rather than via calls to [RingBufWrite\(\)](#) or [RingBufWriteOne\(\)](#). It advances the write index by a given number of bytes. If the *ulNumBytes* parameter is larger than the amount of free space in the buffer, the read pointer will be advanced to cater for the addition. Note that this will result in some of the oldest data in the buffer being discarded.

Returns:

None.

12.2.1.3 RingBufContigFree

Returns number of contiguous free bytes available in a ring buffer.

Prototype:

```
unsigned long  
RingBufContigFree(tRingBufObject *ptRingBuf)
```

Parameters:

ptRingBuf is the ring buffer object to check.

Description:

This function returns the number of contiguous free bytes ahead of the current write pointer in the ring buffer.

Returns:

Returns the number of contiguous bytes available in the ring buffer.

12.2.1.4 RingBufContigUsed

Returns number of contiguous bytes of data stored in ring buffer ahead of the current read pointer.

Prototype:

```
unsigned long  
RingBufContigUsed(tRingBufObject *ptRingBuf)
```

Parameters:

ptRingBuf is the ring buffer object to check.

Description:

This function returns the number of contiguous bytes of data available in the ring buffer ahead of the current read pointer. This represents the largest block of data which does not straddle the buffer wrap.

Returns:

Returns the number of contiguous bytes available.

12.2.1.5 RingBufEmpty

Determines whether the ring buffer whose pointers and size are provided is empty or not.

Prototype:

```
tBoolean  
RingBufEmpty(tRingBufObject *ptRingBuf)
```

Parameters:

ptRingBuf is the ring buffer object to empty.

Description:

This function is used to determine whether or not a given ring buffer is empty. The structure is specifically to ensure that we do not see warnings from the compiler related to the order of volatile accesses being undefined.

Returns:

Returns **true** if the buffer is empty or **false** otherwise.

12.2.1.6 RingBufFlush

Empties the ring buffer.

Prototype:

```
void  
RingBufFlush(tRingBufObject *ptRingBuf)
```

Parameters:

ptRingBuf is the ring buffer object to empty.

Description:

Discards all data from the ring buffer.

Returns:

None.

12.2.1.7 RingBufFree

Returns number of bytes available in a ring buffer.

Prototype:

```
unsigned long  
RingBufFree(tRingBufObject *ptRingBuf)
```

Parameters:

ptRingBuf is the ring buffer object to check.

Description:

This function returns the number of bytes available in the ring buffer.

Returns:

Returns the number of bytes available in the ring buffer.

12.2.1.8 RingBufFull

Determines whether the ring buffer whose pointers and size are provided is full or not.

Prototype:

```
tBoolean  
RingBufFull(tRingBufObject *ptRingBuf)
```

Parameters:

ptRingBuf is the ring buffer object to empty.

Description:

This function is used to determine whether or not a given ring buffer is full. The structure is specifically to ensure that we do not see warnings from the compiler related to the order of volatile accesses being undefined.

Returns:

Returns **true** if the buffer is full or **false** otherwise.

12.2.1.9 RingBufInit

Initialize a ring buffer object.

Prototype:

```
void  
RingBufInit (tRingBufObject *ptRingBuf,  
             unsigned char *pucBuf,  
             unsigned long ulSize)
```

Parameters:

ptRingBuf points to the ring buffer to be initialized.
pucBuf points to the data buffer to be used for the ring buffer.
ulSize is the size of the buffer in bytes.

Description:

This function initializes a ring buffer object, preparing it to store data.

Returns:

None.

12.2.1.10 RingBufRead

Reads data from a ring buffer.

Prototype:

```
void  
RingBufRead (tRingBufObject *ptRingBuf,  
             unsigned char *pucData,  
             unsigned long ulLength)
```

Parameters:

ptRingBuf points to the ring buffer to be read from.
pucData points to where the data should be stored.
ulLength is the number of bytes to be read.

Description:

This function reads a sequence of bytes from a ring buffer.

Returns:

None.

12.2.1.11 RingBufReadOne

Reads a single byte of data from a ring buffer.

Prototype:

```
unsigned char  
RingBufReadOne (tRingBufObject *ptRingBuf)
```

Parameters:

ptRingBuf points to the ring buffer to be written to.

Description:

This function reads a single byte of data from a ring buffer.

Returns:

The byte read from the ring buffer.

12.2.1.12 RingBufSize

Return size in bytes of a ring buffer.

Prototype:

```
unsigned long  
RingBufSize(tRingBufObject *ptRingBuf)
```

Parameters:

ptRingBuf is the ring buffer object to check.

Description:

This function returns the size of the ring buffer.

Returns:

Returns the size in bytes of the ring buffer.

12.2.1.13 RingBufUsed

Returns number of bytes stored in ring buffer.

Prototype:

```
unsigned long  
RingBufUsed(tRingBufObject *ptRingBuf)
```

Parameters:

ptRingBuf is the ring buffer object to check.

Description:

This function returns the number of bytes stored in the ring buffer.

Returns:

Returns the number of bytes stored in the ring buffer.

12.2.1.14 RingBufWrite

Writes data to a ring buffer.

Prototype:

```
void  
RingBufWrite(tRingBufObject *ptRingBuf,  
             unsigned char *pucData,  
             unsigned long ulLength)
```

Parameters:

ptRingBuf points to the ring buffer to be written to.
pucData points to the data to be written.
ulLength is the number of bytes to be written.

Description:

This function write a sequence of bytes into a ring buffer.

Returns:

None.

12.2.1.15 RingBufWriteOne

Writes a single byte of data to a ring buffer.

Prototype:

```
void  
RingBufWriteOne(tRingBufObject *ptRingBuf,  
               unsigned char ucData)
```

Parameters:

ptRingBuf points to the ring buffer to be written to.
ucData is the byte to be written.

Description:

This function writes a single byte of data into a ring buffer.

Returns:

None.

12.3 Programming Example

The following example shows how to pass data through the ring buffer.

```
char pcBuffer[128], pcData[16];  
tRingBufObject sRingBuf;  
  
//  
// Initialize the ring buffer.  
//  
RingBufInit(&sRingBuf, pcBuffer, sizeof(pcBuffer));  
  
//  
// Write some data into the ring buffer.  
//  
RingBufWrite(&sRingBuf, "Hello World", 11);
```

```
//  
// Read the data out of the ring buffer.  
//  
RingBufRead(&sRingBuf, pData, 11);
```

13 Simple Task Scheduler Module

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13.1 Introduction

The simple task scheduler module offers an easy way to implement applications which rely upon a group of functions being called at regular time intervals. The module makes use of an application-defined task table listing functions to be called. Each task is defined by a function pointer, a parameter that will be passed to that function, the period between consecutive calls to the function and a flag indicating whether that particular task is enabled.

The scheduler makes use of the SysTick counter and interrupt to track time and calls enabled functions when the appropriate period has elapsed since the last call to that function.

In addition to providing the task table `g_psSchedulerTable[]` to the module, the application must also define a global variable `g_ulSchedulerNumTasks` containing the number of task entries in the table. The module also requires exclusive access to the SysTick hardware and the application must hook the scheduler's SysTick interrupt handler to the appropriate interrupt vector. Although the scheduler owns SysTick, functions are provided to allow the current system time to be queried and to calculate elapsed time between two system time values or between an earlier time value and the present time.

All times passed to the scheduler or returned from it are expressed in terms of system ticks. The basic system tick rate is set by the application when it initializes the scheduler module.

This module is contained in `utils/scheduler.c`, with `utils/scheduler.h` containing the API definitions for use by applications.

13.2 API Functions

Data Structures

- `tSchedulerTask`

Functions

- unsigned long `SchedulerElapsedTicksCalc` (unsigned long ulTickStart, unsigned long ulTickEnd)
- unsigned long `SchedulerElapsedTicksGet` (unsigned long ulTickCount)
- void `SchedulerInit` (unsigned long ulTicksPerSecond)
- void `SchedulerRun` (void)
- void `SchedulerSysTickIntHandler` (void)
- void `SchedulerTaskDisable` (unsigned long ulIndex)
- void `SchedulerTaskEnable` (unsigned long ulIndex, tBoolean bRunNow)

- unsigned long [SchedulerTickCountGet](#) (void)

Variables

- [tSchedulerTask](#) [g_psSchedulerTable](#)[]
- unsigned long [g_ulSchedulerNumTasks](#)

13.2.1 Data Structure Documentation

13.2.1.1 tSchedulerTask

Definition:

```
typedef struct
{
    void (*pfnFunction) (void *);
    void *pvParam;
    unsigned long ulFrequencyTicks;
    unsigned long ulLastCall;
    tBoolean bActive;
}
tSchedulerTask
```

Members:

pfnFunction A pointer to the function which is to be called periodically by the scheduler.

pvParam The parameter which is to be passed to this function when it is called.

ulFrequencyTicks The frequency the function is to be called expressed in terms of system ticks. If this value is 0, the function will be called on every call to SchedulerRun.

ulLastCall Tick count when this function was last called. This field is updated by the scheduler.

bActive A flag indicating whether or not this task is active. If true, the function will be called periodically. If false, the function is disabled and will not be called.

Description:

The structure defining a function which the scheduler will call periodically.

13.2.2 Function Documentation

13.2.2.1 SchedulerElapsedTicksCalc

Returns the number of ticks elapsed between two times.

Prototype:

```
unsigned long
SchedulerElapsedTicksCalc(unsigned long ulTickStart,
                          unsigned long ulTickEnd)
```

Parameters:

ulTickStart is the system tick count for the start of the period.

ulTickEnd is the system tick count for the end of the period.

Description:

This function may be called by a client to determine the number of ticks which have elapsed between provided starting and ending tick counts. The function takes into account wrapping cases where the end tick count is lower than the starting count assuming that the ending tick count always represents a later time than the starting count.

Returns:

The number of ticks elapsed between the provided start and end counts.

13.2.2.2 SchedulerElapsedTicksGet

Returns the number of ticks elapsed since the provided tick count.

Prototype:

```
unsigned long  
SchedulerElapsedTicksGet(unsigned long ulTickCount)
```

Parameters:

ulTickCount is the tick count from which to determine the elapsed time.

Description:

This function may be called by a client to determine how much time has passed since a particular tick count provided in the *ulTickCount* parameter. This function takes into account wrapping of the global tick counter and assumes that the provided tick count always represents a time in the past. The returned value will, of course, be wrong if the tick counter has wrapped more than once since the passed *ulTickCount*. As a result, please do not use this function if you are dealing with timeouts of 497 days or longer (assuming you use a 10mS tick period).

Returns:

The number of ticks elapsed since the provided tick count.

13.2.2.3 SchedulerInit

Initializes the task scheduler.

Prototype:

```
void  
SchedulerInit(unsigned long ulTicksPerSecond)
```

Parameters:

ulTicksPerSecond sets the basic frequency of the SysTick interrupt used by the scheduler to determine when to run the various task functions.

Description:

This function must be called during application startup to configure the SysTick timer. This is used by the scheduler module to determine when each of the functions provided in the `g_psSchedulerTable` array is called.

The caller is responsible for ensuring that [SchedulerSysTickIntHandler\(\)](#) has previously been installed in the SYSTICK vector in the vector table and must also ensure that interrupts are enabled at the CPU level.

Note that this call does not start the scheduler calling the configured functions. All function calls are made in the context of later calls to [SchedulerRun\(\)](#). This call merely configures the SysTick interrupt that is used by the scheduler to determine what the current system time is.

Returns:

None.

13.2.2.4 SchedulerRun

Instructs the scheduler to update its task table and make calls to functions needing called.

Prototype:

```
void  
SchedulerRun(void)
```

Description:

This function must be called periodically by the client to allow the scheduler to make calls to any configured task functions if it is their time to be called. The call must be made at least as frequently as the most frequent task configured in the `g_psSchedulerTable` array.

Although the scheduler makes use of the SysTick interrupt, all calls to functions configured in `g_psSchedulerTable` are made in the context of [SchedulerRun\(\)](#).

Returns:

None.

13.2.2.5 SchedulerSysTickIntHandler

Handles the SysTick interrupt on behalf of the scheduler module.

Prototype:

```
void  
SchedulerSysTickIntHandler(void)
```

Description:

Applications using the scheduler module must ensure that this function is hooked to the SysTick interrupt vector.

Returns:

None.

13.2.2.6 SchedulerTaskDisable

Disables a task and prevents the scheduler from calling it.

Prototype:

```
void  
SchedulerTaskDisable(unsigned long ulIndex)
```


Parameters:

ulIndex is the index of the task which is to be disabled in the global *g_psSchedulerTable* array.

Description:

This function marks one of the configured tasks as inactive and prevents [SchedulerRun\(\)](#) from calling it. The task may be reenabled by calling [SchedulerTaskEnable\(\)](#).

Returns:

None.

13.2.2.7 SchedulerTaskEnable

Enables a task and allows the scheduler to call it periodically.

Prototype:

```
void  
SchedulerTaskEnable(unsigned long ulIndex,  
                    tBoolean bRunNow)
```

Parameters:

ulIndex is the index of the task which is to be enabled in the global *g_psSchedulerTable* array.

bRunNow is **true** if the task is to be run on the next call to [SchedulerRun\(\)](#) or **false** if one whole period is to elapse before the task is run.

Description:

This function marks one of the configured tasks as enabled and causes [SchedulerRun\(\)](#) to call that task periodically. The caller may choose to have the enabled task run for the first time on the next call to [SchedulerRun\(\)](#) or to wait one full task period before making the first call.

Returns:

None.

13.2.2.8 SchedulerTickCountGet

Returns the current system time in ticks since power on.

Prototype:

```
unsigned long  
SchedulerTickCountGet(void)
```

Description:

This function may be called by a client to retrieve the current system time. The value returned is a count of ticks elapsed since the system last booted.

Returns:

Tick count since last boot.

13.2.3 Variable Documentation

13.2.3.1 g_psSchedulerTable

Definition:

```
tSchedulerTask g_psSchedulerTable[ ]
```

Description:

This global table must be populated by the client and contains information on each function that the scheduler is to call.

13.2.3.2 g_ulSchedulerNumTasks

Definition:

```
unsigned long g_ulSchedulerNumTasks
```

Description:

This global variable must be exported by the client. It must contain the number of entries in the g_psSchedulerTable array.

13.3 Programming Example

The following example shows how to use the task scheduler module. This code illustrates a simple application which toggles two LEDs at different rates and updates a scrolling text string on the display.

```
//*****  
//  
// Definition of the system tick rate. This results in a tick period of 10mS.  
//  
//*****  
#define TICKS_PER_SECOND 100  
  
//*****  
//  
// Prototypes of functions which will be called by the scheduler.  
//  
//*****  
static void ScrollTextBanner(void *pvParam);  
static void ToggleLED(void *pvParam);  
  
//*****  
//  
// This table defines all the tasks that the scheduler is to run, the periods  
// between calls to those tasks, and the parameter to pass to the task.  
//  
//*****  
tSchedulerTask g_psSchedulerTable[] =  
{  
    //  
    // Scroll the text banner 1 character to the left. This function is called  
    // every 20 ticks (5 times per second).  
    //  
    { ScrollTextBanner, (void *)0, 20, 0, true},  
}
```

```

//
// Toggle LED number 0 every 50 ticks (twice per second).
//
{ ToggleLED, (void *)0, 50, 0, true},

//
// Toggle LED number 1 every 100 ticks (once per second).
//
{ ToggleLED, (void *)1, 100, 0, true},
};

//*****
//
// The number of entries in the global scheduler task table.
//
//*****
unsigned long g_ulSchedulerNumTasks = (sizeof(g_psSchedulerTable) /
                                       sizeof(tSchedulerTask));

//*****
//
// This function is called by the scheduler to toggle one of two LEDs
//
//*****
static void
ToggleLED(void *pvParam)
{
    long lState;

    ulState = GPIOPinRead(LED_GPIO_BASE
                          (pvParam ? LED1_GPIO_PIN : LED0_GPIO_PIN));
    GPIOPinWrite(LED_GPIO_BASE, (pvParam ? LED1_GPIO_PIN : LED0_GPIO_PIN),
                 ~lState);
}

//*****
//
// This function is called by the scheduler to scroll a line of text on the
// display.
//
//*****
static void
ScrollTextBanner(void *pvParam)
{
    //
    // Left as an exercise for the reader.
    //
}

//*****
//
// Application main task.
//
//*****
int
main(void)
{
    //
    // Initialize system clock and any peripherals that are to be used.
    //
    SystemInit();

    //
    // Initialize the task scheduler and configure the SysTick to interrupt
    // 100 times per second.

```

```
//
SchedulerInit(TICKS_PER_SECOND);

//
// Turn on interrupts at the CPU level.
//
IntMasterEnable();

//
// Drop into the main loop.
//
while(1)
{
    //
    // Tell the scheduler to call any periodic tasks that are due to be
    // called.
    //
    SchedulerRun();
}
}
```

14 Sine Calculation Module

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14.1 Introduction

This module provides a fixed-point sine function. The input angle is a 0.32 fixed-point value that is the percentage of 360 degrees. This has two benefits; the sine function does not have to handle angles that are outside the range of 0 degrees through 360 degrees (in fact, 360 degrees can not be represented since it would wrap to 0 degrees), and the computation of the angle can be simplified since it does not have to deal with wrapping at values that are not natural for binary arithmetic (such as 360 degrees or 2π radians).

A sine table is used to find the approximate value for a given input angle. The table contains 128 entries that range from 0 degrees through 90 degrees and the symmetry of the sine function is used to determine the value between 90 degrees and 360 degrees. The maximum error caused by this table-based approach is 0.00618, which occurs near 0 and 180 degrees.

This module is contained in `utils/sine.c`, with `utils/sine.h` containing the API definitions for use by applications.

14.2 API Functions

Defines

- `cosine`(ulAngle)

Functions

- long `sine` (unsigned long ulAngle)

14.2.1 Define Documentation

14.2.1.1 cosine

Computes an approximation of the cosine of the input angle.

Definition:

```
#define cosine(ulAngle)
```

Parameters:

ulAngle is an angle expressed as a 0.32 fixed-point value that is the percentage of the way around a circle.

Description:

This function computes the cosine for the given input angle. The angle is specified in 0.32 fixed point format, and is therefore always between 0 and 360 degrees, inclusive of 0 and exclusive of 360.

Returns:

Returns the cosine of the angle, in 16.16 fixed point format.

14.2.2 Function Documentation

14.2.2.1 sine

Computes an approximation of the sine of the input angle.

Prototype:

```
long  
sine(unsigned long ulAngle)
```

Parameters:

ulAngle is an angle expressed as a 0.32 fixed-point value that is the percentage of the way around a circle.

Description:

This function computes the sine for the given input angle. The angle is specified in 0.32 fixed point format, and is therefore always between 0 and 360 degrees, inclusive of 0 and exclusive of 360.

Returns:

Returns the sine of the angle, in 16.16 fixed point format.

14.3 Programming Example

The following example shows how to produce a sine wave with 7 degrees between successive values.

```
unsigned long ulValue;  
  
//  
// Produce a sine wave with each step being 7 degrees advanced from the  
// previous.  
//  
for(ulValue = 0; ; ulValue += 0x04FA4FA4)  
{  
    //  
    // Compute the sine at this angle and do something with the result.  
    //  
    sine(ulValue);  
}
```

15 Software I2C Module

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15.1 Introduction

The software I2C module uses a timer and two GPIO pins to create a slow-speed software I2C peripheral. Multiple software I2C modules can be in use simultaneously, limited only by the availability of resources (RAM for the per-instance data structure, pins for the interface, timers if unique clock rates are required, and processor cycles to execute the code). The software I2C module supports master mode only; multi-master support is not provided. A callback mechanism is used to simulate the interrupts that would be provided by a hardware I2C module.

The API for the software I2C module has been constructed to be as close as possible to the API provided in the Stellaris Peripheral Driver Library for the hardware I2C module. The two notable differences are the function prefix being “SoftI2C” instead of “I2CMaster”, and the first argument of each API is a pointer to the [tSoftI2C](#) data structure instead of the base address of the hardware module.

Timing for the software I2C module is provided by the application. The [SoftI2CTimerTick\(\)](#) function must be called on a periodic basis to provide the timing for the software I2C module. The timer tick function must be called at four times the desired I2C clock rate; for example, to operate the software I2C interface at 10 KHz, the tick function must be called at a 40 KHz rate. By having the application providing the timing, the timer resource can be flexible and multiple software I2C modules can be driven from a single timer resource. Alternatively, if the software I2C module is only needed for brief periods of time and processor usage is not a concern, the timer tick function can simply be called in a loop until the entire I2C transaction has completed (maximizing both I2C clock speed and processor usage, but not requiring a timer).

The software I2C module requires two GPIO pins; one for SCL and one for SDA. The per-instance data structure is approximately 20 bytes in length (the actual length depends on how the structure is packed by the compiler).

As a point of reference, the following are some rough measurements of the processor usage of the software I2C module at various I2C clock speeds with the processor running at 50 MHz. Actual processor usage may vary, depending on how the application uses the software I2C module, processor clock speed, interrupt priority, and compiler.

I2C Clock	% Of Processor	Million Cycles Per Second
5 KHz	4.53	2.26
10 KHz	9.05	4.52
15 KHz	13.53	6.76
20 KHz	18.03	9.01
25 KHz	22.51	11.25
30 KHz	27.05	13.52
35 KHz	31.52	15.76
40 KHz	36.06	18.03
45 KHz	40.54	20.27
50 KHz	44.96	22.48

This module is contained in `utils/softi2c.c`, with `utils/softi2c.h` containing the API definitions for use by applications.

15.2 API Functions

Data Structures

- [tSoftI2C](#)

Functions

- `tBoolean` [SoftI2CBusy](#) ([tSoftI2C](#) *pl2C)
- `void` [SoftI2CCallbackSet](#) ([tSoftI2C](#) *pl2C, `void (*pfnCallback)(void)`)
- `void` [SoftI2CControl](#) ([tSoftI2C](#) *pl2C, `unsigned long ulCmd`)
- `unsigned long` [SoftI2CDataGet](#) ([tSoftI2C](#) *pl2C)
- `void` [SoftI2CDataPut](#) ([tSoftI2C](#) *pl2C, `unsigned char ucData`)
- `unsigned long` [SoftI2CErr](#) ([tSoftI2C](#) *pl2C)
- `void` [SoftI2CInit](#) ([tSoftI2C](#) *pl2C)
- `void` [SoftI2CIntClear](#) ([tSoftI2C](#) *pl2C)
- `void` [SoftI2CIntDisable](#) ([tSoftI2C](#) *pl2C)
- `void` [SoftI2CIntEnable](#) ([tSoftI2C](#) *pl2C)
- `tBoolean` [SoftI2CIntStatus](#) ([tSoftI2C](#) *pl2C, `tBoolean bMasked`)
- `void` [SoftI2CSCLGPIOSet](#) ([tSoftI2C](#) *pl2C, `unsigned long ulBase`, `unsigned char ucPin`)
- `void` [SoftI2CSDAGPIOSet](#) ([tSoftI2C](#) *pl2C, `unsigned long ulBase`, `unsigned char ucPin`)
- `void` [SoftI2CSlaveAddrSet](#) ([tSoftI2C](#) *pl2C, `unsigned char ucSlaveAddr`, `tBoolean bReceive`)
- `void` [SoftI2CTimerTick](#) ([tSoftI2C](#) *pl2C)

15.2.1 Data Structure Documentation

15.2.1.1 tSoftI2C

Definition:

```
typedef struct
{
    void (*pfnIntCallback) (void);
    unsigned long ulSCLGPIO;
    unsigned long ulSDAGPIO;
    unsigned char ucFlags;
    unsigned char ucSlaveAddr;
    unsigned char ucData;
    unsigned char ucState;
    unsigned char ucCurrentBit;
    unsigned char ucIntMask;
    unsigned char ucIntStatus;
}
tSoftI2C
```


Members:

pfnIntCallback The address of the callback function that is called to simulate the interrupts that would be produced by a hardware I2C implementation. This address can be set via a direct structure access or using the `SoftI2CCallbackSet` function.

uiSCLGPIO The address of the GPIO pin to be used for the SCL signal. This member can be set via a direct structure access or using the `SoftI2CSCLGPIOSet` function.

uiSDAGPIO The address of the GPIO pin to be used for the SDA signal. This member can be set via a direct structure access or using the `SoftI2CSDAGPIOSet` function.

ucFlags The flags that control the operation of the SoftI2C module. This member should not be accessed or modified by the application.

ucSlaveAddr The slave address that is currently being accessed. This member should not be accessed or modified by the application.

ucData The data that is currently being transmitted or received. This member should not be accessed or modified by the application.

ucState The current state of the SoftI2C state machine. This member should not be accessed or modified by the application.

ucCurrentBit The number of bits that have been transmitted and received in the current frame. This member should not be accessed or modified by the application.

ucIntMask The set of virtual interrupts that should be sent to the callback function. This member should not be accessed or modified by the application.

ucIntStatus The set of virtual interrupts that are currently asserted. This member should not be accessed or modified by the application.

Description:

This structure contains the state of a single instance of a SoftI2C module.

15.2.2 Function Documentation

15.2.2.1 SoftI2CBusy

Indicates whether or not the SoftI2C module is busy.

Prototype:

```
tBoolean  
SoftI2CBusy(tSoftI2C *pI2C)
```

Parameters:

pI2C specifies the SoftI2C data structure.

Description:

This function returns an indication of whether or not the SoftI2C module is busy transmitting or receiving data.

Returns:

Returns **true** if the SoftI2C module is busy; otherwise, returns **false**.

15.2.2.2 SoftI2CCallbackSet

Sets the callback used by the SoftI2C module.

Prototype:

```
void  
SoftI2CCallbackSet(tSoftI2C *pI2C,  
                  void (*pfnCallback)(void))
```

Parameters:

pI2C specifies the SoftI2C data structure.

pfnCallback is a pointer to the callback function.

Description:

This function sets the address of the callback function that is called when there is an “interrupt” produced by the SoftI2C module.

Returns:

None.

15.2.2.3 SoftI2CControl

Controls the state of the SoftI2C module.

Prototype:

```
void  
SoftI2CControl(tSoftI2C *pI2C,  
              unsigned long ulCmd)
```

Parameters:

pI2C specifies the SoftI2C data structure.

ulCmd command to be issued to the SoftI2C module.

Description:

This function is used to control the state of the SoftI2C module send and receive operations. The *ucCmd* parameter can be one of the following values:

- SOFTI2C_CMD_SINGLE_SEND
- SOFTI2C_CMD_SINGLE_RECEIVE
- SOFTI2C_CMD_BURST_SEND_START
- SOFTI2C_CMD_BURST_SEND_CONT
- SOFTI2C_CMD_BURST_SEND_FINISH
- SOFTI2C_CMD_BURST_SEND_ERROR_STOP
- SOFTI2C_CMD_BURST_RECEIVE_START
- SOFTI2C_CMD_BURST_RECEIVE_CONT
- SOFTI2C_CMD_BURST_RECEIVE_FINISH
- SOFTI2C_CMD_BURST_RECEIVE_ERROR_STOP

Returns:

None.

15.2.2.4 SoftI2CDataGet

Receives a byte that has been sent to the SoftI2C module.

Prototype:

```
unsigned long  
SoftI2CDataGet (tSoftI2C *pI2C)
```

Parameters:

pI2C specifies the SoftI2C data structure.

Description:

This function reads a byte of data from the SoftI2C module that was received as a result of an appropriate call to [SoftI2CControl\(\)](#).

Returns:

Returns the byte received by the SoftI2C module, cast as an unsigned long.

15.2.2.5 SoftI2CDataPut

Transmits a byte from the SoftI2C module.

Prototype:

```
void  
SoftI2CDataPut (tSoftI2C *pI2C,  
               unsigned char ucData)
```

Parameters:

pI2C specifies the SoftI2C data structure.

ucData data to be transmitted from the SoftI2C module.

Description:

This function places the supplied data into SoftI2C module in preparation for being transmitted via an appropriate call to [SoftI2CControl\(\)](#).

Returns:

None.

15.2.2.6 SoftI2CErr

Gets the error status of the SoftI2C module.

Prototype:

```
unsigned long  
SoftI2CErr (tSoftI2C *pI2C)
```

Parameters:

pI2C specifies the SoftI2C data structure.

Description:

This function is used to obtain the error status of the SoftI2C module send and receive operations.

Returns:

Returns the error status, as one of **SOFTI2C_ERR_NONE**, **SOFTI2C_ERR_ADDR_ACK**, or **SOFTI2C_ERR_DATA_ACK**.

15.2.2.7 SoftI2CInit

Initializes the SoftI2C module.

Prototype:

```
void  
SoftI2CInit (tSoftI2C *pI2C)
```

Parameters:

pI2C specifies the SoftI2C data structure.

Description:

This function initializes operation of the SoftI2C module. After successful initialization of the SoftI2C module, the software I2C bus is in the idle state.

Returns:

None.

15.2.2.8 SoftI2CIntClear

Clears the SoftI2C “interrupt”.

Prototype:

```
void  
SoftI2CIntClear (tSoftI2C *pI2C)
```

Parameters:

pI2C specifies the SoftI2C data structure.

Description:

The SoftI2C “interrupt” source is cleared, so that it no longer asserts. This function must be called in the “interrupt” handler to keep it from being called again immediately on exit.

Returns:

None.

15.2.2.9 SoftI2CIntDisable

Disables the SoftI2C “interrupt”.

Prototype:

```
void  
SoftI2CIntDisable (tSoftI2C *pI2C)
```

Parameters:

pI2C specifies the SoftI2C data structure.

Description:

Disables the SoftI2C “interrupt” source.

Returns:

None.

15.2.2.10 SoftI2CIntEnable

Enables the SoftI2C “interrupt”.

Prototype:

```
void  
SoftI2CIntEnable (tSoftI2C *pI2C)
```

Parameters:

pI2C specifies the SoftI2C data structure.

Description:

Enables the SoftI2C “interrupt” source.

Returns:

None.

15.2.2.11 SoftI2CIntStatus

Gets the current SoftI2C “interrupt” status.

Prototype:

```
tBoolean  
SoftI2CIntStatus (tSoftI2C *pI2C,  
                  tBoolean bMasked)
```

Parameters:

pI2C specifies the SoftI2C data structure.

bMasked is **false** if the raw “interrupt” status is requested and **true** if the masked “interrupt” status is requested.

Description:

This returns the “interrupt” status for the SoftI2C module. Either the raw “interrupt” status or the status of “interrupts” that are allowed to reflect to the processor can be returned.

Returns:

The current interrupt status, returned as **true** if active or **false** if not active.

15.2.2.12 SoftI2CSCLogPIOSet

Sets the GPIO pin to be used as the SoftI2C SCL signal.

Prototype:

```
void  
SoftI2CSCLGPIOSet (tSoftI2C *pI2C,  
                   unsigned long ulBase,  
                   unsigned char ucPin)
```

Parameters:

pI2C specifies the SoftI2C data structure.

ulBase is the base address of the GPIO module.

ucPin is the bit-packed representation of the pin to use.

Description:

This function sets the GPIO pin that is used for the SoftI2C SCL signal.

The pin is specified using a bit-packed byte, where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

15.2.2.13 SoftI2CSDAGPIOSet

Sets the GPIO pin to be used as the SoftI2C SDA signal.

Prototype:

```
void  
SoftI2CSDAGPIOSet (tSoftI2C *pI2C,  
                   unsigned long ulBase,  
                   unsigned char ucPin)
```

Parameters:

pI2C specifies the SoftI2C data structure.

ulBase is the base address of the GPIO module.

ucPin is the bit-packed representation of the pin to use.

Description:

This function sets the GPIO pin that is used for the SoftI2C SDA signal.

The pin is specified using a bit-packed byte, where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

15.2.2.14 SoftI2CSlaveAddrSet

Sets the address that the SoftI2C module places on the bus.

Prototype:

```
void  
SoftI2CSlaveAddrSet (tSoftI2C *pI2C,
```

```
unsigned char ucSlaveAddr,  
tBoolean bReceive)
```

Parameters:

pI2C specifies the SoftI2C data structure.

ucSlaveAddr 7-bit slave address

bReceive flag indicating the type of communication with the slave.

Description:

This function sets the address that the SoftI2C module places on the bus when initiating a transaction. When the *bReceive* parameter is set to **true**, the address indicates that the SoftI2C module is initiating a read from the slave; otherwise the address indicates that the SoftI2C module is initiating a write to the slave.

Returns:

None.

15.2.2.15 SoftI2CTimerTick

Performs the periodic update of the SoftI2C module.

Prototype:

```
void  
SoftI2CTimerTick(tSoftI2C *pI2C)
```

Parameters:

pI2C specifies the SoftI2C data structure.

Description:

This function performs the periodic, time-based updates to the SoftI2C module. The transmission and reception of data over the SoftI2C link is performed by the state machine in this function.

This function must be called at four times the desired SoftI2C clock rate. For example, to run the SoftI2C clock at 10 KHz, this function must be called at a 40 KHz rate.

Returns:

None.

15.3 Programming Example

The following example shows how to configure the software I2C module and transmit some data to an external peripheral. This example uses Timer 0 as the timing source.

```
//  
// The instance data for the software I2C.  
//  
tSoftI2C g_sI2C;  
  
//  
// The timer tick function.
```

```
//
void
Timer0AIntHandler(void)
{
    //
    // Clear the timer interrupt.
    //
    TimerIntClear(TIMER0_BASE, TIMER_TIMA_TIMEOUT);

    //
    // Call the software I2C timer tick function.
    //
    SoftI2CTimerTick(&g_sI2C);
}

//
// The callback function for the software I2C. This function is equivalent
// to the interrupt handler for a hardware I2C.
//
void
I2CCallback(void)
{
    //
    // Clear the interrupt.
    //
    SoftI2CIntClear(&g_sI2C);

    //
    // Handle the interrupt.
    //
    ...
}

//
// Setup the software I2C and send some data.
//
void
TestSoftI2C(void)
{
    //
    // Clear the software I2C instance data.
    //
    memset(&g_sI2C, 0, sizeof(g_sI2C));

    //
    // Set the callback function used for this software I2C.
    //
    SoftI2CCallbackSet(&g_sI2C, I2CCallback);

    //
    // Configure the pins used for the software I2C. This example uses
    // pins PD0 and PE1.
    //
    SoftI2CSCLGPIOSet(&g_sI2C, GPIO_PORTD_BASE, GPIO_PIN_0);
    SoftI2CSDAGPIOSet(&g_sI2C, GPIO_PORTE_BASE, GPIO_PIN_1);

    //
    // Enable the GPIO modules that contains the GPIO pins to be used by
    // the software I2C.
    //
    SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOD);
    SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOE);

    //
    // Initialize the software I2C module.
    //
}
```



```

SoftI2CInit(&g_sI2C);

//
// Configure the timer used to generate the timing for the software
// I2C. The interface will be run at 10 KHz, requiring a timer tick
// at 40 KHz.
//
SysCtlPeripheralEnable(SYSCTL_PERIPH_TIMER0);
TimerConfigure(TIMER0_BASE, TIMER_CFG_32_BIT_PER);
TimerLoadSet(TIMER0_BASE, TIMER_A, SysCtlClockGet() / 40000);
TimerIntEnable(TIMER0_BASE, TIMER_TIMA_TIMEOUT);
IntEnable(INT_TIMER0A);
TimerEnable(TIMER0_BASE, TIMER_A);

//
// Enable the software I2C interrupt.
//
SoftI2CIntEnable(&g_sI2C);

//
// Send a single byte to the slave device.
//
SoftI2CSlaveAddrSet(&g_sI2C, 0x55, 0);
SoftI2CDataPut(&g_sI2C, 0xaa);
SoftI2CControl(&g_sI2C, SOFTI2C_CMD_SINGLE_SEND);

//
// Wait until the software I2C is idle. The completion interrupt will
// be sent to the callback function prior to exiting this loop.
//
while(SoftI2CBusy(&g_sI2C))
{
}
}

```

As a comparison, the following is the equivalent code using the hardware I2C module and the Stellaris Peripheral Driver Library.

```

//
// The interrupt handler for the hardware I2C.
//
void
I2C0IntHandler(void)
{
    //
    // Clear the asserted interrupt sources.
    //
    I2CMasterIntClear(I2C0_MASTER_BASE);

    //
    // Handle the interrupt.
    //
    ...
}

//
// Setup the hardware I2C and send some data.
//
void
TestI2C(void)
{
    //
    // Enable the GPIO module that contains the GPIO pins to be used by
    // the I2C, as well as the I2C module.
    //

```

```
SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOB);
SysCtlPeripheralEnable(SYSCTL_PERIPH_I2C0);

//
// Configure the GPIO pins for use by the I2C module.
//
GPIOPinTypeI2C(GPIO_PORTB_BASE, GPIO_PIN_2 | GPIO_PIN_3);

//
// Initialize the hardware I2C module.
//
I2CMasterInitExpClk(I2C0_MASTER_BASE, SysCtlClockGet(), false);

//
// Enable the hardware I2C.
//
I2CMasterEnable(I2C0_MASTER_BASE);

//
// Enable the interrupt in the hardware I2C.
//
I2CMasterIntEnable(I2C0_MASTER_BASE);
IntEnable(INT_I2C0);

//
// Write some data into the hardware I2C transmit FIFO.
//
I2CMasterSlaveAddrSet(I2C0_MASTER_BASE, 0x55, 0);
I2CMasterDataPut(I2C0_MASTER_BASE, 0xaa);
I2CMasterControl(I2C0_MASTER_BASE, I2C_MASTER_CMD_SINGLE_SEND);

//
// Wait until the hardware I2C is idle. The interrupt will be sent to
// the interrupt handler prior to exiting this loop.
//
while(I2CBusy(I2C0_MASTER_BASE))
{
}
```

16 Software SSI Module

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16.1 Introduction

The software SSI module uses a timer and a few GPIO pins to create a slow-speed software SSI peripheral. Multiple software SSI modules can be in use simultaneously, limited only by the availability of resources (RAM for the per-instance data structure, pins for the interface, timers if unique clock rates are required, and processor cycles to execute the code). The software SSI module supports the Motorola® SPI™ formats with 4 to 16 data bits. A callback mechanism is used to simulate the interrupts that would be provided by a hardware SSI module.

The API for the software SSI module has been constructed to be as close as possible to the API provided in the Stellaris Peripheral Driver Library for the hardware SSI module. The two notable difference are the function prefix being “SoftSSI” instead of “SSI”, and the first argument of each API is a pointer to the [tSoftSSI](#) data structure instead of the base address of the hardware module.

Timing for the software SSI module is provided by the application. The [SoftSSITimerTick\(\)](#) function must be called on a periodic basis to provide the timing for the software SSI module. The timer tick function must be called at twice the desired SSI clock rate; for example, to operate the software SSI interface at 10 KHz, the tick function must be called at a 20 KHz rate. By having the application providing the timing, the timer resource to be used is flexible and multiple software SSI modules can be driven from a single timer resource. Alternatively, if the software SSI module is only needed for brief periods of time and processor usage is not a concern, the timer tick function can simply be called in a loop until the entire SSI transaction has completed (maximizing both SSI clock speed and processor usage, but not requiring a timer).

The software SSI module requires a few as two and as many as four GPIO pins. The following table shows the possible pin usages for the software SSI module:

Fss	Clk	Tx	Rx	Pins	Description
	yes	yes		2	transmit only
yes	yes	yes		3	
	yes		yes	2	receive only
yes	yes		yes	3	
	yes	yes	yes	3	transmit and receive
yes	yes	yes	yes	4	

For the cases where Fss is not used, it is up to the application to control that signal (either via a separately-controlled GPIO, or by being tied to ground in the hardware).

The per-instance data structure is approximately 52 bytes in length (the actual length will depend upon how the structure is packed by the compiler in use).

As a point of reference, the following are some rough measurements of the processor usage of the software SSI module at various SSI clock speeds with the processor running at 50 MHz. Actual processor usage may vary, depending upon how the application uses the software SSI module, processor clock speed, interrupt priority, and compiler in use.

SSI Clock	% Of Processor	Million Cycles Per Second
10 KHz	5.26	2.63
20 KHz	10.48	5.24
30 KHz	15.68	7.84
40 KHz	20.90	10.45
50 KHz	26.10	13.05
60 KHz	31.38	15.69
70 KHz	36.54	18.27
80 KHz	41.79	20.89
90 KHz	47.06	23.53
100 KHz	52.17	26.08

This module is contained in `utils/softssi.c`, with `utils/softssi.h` containing the API definitions for use by applications.

16.2 API Functions

Data Structures

- [tSoftSSI](#)

Functions

- `tBoolean` [SoftSSIBusy](#) (`tSoftSSI *pSSI`)
- `void` [SoftSSICallbackSet](#) (`tSoftSSI *pSSI`, `void (*pfnCallback)(void)`)
- `void` [SoftSSIClkGPIOSet](#) (`tSoftSSI *pSSI`, `unsigned long ulBase`, `unsigned char ucPin`)
- `void` [SoftSSIConfigSet](#) (`tSoftSSI *pSSI`, `unsigned char ucProtocol`, `unsigned char ucBits`)
- `tBoolean` [SoftSSIDataAvail](#) (`tSoftSSI *pSSI`)
- `void` [SoftSSIDataGet](#) (`tSoftSSI *pSSI`, `unsigned long *pulData`)
- `long` [SoftSSIDataGetNonBlocking](#) (`tSoftSSI *pSSI`, `unsigned long *pulData`)
- `void` [SoftSSIDataPut](#) (`tSoftSSI *pSSI`, `unsigned long ulData`)
- `long` [SoftSSIDataPutNonBlocking](#) (`tSoftSSI *pSSI`, `unsigned long ulData`)
- `void` [SoftSSIDisable](#) (`tSoftSSI *pSSI`)
- `void` [SoftSSIEnable](#) (`tSoftSSI *pSSI`)
- `void` [SoftSSIFssGPIOSet](#) (`tSoftSSI *pSSI`, `unsigned long ulBase`, `unsigned char ucPin`)
- `void` [SoftSSIIntClear](#) (`tSoftSSI *pSSI`, `unsigned long ulIntFlags`)
- `void` [SoftSSIIntDisable](#) (`tSoftSSI *pSSI`, `unsigned long ulIntFlags`)
- `void` [SoftSSIIntEnable](#) (`tSoftSSI *pSSI`, `unsigned long ulIntFlags`)
- `unsigned long` [SoftSSIIntStatus](#) (`tSoftSSI *pSSI`, `tBoolean bMasked`)
- `void` [SoftSSIRxBufferSet](#) (`tSoftSSI *pSSI`, `unsigned short *pusRxBuffer`, `unsigned short usLen`)
- `void` [SoftSSIRxGPIOSet](#) (`tSoftSSI *pSSI`, `unsigned long ulBase`, `unsigned char ucPin`)
- `tBoolean` [SoftSSISpaceAvail](#) (`tSoftSSI *pSSI`)
- `void` [SoftSSITimerTick](#) (`tSoftSSI *pSSI`)
- `void` [SoftSSITxBufferSet](#) (`tSoftSSI *pSSI`, `unsigned short *pusTxBuffer`, `unsigned short usLen`)
- `void` [SoftSSITxGPIOSet](#) (`tSoftSSI *pSSI`, `unsigned long ulBase`, `unsigned char ucPin`)

16.2.1 Data Structure Documentation

16.2.1.1 tSoftSSI

Definition:

```
typedef struct
{
    void (*pfnIntCallback)(void);
    unsigned long ulFssGPIO;
    unsigned long ulClkGPIO;
    unsigned long ulTxGPIO;
    unsigned long ulRxGPIO;
    unsigned short *pusTxBuffer;
    unsigned short *pusRxBuffer;
    unsigned short usTxBufferLen;
    unsigned short usTxBufferRead;
    unsigned short usTxBufferWrite;
    unsigned short usRxBufferLen;
    unsigned short usRxBufferRead;
    unsigned short usRxBufferWrite;
    unsigned short usTxData;
    unsigned short usRxData;
    unsigned char ucFlags;
    unsigned char ucBits;
    unsigned char ucState;
    unsigned char ucCurrentBit;
    unsigned char ucIntMask;
    unsigned char ucIntStatus;
    unsigned char ucIdleCount;
}
tSoftSSI
```

Members:

pfnIntCallback The address of the callback function that is called to simulate the interrupts that would be produced by a hardware SSI implementation. This address can be set via a direct structure access or using the SoftSSICallbackSet function.

ulFssGPIO The address of the GPIO pin to be used for the Fss signal. If this member is zero, the Fss signal is not generated. This member can be set via a direct structure access or using the SoftSSIFssGPIOSet function.

ulClkGPIO The address of the GPIO pin to be used for the Clk signal. This member can be set via a direct structure access or using the SoftSSIClkGPIOSet function.

ulTxGPIO The address of the GPIO pin to be used for the Tx signal. This member can be set via a direct structure access or using the SoftSSITxGPIOSet function.

ulRxGPIO The address of the GPIO pin to be used for the Rx signal. If this member is zero, the Rx signal is not read. This member can be set via a direct structure access or using the SoftSSIRxGPIOSet function.

pusTxBuffer The address of the data buffer used for the transmit FIFO. This member can be set via a direct structure access or using the SoftSSITxBufferSet function.

pusRxBuffer The address of the data buffer used for the receive FIFO. This member can be set via a direct structure access or using the SoftSSIRxBufferSet function.

usTxBufferLen The length of the transmit FIFO. This member can be set via a direct structure access or using the SoftSSITxBufferSet function.

- usTxBufferRead** The index into the transmit FIFO of the next word to be transmitted. This member should be initialized to zero, but should not be accessed or modified by the application.
- usTxBufferWrite** The index into the transmit FIFO of the next location to store data into the FIFO. This member should be initialized to zero, but should not be accessed or modified by the application.
- usRxBufferLen** The length of the receive FIFO. This member can be set via a direct structure access or using the `SoftSSIRxBufferSet` function.
- usRxBufferRead** The index into the receive FIFO of the next word to be read from the FIFO. This member should be initialized to zero, but should not be accessed or modified by the application.
- usRxBufferWrite** The index into the receive FIFO of the location to store the next word received. This member should be initialized to zero, but should not be accessed or modified by the application.
- usTxData** The word that is currently being transmitted. This member should not be accessed or modified by the application.
- usRxData** The word that is currently being received. This member should not be accessed or modified by the application.
- ucFlags** The flags that control the operation of the SoftSSI module. This member should not be accessed or modified by the application.
- ucBits** The number of data bits in each SoftSSI frame, which also specifies the width of each data item in the transmit and receive FIFOs. This member can be set via a direct structure access or using the `SoftSSIConfigSet` function.
- ucState** The current state of the SoftSSI state machine. This member should not be accessed or modified by the application.
- ucCurrentBit** The number of bits that have been transmitted and received in the current frame. This member should not be accessed or modified by the application.
- ucIntMask** The set of virtual interrupts that should be sent to the callback function. This member should not be accessed or modified by the application.
- ucIntStatus** The set of virtual interrupts that are currently asserted. This member should not be accessed or modified by the application.
- ucIdleCount** The number of tick counts that the SoftSSI module has been idle with data stored in the receive FIFO, which is used to generate the receive timeout interrupt. This member should not be accessed or modified by the application.

Description:

This structure contains the state of a single instance of a SoftSSI module.

16.2.2 Function Documentation

16.2.2.1 SoftSSIBusy

Determines whether the SoftSSI transmitter is busy or not.

Prototype:

```
tBoolean  
SoftSSIBusy(tSoftSSI *pSSI)
```

Parameters:

pSSI specifies the SoftSSI data structure.

Description:

Allows the caller to determine whether all transmitted bytes have cleared the transmitter. If **false** is returned, then the transmit FIFO is empty and all bits of the last transmitted word have left the shift register.

Returns:

Returns **true** if the SoftSSI is transmitting or **false** if all transmissions are complete.

16.2.2.2 SoftSSICallbackSet

Sets the callback used by the SoftSSI module.

Prototype:

```
void  
SoftSSICallbackSet (tSoftSSI *pSSI,  
                   void (*pfnCallback) (void))
```

Parameters:

pSSI specifies the SoftSSI data structure.

pfnCallback is a pointer to the callback function.

Description:

This function sets the address of the callback function that is called when there is an “interrupt” produced by the SoftSSI module.

Returns:

None.

16.2.2.3 SoftSSIClkGPIOSet

Sets the GPIO pin to be used as the SoftSSI Clk signal.

Prototype:

```
void  
SoftSSIClkGPIOSet (tSoftSSI *pSSI,  
                  unsigned long ulBase,  
                  unsigned char ucPin)
```

Parameters:

pSSI specifies the SoftSSI data structure.

ulBase is the base address of the GPIO module.

ucPin is the bit-packed representation of the pin to use.

Description:

This function sets the GPIO pin that is used for the SoftSSI Clk signal.

The pin is specified using a bit-packed byte, where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

16.2.2.4 SoftSSIConfigSet

Sets the configuration of a SoftSSI module.

Prototype:

```
void  
SoftSSIConfigSet (tSoftSSI *pSSI,  
                  unsigned char ucProtocol,  
                  unsigned char ucBits)
```

Parameters:

pSSI specifies the SoftSSI data structure.

ucProtocol specifies the data transfer protocol.

ucBits specifies the number of bits transferred per frame.

Description:

This function configures the data format of a SoftSSI module. The *ucProtocol* parameter can be one of the following values: **SOFTSSI_FRF_MOTO_MODE_0**, **SOFTSSI_FRF_MOTO_MODE_1**, **SOFTSSI_FRF_MOTO_MODE_2**, or **SOFTSSI_FRF_MOTO_MODE_3**. These frame formats imply the following polarity and phase configurations:

Polarity	Phase	Mode
0	0	SOFTSSI_FRF_MOTO_MODE_0
0	1	SOFTSSI_FRF_MOTO_MODE_1
1	0	SOFTSSI_FRF_MOTO_MODE_2
1	1	SOFTSSI_FRF_MOTO_MODE_3

The *ucBits* parameter defines the width of the data transfers, and can be a value between 4 and 16, inclusive.

Returns:

None.

16.2.2.5 SoftSSIDataAvail

Determines if there is any data in the receive FIFO.

Prototype:

```
tBoolean  
SoftSSIDataAvail (tSoftSSI *pSSI)
```

Parameters:

pSSI specifies the SoftSSI data structure.

Description:

This function determines if there is any data available to be read from the receive FIFO.

Returns:

Returns **true** if there is data in the receive FIFO or **false** if there is no data in the receive FIFO.

16.2.2.6 SoftSSIDataGet

Gets a data element from the SoftSSI receive FIFO.

Prototype:

```
void  
SoftSSIDataGet (tSoftSSI *pSSI,  
                unsigned long *pulData)
```

Parameters:

pSSI specifies the SoftSSI data structure.

pulData is a pointer to a storage location for data that was received over the SoftSSI interface.

Description:

This function gets received data from the receive FIFO of the specified SoftSSI module and places that data into the location specified by the *pulData* parameter.

Note:

Only the lower N bits of the value written to *pulData* contain valid data, where N is the data width as configured by [SoftSSIConfigSet\(\)](#). For example, if the interface is configured for 8-bit data width, only the lower 8 bits of the value written to *pulData* contain valid data.

Returns:

None.

16.2.2.7 SoftSSIDataGetNonBlocking

Gets a data element from the SoftSSI receive FIFO.

Prototype:

```
long  
SoftSSIDataGetNonBlocking (tSoftSSI *pSSI,  
                            unsigned long *pulData)
```

Parameters:

pSSI specifies the SoftSSI data structure.

pulData is a pointer to a storage location for data that was received over the SoftSSI interface.

Description:

This function gets received data from the receive FIFO of the specified SoftSSI module and places that data into the location specified by the *ulData* parameter. If there is no data in the FIFO, then this function returns a zero.

Note:

Only the lower N bits of the value written to *pulData* contain valid data, where N is the data width as configured by [SoftSSIConfigSet\(\)](#). For example, if the interface is configured for 8-bit data width, only the lower 8 bits of the value written to *pulData* contain valid data.

Returns:

Returns the number of elements read from the SoftSSI receive FIFO.

16.2.2.8 SoftSSIDataPut

Puts a data element into the SoftSSI transmit FIFO.

Prototype:

```
void  
SoftSSIDataPut (tSoftSSI *pSSI,  
               unsigned long ulData)
```

Parameters:

pSSI specifies the SoftSSI data structure.

ulData is the data to be transmitted over the SoftSSI interface.

Description:

This function places the supplied data into the transmit FIFO of the specified SoftSSI module.

Note:

The upper 32 - N bits of the *ulData* are discarded, where N is the data width as configured by [SoftSSIConfigSet\(\)](#). For example, if the interface is configured for 8-bit data width, the upper 24 bits of *ulData* are discarded.

Returns:

None.

16.2.2.9 SoftSSIDataPutNonBlocking

Puts a data element into the SoftSSI transmit FIFO.

Prototype:

```
long  
SoftSSIDataPutNonBlocking (tSoftSSI *pSSI,  
                           unsigned long ulData)
```

Parameters:

pSSI specifies the SoftSSI data structure.

ulData is the data to be transmitted over the SoftSSI interface.

Description:

This function places the supplied data into the transmit FIFO of the specified SoftSSI module. If there is no space in the FIFO, then this function returns a zero.

Note:

The upper 32 - N bits of the *ulData* are discarded, where N is the data width as configured by [SoftSSIConfigSet\(\)](#). For example, if the interface is configured for 8-bit data width, the upper 24 bits of *ulData* are discarded.

Returns:

Returns the number of elements written to the SSI transmit FIFO.

16.2.2.10 SoftSSIDisable

Disables the SoftSSI module.

Prototype:

```
void  
SoftSSIDisable (tSoftSSI *pSSI)
```

Parameters:

pSSI specifies the SoftSSI data structure.

Description:

This function disables operation of the SoftSSI module. If a data transfer is in progress, it is finished before the module is fully disabled.

Returns:

None.

16.2.2.11 SoftSSIEnable

Enables the SoftSSI module.

Prototype:

```
void  
SoftSSIEnable (tSoftSSI *pSSI)
```

Parameters:

pSSI specifies the SoftSSI data structure.

Description:

This function enables operation of the SoftSSI module. The SoftSSI module must be configured before it is enabled.

Returns:

None.

16.2.2.12 SoftSSIFssGPIOSet

Sets the GPIO pin to be used as the SoftSSI Fss signal.

Prototype:

```
void  
SoftSSIFssGPIOSet (tSoftSSI *pSSI,  
                   unsigned long ulBase,  
                   unsigned char ucPin)
```

Parameters:

pSSI specifies the SoftSSI data structure.

ulBase is the base address of the GPIO module.

ucPin is the bit-packed representation of the pin to use.

Description:

This function sets the GPIO pin that is used for the SoftSSI Fss signal. If there is not a GPIO pin allocated for Fss, the SoftSSI module does not assert/deassert the Fss signal, leaving it to the application either to do manually or to not do at all if the slave device has Fss tied to ground.

The pin is specified using a bit-packed byte, where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

16.2.2.13 SoftSSIIntClear

Clears SoftSSI “interrupt” sources.

Prototype:

```
void  
SoftSSIIntClear(tSoftSSI *pSSI,  
               unsigned long ulIntFlags)
```

Parameters:

pSSI specifies the SoftSSI data structure.

ulIntFlags is a bit mask of the “interrupt” sources to be cleared.

Description:

The specified SoftSSI “interrupt” sources are cleared so that they no longer assert. This function must be called in the “interrupt” handler to keep the “interrupt” from being recognized again immediately upon exit. The *ulIntFlags* parameter is the logical OR of any of the **SOFTSSI_TXEOT**, **SOFTSSI_RXTO**, and **SOFTSSI_RXOR** values.

Returns:

None.

16.2.2.14 SoftSSIIntDisable

Disables individual SoftSSI “interrupt” sources.

Prototype:

```
void  
SoftSSIIntDisable(tSoftSSI *pSSI,  
                 unsigned long ulIntFlags)
```

Parameters:

pSSI specifies the SoftSSI data structure.

ulIntFlags is a bit mask of the “interrupt” sources to be disabled.

Description:

Disables the indicated SoftSSI “interrupt” sources. The *ulIntFlags* parameter can be any of the **SOFTSSI_TXEOT**, **SOFTSSI_TXFF**, **SOFTSSI_RXFF**, **SOFTSSI_RXTO**, or **SOFTSSI_RXOR** values.

Returns:

None.

16.2.2.15 SoftSSIIntEnable

Enables individual SoftSSI “interrupt” sources.

Prototype:

```
void  
SoftSSIIntEnable(tSoftSSI *pSSI,  
                unsigned long ulIntFlags)
```

Parameters:

pSSI specifies the SoftSSI data structure.

ulIntFlags is a bit mask of the “interrupt” sources to be enabled.

Description:

Enables the indicated SoftSSI “interrupt” sources. Only the sources that are enabled can be reflected to the callback function; disabled sources do not result in a callback. The *ulIntFlags* parameter can be any of the **SOFTSSI_TXEOT**, **SOFTSSI_TXFF**, **SOFTSSI_RXFF**, **SOFTSSI_RXTO**, or **SOFTSSI_RXOR** values.

Returns:

None.

16.2.2.16 SoftSSIIntStatus

Gets the current “interrupt” status.

Prototype:

```
unsigned long  
SoftSSIIntStatus(tSoftSSI *pSSI,  
                tBoolean bMasked)
```

Parameters:

pSSI specifies the SoftSSI data structure.

bMasked is **false** if the raw “interrupt” status is required or **true** if the masked “interrupt” status is required.

Description:

This function returns the “interrupt” status for the SoftSSI module. Either the raw “interrupt” status or the status of “interrupts” that are allowed to reflect to the callback can be returned.

Returns:

The current “interrupt” status, enumerated as a bit field of **SOFTSSI_TXEOT**, **SOFTSSI_TXFF**, **SOFTSSI_RXFF**, **SOFTSSI_RXTO**, and **SOFTSSI_RXOR**.

16.2.2.17 SoftSSIRxBufferSet

Sets the receive FIFO buffer for a SoftSSI module.

Prototype:

```
void  
SoftSSIRxBufferSet (tSoftSSI *pSSI,  
                    unsigned short *pusRxBuffer,  
                    unsigned short usLen)
```

Parameters:

pSSI specifies the SoftSSI data structure.

pusRxBuffer is the address of the receive FIFO buffer.

usLen is the size, in 16-bit half-words, of the receive FIFO buffer.

Description:

This function sets the address and size of the receive FIFO buffer and also resets the read and write pointers, marking the receive FIFO as empty. When the buffer pointer and length are configured as zero, all data received from the slave device is discarded. This capability is useful when there is no GPIO pin allocated for the Rx signal.

Returns:

None.

16.2.2.18 SoftSSIRxGPIOSet

Sets the GPIO pin to be used as the SoftSSI Rx signal.

Prototype:

```
void  
SoftSSIRxGPIOSet (tSoftSSI *pSSI,  
                  unsigned long ulBase,  
                  unsigned char ucPin)
```

Parameters:

pSSI specifies the SoftSSI data structure.

ulBase is the base address of the GPIO module.

ucPin is the bit-packed representation of the pin to use.

Description:

This function sets the GPIO pin that is used for the SoftSSI Rx signal. If there is not a GPIO pin allocated for Rx, the SoftSSI module does not read data from the slave device.

The pin is specified using a bit-packed byte, where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

16.2.2.19 SoftSSISpaceAvail

Determines if there is any space in the transmit FIFO.

Prototype:

```
tBoolean  
SoftSSISpaceAvail (tSoftSSI *pSSI)
```

Parameters:

pSSI specifies the SoftSSI data structure.

Description:

This function determines if there is space available in the transmit FIFO.

Returns:

Returns **true** if there is space available in the transmit FIFO or **false** if there is no space available in the transmit FIFO.

16.2.2.20 SoftSSITimerTick

Performs the periodic update of the SoftSSI module.

Prototype:

```
void  
SoftSSITimerTick (tSoftSSI *pSSI)
```

Parameters:

pSSI specifies the SoftSSI data structure.

Description:

This function performs the periodic, time-based updates to the SoftSSI module. The transmission and reception of data over the SoftSSI link is performed by the state machine in this function.

This function must be called at twice the desired SoftSSI clock rate. For example, to run the SoftSSI clock at 10 KHz, this function must be called at a 20 KHz rate.

Returns:

None.

16.2.2.21 SoftSSITxBufferSet

Sets the transmit FIFO buffer for a SoftSSI module.

Prototype:

```
void  
SoftSSITxBufferSet (tSoftSSI *pSSI,  
                    unsigned short *pusTxBuffer,  
                    unsigned short usLen)
```

Parameters:

pSSI specifies the SoftSSI data structure.

pusTxBuffer is the address of the transmit FIFO buffer.

usLen is the size, in 16-bit half-words, of the transmit FIFO buffer.

Description:

This function sets the address and size of the transmit FIFO buffer and also resets the read and write pointers, marking the transmit FIFO as empty.

Returns:

None.

16.2.2.22 SoftSSITxGPIOSet

Sets the GPIO pin to be used as the SoftSSI Tx signal.

Prototype:

```
void  
SoftSSITxGPIOSet (tSoftSSI *pSSI,  
                  unsigned long ulBase,  
                  unsigned char ucPin)
```

Parameters:

pSSI specifies the SoftSSI data structure.

ulBase is the base address of the GPIO module.

ucPin is the bit-packed representation of the pin to use.

Description:

This function sets the GPIO pin that is used for the SoftSSI Tx signal.

The pin is specified using a bit-packed byte, where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

16.3 Programming Example

The following example shows how to configure the software SSI module and transmit some data to an external peripheral. This example uses Timer 0 as the timing source.

```
//  
// The instance data for the software SSI.  
//  
tSoftSSI g_sSSI;  
  
//  
// The buffer used to hold the transmit data.  
//  
unsigned short g_pusTxBuffer[8];  
  
//  
// The timer tick function.  
//
```



```

void
Timer0AIntHandler(void)
{
    //
    // Clear the timer interrupt.
    //
    TimerIntClear(TIMER0_BASE, TIMER_TIMA_TIMEOUT);

    //
    // Call the software SSI timer tick function.
    //
    SoftSSITimerTick(&g_sSSI);
}

//
// The callback function for the software SSI. This function is equivalent
// to the interrupt handler for a hardware SSI.
//
void
SSICallback(void)
{
    unsigned long ulInts;

    //
    // Read the asserted interrupt sources.
    //
    ulInts = SoftSSIIntStatus(&g_sSSI, true);

    //
    // Clear the asserted interrupt sources.
    //
    SoftSSIIntClear(&g_sSSI, ulInts);

    //
    // Handle the asserted interrupts.
    //
    ...
}

//
// Setup the software SSI and send some data.
//
void
TestSoftSSI(void)
{
    //
    // Clear the software SSI instance data.
    //
    memset(&g_sSSI, 0, sizeof(g_sSSI));

    //
    // Set the callback function used for this software SSI.
    //
    SoftSSICallbackSet(&g_sSSI, SSICallback);

    //
    // Configure the pins used for the software SSI. This example uses
    // pins PD0, PE1, and PF2.
    //
    SoftSSIFssGPIOSet(&g_sSSI, GPIO_PORTD_BASE, GPIO_PIN_0);
    SoftSSIClkGPIOSet(&g_sSSI, GPIO_PORTE_BASE, GPIO_PIN_1);
    SoftSSITxGPIOSet(&g_sSSI, GPIO_PORTF_BASE, GPIO_PIN_2);

    //
    // Configure the data buffer used as the transmit FIFO.
    //

```

```
SoftSSITxBufferSet(&g_sSSI, g_pusTxBuffer, 8);

//
// Enable the GPIO modules that contains the GPIO pins to be used by
// the software SSI.
//
SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOD);
SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOE);
SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOF);

//
// Initialize the software SSI module, using mode 3 and 8 data bits.
//
SoftSSIConfigSet(&g_sSSI, SOFTSSI_FRF_MOTO_MODE_3, 8);

//
// Enable the software SSI.
//
SoftSSIEnable(&g_sSSI);

//
// Configure the timer used to generate the timing for the software
// SSI. The interface will be run at 10 KHz, requiring a timer tick
// at 20 KHz.
//
SysCtlPeripheralEnable(SYSCTL_PERIPH_TIMER0);
TimerConfigure(TIMER0_BASE, TIMER_CFG_32_BIT_PER);
TimerLoadSet(TIMER0_BASE, TIMER_A, SysCtlClockGet() / 20000);
TimerIntEnable(TIMER0_BASE, TIMER_TIMA_TIMEOUT);
IntEnable(INT_TIMER0A);
TimerEnable(TIMER0_BASE, TIMER_A);

//
// Enable the transmit FIFO half full interrupt in the software SSI.
//
SoftSSIIntEnable(&g_sSSI, SOFTSSI_TXFF);

//
// Write some data into the software SSI transmit FIFO.
//
SoftSSIDataPut(&g_sSSI, 0x55);
SoftSSIDataPut(&g_sSSI, 0xaa);
SoftSSIDataPut(&g_sSSI, 0x55);
SoftSSIDataPut(&g_sSSI, 0xaa);
SoftSSIDataPut(&g_sSSI, 0x55);
SoftSSIDataPut(&g_sSSI, 0xaa);

//
// Wait until the software SSI is idle. The transmit FIFO half full
// interrupt will be sent to the callback function prior to exiting
// this loop.
//
while(SoftSSIBusy(&g_sSSI))
{
}
}
```

As a comparison, the following is the equivalent code using the hardware SSI module and the Stellaris Peripheral Driver Library.

```
//
// The interrupt handler for the hardware SSI.
//
void
SSI0IntHandler(void)
```

```
{
    unsigned long ulInts;

    //
    // Read the asserted interrupt sources.
    //
    ulInts = SSIIntStatus(SSIO_BASE, true);

    //
    // Clear the asserted interrupt sources.
    //
    SSIIntClear(SSIO_BASE, ulInts);

    //
    // Handle the asserted interrupts.
    //
    ...
}

//
// Setup the hardware SSI and send some data.
//
void
TestSSI(void)
{
    //
    // Enable the GPIO module that contains the GPIO pins to be used by
    // the SSI, as well as the SSI module.
    //
    SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOA);
    SysCtlPeripheralEnable(SYSCTL_PERIPH_SSI0);

    //
    // Configure the GPIO pins for use by the SSI module.
    //
    GPIOPinTypeSSI(GPIO_PORTA_BASE, (GPIO_PIN_2 | GPIO_PIN_3 |
                                     GPIO_PIN_4 | GPIO_PIN_5));

    //
    // Initialize the hardware SSI module, using mode 3 and 8 data bits.
    //
    SSIConfigSetExpClk(SSIO_BASE, SysCtlClockGet(), SSI_FRF_MOTO_MODE_3,
                      SSI_MODE_MASTER, 10000, 8);

    //
    // Enable the hardware SSI.
    //
    SSIEnable(SSIO_BASE);

    //
    // Enable the transmit FIFO half full interrupt in the hardware SSI.
    //
    SSIIntEnable(SSIO_BASE, SSI_TXFF);
    IntEnable(INT_SSI0);

    //
    // Write some data into the hardware SSI transmit FIFO.
    //
    SSIDataPut(SSIO_BASE, 0x55);
    SSIDataPut(SSIO_BASE, 0xaa);
    SSIDataPut(SSIO_BASE, 0x55);
    SSIDataPut(SSIO_BASE, 0xaa);
    SSIDataPut(SSIO_BASE, 0x55);
    SSIDataPut(SSIO_BASE, 0xaa);

    //

```

```
// Wait until the hardware SSI is idle. The transmit FIFO half full
// interrupt will be sent to the interrupt handler prior to exiting
// this loop.
//
while(SSIBusy(SSIO_BASE))
{
}
```

17 Software UART Module

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17.1 Introduction

The software UART module uses two timers and a two GPIO pins to create a software UART peripheral. Multiple software UART modules can be in use simultaneously, limited only by the availability of resources (RAM for the per-instance data structure, pins for the interface, timers, and processor cycles to execute the code). The software UART module supports five through eight data bits, a variety of parity modes (odd, even, one, zero, and none), and one or two stop bits. A callback mechanism is used to simulate the interrupts that would be provided by a hardware UART module.

The API for the software UART module has been constructed to be as close as possible to the API provided in the Stellaris Peripheral Driver Library for the hardware UART module. The two notable difference are the function prefix being “SoftUART” instead of “UART”, and the first argument of each API is a pointer to the `tSoftUART` data structure instead of the base address of the hardware module.

The software UART transmitter and receiver are handled independently (because of the asynchronous nature of the two). As a result, there are separate timers for each, and if only one is required then the other does not need to be utilized.

Timing for the software UART transmitter is provided by the application. The `SoftUARTTx-TimerTick()` function must be called on a periodic basis to provide the timing for the software UART transmitter. The timer tick function must be called at the desired UART baud rate; for example, to operate the software UART transmitter at 38,400 baud, the tick function must be called at a 38,400 Hz rate. Because the application provides the timing, the timer resource can be flexible and multiple software UART transmitters can be driven from a single timer resource.

Timing for the software UART receiver is also provided by the application. Initially, the Rx pin is configured by the software UART module for a GPIO edge interrupt. The GPIO edge interrupt handler must be provided by the application (so that it can be shared with other possible GPIO interrupts on that port). When the interrupt occurs, a timer must be started at the desired baud rate (i.e. for 38,400 baud, it must run at 38,400 Hz) and the `SoftUARTRxTick()` function must be called. Then, whenever the timer interrupt occurs, the `SoftUARTRxTick()` function must be called. The timer is disabled whenever `SoftUARTRxTick()` indicates that it is no longer needed. Because the application provides the timing, the timer resource can be flexible. However, each software UART receiver must have its own timer resource.

The software UART module requires one or two GPIO pins. The following table shows the possible pin usages for the software UART module:

Tx	Rx	Pins	Description
yes		1	transmit only
	yes	1	receive only
yes	yes	2	transmit and receive

The per-instance data structure is approximately 52 bytes in length (the actual length depends on how the structure is packed by the compiler in use).

The following table shows some approximate measurements of the processor usage of the software UART module at various baud rates with the processor running at 50 MHz. Actual processor usage may vary, depending on how the application uses the software UART module, processor clock speed, interrupt priority, and compiler in use.

UART Baud Rate	% Of Processor	Million Cycles Per Second
9600	5.32	2.66
14400	7.99	3.99
19200	10.65	5.32
28800	15.96	7.98
38400	21.28	10.64
57600	32.00	16.00
115200	64.04	32.02

This module is contained in `utils/softuart.c`, with `utils/softuart.h` containing the API definitions for use by applications.

17.2 API Functions

Data Structures

- [tSoftUART](#)

Functions

- void [SoftUARTBreakCtl](#) ([tSoftUART](#) *pUART, tBoolean bBreakState)
- tBoolean [SoftUARTBusy](#) ([tSoftUART](#) *pUART)
- void [SoftUARTCallbackSet](#) ([tSoftUART](#) *pUART, void (*pfnCallback)(void))
- long [SoftUARTCharGet](#) ([tSoftUART](#) *pUART)
- long [SoftUARTCharGetNonBlocking](#) ([tSoftUART](#) *pUART)
- void [SoftUARTCharPut](#) ([tSoftUART](#) *pUART, unsigned char ucData)
- tBoolean [SoftUARTCharPutNonBlocking](#) ([tSoftUART](#) *pUART, unsigned char ucData)
- tBoolean [SoftUARTCharsAvail](#) ([tSoftUART](#) *pUART)
- void [SoftUARTConfigGet](#) ([tSoftUART](#) *pUART, unsigned long *pulConfig)
- void [SoftUARTConfigSet](#) ([tSoftUART](#) *pUART, unsigned long ulConfig)
- void [SoftUARTDisable](#) ([tSoftUART](#) *pUART)
- void [SoftUARTEnable](#) ([tSoftUART](#) *pUART)
- void [SoftUARTFIFOLevelGet](#) ([tSoftUART](#) *pUART, unsigned long *pulTxLevel, unsigned long *pulRxLevel)
- void [SoftUARTFIFOLevelSet](#) ([tSoftUART](#) *pUART, unsigned long ulTxLevel, unsigned long ulRxLevel)
- void [SoftUARTInit](#) ([tSoftUART](#) *pUART)
- void [SoftUARTIntClear](#) ([tSoftUART](#) *pUART, unsigned long ulIntFlags)
- void [SoftUARTIntDisable](#) ([tSoftUART](#) *pUART, unsigned long ulIntFlags)
- void [SoftUARTIntEnable](#) ([tSoftUART](#) *pUART, unsigned long ulIntFlags)

- unsigned long `SoftUARTIntStatus` (`tSoftUART *pUART`, `tBoolean bMasked`)
- unsigned long `SoftUARTParityModeGet` (`tSoftUART *pUART`)
- void `SoftUARTParityModeSet` (`tSoftUART *pUART`, unsigned long `ulParity`)
- void `SoftUARTRxBufferSet` (`tSoftUART *pUART`, unsigned short `*pusRxBuffer`, unsigned short `usLen`)
- void `SoftUARTRxErrorClear` (`tSoftUART *pUART`)
- unsigned long `SoftUARTRxErrorGet` (`tSoftUART *pUART`)
- void `SoftUARTRxGPIOSet` (`tSoftUART *pUART`, unsigned long `ulBase`, unsigned char `ucPin`)
- unsigned long `SoftUARTRxTick` (`tSoftUART *pUART`, `tBoolean bEdgeInt`)
- `tBoolean` `SoftUARTSpaceAvail` (`tSoftUART *pUART`)
- void `SoftUARTTxBufferSet` (`tSoftUART *pUART`, unsigned char `*pucTxBuffer`, unsigned short `usLen`)
- void `SoftUARTTxGPIOSet` (`tSoftUART *pUART`, unsigned long `ulBase`, unsigned char `ucPin`)
- void `SoftUARTTxTimerTick` (`tSoftUART *pUART`)

17.2.1 Data Structure Documentation

17.2.1.1 tSoftUART

Definition:

```
typedef struct
{
    void (*pfnIntCallback) (void);
    unsigned long ulTxGPIO;
    unsigned long ulRxGPIOPort;
    unsigned char *pucTxBuffer;
    unsigned short *pusRxBuffer;
    unsigned short usTxBufferLen;
    unsigned short usTxBufferRead;
    unsigned short usTxBufferWrite;
    unsigned short usTxBufferLevel;
    unsigned short usRxBufferLen;
    unsigned short usRxBufferRead;
    unsigned short usRxBufferWrite;
    unsigned short usRxBufferLevel;
    unsigned short usIntStatus;
    unsigned short usIntMask;
    unsigned short usConfig;
    unsigned char ucFlags;
    unsigned char ucTxState;
    unsigned char ucTxNext;
    unsigned char ucTxData;
    unsigned char ucRxPin;
    unsigned char ucRxState;
    unsigned char ucRxData;
    unsigned char ucRxFlags;
    unsigned char ucRxStatus;
}
tSoftUART
```

Members:

- pfIntCallback*** The address of the callback function that is called to simulate the interrupts that would be produced by a hardware UART implementation. This address can be set via a direct structure access or using the `SoftUARTCallbackSet` function.
- ulTxGPIO*** The address of the GPIO pin to be used for the Tx signal. This member can be set via a direct structure access or using the `SoftUARTTxGPIOSet` function.
- ulRxGPIOPort*** The address of the GPIO port to be used for the Rx signal. This member can be set via a direct structure access or using the `SoftUARTRxGPIOSet` function.
- pucTxBuffer*** The address of the data buffer used for the transmit buffer. This member can be set via a direct structure access or using the `SoftUARTTxBufferSet` function.
- pusRxBuffer*** The address of the data buffer used for the receive buffer. This member can be set via a direct structure access or using the `SoftUARTRxBufferSet` function.
- usTxBufferLen*** The length of the transmit buffer. This member can be set via a direct structure access or using the `SoftUARTTxBufferSet` function.
- usTxBufferRead*** The index into the transmit buffer of the next character to be transmitted. This member should not be accessed or modified by the application.
- usTxBufferWrite*** The index into the transmit buffer of the next location to store a character into the buffer. This member should not be accessed or modified by the application.
- usTxBufferLevel*** The transmit buffer level at which the transmit interrupt is asserted. This member should not be accessed or modified by the application.
- usRxBufferLen*** The length of the receive buffer. This member can be set via a direct structure access or using the `SoftUARTRxBufferSet` function.
- usRxBufferRead*** The index into the receive buffer of the next character to be read from the buffer. This member should not be accessed or modified by the application.
- usRxBufferWrite*** The index into the receive buffer of the location to store the next character received. This member should not be accessed or modified by the application.
- usRxBufferLevel*** The receive buffer level at which the receive interrupt is asserted. This member should not be accessed or modified by the application.
- usIntStatus*** The set of virtual interrupts that are currently asserted. This member should not be accessed or modified by the application.
- usIntMask*** The set of virtual interrupts that should be sent to the callback function. This member should not be accessed or modified by the application.
- usConfig*** The configuration of the SoftUART module. This member can be set via the `SoftUARTConfigSet` and `SoftUARTFIFOLevelSet` functions.
- ucFlags*** The flags that control the operation of the SoftUART module. This member should not be accessed or modified by the application.
- ucTxState*** The current state of the SoftUART transmit state machine. This member should not be accessed or modified by the application.
- ucTxNext*** The value that is written to the Tx pin at the start of the next transmit timer tick. This member should not be accessed or modified by the application.
- ucTxData*** The character that is currently being sent via the Tx pin. This member should not be accessed or modified by the application.
- ucRxPin*** The GPIO pin to be used for the Rx signal. This member can be set via a direct structure access or using the `SoftUARTRxGPIOSet` function.
- ucRxState*** The current state of the SoftUART receive state machine. This member should not be accessed or modified by the application.
- ucRxData*** The character that is currently being received via the Rx pin. This member should not be accessed or modified by the application.

ucRxFlags The flags that indicate any errors that have occurred during the reception of the current character via the Rx pin. This member should not be accessed or modified by the application.

ucRxStatus The receive error status. This member should only be accessed via the SoftUARTRxErrorGet and SoftUARTRxErrorClear functions.

Description:

This structure contains the state of a single instance of a SoftUART module.

17.2.2 Function Documentation

17.2.2.1 SoftUARTBreakCtl

Causes a BREAK to be sent.

Prototype:

```
void  
SoftUARTBreakCtl (tSoftUART *pUART,  
                  tBoolean bBreakState)
```

Parameters:

pUART specifies the SoftUART data structure.

bBreakState controls the output level.

Description:

Calling this function with *bBreakState* set to **true** asserts a break condition on the SoftUART. Calling this function with *bBreakState* set to **false** removes the break condition. For proper transmission of a break command, the break must be asserted for at least two complete frames.

Returns:

None.

17.2.2.2 SoftUARTBusy

Determines whether the UART transmitter is busy or not.

Prototype:

```
tBoolean  
SoftUARTBusy (tSoftUART *pUART)
```

Parameters:

pUART specifies the SoftUART data structure.

Description:

Allows the caller to determine whether all transmitted bytes have cleared the transmitter hardware. If **false** is returned, the transmit buffer is empty and all bits of the last transmitted character, including all stop bits, have left the hardware shift register.

Returns:

Returns **true** if the UART is transmitting or **false** if all transmissions are complete.

17.2.2.3 SoftUARTCallbackSet

Sets the callback used by the SoftUART module.

Prototype:

```
void  
SoftUARTCallbackSet (tSoftUART *pUART,  
                     void (*pfnCallback) (void))
```

Parameters:

pUART specifies the SoftUART data structure.
pfnCallback is a pointer to the callback function.

Description:

This function sets the address of the callback function that is called when there is an “interrupt” produced by the SoftUART module.

Returns:

None.

17.2.2.4 SoftUARTCharGet

Waits for a character from the specified port.

Prototype:

```
long  
SoftUARTCharGet (tSoftUART *pUART)
```

Parameters:

pUART specifies the SoftUART data structure.

Description:

Gets a character from the receive buffer for the specified port. If there are no characters available, this function waits until a character is received before returning.

Returns:

Returns the character read from the specified port, cast as a *long*.

17.2.2.5 SoftUARTCharGetNonBlocking

Receives a character from the specified port.

Prototype:

```
long  
SoftUARTCharGetNonBlocking (tSoftUART *pUART)
```

Parameters:

pUART specifies the SoftUART data structure.

Description:

Gets a character from the receive buffer for the specified port.

Returns:

Returns the character read from the specified port, cast as a *long*. A **-1** is returned if there are no characters present in the receive buffer. The [SoftUARTCharsAvail\(\)](#) function should be called before attempting to call this function.

17.2.2.6 SoftUARTCharPut

Waits to send a character from the specified port.

Prototype:

```
void  
SoftUARTCharPut (tSoftUART *pUART,  
                 unsigned char ucData)
```

Parameters:

pUART specifies the SoftUART data structure.

ucData is the character to be transmitted.

Description:

Sends the character *ucData* to the transmit buffer for the specified port. If there is no space available in the transmit buffer, this function waits until there is space available before returning.

Returns:

None.

17.2.2.7 SoftUARTCharPutNonBlocking

Sends a character to the specified port.

Prototype:

```
tBoolean  
SoftUARTCharPutNonBlocking (tSoftUART *pUART,  
                             unsigned char ucData)
```

Parameters:

pUART specifies the SoftUART data structure.

ucData is the character to be transmitted.

Description:

Writes the character *ucData* to the transmit buffer for the specified port. This function does not block, so if there is no space available, then a **false** is returned, and the application must retry the function later.

Returns:

Returns **true** if the character was successfully placed in the transmit buffer or **false** if there was no space available in the transmit buffer.

17.2.2.8 SoftUARTCharsAvail

Determines if there are any characters in the receive buffer.

Prototype:

```
tBoolean  
SoftUARTCharsAvail (tSoftUART *pUART)
```

Parameters:

pUART specifies the SoftUART data structure.

Description:

This function returns a flag indicating whether or not there is data available in the receive buffer.

Returns:

Returns **true** if there is data in the receive buffer or **false** if there is no data in the receive buffer.

17.2.2.9 SoftUARTConfigGet

Gets the current configuration of a UART.

Prototype:

```
void  
SoftUARTConfigGet (tSoftUART *pUART,  
                   unsigned long *pulConfig)
```

Parameters:

pUART specifies the SoftUART data structure.

pulConfig is a pointer to storage for the data format.

Description:

Returns the data format of the SoftUART. The data format returned in *pulConfig* is enumerated the same as the *ulConfig* parameter of [SoftUARTConfigSet\(\)](#).

Returns:

None.

17.2.2.10 SoftUARTConfigSet

Sets the configuration of a SoftUART module.

Prototype:

```
void  
SoftUARTConfigSet (tSoftUART *pUART,  
                   unsigned long ulConfig)
```

Parameters:

pUART specifies the SoftUART data structure.

ulConfig is the data format for the port (number of data bits, number of stop bits, and parity).

Description:

This function configures the SoftUART for operation in the specified data format, as specified in the *ulConfig* parameter.

The *ulConfig* parameter is the logical OR of three values: the number of data bits, the number of stop bits, and the parity. **SOFTUART_CONFIG_WLEN_8**, **SOFTUART_CONFIG_WLEN_7**, **SOFTUART_CONFIG_WLEN_6**, and **SOFTUART_CONFIG_WLEN_5** select from eight to five data bits per byte (respectively). **SOFTUART_CONFIG_STOP_ONE** and **SOFTUART_CONFIG_STOP_TWO** select one or two stop bits (respectively). **SOFTUART_CONFIG_PAR_NONE**, **SOFTUART_CONFIG_PAR_EVEN**, **SOFTUART_CONFIG_PAR_ODD**, **SOFTUART_CONFIG_PAR_ONE**, and **SOFTUART_CONFIG_PAR_ZERO** select the parity mode (no parity bit, even parity bit, odd parity bit, parity bit always one, and parity bit always zero, respectively).

Returns:

None.

17.2.2.11 SoftUARTDisable

Disables the SoftUART.

Prototype:

```
void  
SoftUARTDisable(tSoftUART *pUART)
```

Parameters:

pUART specifies the SoftUART data structure.

Description:

This function disables the SoftUART after waiting for it to become idle.

Returns:

None.

17.2.2.12 SoftUARTEnable

Enables the SoftUART.

Prototype:

```
void  
SoftUARTEnable(tSoftUART *pUART)
```

Parameters:

pUART specifies the SoftUART data structure.

Description:

This function enables the SoftUART, allowing data to be transmitted and received.

Returns:

None.

17.2.2.13 SoftUARTFIFOLevelGet

Gets the buffer level at which “interrupts” are generated.

Prototype:

```
void  
SoftUARTFIFOLevelGet (tSoftUART *pUART,  
                      unsigned long *pulTxLevel,  
                      unsigned long *pulRxLevel)
```

Parameters:

pUART specifies the SoftUART data structure.

pulTxLevel is a pointer to storage for the transmit buffer level, returned as one of **UART_FIFO_TX1_8**, **UART_FIFO_TX2_8**, **UART_FIFO_TX4_8**, **UART_FIFO_TX6_8**, or **UART_FIFO_TX7_8**.

pulRxLevel is a pointer to storage for the receive buffer level, returned as one of **UART_FIFO_RX1_8**, **UART_FIFO_RX2_8**, **UART_FIFO_RX4_8**, **UART_FIFO_RX6_8**, or **UART_FIFO_RX7_8**.

Description:

This function gets the buffer level at which transmit and receive “interrupts” are generated.

Returns:

None.

17.2.2.14 SoftUARTFIFOLevelSet

Sets the buffer level at which “interrupts” are generated.

Prototype:

```
void  
SoftUARTFIFOLevelSet (tSoftUART *pUART,  
                      unsigned long ulTxLevel,  
                      unsigned long ulRxLevel)
```

Parameters:

pUART specifies the SoftUART data structure.

ulTxLevel is the transmit buffer “interrupt” level, specified as one of **UART_FIFO_TX1_8**, **UART_FIFO_TX2_8**, **UART_FIFO_TX4_8**, **UART_FIFO_TX6_8**, or **UART_FIFO_TX7_8**.

ulRxLevel is the receive buffer “interrupt” level, specified as one of **UART_FIFO_RX1_8**, **UART_FIFO_RX2_8**, **UART_FIFO_RX4_8**, **UART_FIFO_RX6_8**, or **UART_FIFO_RX7_8**.

Description:

This function sets the buffer level at which transmit and receive “interrupts” are generated.

Returns:

None.

17.2.2.15 SoftUARTInit

Initializes the SoftUART module.

Prototype:

```
void  
SoftUARTInit (tSoftUART *pUART)
```

Parameters:

pUART specifies the soft UART data structure.

Description:

This function initializes the data structure for the SoftUART module, putting it into the default configuration.

Returns:

None.

17.2.2.16 SoftUARTIntClear

Clears SoftUART “interrupt” sources.

Prototype:

```
void  
SoftUARTIntClear (tSoftUART *pUART,  
                  unsigned long ulIntFlags)
```

Parameters:

pUART specifies the SoftUART data structure.

ulIntFlags is a bit mask of the “interrupt” sources to be cleared.

Description:

The specified SoftUART “interrupt” sources are cleared, so that they no longer assert. This function must be called in the callback function to keep the “interrupt” from being recognized again immediately upon exit.

The *ulIntFlags* parameter has the same definition as the *ulIntFlags* parameter to [SoftUARTIntEnable\(\)](#).

Returns:

None.

17.2.2.17 SoftUARTIntDisable

Disables individual SoftUART “interrupt” sources.

Prototype:

```
void  
SoftUARTIntDisable (tSoftUART *pUART,  
                    unsigned long ulIntFlags)
```

Parameters:

pUART specifies the SoftUART data structure.

ulIntFlags is the bit mask of the “interrupt” sources to be disabled.

Description:

Disables the indicated SoftUART “interrupt” sources. Only the sources that are enabled can be reflected to the SoftUART callback.

The *ulIntFlags* parameter has the same definition as the *ulIntFlags* parameter to [SoftUARTIntEnable\(\)](#).

Returns:

None.

17.2.2.18 SoftUARTIntEnable

Enables individual SoftUART “interrupt” sources.

Prototype:

```
void  
SoftUARTIntEnable(tSoftUART *pUART,  
                  unsigned long ulIntFlags)
```

Parameters:

pUART specifies the SoftUART data structure.

ulIntFlags is the bit mask of the “interrupt” sources to be enabled.

Description:

Enables the indicated SoftUART “interrupt” sources. Only the sources that are enabled can be reflected to the SoftUART callback.

The *ulIntFlags* parameter is the logical OR of any of the following:

- **SOFTUART_INT_OE** - Overrun Error “interrupt”
- **SOFTUART_INT_BE** - Break Error “interrupt”
- **SOFTUART_INT_PE** - Parity Error “interrupt”
- **SOFTUART_INT_FE** - Framing Error “interrupt”
- **SOFTUART_INT_RT** - Receive Timeout “interrupt”
- **SOFTUART_INT_TX** - Transmit “interrupt”
- **SOFTUART_INT_RX** - Receive “interrupt”

Returns:

None.

17.2.2.19 SoftUARTIntStatus

Gets the current SoftUART “interrupt” status.

Prototype:

```
unsigned long  
SoftUARTIntStatus(tSoftUART *pUART,  
                  tBoolean bMasked)
```


Parameters:

pUART specifies the SoftUART data structure.

bMasked is **false** if the raw “interrupt” status is required and **true** if the masked “interrupt” status is required.

Description:

This returns the “interrupt” status for the SoftUART. Either the raw “interrupt” status or the status of “interrupts” that are allowed to reflect to the SoftUART callback can be returned.

Returns:

Returns the current “interrupt” status, enumerated as a bit field of values described in [SoftUARTIntEnable\(\)](#).

17.2.2.20 SoftUARTParityModeGet

Gets the type of parity currently being used.

Prototype:

```
unsigned long  
SoftUARTParityModeGet (tSoftUART *pUART)
```

Parameters:

pUART specifies the SoftUART data structure.

Description:

This function gets the type of parity used for transmitting data and expected when receiving data.

Returns:

Returns the current parity settings, specified as one of **SOFTUART_CONFIG_PAR_NONE**, **SOFTUART_CONFIG_PAR_EVEN**, **SOFTUART_CONFIG_PAR_ODD**, **SOFTUART_CONFIG_PAR_ONE**, or **SOFTUART_CONFIG_PAR_ZERO**.

17.2.2.21 SoftUARTParityModeSet

Sets the type of parity.

Prototype:

```
void  
SoftUARTParityModeSet (tSoftUART *pUART,  
                        unsigned long ulParity)
```

Parameters:

pUART specifies the SoftUART data structure.

ulParity specifies the type of parity to use.

Description:

Sets the type of parity to use for transmitting and expect when receiving. The *ulParity* parameter must be one of **SOFTUART_CONFIG_PAR_NONE**, **SOFTUART_CONFIG_PAR_EVEN**, **SOFTUART_CONFIG_PAR_ODD**, **SOFTUART_CONFIG_PAR_ONE**, or **SOFTUART_CONFIG_PAR_ZERO**. The last two allow direct control of the parity bit; it is always either one or zero based on the mode.

Returns:

None.

17.2.2.22 SoftUARTRxBufferSet

Sets the receive buffer for a SoftUART module.

Prototype:

```
void  
SoftUARTRxBufferSet (tSoftUART *pUART,  
                     unsigned short *pusRxBuffer,  
                     unsigned short usLen)
```

Parameters:

pUART specifies the SoftUART data structure.

pusRxBuffer is the address of the receive buffer.

usLen is the size, in 16-bit half-words, of the receive buffer.

Description:

This function sets the address and size of the receive buffer. It also resets the read and write pointers, marking the receive buffer as empty.

Returns:

None.

17.2.2.23 SoftUARTRxErrorClear

Clears all reported receiver errors.

Prototype:

```
void  
SoftUARTRxErrorClear (tSoftUART *pUART)
```

Parameters:

pUART specifies the SoftUART data structure.

Description:

This function is used to clear all receiver error conditions reported via [SoftUARTRxErrorGet\(\)](#). If using the overrun, framing error, parity error or break interrupts, this function must be called after clearing the interrupt to ensure that later errors of the same type trigger another interrupt.

Returns:

None.

17.2.2.24 SoftUARTRxErrorGet

Gets current receiver errors.

Prototype:

```
unsigned long  
SoftUARTRxErrorGet (tSoftUART *pUART)
```

Parameters:

pUART specifies the SoftUART data structure.

Description:

This function returns the current state of each of the 4 receiver error sources. The returned errors are equivalent to the four error bits returned via the previous call to [SoftUARTCharGet\(\)](#) or [SoftUARTCharGetNonBlocking\(\)](#) with the exception that the overrun error is set immediately when the overrun occurs rather than when a character is next read.

Returns:

Returns a logical OR combination of the receiver error flags, **SOFTUART_RXERROR_FRAMING**, **SOFTUART_RXERROR_PARITY**, **SOFTUART_RXERROR_BREAK** and **SOFTUART_RXERROR_OVERRUN**.

17.2.2.25 SoftUARTRxGPIOSet

Sets the GPIO pin to be used as the SoftUART Rx signal.

Prototype:

```
void  
SoftUARTRxGPIOSet (tSoftUART *pUART,  
                   unsigned long ulBase,  
                   unsigned char ucPin)
```

Parameters:

pUART specifies the SoftUART data structure.
ulBase is the base address of the GPIO module.
ucPin is the bit-packed representation of the pin to use.

Description:

This function sets the GPIO pin that is used when the SoftUART must sample the Rx signal. If there is not a GPIO pin allocated for Rx, the SoftUART module will not read data from the slave device.

The pin is specified using a bit-packed byte, where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

17.2.2.26 SoftUARTRxTick

Performs the periodic update of the SoftUART receiver.

Prototype:

```
unsigned long  
SoftUARTRxTick (tSoftUART *pUART,  
                tBoolean bEdgeInt)
```

Parameters:

pUART specifies the SoftUART data structure.

bEdgeInt should be **true** if this function is being called because of a GPIO edge interrupt and **false** if it is being called because of a timer interrupt.

Description:

This function performs the periodic, time-based updates to the SoftUART receiver. The reception of data to the SoftUART is performed by the state machine in this function.

This function must be called by the GPIO interrupt handler, and then periodically at the desired SoftUART baud rate. For example, to run the SoftUART at 115,200 baud, this function must be called at a 115,200 Hz rate.

Returns:

Returns **SOFTUART_RXTIMER_NOP** if the receive timer should continue to operate or **SOFTUART_RXTIMER_END** if it should be stopped.

17.2.2.27 SoftUARTSpaceAvail

Determines if there is any space in the transmit buffer.

Prototype:

```
tBoolean  
SoftUARTSpaceAvail (tSoftUART *pUART)
```

Parameters:

pUART specifies the SoftUART data structure.

Description:

This function returns a flag indicating whether or not there is space available in the transmit buffer.

Returns:

Returns **true** if there is space available in the transmit buffer or **false** if there is no space available in the transmit buffer.

17.2.2.28 SoftUARTTxBufferSet

Sets the transmit buffer for a SoftUART module.

Prototype:

```
void  
SoftUARTTxBufferSet (tSoftUART *pUART,  
                     unsigned char *pucTxBuffer,  
                     unsigned short usLen)
```

Parameters:

pUART specifies the SoftUART data structure.

pucTxBuffer is the address of the transmit buffer.

usLen is the size, in 8-bit bytes, of the transmit buffer.

Description:

This function sets the address and size of the transmit buffer. It also resets the read and write pointers, marking the transmit buffer as empty.

Returns:

None.

17.2.2.29 SoftUARTTxGPIOSet

Sets the GPIO pin to be used as the SoftUART Tx signal.

Prototype:

```
void  
SoftUARTTxGPIOSet (tSoftUART *pUART,  
                   unsigned long ulBase,  
                   unsigned char ucPin)
```

Parameters:

pUART specifies the SoftUART data structure.

ulBase is the base address of the GPIO module.

ucPin is the bit-packed representation of the pin to use.

Description:

This function sets the GPIO pin that is used when the SoftUART must assert the Tx signal.

The pin is specified using a bit-packed byte, where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

17.2.2.30 SoftUARTTxTimerTick

Performs the periodic update of the SoftUART transmitter.

Prototype:

```
void  
SoftUARTTxTimerTick (tSoftUART *pUART)
```

Parameters:

pUART specifies the SoftUART data structure.

Description:

This function performs the periodic, time-based updates to the SoftUART transmitter. The transmission of data from the SoftUART is performed by the state machine in this function.

This function must be called at the desired SoftUART baud rate. For example, to run the SoftUART at 115,200 baud, this function must be called at a 115,200 Hz rate.

Returns:

None.

17.3 Programming Example

The following example shows how to configure the software UART module and transmit some data to an external peripheral. This example uses Timer 0 as the timing source.

```
//
// The instance data for the software UART.
//
tSoftUART g_sUART;

//
// The buffer used to hold the transmit data.
//
unsigned char g_pucTxBuffer[16];

//
// The buffer used to hold the receive data.
//
unsigned short g_pusRxBuffer[16];

//
// The number of processor clocks in the time period of a single bit on the
// software UART interface.
//
unsigned long g_ulBitTime;

//
// The transmit timer tick function.
//
void
Timer0AIntHandler(void)
{
    //
    // Clear the timer interrupt.
    //
    TimerIntClear(TIMER0_BASE, TIMER_TIMA_TIMEOUT);

    //
    // Call the software UART transmit timer tick function.
    //
    SoftUARTTxTimerTick(&g_sUART);
}

//
// The receive timer tick function.
//
void
Timer0BIntHandler(void)
{
    //
    // Clear the timer interrupt.
    //
    TimerIntClear(TIMER0_BASE, TIMER_TIMA_TIMEOUT);

    //
    // Call the software UART receive timer tick function, and see if the
    // timer should be disabled.
    //
    if(SoftUARTRxTick(&g_sUART, false) == SOFTUART_RXTIMER_END)
    {
        //
        // Disable the timer interrupt since the software UART doesn't need
        // it any longer.
        //
    }
}
```

```

        TimerDisable(TIMER0_BASE, TIMER_B);
    }
}

//
// The interrupt handler for the software UART GPIO edge interrupt.
//
void
GPIOIntHandler(void)
{
    //
    // Configure the software UART receive timer so that it samples at the
    // mid-bit time of this character.
    //
    TimerDisable(TIMER0_BASE, TIMER_B);
    TimerLoadSet(TIMER0_BASE, TIMER_B, g_ulBitTime);
    TimerIntClear(TIMER0_BASE, TIMER_TIMB_TIMEOUT);
    TimerEnable(TIMER0_BASE, TIMER_B);

    //
    // Call the software UART receive timer tick function.
    //
    SoftUARTRxTick(&g_sUART, true);
}

//
// The callback function for the software UART. This function is
// equivalent to the interrupt handler for a hardware UART.
//
void
UARTCallback(void)
{
    unsigned long ulInts;

    //
    // Read the asserted interrupt sources.
    //
    ulInts = SoftUARTIntStatus(&g_sUART, true);

    //
    // Clear the asserted interrupt sources.
    //
    SoftUARTIntClear(&g_sUART, ulInts);

    //
    // Handle the asserted interrupts.
    //
    ...
}

//
// Setup the software UART and send some data.
//
void
TestSoftUART(void)
{
    //
    // Initialize the software UART instance data.
    //
    SoftUARTInit(&g_sUART);

    //
    // Set the callback function used for this software UART.
    //
    SoftUARTCallbackSet(&g_sUART, UARTCallback);
}

```

```
//
// Configure the pins used for the software UART. This example uses
// pins PD0 and PE1.
//
SoftUARTTxGPIOSet(&g_sUART, GPIO_PORTD_BASE, GPIO_PIN_0);
SoftUARTRxGPIOSet(&g_sUART, GPIO_PORTE_BASE, GPIO_PIN_1);

//
// Configure the data buffers used as the transmit and receive buffers.
//
SoftUARTTxBufferSet(&g_sUART, g_pucTxBuffer, 16);
SoftUARTRxBufferSet(&g_sUART, g_pusRxBuffer, 16);

//
// Enable the GPIO modules that contains the GPIO pins to be used by
// the software UART.
//
SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOD);
SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOE);

//
// Configure the software UART module: 8 data bits, no parity, and one
// stop bit.
//
SoftUARTConfigSet(&g_sUART,
                  (SOFTUART_CONFIG_WLEN_8 | SOFTUART_CONFIG_PAR_NONE |
                   SOFTUART_CONFIG_STOP_ONE));

//
// Compute the bit time for 38,400 baud.
//
g_ulBitTime = (SysCtlClockGet() / 38400) - 1;

//
// Configure the timers used to generate the timing for the software
// UART. The interface in this example is run at 38,400 baud,
// requiring a timer tick at 38,400 Hz.
//
SysCtlPeripheralEnable(SYSCTL_PERIPH_TIMER0);
TimerConfigure(TIMER0_BASE,
               (TIMER_CFG_16_BIT_PAIR | TIMER_CFG_A_PERIODIC |
                TIMER_CFG_B_PERIODIC));
TimerLoadSet(TIMER0_BASE, TIMER_A, g_ulBitTime);
TimerIntEnable(TIMER0_BASE, TIMER_TIMA_TIMEOUT | TIMER_TIMB_TIMEOUT);
TimerEnable(TIMER0_BASE, TIMER_A);

//
// Set the priorities of the interrupts associated with the software
// UART. The receiver is higher priority than the transmitter, and the
// receiver edge interrupt is higher priority than the receiver timer
// interrupt.
//
IntPrioritySet(INT_GPIOE, 0x00);
IntPrioritySet(INT_TIMER0B, 0x40);
IntPrioritySet(INT_TIMER0A, 0x80);

//
// Enable the interrupts associated with the software UART.
//
IntEnable(INT_GPIOE);
IntEnable(INT_TIMER0A);
IntEnable(INT_TIMER0B);

//
// Enable the transmit FIFO half full interrupt in the software UART.
//
```



```
SoftUARTIntEnable(&g_sUART, SOFTUART_INT_TX);

//
// Write some data into the software UART transmit FIFO.
//
SoftUARTCharPut(&g_sUART, 0x55);
SoftUARTCharPut(&g_sUART, 0xaa);
SoftUARTCharPut(&g_sUART, 0x55);
SoftUARTCharPut(&g_sUART, 0xaa);
SoftUARTCharPut(&g_sUART, 0x55);
SoftUARTCharPut(&g_sUART, 0xaa);
SoftUARTCharPut(&g_sUART, 0x55);
SoftUARTCharPut(&g_sUART, 0xaa);
SoftUARTCharPut(&g_sUART, 0x55);
SoftUARTCharPut(&g_sUART, 0xaa);
SoftUARTCharPut(&g_sUART, 0x55);
SoftUARTCharPut(&g_sUART, 0xaa);

//
// Wait until the software UART is idle. The transmit FIFO half full
// interrupt is sent to the callback function prior to exiting this
// loop.
//
while(SoftUARTBusy(&g_sUART))
{
}
}
```

As a comparison, the following is the equivalent code using the hardware UART module and the Stellaris Peripheral Driver Library.

```
//
// The interrupt handler for the hardware UART.
//
void
UART0IntHandler(void)
{
    unsigned long ulInts;

    //
    // Read the asserted interrupt sources.
    //
    ulInts = UARTIntStatus(UART0_BASE, true);

    //
    // Clear the asserted interrupt sources.
    //
    UARTIntClear(UART0_BASE, ulInts);

    //
    // Handle the asserted interrupts.
    //
    ...
}

//
// Setup the hardware UART and send some data.
//
void
TestUART(void)
{
    //
    // Enable the GPIO module that contains the GPIO pins to be used by
    // the UART, as well as the UART module.
    //
}
```

```
SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOA);
SysCtlPeripheralEnable(SYSCTL_PERIPH_UART0);

//
// Configure the GPIO pins for use by the UART module.
//
GPIOPinTypeUART(GPIO_PORTA_BASE, GPIO_PIN_0 | GPIO_PIN_1);

//
// Initialize the hardware UART module: 8 data bits, no parity, one stop
// bit, and 38,400 baud rate.
//
UARTConfigSetExpClk(UART0_BASE, SysCtlClockGet(), 38400,
                    (UART_CONFIG_WLEN_8 | UART_CONFIG_PAR_NONE |
                     UART_CONFIG_STOP_ONE));

//
// Enable the transmit FIFO half full interrupt in the hardware UART.
//
UARTIntEnable(UART0_BASE, UART_INT_TX);
IntEnable(INT_UART0);

//
// Write some data into the hardware UART transmit FIFO.
//
UARTCharPut(UART0_BASE, 0x55);
UARTCharPut(UART0_BASE, 0xaa);
UARTCharPut(UART0_BASE, 0x55);
UARTCharPut(UART0_BASE, 0xaa);
UARTCharPut(UART0_BASE, 0x55);
UARTCharPut(UART0_BASE, 0xaa);
UARTCharPut(UART0_BASE, 0x55);
UARTCharPut(UART0_BASE, 0xaa);
UARTCharPut(UART0_BASE, 0x55);
UARTCharPut(UART0_BASE, 0xaa);
UARTCharPut(UART0_BASE, 0x55);
UARTCharPut(UART0_BASE, 0xaa);

//
// Wait until the hardware UART is idle. The transmit FIFO half full
// interrupt is sent to the interrupt handler prior to exiting this
// loop.
//
while(UARTBusy(UART0_BASE))
{
}
}
```

18 Micro Standard Library Module

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18.1 Introduction

The micro standard library module provides a set of small implementations of functions normally found in the C library. These functions provide reduced or greatly reduced functionality in order to remain small while still being useful for most embedded applications.

The following functions are provided, along with the C library equivalent:

Function	C library equivalent
<code>usprintf</code>	<code>sprintf</code>
<code>usnprintf</code>	<code>snprintf</code>
<code>uvsnprintf</code>	<code>vsnprintf</code>
<code>ustrnicmp</code>	<code>strnicmp</code>
<code>ustrtoul</code>	<code>strtoul</code>
<code>ustrstr</code>	<code>strstr</code>
<code>ulocaltime</code>	<code>localtime</code>

This module is contained in `utils/ustdlib.c`, with `utils/ustdlib.h` containing the API definitions for use by applications.

18.2 API Functions

Data Structures

- [tTime](#)

Functions

- void [ulocaltime](#) (unsigned long ulTime, [tTime](#) *psTime)
- unsigned long [umktime](#) ([tTime](#) *psTime)
- int [urand](#) (void)
- int [usnprintf](#) (char *pcBuf, unsigned long ulSize, const char *pcString,...)
- int [usprintf](#) (char *pcBuf, const char *pcString,...)
- void [usrand](#) (unsigned long ulSeed)
- int [ustrcasecmp](#) (const char *pcStr1, const char *pcStr2)
- int [ustrcmp](#) (const char *pcStr1, const char *pcStr2)
- int [ustrlen](#) (const char *pcStr)
- int [ustrncmp](#) (const char *pcStr1, const char *pcStr2, int iCount)

- char * [ustrncpy](#) (char *pcDst, const char *pcSrc, int iNum)
- int [ustrnicmp](#) (const char *pcStr1, const char *pcStr2, int iCount)
- char * [ustrstr](#) (const char *pcHaystack, const char *pcNeedle)
- unsigned long [ustrtoul](#) (const char *pcStr, const char **ppcStrRet, int iBase)
- int [uvsnprintf](#) (char *pcBuf, unsigned long ulSize, const char *pcString, va_list vaArgP)

18.2.1 Data Structure Documentation

18.2.1.1 tTime

Definition:

```
typedef struct
{
    unsigned short usYear;
    unsigned char ucMon;
    unsigned char ucMday;
    unsigned char ucWday;
    unsigned char ucHour;
    unsigned char ucMin;
    unsigned char ucSec;
}
tTime
```

Members:

usYear The number of years since 0 AD.
ucMon The month, where January is 0 and December is 11.
ucMday The day of the month.
ucWday The day of the week, where Sunday is 0 and Saturday is 6.
ucHour The number of hours.
ucMin The number of minutes.
ucSec The number of seconds.

Description:

A structure that contains the broken down date and time.

18.2.2 Function Documentation

18.2.2.1 ulocaltime

Converts from seconds to calendar date and time.

Prototype:

```
void
ulocaltime(unsigned long ulTime,
            tTime *psTime)
```

Parameters:

ulTime is the number of seconds.
psTime is a pointer to the time structure that is filled in with the broken down date and time.

Description:

This function converts a number of seconds since midnight GMT on January 1, 1970 (traditional Unix epoch) into the equivalent month, day, year, hours, minutes, and seconds representation.

Returns:

None.

18.2.2.2 umktime

Converts calendar date and time to seconds.

Prototype:

```
unsigned long
umktime(tTime *psTime)
```

Parameters:

psTime is a pointer to the time structure that is filled in with the broken down date and time.

Description:

This function converts the date and time represented by the *psTime* structure pointer to the number of seconds since midnight GMT on January 1, 1970 (traditional Unix epoch).

Returns:

Returns the calendar time and date as seconds. If the conversion was not possible then the function returns (unsigned long)(-1).

18.2.2.3 urand

Generate a new (pseudo) random number

Prototype:

```
int
urand(void)
```

Description:

This function is very similar to the C library `rand()` function. It will generate a pseudo-random number sequence based on the seed value.

Returns:

A pseudo-random number will be returned.

18.2.2.4 usnprintf

A simple `snprintf` function supporting %c, %d, %p, %s, %u, %x, and %X.

Prototype:

```
int
usnprintf(char *pcBuf,
          unsigned long ulSize,
          const char *pcString,
          ...)
```

Parameters:

pcBuf is the buffer where the converted string is stored.

ulSize is the size of the buffer.

pcString is the format string.

... are the optional arguments, which depend on the contents of the format string.

Description:

This function is very similar to the C library `sprintf()` function. Only the following formatting characters are supported:

- `%c` to print a character
- `%d` or `%i` to print a decimal value
- `%s` to print a string
- `%u` to print an unsigned decimal value
- `%x` to print a hexadecimal value using lower case letters
- `%X` to print a hexadecimal value using upper case letters (not lower case letters as would typically be used)
- `%p` to print a pointer as a hexadecimal value
- `%%` to print out a `%` character

For `%d`, `%i`, `%p`, `%s`, `%u`, `%x`, and `%X`, an optional number may reside between the `%` and the format character, which specifies the minimum number of characters to use for that value; if preceded by a 0 then the extra characters will be filled with zeros instead of spaces. For example, `"%8d"` will use eight characters to print the decimal value with spaces added to reach eight; `"%08d"` will use eight characters as well but will add zeros instead of spaces.

The type of the arguments after *pcString* must match the requirements of the format string. For example, if an integer was passed where a string was expected, an error of some kind will most likely occur.

The function will copy at most *ulSize* - 1 characters into the buffer *pcBuf*. One space is reserved in the buffer for the null termination character.

The function will return the number of characters that would be converted as if there were no limit on the buffer size. Therefore it is possible for the function to return a count that is greater than the specified buffer size. If this happens, it means that the output was truncated.

Returns:

Returns the number of characters that were to be stored, not including the NULL termination character, regardless of space in the buffer.

18.2.2.5 `usprintf`

A simple `sprintf` function supporting `%c`, `%d`, `%p`, `%s`, `%u`, `%x`, and `%X`.

Prototype:

```
int
usprintf(char *pcBuf,
         const char *pcString,
         ...)
```

Parameters:

pcBuf is the buffer where the converted string is stored.

pcString is the format string.

... are the optional arguments, which depend on the contents of the format string.

Description:

This function is very similar to the C library `sprintf()` function. Only the following formatting characters are supported:

- `%c` to print a character
- `%d` or `%i` to print a decimal value
- `%s` to print a string
- `%u` to print an unsigned decimal value
- `%x` to print a hexadecimal value using lower case letters
- `%X` to print a hexadecimal value using upper case letters (not lower case letters as would typically be used)
- `%p` to print a pointer as a hexadecimal value
- `%%` to print out a `%` character

For `%d`, `%i`, `%p`, `%s`, `%u`, `%x`, and `%X`, an optional number may reside between the `%` and the format character, which specifies the minimum number of characters to use for that value; if preceded by a 0 then the extra characters will be filled with zeros instead of spaces. For example, `"%8d"` will use eight characters to print the decimal value with spaces added to reach eight; `"%08d"` will use eight characters as well but will add zeros instead of spaces.

The type of the arguments after *pcString* must match the requirements of the format string. For example, if an integer was passed where a string was expected, an error of some kind will most likely occur.

The caller must ensure that the buffer *pcBuf* is large enough to hold the entire converted string, including the null termination character.

Returns:

Returns the count of characters that were written to the output buffer, not including the NULL termination character.

18.2.2.6 `usrand`

Set the random number generator seed.

Prototype:

```
void  
usrand(unsigned long ulSeed)
```

Parameters:

ulSeed is the new seed value to use for the random number generator.

Description:

This function is very similar to the C library `srand()` function. It will set the seed value used in the `urand()` function.

Returns:

None

18.2.2.7 `ustrcasecmp`

Compares two strings without regard to case.

Prototype:

```
int
ustrcasecmp(const char *pcStr1,
            const char *pcStr2)
```

Parameters:

pcStr1 points to the first string to be compared.
pcStr2 points to the second string to be compared.

Description:

This function is very similar to the C library `strcasecmp()` function. It compares two strings without regard to case. The comparison ends if a terminating NULL character is found in either string. In this case, the shorter string is deemed the lesser.

Returns:

Returns 0 if the two strings are equal, -1 if *pcStr1* is less than *pcStr2* and 1 if *pcStr1* is greater than *pcStr2*.

18.2.2.8 `ustrcmp`

Compares two strings.

Prototype:

```
int
ustrcmp(const char *pcStr1,
        const char *pcStr2)
```

Parameters:

pcStr1 points to the first string to be compared.
pcStr2 points to the second string to be compared.

Description:

This function is very similar to the C library `strcmp()` function. It compares two strings, taking case into account. The comparison ends if a terminating NULL character is found in either string. In this case, the shorter string is deemed the lesser.

Returns:

Returns 0 if the two strings are equal, -1 if *pcStr1* is less than *pcStr2* and 1 if *pcStr1* is greater than *pcStr2*.

18.2.2.9 `ustrlen`

Retruns the length of a null-terminated string.

Prototype:

```
int
ustrlen(const char *pcStr)
```


Parameters:

pcStr is a pointer to the string whose length is to be found.

Description:

This function is very similar to the C library `strlen()` function. It determines the length of the null-terminated string passed and returns this to the caller.

This implementation assumes that single byte character strings are passed and will return incorrect values if passed some UTF-8 strings.

Returns:

Returns the length of the string pointed to by *pcStr*.

18.2.2.10 `ustrncmp`

Compares two strings.

Prototype:

```
int
ustrncmp(const char *pcStr1,
         const char *pcStr2,
         int iCount)
```

Parameters:

pcStr1 points to the first string to be compared.

pcStr2 points to the second string to be compared.

iCount is the maximum number of characters to compare.

Description:

This function is very similar to the C library `strncmp()` function. It compares at most *iCount* characters of two strings taking case into account. The comparison ends if a terminating NULL character is found in either string before *iCount* characters are compared. In this case, the shorter string is deemed the lesser.

Returns:

Returns 0 if the two strings are equal, -1 if *pcStr1* is less than *pcStr2* and 1 if *pcStr1* is greater than *pcStr2*.

18.2.2.11 `ustrncpy`

Copies a certain number of characters from one string to another.

Prototype:

```
char *
ustrncpy(char *pcDst,
         const char *pcSrc,
         int iNum)
```

Parameters:

pcDst is a pointer to the destination buffer into which characters are to be copied.

pcSrc is a pointer to the string from which characters are to be copied.

iNum is the number of characters to copy to the destination buffer.

Description:

This function copies at most *iNum* characters from the string pointed to by *pcSrc* into the buffer pointed to by *pcDst*. If the end of *pcSrc* is found before *iNum* characters have been copied, remaining characters in *pcDst* will be padded with zeroes until *iNum* characters have been written. Note that the destination string will only be NULL terminated if the number of characters to be copied is greater than the length of *pcSrc*.

Returns:

Returns *pcDst*.

18.2.2.12 ustrnicmp

Compares two strings without regard to case.

Prototype:

```
int
ustrnicmp(const char *pcStr1,
          const char *pcStr2,
          int iCount)
```

Parameters:

pcStr1 points to the first string to be compared.

pcStr2 points to the second string to be compared.

iCount is the maximum number of characters to compare.

Description:

This function is very similar to the C library `strnicmp()` function. It compares at most *iCount* characters of two strings without regard to case. The comparison ends if a terminating NULL character is found in either string before *iCount* characters are compared. In this case, the shorter string is deemed the lesser.

Returns:

Returns 0 if the two strings are equal, -1 if *pcStr1* is less than *pcStr2* and 1 if *pcStr1* is greater than *pcStr2*.

18.2.2.13 ustrstr

Finds a substring within a string.

Prototype:

```
char *
ustrstr(const char *pcHaystack,
        const char *pcNeedle)
```

Parameters:

pcHaystack is a pointer to the string that will be searched.

pcNeedle is a pointer to the substring that is to be found within *pcHaystack*.

Description:

This function is very similar to the C library `strstr()` function. It scans a string for the first instance of a given substring and returns a pointer to that substring. If the substring cannot be found, a NULL pointer is returned.

Returns:

Returns a pointer to the first occurrence of *pcNeedle* within *pcHaystack* or NULL if no match is found.

18.2.2.14 strtoul

Converts a string into its numeric equivalent.

Prototype:

```
unsigned long
strtoul(const char *pcStr,
        const char **ppcStrRet,
        int iBase)
```

Parameters:

pcStr is a pointer to the string containing the integer.

ppcStrRet is a pointer that will be set to the first character past the integer in the string.

iBase is the radix to use for the conversion; can be zero to auto-select the radix or between 2 and 16 to explicitly specify the radix.

Description:

This function is very similar to the C library `strtoul()` function. It scans a string for the first token (that is, non-white space) and converts the value at that location in the string into an integer value.

Returns:

Returns the result of the conversion.

18.2.2.15 uvsnprintf

A simple `vsnprintf` function supporting %c, %d, %p, %s, %u, %x, and %X.

Prototype:

```
int
uvsnprintf(char *pcBuf,
            unsigned long ulSize,
            const char *pcString,
            va_list vaArgP)
```

Parameters:

pcBuf points to the buffer where the converted string is stored.

ulSize is the size of the buffer.

pcString is the format string.

vaArgP is the list of optional arguments, which depend on the contents of the format string.

Description:

This function is very similar to the C library `vsnprintf()` function. Only the following formatting characters are supported:

- `%c` to print a character
- `%d` or `%i` to print a decimal value
- `%s` to print a string
- `%u` to print an unsigned decimal value
- `%x` to print a hexadecimal value using lower case letters
- `%X` to print a hexadecimal value using upper case letters (not lower case letters as would typically be used)
- `%p` to print a pointer as a hexadecimal value
- `%%` to print out a `%` character

For `%d`, `%i`, `%p`, `%s`, `%u`, `%x`, and `%X`, an optional number may reside between the `%` and the format character, which specifies the minimum number of characters to use for that value; if preceded by a 0 then the extra characters will be filled with zeros instead of spaces. For example, `"%8d"` will use eight characters to print the decimal value with spaces added to reach eight; `"%08d"` will use eight characters as well but will add zeroes instead of spaces.

The type of the arguments after *pcString* must match the requirements of the format string. For example, if an integer was passed where a string was expected, an error of some kind will most likely occur.

The *ulSize* parameter limits the number of characters that will be stored in the buffer pointed to by *pcBuf* to prevent the possibility of a buffer overflow. The buffer size should be large enough to hold the expected converted output string, including the null termination character.

The function will return the number of characters that would be converted as if there were no limit on the buffer size. Therefore it is possible for the function to return a count that is greater than the specified buffer size. If this happens, it means that the output was truncated.

Returns:

Returns the number of characters that were to be stored, not including the NULL termination character, regardless of space in the buffer.

18.3 Programming Example

The following example shows how to use some of the micro standard library functions.

```
unsigned long ulValue;
char pcBuffer[32];
tTime sTime;

//
// Convert the number in pcBuffer (previous read from somewhere) into an
// integer. Note that this supports converting decimal values (such as
// 4583), octal values (such as 036583), and hexadecimal values (such as
// 0x3425).
//
ulValue = strtoul(pcBuffer, 0, 0);

//
// Convert that integer from a number of seconds into a broken down date.
```

```
//  
ulocaltime(ulValue, &sTime);  
  
//  
// Print out the corresponding time of day in military format.  
//  
usprintf(pcBuffer, "%02d:%02d", sTime.ucHour, sTime.ucMin);
```


19 UART Standard IO Module

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19.1 Introduction

The UART standard IO module provides a simple interface to a UART that is similar to the standard IO package available in the C library. Only a very small subset of the normal functions are provided; [UARTprintf\(\)](#) is an equivalent to the C library `printf()` function and [UARTgets\(\)](#) is an equivalent to the C library `fgets()` function.

This module is contained in `utils/uartstdio.c`, with `utils/uartstdio.h` containing the API definitions for use by applications.

19.1.1 Unbuffered Operation

Unbuffered operation is selected by not defining **UART_BUFFERED** when building the UART standard IO module. In unbuffered mode, calls to the module will not return until the operation has been completed. So, for example, a call to [UARTprintf\(\)](#) will not return until the entire string has been placed into the UART's FIFO. If it is not possible for the function to complete its operation immediately, it will busy wait.

19.1.2 Buffered Operation

Buffered operation is selected by defining **UART_BUFFERED** when building the UART standard IO module. In buffered mode, there is a larger UART data FIFO in SRAM that extends the size of the hardware FIFO. Interrupts from the UART are used to transfer data between the SRAM buffer and the hardware FIFO. It is the responsibility of the application to ensure that [UARTStdioIntHandler\(\)](#) is called when the UART interrupt occurs; typically this is accomplished by placing it in the vector table in the startup code for the application.

In addition to providing a larger UART buffer, the behavior of [UARTprintf\(\)](#) is slightly modified. If the output buffer is full, [UARTprintf\(\)](#) will discard the remaining characters from the string instead of waiting until space becomes available in the buffer. If this behavior is not desired, [UARTFlushTx\(\)](#) may be called to ensure that the transmit buffer is emptied prior to adding new data via [UARTprintf\(\)](#) (though this will not work if the string to be printed is larger than the buffer).

[UARTPeek\(\)](#) can be used to determine whether a line end is present prior to calling [UARTgets\(\)](#) if a non-blocking operation is required. In cases where the buffer supplied on [UARTgets\(\)](#) fills before a line termination character is received, the call will return with a full buffer.

19.2 API Functions

Functions

- void [UARTEchoSet](#) (tBoolean bEnable)
- void [UARTFlushRx](#) (void)
- void [UARTFlushTx](#) (tBoolean bDiscard)
- unsigned char [UARTgetc](#) (void)
- int [UARTgets](#) (char *pcBuf, unsigned long ulLen)
- int [UARTPeek](#) (unsigned char ucChar)
- void [UARTprintf](#) (const char *pcString,...)
- int [UARTRxBytesAvail](#) (void)
- void [UARTStdioConfig](#) (unsigned long ulPortNum, unsigned long ulBaud, unsigned long ulSrcClock)
- void [UARTStdioInit](#) (unsigned long ulPortNum)
- void [UARTStdioInitExpClk](#) (unsigned long ulPortNum, unsigned long ulBaud)
- void [UARTStdioIntHandler](#) (void)
- int [UARTTxBytesFree](#) (void)
- int [UARTwrite](#) (const char *pcBuf, unsigned long ulLen)

19.2.1 Function Documentation

19.2.1.1 UARTEchoSet

Enables or disables echoing of received characters to the transmitter.

Prototype:

```
void
UARTEchoSet (tBoolean bEnable)
```

Parameters:

bEnable must be set to **true** to enable echo or **false** to disable it.

Description:

This function, available only when the module is built to operate in buffered mode using **UART_BUFFERED**, may be used to control whether or not received characters are automatically echoed back to the transmitter. By default, echo is enabled and this is typically the desired behavior if the module is being used to support a serial command line. In applications where this module is being used to provide a convenient, buffered serial interface over which application-specific binary protocols are being run, however, echo may be undesirable and this function can be used to disable it.

Returns:

None.

19.2.1.2 UARTFlushRx

Flushes the receive buffer.

Prototype:

```
void  
UARTFlushRx(void)
```

Description:

This function, available only when the module is built to operate in buffered mode using **UART_BUFFERED**, may be used to discard any data received from the UART but not yet read using [UARTgets\(\)](#).

Returns:

None.

19.2.1.3 UARTFlushTx

Flushes the transmit buffer.

Prototype:

```
void  
UARTFlushTx(tBoolean bDiscard)
```

Parameters:

bDiscard indicates whether any remaining data in the buffer should be discarded (**true**) or transmitted (**false**).

Description:

This function, available only when the module is built to operate in buffered mode using **UART_BUFFERED**, may be used to flush the transmit buffer, either discarding or transmitting any data received via calls to [UARTprintf\(\)](#) that is waiting to be transmitted. On return, the transmit buffer will be empty.

Returns:

None.

19.2.1.4 UARTgetc

Read a single character from the UART, blocking if necessary.

Prototype:

```
unsigned char  
UARTgetc(void)
```

Description:

This function will receive a single character from the UART and store it at the supplied address.

In both buffered and unbuffered modes, this function will block until a character is received. If non-blocking operation is required in buffered mode, a call to [UARTRxAvail\(\)](#) may be made to determine whether any characters are currently available for reading.

Returns:

Returns the character read.

19.2.1.5 UARTgets

A simple UART based get string function, with some line processing.

Prototype:

```
int
UARTgets(char *pcBuf,
          unsigned long ulLen)
```

Parameters:

pcBuf points to a buffer for the incoming string from the UART.

ulLen is the length of the buffer for storage of the string, including the trailing 0.

Description:

This function will receive a string from the UART input and store the characters in the buffer pointed to by *pcBuf*. The characters will continue to be stored until a termination character is received. The termination characters are CR, LF, or ESC. A CRLF pair is treated as a single termination character. The termination characters are not stored in the string. The string will be terminated with a 0 and the function will return.

In both buffered and unbuffered modes, this function will block until a termination character is received. If non-blocking operation is required in buffered mode, a call to [UARTPeek\(\)](#) may be made to determine whether a termination character already exists in the receive buffer prior to calling [UARTgets\(\)](#).

Since the string will be null terminated, the user must ensure that the buffer is sized to allow for the additional null character.

Returns:

Returns the count of characters that were stored, not including the trailing 0.

19.2.1.6 UARTPeek

Looks ahead in the receive buffer for a particular character.

Prototype:

```
int
UARTPeek(unsigned char ucChar)
```

Parameters:

ucChar is the character that is to be searched for.

Description:

This function, available only when the module is built to operate in buffered mode using **UART_BUFFERED**, may be used to look ahead in the receive buffer for a particular character and report its position if found. It is typically used to determine whether a complete line of user input is available, in which case ucChar should be set to CR ('\r') which is used as the line end marker in the receive buffer.

Returns:

Returns -1 to indicate that the requested character does not exist in the receive buffer. Returns a non-negative number if the character was found in which case the value represents the position of the first instance of *ucChar* relative to the receive buffer read pointer.

19.2.1.7 UARTprintf

A simple UART based printf function supporting %c, %d, %p, %s, %u, %x, and %X.

Prototype:

```
void
UARTprintf(const char *pcString,
           ...)
```

Parameters:

pcString is the format string.

... are the optional arguments, which depend on the contents of the format string.

Description:

This function is very similar to the C library `fprintf()` function. All of its output will be sent to the UART. Only the following formatting characters are supported:

- %c to print a character
- %d or %i to print a decimal value
- %s to print a string
- %u to print an unsigned decimal value
- %x to print a hexadecimal value using lower case letters
- %X to print a hexadecimal value using upper case letters (not lower case letters as would typically be used)
- %p to print a pointer as a hexadecimal value
- %% to print out a % character

For %s, %d, %i, %u, %p, %x, and %X, an optional number may reside between the % and the format character, which specifies the minimum number of characters to use for that value; if preceded by a 0 then the extra characters will be filled with zeros instead of spaces. For example, "%8d" will use eight characters to print the decimal value with spaces added to reach eight; "%08d" will use eight characters as well but will add zeroes instead of spaces.

The type of the arguments after *pcString* must match the requirements of the format string. For example, if an integer was passed where a string was expected, an error of some kind will most likely occur.

Returns:

None.

19.2.1.8 UARTRxBytesAvail

Returns the number of bytes available in the receive buffer.

Prototype:

```
int
UARTRxBytesAvail(void)
```

Description:

This function, available only when the module is built to operate in buffered mode using **UART_BUFFERED**, may be used to determine the number of bytes of data currently available in the receive buffer.

Returns:

Returns the number of available bytes.

19.2.1.9 UARTStdioConfig

Configures the UART console.

Prototype:

```
void
UARTStdioConfig(unsigned long ulPortNum,
                 unsigned long ulBaud,
                 unsigned long ulSrcClock)
```

Parameters:

ulPortNum is the number of UART port to use for the serial console (0-2)

ulBaud is the bit rate that the UART is to be configured to use.

ulSrcClock is the frequency of the source clock for the UART module.

Description:

This function will configure the specified serial port to be used as a serial console. The serial parameters are set to the baud rate specified by the *ulBaud* parameter and use 8 bit, no parity, and 1 stop bit.

This function must be called prior to using any of the other UART console functions: [UART-printf\(\)](#) or [UARTgets\(\)](#). This function assumes that the caller has previously configured the relevant UART pins for operation as a UART rather than as GPIOs.

Returns:

None.

19.2.1.10 UARTStdioInit

Initializes the UART console.

Prototype:

```
void
UARTStdioInit(unsigned long ulPortNum)
```

Parameters:

ulPortNum is the number of UART port to use for the serial console (0-2)

Description:

This function will initialize the specified serial port to be used as a serial console. The serial parameters will be set to 115200, 8-N-1. An application wishing to use a different baud rate may call [UARTStdioInitExpClk\(\)](#) instead of this function.

This function or [UARTStdioInitExpClk\(\)](#) must be called prior to using any of the other UART console functions: [UARTprintf\(\)](#) or [UARTgets\(\)](#). In order for this function to work correctly, [SysCtlClockSet\(\)](#) must be called prior to calling this function.

It is assumed that the caller has previously configured the relevant UART pins for operation as a UART rather than as GPIOs.

Returns:

None.

19.2.1.11 UARTStdioInitExpClk

Initializes the UART console and allows the baud rate to be selected.

Prototype:

```
void
UARTStdioInitExpClk(unsigned long ulPortNum,
                    unsigned long ulBaud)
```

Parameters:

ulPortNum is the number of UART port to use for the serial console (0-2)

ulBaud is the bit rate that the UART is to be configured to use.

Description:

This function will initialize the specified serial port to be used as a serial console. The serial parameters will be set to 8-N-1 and the bit rate set according to the value of the *ulBaud* parameter.

This function or [UARTStdioInit\(\)](#) must be called prior to using any of the other UART console functions: [UARTprintf\(\)](#) or [UARTgets\(\)](#). In order for this function to work correctly, [SysCtlClockSet\(\)](#) must be called prior to calling this function. An application wishing to use 115,200 baud may call [UARTStdioInit\(\)](#) instead of this function but should not call both functions.

It is assumed that the caller has previously configured the relevant UART pins for operation as a UART rather than as GPIOs.

Returns:

None.

19.2.1.12 UARTStdioIntHandler

Handles UART interrupts.

Prototype:

```
void
UARTStdioIntHandler(void)
```

Description:

This function handles interrupts from the UART. It will copy data from the transmit buffer to the UART transmit FIFO if space is available, and it will copy data from the UART receive FIFO to the receive buffer if data is available.

Returns:

None.

19.2.1.13 UARTTxBytesFree

Returns the number of bytes free in the transmit buffer.

Prototype:

```
int
UARTTxBytesFree(void)
```

Description:

This function, available only when the module is built to operate in buffered mode using **UART_BUFFERED**, may be used to determine the amount of space currently available in the transmit buffer.

Returns:

Returns the number of free bytes.

19.2.1.14 UARTwrite

Writes a string of characters to the UART output.

Prototype:

```
int
UARTwrite(const char *pcBuf,
          unsigned long ulLen)
```

Parameters:

pcBuf points to a buffer containing the string to transmit.

ulLen is the length of the string to transmit.

Description:

This function will transmit the string to the UART output. The number of characters transmitted is determined by the *ulLen* parameter. This function does no interpretation or translation of any characters. Since the output is sent to a UART, any LF (/n) characters encountered will be replaced with a CRLF pair.

Besides using the *ulLen* parameter to stop transmitting the string, if a null character (0) is encountered, then no more characters will be transmitted and the function will return.

In non-buffered mode, this function is blocking and will not return until all the characters have been written to the output FIFO. In buffered mode, the characters are written to the UART transmit buffer and the call returns immediately. If insufficient space remains in the transmit buffer, additional characters are discarded.

Returns:

Returns the count of characters written.

19.3 Programming Example

The following example shows how to use the UART standard IO module to write a string to the UART “console”.

```
//  
// Configure the appropriate pins as UART pins; in this case, PA0/PA1 are  
// used for UART0.  
//  
SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOA);  
GPIOPinTypeUART(GPIO_PORTA_BASE, GPIO_PIN_0 | GPIO_PIN_1);  
  
//  
// Initialize the UART standard IO module.  
//  
UARTStdioInit(0);  
  
//  
// Print a string.  
//  
UARTprintf("Hello world!\n");
```

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