

# **MSP430® Peripheral Driver Library**

## **USER'S GUIDE**

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# 1 Introduction

The Texas Instruments® MSP430® Peripheral Driver Library is a set of drivers for accessing the peripherals found on the MSP430 family of microcontrollers. While they are not drivers in the pure operating system sense (that is, they do not have a common interface and do not connect into a global device driver infrastructure), they do provide a mechanism that makes it easy to use the device's peripherals.

The capabilities and organization of the drivers are governed by the following design goals:

- They are written entirely in C except where absolutely not possible.
- They demonstrate how to use the peripheral in its common mode of operation.
- They are easy to understand.
- They are reasonably efficient in terms of memory and processor usage.
- They are as self-contained as possible.
- Where possible, computations that can be performed at compile time are done there instead of at run time.
- They can be built with more than one tool chain.

Some consequences of these design goals are:

- The drivers are not necessarily as efficient as they could be (from a code size and/or execution speed point of view). While the most efficient piece of code for operating a peripheral would be written in assembly and custom tailored to the specific requirements of the application, further size optimizations of the drivers would make them more difficult to understand.
- The drivers do not support the full capabilities of the hardware. Some of the peripherals provide complex capabilities which cannot be utilized by the drivers in this library, though the existing code can be used as a reference upon which to add support for the additional capabilities.
- The APIs have a means of removing all error checking code. Because the error checking is usually only useful during initial program development, it can be removed to improve code size and speed.

For many applications, the drivers can be used as is. But in some cases, the drivers will have to be enhanced or rewritten in order to meet the functionality, memory, or processing requirements of the application. If so, the existing driver can be used as a reference on how to operate the peripheral.

Each MSP430ware driverlib API takes in the base address of the corresponding peripheral as the first parameter. This base address is obtained from the msp430 device specific header files (or from the device datasheet). The example code for the various peripherals show how base address is used. When using CCS, the eclipse shortcut "Ctrl + Space" helps. Type `__MSP430` and "Ctrl + Space", and the list of base addresses from the included device specific header files is listed.

The following tool chains are supported:

- IAR Embedded Workbench®
- Texas Instruments Code Composer Studio™



## 2 How to create a new project that uses Driverlib

To create a driverlib project from scratch An emptyProject has been created for the convenience of the user so that he can create a project that uses driverlib. This is available in "C:\ti\msp430\MSP430ware\_x\_xx\_xx\_xx\examples\driverlib\5xx\_6xx\emptyProject\IAR" "C:\ti\msp430\MSP430ware\_x\_xx\_xx\_xx\examples\driverlib\5xx\_6xx\emptyProject\CCS" or the corresponding relative path where MSP430ware is installed. The features of the emptyProject are

- Includes driverlib library file by default
- Includes a main.c by default that has the following statements

```
"#include "inc/hw_memmap.h"
```

```
void main (void) { } "
```

- Project is build by default for MSP430F5438A and has a large data model since driverlib is built by default for large data model.
- The project include path has the following added "C:\ti\msp430\MSP430ware\_x\_xx\_xx\_xx" or the corresponding path where MSP430ware is installed.





## 3 10-Bit Analog-to-Digital Converter (ADC10)

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### 3.1 Introduction

The 10-Bit Analog-to-Digital (ADC10) API provides a set of functions for using the MSP430Ware ADC10 modules. Functions are provided to initialize the ADC10 modules, setup signal sources and reference voltages, and manage interrupts for the ADC10 modules.

The ADC10 module provides the ability to convert analog signals into a digital value in respect to given reference voltages. The ADC10 can generate digital values from 0 to  $V_{CC}$  with an 8- or 10-bit resolution. It operates in 2 different sampling modes, and 4 different conversion modes. The sampling modes are extended sampling and pulse sampling, in extended sampling the sample/hold signal must stay high for the duration of sampling, while in pulse mode a sampling timer is setup to start on a rising edge of the sample/hold signal and sample for a specified amount of clock cycles. The 4 conversion modes are single-channel single conversion, sequence of channels single-conversion, repeated single channel conversions, and repeated sequence of channels conversions.

The ADC10 module can generate multiple interrupts. An interrupt can be asserted when a conversion is complete, when a conversion is about to overwrite the converted data in the memory buffer before it has been read out, and/or when a conversion is about to start before the last conversion is complete. The ADC10 also has a window comparator feature which asserts interrupts when the input signal is above a high threshold, below a low threshold, or between the two at any given moment.

This driver is contained in `driverlib/5xx_6xx/adc10.c`, with `driverlib/5xx_6xx/adc10.h` containing the API definitions for use by applications.

### 3.2 API Functions

The ADC10 API is broken into three groups of functions: those that deal with initialization and conversions, those that handle interrupts, and those that handle auxiliary features of the ADC10.

The ADC10 initialization and conversion functions are

- `ADC10_init`
- `ADC10_memoryConfigure`
- `ADC10_setupSamplingTimer`
- `ADC10_disableSamplingTimer`
- `ADC10_setWindowComp`
- `ADC10_startConversion`
- `ADC10_disableConversions`
- `ADC10_getResults`
- `ADC10_isBusy`

The ADC10 interrupts are handled by

- `ADC10_enableInterrupt`
- `ADC10_disableInterrupt`
- `ADC10_clearInterrupt`
- `ADC10_getInterruptStatus`

Auxiliary features of the ADC10 are handled by

- `ADC10_setResolution`

- ADC10\_setSampleHoldSignalInversion
- ADC10\_setDataReadBackFormat
- ADC10\_enableReferenceBurst
- ADC10\_disableReferenceBurst
- ADC10\_setReferenceBufferSamplingRate
- ADC10\_getMemoryAddressForDMA
- ADC10\_enable
- ADC10\_disable

## 3.3 Programming Example

The following example shows how to initialize and use the ADC10 API to start a single channel, single conversion.

```
// Initialize ADC10 with ADC10's built-in oscillator
ADC10_init ( __MSP430_BASEADDRESS_ADC10__,
             ADC10_SAMPLEHOLDSOURCE_SC,
             ADC10_CLOCKSOURCE_ADC10OSC,
             ADC10_CLOCKDIVIDEBY_1);

//Switch ON ADC10
ADC10_enable ( __MSP430_BASEADDRESS_ADC10__ );

// Setup sampling timer to sample-and-hold for 16 clock cycles
ADC10_setupSamplingTimer ( __MSP430_BASEADDRESS_ADC10__,
                          ADC10_CYCLEHOLD_16_CYCLES,
                          FALSE);

// Configure the Input to the Memory Buffer with the specified Reference Voltages
ADC10_memoryConfigure ( __MSP430_BASEADDRESS_ADC10__,
                       ADC10_INPUT_A0,
                       ADC10_VREF_AVCC, // Vref+ = AVcc
                       ADC10_VREF_AVSS  // Vref- = AVss
                       );

while (1)
{
    // Start a single conversion, no repeating or sequences.
    ADC10_startConversion ( __MSP430_BASEADDRESS_ADC10__,
                           ADC10_SINGLECHANNEL);

    // Wait for the Interrupt Flag to assert
    while( !(ADC10_getInterruptStatus ( __MSP430_BASEADDRESS_ADC10__, ADC10IFG0) ) );

    // Clear the Interrupt Flag and start another conversion
    ADC10_clearInterrupt ( __MSP430_BASEADDRESS_ADC10__, ADC10IFG0);
}
```

## 4 12-Bit Analog-to-Digital Converter (ADC12)

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### 4.1 Introduction

The 12-Bit Analog-to-Digital (ADC12) API provides a set of functions for using the MSP430Ware ADC12 modules. Functions are provided to initialize the ADC12 modules, setup signal sources and reference voltages for each memory buffer, and manage interrupts for the ADC12 modules.

The ADC12 module provides the ability to convert analog signals into a digital value in respect to given reference voltages. The ADC12 can generate digital values from 0 to Vcc with an 8-, 10- or 12-bit resolution, with 16 different memory buffers to store conversion results. It operates in 2 different sampling modes, and 4 different conversion modes. The sampling modes are extended sampling and pulse sampling, in extended sampling the sample/hold signal must stay high for the duration of sampling, while in pulse mode a sampling timer is setup to start on a rising edge of the sample/hold signal and sample for a specified amount of clock cycles. The 4 conversion modes are single-channel single conversion, sequence of channels single-conversion, repeated single channel conversions, and repeated sequence of channels conversions.

The ADC12 module can generate multiple interrupts. An interrupt can be asserted for each memory buffer when a conversion is complete, or when a conversion is about to overwrite the converted data in any of the memory buffers before it has been read out, and/or when a conversion is about to start before the last conversion is complete.

This driver is contained in `driverlib/5xx_6xx/adc12.c`, with `driverlib/5xx_6xx/adc12.h` containing the API definitions for use by applications.

### 4.2 API Functions

The ADC12 API is broken into three groups of functions: those that deal with initialization and conversions, those that handle interrupts, and those that handle auxiliary features of the ADC12.

The ADC12 initialization and conversion functions are

- `ADC12_init`
- `ADC12_memoryConfigure`
- `ADC12_setupSamplingTimer`
- `ADC12_disableSamplingTimer`
- `ADC12_startConversion`
- `ADC12_disableConversions`
- `ADC12_readResults`
- `ADC12_isBusy`

The ADC12 interrupts are handled by

- ADC12\_enableInterrupt
- ADC12\_disableInterrupt
- ADC12\_clearInterrupt
- ADC12\_getInterruptStatus

Auxiliary features of the ADC12 are handled by

- ADC12\_setResolution
- ADC12\_setSampleHoldSignalInversion
- ADC12\_setDataReadBackFormat
- ADC12\_enableReferenceBurst
- ADC12\_disableReferenceBurst
- ADC12\_setReferenceBufferSamplingRate
- ADC12\_getMemoryAddressForDMA
- ADC12\_enable
- ADC12\_disable

## 4.3 Programming Example

The following example shows how to initialize and use the ADC12 API to start a single channel, single conversion.

```
// Initialize ADC12 with ADC12's built-in oscillator
ADC12_init (__MSP430_BASEADDRESS_ADC12__,
            ADC12_SAMPLEHOLDSOURCE_SC,
            ADC12_CLOCKSOURCE_ADC12OSC,
            ADC12_CLOCKDIVIDEBY_1);

//Switch ON ADC12
ADC12_enable(__MSP430_BASEADDRESS_ADC12__);

// Setup sampling timer to sample-and-hold for 16 clock cycles
ADC12_setupSamplingTimer (__MSP430_BASEADDRESS_ADC12__,
                           ADC12_CYCLEHOLD_64_CYCLES,
                           ADC12_CYCLEHOLD_4_CYCLES,
                           FALSE);

// Configure the Input to the Memory Buffer with the specified Reference Voltages
ADC12_memoryConfigure (__MSP430_BASEADDRESS_ADC12__,
                       ADC12_MEMORY_0,
                       ADC12_INPUT_A0,
                       ADC12_VREF_AVCC, // Vref+ = AVcc
                       ADC12_VREF_AVSS, // Vref- = AVss
                       FALSE
                       );

while (1)
{
    // Start a single conversion, no repeating or sequences.
    ADC12_startConversion (__MSP430_BASEADDRESS_ADC12__,
                           ADC12_MEMORY_0,
                           ADC12_SINGLECHANNEL);

    // Wait for the Interrupt Flag to assert
    while( !(ADC12_getInterruptStatus(__MSP430_BASEADDRESS_ADC12__,ADC12IFG0)) );
}
```

```
        // Clear the Interrupt Flag and start another conversion
        ADC12_clearInterrupt (__MSP430_BASEADDRESS_ADC12__, ADC12IFG0);
    }
```



## 5 Comparator (COMPB)

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### 5.1 Introduction

The Comparator B (COMPB) API provides a set of functions for using the MSP430Ware COMPB modules. Functions are provided to initialize the COMPB modules, setup reference voltages for input, and manage interrupts for the COMPB modules.

The COMPB module provides the ability to compare two analog signals and use the output in software and on an output pin. The output represents whether the signal on the positive terminal is higher than the signal on the negative terminal. The COMPB may be used to generate a hysteresis. There are 16 different inputs that can be used, as well as the ability to short 2 input together. The COMPB module also has control over the REF module to generate a reference voltage as an input.

The COMPB module can generate multiple interrupts. An interrupt may be asserted for the output, with separate interrupts on whether the output rises, or falls.

This driver is contained in `driverlib/5xx_6xx/compb.c`, with `driverlib/5xx_6xx/compb.h` containing the API definitions for use by applications.

### 5.2 API Functions

The COMPB API is broken into three groups of functions: those that deal with initialization and output, those that handle interrupts, and those that handle auxiliary features of the COMPB.

The COMPB initialization and output functions are

- COMPB\_init
- COMPB\_setReferenceVoltage
- COMPB\_enable
- COMPB\_disable
- COMPB\_outputValue

The COMPB interrupts are handled by

- COMPB\_enableInterrupt
- COMPB\_disableInterrupt
- COMPB\_clearInterrupt
- COMPB\_getInterruptStatus
- COMPB\_interruptSetEdgeDirection
- COMPB\_interruptToggleEdgeDirection

Auxiliary features of the COMPB are handled by

- COMPB\_enableShortOfInputs
- COMPB\_disableShortOfInputs
- COMPB\_disableInputBuffer
- COMPB\_enableInputBuffer
- COMPB\_IOSwap

## 5.3 Programming Example

The following example shows how to initialize and use the COMPB API to turn on an LED when the input to the positive terminal is highed than the input to the negative terminal.

```
// Initialize the Comparator B module
/* Base Address of Comparator B,
   Pin CB0 to Positive(+) Terminal,
   Reference Voltage to Negative(-) Terminal,
   Normal Power Mode,
   Output Filter On with minimal delay,
   Non-Inverted Output Polarity
*/
COMPB_init(__MSP430_BASEADDRESS_COMPB__,
           COMPB_INPUT0,
           COMPB_VREF,
           COMPB_POWERMODE_NORMALMODE,
           COMPB_FILTEROUTPUT_DLYLVL1,
           COMPB_NORMALOUTPUTPOLARITY
           );

// Set the reference voltage that is being supplied to the (-) terminal
/* Base Address of Comparator B,
   Reference Voltage of 2.0 V,
   Upper Limit of 2.0*(32/32) = 2.0V,
   Lower Limit of 2.0*(32/32) = 2.0V
*/
COMPB_setReferenceVoltage(__MSP430_BASEADDRESS_COMPB__,
                          COMPB_VREFBASE2_5V,
                          32,
                          32
                          );

// Allow power to Comparator module
COMPB_enable(__MSP430_BASEADDRESS_COMPB__);

// delay for the reference to settle
__delay_cycles(75);
```



## 6 Cyclical Redundancy Check (CRC)

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### 6.1 Introduction

The Cyclic Redundancy Check (CRC) API provides a set of functions for using the MSP430Ware CRC module. Functions are provided to initialize the CRC and create a CRC signature to check the validity of data. This is mostly useful in the communication of data, or as a startup procedure to as a more complex and accurate check of data.

The CRC module offers no interrupts and is used only to generate CRC signatures to verify against pre-made CRC signatures (Checksums).

This driver is contained in `driverlib/5xx_6xx/crc.c`, with `driverlib/5xx_6xx/crc.h` containing the API definitions for use by applications.

### 6.2 API Functions

The CRC API is one group that controls the CRC module.

- `CRC_setSeed`
- `CRC_setData`
- `CRC_setSignatureByteReversed`
- `CRC_getSignature`
- `CRC_getResult`
- `CRC_getResultBitReversed`

### 6.3 Programming Example

The following example shows how to initialize and use the CRC API to generate a CRC signature on an array of data that can be included in a UART message with the data to check for validity.

```
unsigned int crcSeed = 0xBEEF;
unsigned int data[] = {0x0123,
                      0x4567,
                      0x8910,
                      0x1112,
                      0x1314};

unsigned int crcResult;
int i;

// Stop WDT
WDT_hold(__MSP430_BASEADDRESS_WDT_A__);
```

```
// Set P1.0 as an output
GPIO_setAsOutputPin(__MSP430_BASEADDRESS_PORT1_R__,
                    GPIO_PORT_P1,
                    GPIO_PIN0);

// Set the CRC seed
CRC_setSeed(__MSP430_BASEADDRESS_CRC__,
            crcSeed);

for(i=0; i<5; i++)
{
    // Add all of the values into the CRC signature
    CRC_setData(__MSP430_BASEADDRESS_CRC__,
                data[i]);
}

// Save the current CRC signature checksum to be compared for later
crcResult = CRC_getResult(__MSP430_BASEADDRESS_CRC__);
```

## 7 12-bit Digital-to-Analog Converter (DAC12)

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### 7.1 Introduction

The 12-Bit Digital-to-Analog (DAC12) API provides a set of functions for using the MSP430Ware DAC12 modules. Functions are provided to initialize setup the DAC12 modules, calibrate the output signal, and manage the interrupts for the DAC12 modules.

The DAC12 module provides the ability to convert digital values into an analog signal for output to a pin. The DAC12 can generate signals from 0 to Vcc from an 8- or 12-bit value. There can be one or two DAC12 modules in a device, and if there are two they can be grouped together to create two analog signals simultaneously. There are 3 ways to latch data in to the DAC module, and those are by software with the startConversion API function call, as well as by the Timer A output of CCR1 or Timer B output of CCR2.

The calibration API will unlock and start calibration, then wait for the calibration to end before locking it back up, all in one API. There are also functions to read out the calibration data, as well as be able to set it manually.

The DAC12 module can generate one interrupt for each DAC module. It will generate the interrupt when the data has been latched into the DAC module to be output into an analog signal.

This driver is contained in `driverlib/5xx_6xx/dac12.c`, with `driverlib/5xx_6xx/dac12.h` containing the API definitions for use by applications.

### 7.2 API Functions

The DAC12 API is broken into three groups of functions: those that deal with initialization and conversions, those that deal with calibration of the output, and those that handle interrupts.

The DAC12 initialization and conversion functions are

- DAC12\_init
- DAC12\_setAmplifierSetting
- DAC12\_disable
- DAC12\_enableGrouping
- DAC12\_disableGrouping
- DAC12\_enableConversions
- DAC12\_setData
- DAC12\_disableConversions
- DAC12\_setResolution
- DAC12\_setInputDataFormat
- DAC12\_getDataBufferMemoryAddressForDMA

Calibration features of the DAC12 are handled by

- DAC12\_calibrateOutput
- DAC12\_getCalibrationData
- DAC12\_setCalibrationOffset

The DAC12 interrupts are handled by

- DAC12\_enableInterrupt
- DAC12\_disableInterrupt
- DAC12\_getInterruptStatus
- DAC12\_clearInterrupt

## 7.3 Programming Example

The following example shows how to initialize and use the DAC12 API to output a 1.5V analog signal.

```
DAC12_init ( __MSP430_BASEADDRESS_DAC12_2__,  
            DAC12_SUBMODULE_0,           // Initialize DAC12_0  
            DAC12_OUTPUT_1,              // Choose P6.6 as output  
            DAC12_VREF_AVCC,              // Use AVcc as Vref+  
            DAC12_VREFx1,                 // Multiply Vout by 1  
            DAC12_AMP_MEDIN_MEDOUT,       // Use medium settling speed/current  
            DAC12_TRIGGER_ENCBYPASS       // Auto trigger as soon as data is set  
            );  
  
// Calibrate output buffer for DAC12_0  
DAC12_calibrateOutput ( __MSP430_BASEADDRESS_DAC12_2__,  
                       DAC12_SUBMODULE_0 );  
  
DAC12_setData ( __MSP430_BASEADDRESS_DAC12_2__,  
               DAC12_SUBMODULE_0,         // Set 0x7FF (~1.5V)  
               0x7FF,                     // into data buffer for DAC12_0  
               );
```

## 8 Direct Memory Access (DMA)

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### 8.1 Introduction

The Direct Memory Access (DMA) API provides a set of functions for using the MSP430Ware DMA modules. Functions are provided to initialize and setup each DMA channel with the source and destination addresses, manage the interrupts for each channel, and set bits that affect all DMA channels.

The DMA module provides the ability to move data from one address in the device to another, and that includes other peripheral addresses to RAM or vice-versa, all without the actual use of the CPU. Please be advised, that the DMA module does halt the CPU for 2 cycles while transferring, but does not have to edit any registers or anything. The DMA can transfer by bytes or words at a time, and will automatically increment or decrement the source or destination address if desired. There are also 6 different modes to transfer by, including single-transfer, block-transfer, and burst-block-transfer, as well as repeated versions of those three different kinds which allows transfers to be repeated without having re-enable transfers.

The DMA settings that affect all DMA channels include prioritization, from a fixed priority to dynamic round-robin priority. Another setting that can be changed is when transfers occur, the CPU may be in a read-modify-write operation which can be disastrous to time sensitive material, so this can be disabled. And Non-Maskable-Interrupts can indeed be maskable to the DMA module if not enabled.

The DMA module can generate one interrupt per channel. The interrupt is only asserted when the specified amount of transfers has been completed. With single-transfer, this occurs when that many single transfers have occurred, while with block or burst-block transfers, once the block is completely transferred the interrupt is asserted.

### 8.2 API Functions

The DMA API is broken into three groups of functions: those that deal with initialization and transfers, those that handle interrupts, and those that affect all DMA channels.

The DMA initialization and transfer functions are: `DMA_init` `DMA_setSrcAddress` `DMA_setDstAddress` `DMA_enableTransfers` `DMA_disableTransfers` `DMA_startTransfer` `DMA_setTransferSize`

The DMA interrupts are handled by: `DMA_enableInterrupt` `DMA_disableInterrupt` `DMA_getInterruptStatus` `DMA_clearInterrupt` `DMA_NMIAbortStatus` `DMA_clearNMIAbort`

Features of the DMA that affect all channels are handled by: `DMA_disableTransferDuringReadModifyWrite` `DMA_enableTransferDuringReadModifyWrite` `DMA_enableRoundRobinPriority` `DMA_disableRoundRobinPriority` `DMA_enableNMIAbort` `DMA_disableNMIAbort`

## 8.3 Programming Example

The following example shows how to initialize and use the DMA API to transfer words from one spot in RAM to another.

```
// Initialize and Setup DMA Channel 0
/*
Base Address of the DMA Module
Configure DMA channel 0
Configure channel for repeated block transfers
DMA interrupt flag will be set after every 16 transfers
Use DMA_startTransfer() function to trigger transfers
Transfer Word-to-Word
Trigger upon Rising Edge of Trigger Source Signal
*/
DMA_init(__MSP430_BASEADDRESS_DMAX_3__,
        DMA_CHANNEL_0,
        DMA_TRANSFER_REPEATED_BLOCK,
        16,
        DMA_TRIGGERSOURCE_0,
        DMA_SIZE_SRCWORD_DSTWORD,
        DMA_TRIGGER_RISINGEDGE);

/*
Base Address of the DMA Module
Configure DMA channel 0
Use 0x1C00 as source
Increment source address after every transfer
*/
DMA_setSrcAddress(__MSP430_BASEADDRESS_DMAX_3__,
                 DMA_CHANNEL_0,
                 0x1C00,
                 DMA_DIRECTION_INCREMENT);

/*
Base Address of the DMA Module
Configure DMA channel 0
Use 0x1C20 as destination
Increment destination address after every transfer
*/
DMA_setDstAddress(__MSP430_BASEADDRESS_DMAX_3__,
                 DMA_CHANNEL_0,
                 0x1C20,
                 DMA_DIRECTION_INCREMENT);

// Enable transfers on DMA channel 0
DMA_enableTransfers(__MSP430_BASEADDRESS_DMAX_3__,
                   DMA_CHANNEL_0);

while(1)
{
    // Start block transfer on DMA channel 0
    DMA_startTransfer(__MSP430_BASEADDRESS_DMAX_3__,
                     DMA_CHANNEL_0);
}
```

## 9 Flash Memory Controller

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### 9.1 Introduction

The flash memory is byte, word, and long-word addressable and programmable. The flash memory module has an integrated controller that controls programming and erase operations. The flash main memory is partitioned into 512-byte segments. Single bits, bytes, or words can be written to flash memory, but a segment is the smallest size of the flash memory that can be erased. The flash memory is partitioned into main and information memory sections. There is no difference in the operation of the main and information memory sections. Code and data can be located in either section. The difference between the sections is the segment size. There are four information memory segments, A through D. Each information memory segment contains 128 bytes and can be erased individually. The bootstrap loader (BSL) memory consists of four segments, A through D. Each BSL memory segment contains 512 bytes and can be erased individually. The main memory segment size is 512 byte. See the device-specific data sheet for the start and end addresses of each bank, when available, and for the complete memory map of a device. This library provides the API for flash segment erase, flash writes and flash operation status check.

This driver is contained in `driverlib/5xx_6xx/flash.c`, with `driverlib/5xx_6xx/flash.h` containing the API definitions for use by applications.

### 9.2 API Functions

`Flash_segmentErase` helps erase a single segment of the flash memory. A pointer to the flash segment being erased is passed on to this function.

`Flash_eraseCheck` helps check if a specific number of bytes in flash are currently erased. A pointer to the starting location of the erase check and the number of bytes to be checked is passed into this function.

Depending on the kind of writes being performed to the flash, this library provides APIs for flash writes.

`Flash_write8` facilitates writing into the flash memory in byte format. `Flash_write16` facilitates writing into the flash memory in word format. `Flash_write32` facilitates writing into the flash memory in long format, pass by reference. `Flash_memoryFill32` facilitates writing into the flash memory in long format, pass by value. `Flash_status` checks if the flash is currently busy erasing or programming.

The Flash API is broken into 3 groups of functions: those that deal with flash erase, those that write into flash, and those that give status of flash.

The flash erase operations are managed by

- `Flash_segmentErase`
- `Flash_eraseCheck`
- `Flash_bankErase`

Flash writes are managed by

- Flash\_write8
- Flash\_write16
- Flash\_write32
- Flash\_memoryFill32

The status is given by

- Flash\_status
- Flash\_eraseCheck

## 9.3 Programming Example

The following example shows some flash operations using the APIs

```
do{
    Flash_segmentErase(__MSP430_BASEADDRESS_FLASH__,
                      (unsigned char *)INFOD_START
                      );
    status = Flash_eraseCheck(__MSP430_BASEADDRESS_FLASH__,
                              (unsigned char *)INFOD_START,
                              128
                              );
}while(status == STATUS_FAIL);

//Flash write
Flash_write32(__MSP430_BASEADDRESS_FLASH__,
              calibration_data,
              (unsigned long *) (INFOD_START), 1);
```



# 10 GPIO

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## 10.1 Introduction

The digital I/O features include:

- Independently programmable individual I/Os
- Any combination of input or output
- Individually configurable P1 and P2 interrupts. Some devices may include additional port interrupts.
- Independent input and output data registers
- Individually configurable pullup or pulldown resistors

Devices within the family may have up to twelve digital I/O ports implemented (P1 to P11 and PJ). Most ports contain eight I/O lines; however, some ports may contain less (see the device-specific data sheet for ports available). Each I/O line is individually configurable for input or output direction, and each can be individually read or written. Each I/O line is individually configurable for pullup or pulldown resistors, as well as, configurable drive strength, full or reduced. PJ contains only four I/O lines.

Ports P1 and P2 always have interrupt capability. Each interrupt for the P1 and P2 I/O lines can be individually enabled and configured to provide an interrupt on a rising or falling edge of an input signal. All P1 I/O lines source a single interrupt vector P1IV, and all P2 I/O lines source a different, single interrupt vector P2IV. On some devices, additional ports with interrupt capability may be available (see the device-specific data sheet for details) and contain their own respective interrupt vectors. Individual ports can be accessed as byte-wide ports or can be combined into word-wide ports and accessed via word formats. Port pairs P1/P2, P3/P4, P5/P6, P7/P8, etc., are associated with the names PA, PB, PC, PD, etc., respectively. All port registers are handled in this manner with this naming convention except for the interrupt vector registers, P1IV and P2IV; that is, PAIV does not exist. When writing to port PA with word operations, all 16 bits are written to the port. When writing to the lower byte of the PA port using byte operations, the upper byte remains unchanged. Similarly, writing to the upper byte of the PA port using byte instructions leaves the lower byte unchanged. When writing to a port that contains less than the maximum number of bits possible, the unused bits are a "don't care". Ports PB, PC, PD, PE, and PF behave similarly.

Reading of the PA port using word operations causes all 16 bits to be transferred to the destination. Reading the lower or upper byte of the PA port (P1 or P2) and storing to memory using byte operations causes only the lower or upper byte to be transferred to the destination, respectively. Reading of the PA port and storing to a general-purpose register using byte operations causes the byte transferred to be written to the least significant byte of the register. The upper significant byte of the destination register is cleared automatically. Ports PB, PC, PD, PE, and PF behave similarly. When reading from ports that contain less than the maximum bits possible, unused bits are read as zeros (similarly for port PJ).

The GPIO pin may be configured as an I/O pin with `GPIO_setAsOutputPin()`,  
`GPIO_setAsInputPin()`, `GPIO_setAsInputPinWithPullDownresistor()` or

GPIO\_setAsInputPinWithPullUpresistor(). The GPIO pin may instead be configured to operate in the Peripheral Module assigned function by configuring the GPIO using GPIO\_setAsPeripheralModuleFunctionOutputPin() or GPIO\_setAsPeripheralModuleFunctionInputPin().

This driver is contained in `driverlib/5xx_6xx/gpio.c`, with `driverlib/5xx_6xx/gpio.h` containing the API definitions for use by applications.

## 10.2 API Functions

The GPIO API is broken into three groups of functions: those that deal with configuring the GPIO pins, those that deal with interrupts, and those that access the pin value.

The GPIO pins are configured with

- GPIO\_setAsOutputPin()
- GPIO\_setAsInputPin()
- GPIO\_setAsInputPinWithPullDownresistor()
- GPIO\_setAsInputPinWithPullUpresistor()
- GPIO\_setDriveStrength()
- GPIO\_setAsPeripheralModuleFunctionOutputPin()
- GPIO\_setAsPeripheralModuleFunctionInputPin()

The GPIO interrupts are handled with

- GPIO\_enableInterrupt()
- GPIO\_disableInterrupt()
- GPIO\_clearInterruptFlag()
- GPIO\_getInterruptStatus()
- GPIO\_interruptEdgeSelect()

The GPIO pin state is accessed with

- GPIO\_setOutputHighOnPin()
- GPIO\_setOutputLowOnPin()
- GPIO\_toggleOutputOnPin()
- GPIO\_getInputPinValue()

## 10.3 Programming Example

The following example shows how to use the GPIO API.

```
// Set P1.0 to output direction
GPIO_setAsOutputPin(__MSP430_BASEADDRESS_PORT1_R__,
                    GPIO_PORT_P1,
                    GPIO_PIN0
                    );
```

```
// Set P1.4 to input direction
GPIO_setAsInputPin(__MSP430_BASEADDRESS_PORT1_R__,
                  GPIO_PORT_P1,
                  GPIO_PIN4
                  );

while (1)
{
    // Test P1.4
    if (GPIO_INPUT_PIN_HIGH == GPIO_getInputPinValue(
        __MSP430_BASEADDRESS_PORT1_R__,
        GPIO_PORT_P1,
        GPIO_PIN4
        ))
    {
        // if P1.4 set, set P1.0
        GPIO_setOutputHighOnPin(
            __MSP430_BASEADDRESS_PORT1_R__,
            GPIO_PORT_P1,
            GPIO_PIN0
            );
    }
    else
    {
        // else reset
        GPIO_setOutputLowOnPin(
            __MSP430_BASEADDRESS_PORT1_R__,
            GPIO_PORT_P1,
            GPIO_PIN0
            );
    }
}
```



# 11 Inter-Integrated Circuit (I2C)

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## 11.1 Introduction

The Inter-Integrated Circuit (I2C) API provides a set of functions for using the MSP430Ware I2C modules. Functions are provided to initialize the I2C modules, to send and receive data, obtain status, and to manage interrupts for the I2C modules.

The I2C module provide the ability to communicate to other IC devices over an I2C bus. The I2C bus is specified to support devices that can both transmit and receive (write and read) data. Also, devices on the I2C bus can be designated as either a master or a slave. The MSP430Ware I2C modules support both sending and receiving data as either a master or a slave, and also support the simultaneous operation as both a master and a slave. Finally, the MSP430Ware I2C modules can operate at two speeds: Standard (100 kb/s) and Fast (400 kb/s).

I2C module can generate interrupts. The I2C module configured as a master will generate interrupts when a transmit or receive operation is completed (or aborted due to an error). The I2C module configured as a slave will generate interrupts when data has been sent or requested by a master.

### 11.1.1 Master Operations

To drive the master module, the APIs need to be invoked in the following order

- **I2C\_masterInit**
- **I2C\_setSlaveAddress**
- **I2C\_setMode**
- **I2C\_enable**
- **I2C\_enableInterrupt** ( if interrupts are being used ) This may be followed by the APIs for transmit or receive as required

The user must first initialize the I2C module and configure it as a master with a call to `I2C_masterInit()`. That function will set the clock and data rates. This is followed by a call to set the slave address with which the master intends to communicate with using `I2C_setSlaveAddress`. Then the mode of operation (transmit or receive) is chosen using `I2C_setMode`. The I2C module may now be enabled using `I2C_enable`. It is recommended to enable the I2C module before enabling the interrupts. Any transmission or reception of data may be initiated at this point after interrupts are enabled (if any).

The transaction can then be initiated on the bus by calling the transmit or receive related APIs as listed below.

Master Single Byte Transmission

- **I2C\_masterSendSingleByte**

Master Multiple Byte Transmission

- I2C\_masterMultiByteSendStart
- I2C\_masterMultiByteSendNext
- I2C\_masterMultiByteSendFinish
- I2C\_masterMultiByteSendStop

#### Master Single Byte Reception

- I2C\_masterSingleReceiveStart
- I2C\_masterSingleReceive

#### Master Multiple Byte Reception

- I2C\_masterMultiByteReceiveStart
- I2C\_masterMultiByteReceiveNext
- I2C\_masterMultiByteReceiveFinish
- I2C\_masterMultiByteReceiveStop

For the interrupt-driven transaction, the user must register an interrupt handler for the I2C devices and enable the I2C interrupt.

## 11.1.2 Slave Operations

To drive the slave module, the APIs need to be invoked in the following order

- **I2C\_slaveInit**
- **I2C\_setMode**
- **I2C\_enable**
- **I2C\_enableInterrupt** ( if interrupts are being used ) This may be followed by the APIs for transmit or receive as required

The user must first call the I2C\_slaveInit to initialize the slave module in I2C mode and set the slave address. This is followed by a call to set the mode of operation ( transmit or receive ).The I2C module may now be enabled using I2C\_enable. It is recommended to enable the I2C module before enabling the interrupts. Any transmission or reception of data may be initiated at this point after interrupts are enabled (if any).

The transaction can then be initiated on the bus by calling the transmit or receive related APIs as listed below.

#### Slave Transmission API

- I2C\_slaveDataPut

#### Slave Reception API

- I2C\_slaveDataGet

For the interrupt-driven transaction, the user must register an interrupt handler for the I2C devices and enable the I2C interrupt.

This driver is contained in `driverlib/5xx_6xx/i2c.c`, with `driverlib/5xx_6xx/i2c.h` containing the API definitions for use by applications.

## 11.2 API Functions

The I2C API is broken into three groups of functions: those that deal with interrupts, those that handle status and initialization, and those that deal with sending and receiving data.

The I2C master and slave interrupts are handled by

- I2C\_enableInterrupt
- I2C\_disableInterrupt
- UART\_clearInterruptFlag
- I2C\_getInterruptStatus

Status and initialization functions for the I2C modules are

- I2C\_masterInit
- I2C\_enable
- I2C\_disable
- I2C\_isBusBusy
- I2C\_isBusy
- I2C\_slaveInit
- I2C\_interruptStatus
- I2C\_setSlaveAddress
- I2C\_setMode

Sending and receiving data from the I2C slave module is handled by

- I2C\_slaveDataPut
- I2C\_slaveDataGet

Sending and receiving data from the I2C slave module is handled by

- I2C\_masterSendSingleByte
- I2C\_masterMultiByteSendStart
- I2C\_masterMultiByteSendNext
- I2C\_masterMultiByteSendFinish
- I2C\_masterMultiByteSendStop
- I2C\_masterMultiByteReceiveStart
- I2C\_masterMultiByteReceiveNext
- I2C\_masterMultiByteReceiveFinish
- I2C\_masterMultiByteReceiveStop
- I2C\_masterSingleReceiveStart
- I2C\_masterSingleReceive
- I2C\_getReceiveBufferAddressForDMA
- I2C\_getTransmitBufferAddressForDMA

DMA related

- I2C\_getReceiveBufferAddressForDMA
- I2C\_getTransmitBufferAddressForDMA

## 11.3 Programming Example

The following example shows how to use the I2C API to send data as a master.

```
// Initialize Master
I2C_masterInit(USCI_B0_BASE, SMCLK, CLK_getSMClk(), I2C_SET_DATA_RATE_400KBPS);

// Specify slave address
I2C_setSlaveAddress(USCI_B0_BASE, SLAVE_ADDRESS);

// Set in transmit mode
I2C_setMode(USCI_B0_BASE, I2C_TRANSMIT_MODE);

//Enable I2C Module to start operations
I2C_enable(USCI_B0_BASE);

while (1)
{
    // Send single byte data.
    I2C_masterSendSingleByte(USCI_B0_BASE, transmitData);

    // Delay until transmission completes
    while(I2C_busBusy(USCI_B0_BASE));

    // Increment transmit data counter
    transmitData++;
}
```



## 12 LDO-PWR

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### 12.1 Introduction

The features of the LDO-PWR module include:

- Integrated 3.3-V LDO regulator with sufficient output to power the entire MSP430Ž microcontroller and system circuitry from 5-V external supply
- Current-limiting capability on 3.3-V LDO output with detection flag and interrupt generation
- LDO input voltage detection flag and interrupt generation

The LDO-PWR power system incorporates an integrated 3.3-V LDO regulator that allows the entire MSP430 microcontroller to be powered from nominal 5-V LDOI when it is made available from the system. Alternatively, the power system can supply power only to other components within the system, or it can be unused altogether.

This driver is contained in `driverlib/5xx_6xx/ldoPwr.c`, with `driverlib/5xx_6xx/ldoPwr.h` containing the API definitions for use by applications.

### 12.2 API Functions

The `ldoPwr` configuration is handled by

- `LDOPWR_unlockConfiguration()`
- `LDOPWR_lockConfiguration()`
- `LDOPWR_enablePort_U_inputs()`
- `LDOPWR_disablePort_U_inputs()`
- `LDOPWR_enablePort_U_outputs()`
- `LDOPWR_disablePort_U_outputs()`
- `LDOPWR_enable()`
- `LDOPWR_disable()`
- `LDOPWR_enableOverloadAutoOff()`
- `LDOPWR_disableOverloadAutoOff()`

Handling the read/write of output data is handled by

- `LDOPWR_getPort_U1_inputData()`
- `LDOPWR_getPort_U0_inputData()`
- `LDOPWR_getPort_U1_outputData()`

- LDOPWR\_getPort\_U0\_outputData()
- LDOPWR\_getOverloadAutoOffStatus()
- LDOPWR\_setPort\_U0\_outputData()
- LDOPWR\_togglePort\_U1\_outputData()
- LDOPWR\_togglePort\_U0\_outputData()
- LDOPWR\_setPort\_U1\_outputData()

The interrupt and status operations are handled by

- LDOPWR\_enableInterrupt()
- LDOPWR\_disableInterrupt()
- LDOPWR\_getInterruptStatus()
- LDOPWR\_clearInterruptStatus()
- LDOPWR\_isLDOInputValid()
- LDOPWR\_getOverloadAutoOffStatus()

## 12.3 Programming Example

The following example shows how to use the LDO-PWR API.

```
{
    // Enable access to config registers
    LDOPWR_unlockConfiguration(__MSP430_BASEADDRESS_PU__);

    // Configure PU.0 as output pins
    LDOPWR_enablePort_U_outputs(__MSP430_BASEADDRESS_PU__);

    //Set PU.1 = high
    LDOPWR_setPort_U1_outputData(__MSP430_BASEADDRESS_PU__,
                                LDOPWR_PORTU_PIN_HIGH
                                );

    //Set PU.0 = low
    LDOPWR_setPort_U0_outputData(__MSP430_BASEADDRESS_PU__,
                                LDOPWR_PORTU_PIN_LOW
                                );

    // Enable LDO overload indication interrupt
    LDOPWR_enableInterrupt(__MSP430_BASEADDRESS_PU__,
                           LDOPWR_LDO_OVERLOAD_INDICATION_INTERRUPT
                           );

    // Disbale access to config registers
    LDOPWR_lockConfiguration(__MSP430_BASEADDRESS_PU__);

    // continuous loop
    while(1)
    {
        // Delay
        for(i=50000;i>0;i--);

        // Enable access to config registers
        LDOPWR_unlockConfiguration(__MSP430_BASEADDRESS_PU__);

        // XOR PU.0/1
```

```

    LDOPWR_togglePort_U1_outputData(__MSP430_BASEADDRESS_PU__);
    LDOPWR_togglePort_U0_outputData(__MSP430_BASEADDRESS_PU__);

    // Disbale access to config registers
    LDOPWR_lockConfiguration(__MSP430_BASEADDRESS_PU__);
}

//*****
//
// This is the LDO_PWR_VECTOR interrupt vector service routine.
//
//*****
__interrupt void LDOInterruptHandler(void)
{
    if (LDOPWR_getInterruptStatus(__MSP430_BASEADDRESS_PU__,
                                LDOPWR_LDO_OVERLOAD_INDICATION_INTERRUPT
                                ))
    {
        // Enable access to config registers
        LDOPWR_unLockConfiguration(__MSP430_BASEADDRESS_PU__);

        // Software clear IFG
        LDOPWR_clearInterruptStatus(__MSP430_BASEADDRESS_PU__,
                                    LDOPWR_LDO_OVERLOAD_INDICATION_INTERRUPT
                                    );

        // Disable access to config registers
        LDOPWR_lockConfiguration(__MSP430_BASEADDRESS_PU__);

        // Over load indication; take necessary steps in application firmware
        while(1);
    }
}

```



## 13 32-Bit Hardware Multiplier (MPY32)

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### 13.1 Introduction

The 32-Bit Hardware Multiplier (MPY32) API provides a set of functions for using the MSP430Ware MPY32 modules. Functions are provided to setup the MPY32 modules, set the operand registers, and obtain the results.

The MPY32 Modules does not generate any interrupts.

This driver is contained in `driverlib/5xx_6xx/mpy32.c`, with `driverlib/5xx_6xx/mpy32.h` containing the API definitions for use by applications.

### 13.2 API Functions

The MPY32 API is broken into three groups of functions: those that control the settings, those that set the operand registers, and those that return the results, sum extension, and carry bit value.

The settings are handled by

- `MPY32_setWriteDelay`
- `MPY32_setSaturationMode`
- `MPY32_resetSaturationMode`
- `MPY32_setFractionMode`
- `MPY32_resetFractionMode`

The operand registers are set by

- `MPY32_setOperandOne8Bit`
- `MPY32_setOperandOne16Bit`
- `MPY32_setOperandOne24Bit`
- `MPY32_setOperandOne32Bit`
- `MPY32_setOperandTwo8Bit`
- `MPY32_setOperandTwo16Bit`
- `MPY32_setOperandTwo24Bit`
- `MPY32_setOperandTwo32Bit`

The results can be returned by

- `MPY32_getResult8Bit`
- `MPY32_getResult16Bit`
- `MPY32_getResult24Bit`

- MPY32\_getResult32Bit
- MPY32\_getResult64Bit
- MPY32\_getSumExtension
- MPY32\_getCarryBitValue

## 13.3 Programming Example

The following example shows how to initialize and use the MPY32 API to calculate a 16-bit by 16-bit unsigned multiplication operation.

```
WDT_hold(__MSP430_BASEADDRESS_WDT_A__);    // Stop WDT

// Set a 16-bit Operand into the specific Operand 1 register to specify
// unsigned multiplication
MPY32_setOperandOne16Bit(__MSP430_BASEADDRESS_MPY32__,
                        MPY32_MULTIPLY_UNSIGNED,
                        0x1234);
// Set Operand 2 to begin the multiplication operation
MPY32_setOperandTwo16Bit(__MSP430_BASEADDRESS_MPY32__,
                        0x5678);

__bis_SR_register(LPM4_bits);                // Enter LPM4
__no_operation();                            // BREAKPOINT HERE to verify the
                                           // correct result in the registers
```

# 14 Power Management Module (PMM)

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## 14.1 Introduction

The PMM manages the following internal circuitry:

- An integrated low-dropout voltage regulator (LDO) that produces a secondary core voltage (VCORE) from the primary voltage that is applied to the device (DVCC)
- Supply voltage supervisors (SVS) and supply voltage monitors (SVM) for the primary voltage (DVCC) and the secondary voltage (VCORE). The SVS and SVM include programmable threshold levels and power-fail indicators. Therefore, the PMM plays a crucial role in defining the maximum performance, valid voltage conditions, and current consumption for an application running on an MSP430x5xx or MSP430x6xx device. The secondary voltage that is generated by the integrated LDO, VCore, is programmable to one of four core voltage levels, shown as 0, 1, 2, and 3. Each increase in VCore allows the CPU to operate at a higher maximum frequency. The values of these frequencies are specified in the device-specific data sheet. This feature allows the user the flexibility to trade power consumption in active and low-power modes for different degrees of maximum performance and minimum supply voltage.

**NOTE:** To align with the nomenclature in the MSP430x5xx/MSP430x6xx Family User's Guide, the primary voltage domain (DVCC) is referred to as the high-side voltage (SvsH/SVMH) and the secondary voltage domain (VCORE) is referred to as the low-side voltage (SvsL/SvmL).

Moving between the different VCore voltages requires a specific sequence of events and can be done only one level at a time; for example, to change from level 0 to level 3, the application code must step through level 1 and level 2.

**VCore increase:** 1. SvmL monitor level is incremented. 2. VCore level is incremented. 3. The SvmL Level Reached Interrupt Flag (SVSMLVLRIFG) in the PMMIFG register is polled. When asserted, SVSMLVLRIFG indicates that the VCore voltage has reached its next level. 4. SvsL is increased. SvsL is changed last, because if SVSL were incremented prior to VCore, it would potentially cause a reset.

**VCore decrease:** 5. Decrement SvmL and SVSL levels. 6. Decrement VCore. The PMM\_setVCore() function appropriately handles an increase or decrease of the core voltage. **NOTE:** The procedure recommended above provides a workaround for the erratum FLASH37. See the device-specific erratasheet to determine if a device is affected by FLASH37. The workaround is also highlighted in the source code for the PMM library

**Recommended SVS and SVM Settings** The SVS and SVM on both the high side and the low side are enabled in normal performance mode following a brown-out reset condition. The device is held in reset until the SVS and SVM verify that the external and core voltages meet the minimum requirements of the default core voltage, which is level zero. The SVS and SVM remain enabled unless disabled by the firmware. The low-side SVS and SVM are useful for verifying the startup conditions and for verifying any modification to the core voltage. However, in their default mode, they prevent the CPU from executing code on wake-up from low-power modes 2, 3, and 4 for a full 150  $\mu$ s, not 5  $\mu$ s. This is because, in their default states, the SVSL and SvmL are powered down in the low-power mode of the PMM and need time for their comparators to wake and stabilize

before they can verify the voltage condition and release the CPU for execution. Note that the high-side SVS and SVM do not influence the wake time from low-power modes. If the wake-up from low-power modes needs to be shortened to 5  $\mu$ s, the SVSL and SvmL should be disabled after the initialization of the core voltage at the beginning of the application. Disabling SVSL and SvmL prevents them from gating the CPU on wake-up from LPM2, LPM3, and LPM4. The application is still protected on the high side with SvsH and SVMH. The PMM\_setVCore() function automatically enables and disables the SVS and SVM as necessary if a non-zero core voltage level is required. If the application does not require a change in the core voltage (that is, when the target MCLK is less than 8 MHz), the PMM\_disableSVSLSvmL() and PMM\_enableSvsHReset() macros can be used to disable the low-side SVS and SVM circuitry and enable only the high-side SVS POR reset, respectively.

**Setting SVS/SVM Threshold Levels** The voltage thresholds for the SVS and SVM modules are programmable. On the high side, there are two bit fields that control these threshold levels — the SvsHRVL and SVSMHRRL. The SvsHRVL field defines the voltage threshold at which the SvsH triggers a reset (also known as the SvsH ON voltage level). The SVSMHRRL field defines the voltage threshold at which the SvsH releases the device from a reset (also known as SvsH OFF voltage level). The MSP430x5xx/MSP430x6xx Family User's Guide (SLAU208) [1] recommends the settings shown in Table 1 when setting these bits. The PMM\_setVCore() function follows these recommendations and ensures that the SVS levels match the core voltage levels that are used.

**Advanced SVS Controls and Trade-offs** In addition to the default SVS settings that are provided with the PMM\_setVCore() function, the SVS/SVM modules can be optimized for wake-up speed, response time (propagation delay), and current consumption, as needed. The following controls can be optimized for the SVS/SVM modules:

- Protection in low power modes - LPM2, LPM3, and LPM4
- Wake-up time from LPM2, LPM3, and LPM4
- Response time to react to an SVS event Selecting the LPM option, wake-up time, and response time that is best suited for the application is left to the user. A few typical examples illustrate the trade-offs: Case A: The most robust protection that stays on in LPMs and has the fastest response and wake-up time consumes the most power. Case B: With SVS high side active only in AM, no protection in LPMs, slow wake-up, and slow response time has SVS protection with the least current consumption. Case C: An optimized case is described - turn off the low-side monitor and supervisor, thereby saving power while keeping response time fast on the high side to help with timing critical applications. The user can call the PMM\_setVCore() function, which configures SVS/SVM high side and low side with the recommended or default configurations, or can call the APIs provided to control the parameters as the application demands.

Any writes to the SVSMLCTL and SVSMHCTL registers require a delay time for these registers to settle before the new settings take effect. This delay time is dependent on whether the SVS and SVM modules are configured for normal or full performance. See device-specific data sheet for exact delay times.

## 14.2 API Functions

**PMM\_enableSvsL() / PMM\_disableSvsL()** Enables or disables the low-side SVS circuitry

**PMM\_enableSvmL() / PMM\_disableSvmL()** Enables or disables the low-side SVM circuitry

**PMM\_enableSvsH() / PMM\_disableSvsH()** Enables or disables the high-side SVS circuitry



**PMM\_enableSVMH() / PMM\_disableSVMH()** Enables or disables the high-side SVM circuitry

**PMM\_enableSvsLSvmL() / PMM\_disableSvsLSvmL()** Enables or disables the low-side SVS and SVM circuitry

**PMM\_enableSvsHSvmH() / PMM\_disableSvsHSvmH()** Enables or disables the high-side SVS and SVM circuitry

**PMM\_enableSvsLReset() / PMM\_disableSvsLReset()** Enables or disables the POR signal generation when a low-voltage event is registered by the low-side SVS

**PMM\_enableSvmLInterrupt() / PMM\_disableSvmLInterrupt()** Enables or disables the interrupt generation when a low-voltage event is registered by the low-side SVM

**PMM\_enableSvsHReset() / PMM\_disableSvsHReset()** Enables or disables the POR signal generation when a low-voltage event is registered by the high-side SVS

**PMM\_enableSVMHInterrupt() / PMM\_disableSVMHInterrupt()** Enables or disables the interrupt generation when a low-voltage event is registered by the high-side SVM

**PMM\_clearPMMIFGS()** Clear all interrupt flags for the PMM

**PMM\_SvsLEnabledInLPMFastWake()** Enables supervisor low side in LPM with twake-up-fast from LPM2, LPM3, and LPM4

**PMM\_SvsLEnabledInLPMSlowWake()** Enables supervisor low side in LPM with twake-up-slow from LPM2, LPM3, and LPM4

**PMM\_SvsLDisabledInLPMFastWake()** Disables supervisor low side in LPM with twake-up-fast from LPM2, LPM3, and LPM4

**PMM\_SvsLDisabledInLPMSlowWake()** Disables supervisor low side in LPM with twake-up-slow from LPM2, LPM3, and LPM4

**PMM\_SvsHEnabledInLPMNormPerf()** Enables supervisor high side in LPM with  $t_{pd} = 20 \mu s(1)$

**PMM\_SvsHEnabledInLPMFullPerf()** Enables supervisor high side in LPM with  $t_{pd} = 2.5 \mu s(1)$

**PMM\_SvsHDisabledInLPMNormPerf()** Disables supervisor high side in LPM with  $t_{pd} = 20 \mu s(1)$

**PMM\_SvsHDisabledInLPMFullPerf()** Disables supervisor high side in LPM with  $t_{pd} = 2.5 \mu s(1)$

**PMM\_SvsLOptimizedInLPMFastWake()** Optimized to provide twake-up-fast from LPM2, LPM3, and LPM4 with least power

**PMM\_SvsHOptimizedInLPMFullPerf()** Optimized to provide  $t_{pd} = 2.5 \mu s(1)$  in LPM with least power

**PMM\_getInterruptStatus()** Returns interrupt status of the PMM module

**PMM\_setVCore()** Sets the appropriate VCore level. Calls the PMM\_setVCoreUp() or PMM\_setVCoreDown() function the required number of times depending on the current VCore level, because the levels must be stepped through individually. A status indicator equal to STATUS\_SUCCESS or STATUS\_FAIL that indicates a valid or invalid VCore transition, respectively. An invalid VCore transition exists if DVCC is less than the minimum required voltage for the target VCore voltage.

This driver is contained in `driverlib/5xx_6xx/pmm.c`, with `driverlib/5xx_6xx/pmm.h` containing the API definitions for use by applications.

## 14.3 Programming Example

The following example shows some pmm operations using the APIs

```
do{
    status = PMM_setVCore(__MSP430_BASEADDRESS_PMM__, PMMCOREV_3);
    // Use the line below to bring the level back to 0
    status = PMM_setVCore(__MSP430_BASEADDRESS_PMM__, PMMCOREV_0);

    // P1.0 set as output
    P1DIR |= BIT0;

    // continuous loop
    while(1)
    {
        // XOR P1.0
        P1OUT ^= BIT0;

        // Delay
        __delay_cycles(20000);
    }
}
```

# 15 Port Mapping Controller

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## 15.1 Introduction

The port mapping controller allows the flexible and reconfigurable mapping of digital functions to port pins. The port mapping controller features are:

- Configuration protected by write access key.
- Default mapping provided for each port pin (device-dependent, the device pinout in the device-specific data sheet).
- Mapping can be reconfigured during runtime.
- Each output signal can be mapped to several output pins.

This driver is contained in `driverlib/5xx_6xx/pmap.c`, with `driverlib/5xx_6xx/pmap.h` containing the API definitions for use by applications.

## 15.2 API Functions

The MSP430ware API that configures Port Mapping is `PMAP_configurePorts()`

It needs the following data to configure port mapping. `portMapping` - pointer to init Data `PxMAPy`  
 - pointer start of first Port Mapper to initialize `numberOfPorts` - number of Ports to initialize  
`portMapReconfigure` - to enable/disable reconfiguration

## 15.3 Programming Example

The following example shows some Port Mapping Controller operations using the APIs

```
const unsigned char port_mapping[] = {
    //Port P4:
    PM_TB0CCR0A,
    PM_TB0CCR1A,
    PM_TB0CCR2A,
    PM_TB0CCR3A,
    PM_TB0CCR4A,
    PM_TB0CCR5A,
    PM_TB0CCR6A,
    PM_NONE
};

//CONFIGURE PORTS- pass the port_mapping array, start @ P4MAP01, initialize
//a single port, do not allow run-time reconfiguration of port mapping
PMAP_configurePorts(__MSP430_BASEADDRESS_PORT_MAPPING__,
```

```
(const unsigned char *)port_mapping,  
(unsigned char *)&P4MAP01,  
1,  
PMAP_DISABLE_RECONFIGURATION  
);
```

## 16 RAM Controller

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### 16.1 Introduction

The RAMCTL provides access to the different power modes of the RAM. The RAMCTL allows the ability to reduce the leakage current while the CPU is off. The RAM can also be switched off. In retention mode, the RAM content is saved while the RAM content is lost in off mode. The RAM is partitioned in sectors, typically of 4KB (sector) size. See the device-specific data sheet for actual block allocation and size. Each sector is controlled by the RAM controller RAM Sector Off control bit (RCRSyOFF) of the RAMCTL Control 0 register (RCCTL0). The RCCTL0 register is protected with a key. Only if the correct key is written during a word write, the RCCTL0 register content can be modified. Byte write accesses or write accesses with a wrong key are ignored.

This driver is contained in `driverlib/5xx_6xx/ramcontroller.c`, with `driverlib/5xx_6xx/ramcontroller.h` containing the API definitions for use by applications.

### 16.2 API Functions

The MSP430ware API that configure the RAM controller are:

`ramController_setSectorOff()` - Set specified RAM sector off `ramController_getSectorState()` - Get RAM sector ON/OFF status

### 16.3 Programming Example

The following example shows some RAM Controller operations using the APIs

```
//Start timer
Timer_startUpMode( __MSP430_BASEADDRESS_T0B7__,
    TIMER_CLOCKSOURCE_ACLK,
    TIMER_CLOCKSOURCE_DIVIDER_1,
    25000,
    TIMER_TAIE_INTERRUPT_DISABLE,
    TIMER_CAPTURECOMPARE_INTERRUPT_ENABLE,
    TIMER_DO_CLEAR
);

//RAM controller sector off
ramController_setSectorOff(__MSP430_BASEADDRESS_RC__,
    RAMCONTROL_SECTOR2
);

//Enter LPM0, enable interrupts
__bis_SR_register(LPM3_bits + GIE);
```

```
        //For debugger
        __no_operation();
    }

    //*****
    //
    //This is the Timer B0 interrupt vector service routine.
    //
    //*****
    #pragma vector=TIMERB0_VECTOR
    __interrupt void TIMERB0_ISR (void)
    {
        returnValue = ramController_getSectorState(__MSP430_BASEADDRESS_RC__,
            RAMCONTROL_SECTOR0 +
            RAMCONTROL_SECTOR1 +
            RAMCONTROL_SECTOR2 +
            RAMCONTROL_SECTOR3);
    }
```

# 17 Internal Reference (REF)

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## 17.1 Introduction

The Internal Reference (REF) API provides a set of functions for using the MSP430Ware REF modules. Functions are provided to setup and enable use of the Reference voltage, enable or disable the internal temperature sensor, and view the status of the inner workings of the REF module.

The reference module (REF) is responsible for generation of all critical reference voltages that can be used by various analog peripherals in a given device. These include, but are not necessarily limited to, the ADC10\_A, ADC12\_A, DAC12\_A, LCD\_B, and COMP\_B modules dependent upon the particular device. The heart of the reference system is the bandgap from which all other references are derived by unity or non-inverting gain stages. The REFGEN sub-system consists of the bandgap, the bandgap bias, and the non-inverting buffer stage which generates the three primary voltage reference available in the system, namely 1.5 V, 2.0 V, and 2.5 V. In addition, when enabled, a buffered bandgap voltage is also available.

This driver is contained in `driverlib/5xx_6xx/ref.c`, with `driverlib/5xx_6xx/ref.h` containing the API definitions for use by applications.

## 17.2 API Functions

The DMA API is broken into three groups of functions: those that deal with the reference voltage, those that handle the internal temperature sensor, and those that return the status of the REF module.

The reference voltage of the REF module is handled by

- `REF_setReferenceVoltage`
- `REF_enableReferenceVoltageOutput`
- `REF_disableReferenceVoltageOutput`
- `REF_enableReferenceVoltage`
- `REF_disableReferenceVoltage`

The internal temperature sensor is handled by

- `REF_disableTempSensor`
- `REF_enableTempSensor`

The status of the REF module is handled by

- `REF_getBandgapMode`
- `REF_isBandgapActive`

- REF\_isRefGenBusy
- REF\_isRefGen

## 17.3 Programming Example

The following example shows how to initialize and use the REF API with the ADC12 module to use as a positive reference to the analog signal input.

```
// By default, REFMSTR=1 => REFCTL is used to configure the internal reference

// If ref generator busy, WAIT
while(REF_refGenBusyStatus(__MSP430_BASEADDRESS_REF__));
// Select internal ref = 2.5V
REF_setReferenceVoltage(__MSP430_BASEADDRESS_REF__,
                       REF_VREF2_5V);
// Internal Reference ON
REF_enableReferenceVoltage(__MSP430_BASEADDRESS_REF__);

__delay_cycles(75); // Delay (~75us) for Ref to settle

// Initialize the ADC12 Module
/*
Base address of ADC12 Module
Use internal ADC12 bit as sample/hold signal to start conversion
USE MODOSC 5MHZ Digital Oscillator as clock source
Use default clock divider of 1
*/
ADC12_init(__MSP430_BASEADDRESS_ADC12_PLUS__,
           ADC12_SAMPLEHOLDSOURCE_SC,
           ADC12_CLOCKSOURCE_ADC12OSC,
           ADC12_CLOCKDIVIDEBY_1);

/*
Base address of ADC12 Module
For memory buffers 0-7 sample/hold for 64 clock cycles
For memory buffers 8-15 sample/hold for 4 clock cycles (default)
Disable Multiple Sampling
*/
ADC12_setupSamplingTimer(__MSP430_BASEADDRESS_ADC12_PLUS__,
                        ADC12_CYCLEHOLD_64_CYCLES,
                        ADC12_CYCLEHOLD_4_CYCLES,
                        ADC12_MULTIPLESAMPLESENABLE);

// Configure Memory Buffer
/*
Base address of the ADC12 Module
Configure memory buffer 0
Map input A0 to memory buffer 0
Vref+ = Vref+ (INT)
Vref- = AVss
*/
ADC12_memoryConfigure(__MSP430_BASEADDRESS_ADC12_PLUS__,
                     ADC12_MEMORY_0,
                     ADC12_INPUT_A0,
                     ADC12_VREFPOS_INT,
                     ADC12_VREFNEG_AVSS,
                     ADC12_NOTENDOFSEQUENCE);

while (1)
{
    // Enable/Start sampling and conversion
    /*
```



```
Base address of ADC12 Module
Start the conversion into memory buffer 0
Use the single-channel, single-conversion mode
*/
ADC12_startConversion(__MSP430_BASEADDRESS_ADC12_PLUS__,
                     ADC12_MEMORY_0,
                     ADC12_SINGLECHANNEL);

// Poll for interrupt on memory buffer 0
while(!ADC12_interruptStatus(__MSP430_BASEADDRESS_ADC12_PLUS__, ADC12IFG0));

__no_operation();                // SET BREAKPOINT HERE
}
```



## 18 Real-Time Clock (RTC)

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### 18.1 Introduction

The Real Time Clock (RTC) API provides a set of functions for using the MSP430Ware RTC modules. Functions are provided to calibrate the clock, initialize the RTC modules in Calendar mode, and setup conditions for, and enable, interrupts for the RTC modules. If an RTC\_A module is used, then Counter mode may also be initialized, as well as prescale counters.

The RTC module provides the ability to keep track of the current time and date in calendar mode, or can be setup as a 32-bit counter (RTC\_A Only).

The RTC module generates multiple interrupts. There are 2 interrupts that can be defined in calendar mode, and 1 interrupt in counter mode for counter overflow, as well as an interrupt for each prescaler.

This driver is contained in `driverlib/5xx_6xx/rtc.c`, with `driverlib/5xx_6xx/rtc.h` containing the API definitions for use by applications.

### 18.2 API Functions

The RTC API is broken into 4 groups of functions: clock settings, calendar mode, counter mode, and interrupt condition setup and enable functions.

The RTC clock settings are handled by

- `RTC_startClock`
- `RTC_holdClock`
- `RTC_setCalibrationFrequency`
- `RTC_setCalibrationData`

The RTC Calendar Mode is initialized and setup by

- `RTC_calenderInit`
- `RTC_getCalenderTime`
- `RTC_getPrescaleValue`
- `RTC_setPrescaleValue`

The RTC Counter Mode is initialized and setup by (Available in RTC\_A Only)

- `RTC_counterInit`
- `RTC_getCounterValue`
- `RTC_setCounterValue`

- RTC\_counterPrescaleInit
- RTC\_counterPrescaleHold
- RTC\_counterPrescaleStart
- RTC\_getPrescaleValue
- RTC\_setPrescaleValue

The RTC interrupts are handled by

- RTC\_setCalenderAlarm
- RTC\_setCalenderEvent
- RTC\_definePrescaleEvent
- RTC\_enableInterrupt
- RTC\_disableInterrupt
- RTC\_getInterruptStatus
- RTC\_clearInterrupt

The following API are available in RTC\_B Only

- RTC\_convertBCDToBinary
- RTC\_convertBinaryToBCD

## 18.3 Programming Example

The following example shows how to initialize and use the RTC API to setup Calender Mode with the current time and various interrupts.

```
Calendar currentTime;

WDT_hold(__MSP430_BASEADDRESS_WDT_A__);
P1DIR |= BIT0;                               // Set P1.0 as output

// Initialize LFXTL
P7SEL |= 0x03;                               // Select XT1
UCSCTL6 &= ~(XT1OFF);                        // XT1 On
UCSCTL6 |= XCAP_3;                           // Internal load cap

// Loop until XT1,XT2 & DCO fault flag is cleared
do
{
    UCSCTL7 &= ~(XT2OFFG + XT1LFOFFG + XT1HFOFFG + DCOFFG);
                                                    // Clear XT2,XT1,DCO fault flags

    // Clear SFR Fault Flag
    SFR_clearInterrupt(__MSP430_BASEADDRESS_SFR__,
                      OFIFG);

    // Test oscillator fault flag
}while (SFR_interruptStatus(__MSP430_BASEADDRESS_SFR__, OFIFG));

// Setup Current Time for Calendar
currentTime.Seconds   = 0x00;
currentTime.Minutes   = 0x26;
currentTime.Hours     = 0x13;
```

```
currentTime.DayOfWeek = 0x03;
currentTime.DayOfMonth = 0x20;
currentTime.Month = 0x07;
currentTime.Year = 0x2011;

// Initialize Calendar Mode of RTC
/*
Base Address of the RTC_A
Pass in current time, initialized above
Use BCD as Calendar Register Format
*/
RTC_calendarInit (__MSP430_BASEADDRESS_RTC__,
                  currentTime,
                  RTC_FORMAT_BCD);

// Setup Calendar Alarm for 5:00pm on the 5th day of the week.
// Note: Does not specify day of the week.
RTC_setCalendarAlarm (__MSP430_BASEADDRESS_RTC__,
                     0x00,
                     0x17,
                     RTC_ALARM_OFF,
                     0x05);

// Specify an interrupt to assert every minute
RTC_setCalendarEvent (__MSP430_BASEADDRESS_RTC__,
                     RTC_CALENDAREVENT_MINUTECHANGE);

// Enable interrupt for RTC Ready Status, which asserts when the RTC
// Calendar registers are ready to read.
// Also, enable interrupts for the Calendar alarm and Calendar event.
RTC_enableInterrupt (__MSP430_BASEADDRESS_RTC__,
                    RTCRDYIE + RTCTEVIE + RTCAIE);

// Start RTC Clock
RTC_startClock (__MSP430_BASEADDRESS_RTC__);
```



## 19 SFR-SYS Modules

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### 19.1 Introduction

The Special Function Registers & System Control (SFR\_SYS) API provides a set of functions for using the MSP430Ware SFR and SYS modules. Functions are provided to enable interrupts, control the ~RST/NMI pin, control various SYS controls, setup the BSL, and control the JTAG Mailbox.

The SFR\_SYS module can enable interrupts to be generated from other peripherals of the device.

This driver is contained in `driverlib/5xx_6xx/sfr_sys.c`, with `driverlib/5xx_6xx/sfr_sys.h` containing the API definitions for use by applications.

### 19.2 API Functions

The SFR\_SYS API is broken into 5 groups: the SFR interrupts, the SFR ~RST/NMI pin control, the various SYS controls, the BSL controls, and the JTAG mailbox controls.

The SFR interrupts are handled by

- `SFR_enableInterrupt`
- `SFR_disableInterrupt`
- `SFR_getInterruptStatus`
- `SFR_clearInterrupt`

The SFR ~RST/NMI pin is controlled by

- `SFR_setResetPinPullResistor`
- `SFR_setNMIEdge`
- `SFR_setResetNMIPinFunction`

The various SYS controls are handled by

- `SYS_enableDedicatedJTAGPins`
- `SYS_getBSLEntryIndication`
- `SYS_enablePMMAccessProtect`
- `SYS_enableRAMBasedInterruptVectors`
- `SYS_disableRAMBasedInterruptVectors`

The BSL controls are handled by

- SYS\_enableBSLProtect
- SYS\_disableBSLProtect
- SYS\_disableBSLMemory
- SYS\_enableBSLMemory
- SYS\_setRAMAssignedToBSL
- SYS\_setBSLSize

The JTAG Mailbox controls are handled by

- SYS\_JTAGMailboxInit
- SYS\_getJTAGMailboxFlagStatus
- SYS\_getJTAGInboxMessage16Bit
- SYS\_getJTAGInboxMessage32Bit
- SYS\_setJTAGOutgoingMessage16Bit
- SYS\_setJTAGOutgoingMessage32Bit
- SYS\_clearJTAGMailboxFlagStatus

## 19.3 Programming Example

The following example shows how to initialize and use the SFR API

```
do
{
    // Clear XT2,XT1,DCO fault flags
    UCS_clearFaultFlag (__MSP430_BASEADDRESS_UCS__,
                        UCS_XT2OFFG + UCS_XT1HFOFFG +
                        UCS_XT1LFOFFG + UCS_DCOFFG
    );

    // Clear SFR Fault Flag
    SFR_clearInterrupt (__MSP430_BASEADDRESS_SFR__,
                       OFIFG);

    // Test oscillator fault flag
}while (SFR_getInterruptStatus (__MSP430_BASEADDRESS_SFR__, OFIFG));
```



## 20 Synchronous Peripheral Interface (SPI)

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### 20.1 Introduction

The Serial Peripheral Interface Bus or SPI bus is a synchronous serial data link standard named by Motorola that operates in full duplex mode. Devices communicate in master/slave mode where the master device initiates the data frame.

This library provides the API for handling a 3-wire SPI communication

The SPI module can be configured as either a master or a slave device.

The SPI module also includes a programmable bit rate clock divider and prescaler to generate the output serial clock derived from the SSI module's input clock.

This driver is contained in `driverlib/5xx_6xx/spi.c`, with `driverlib/5xx_6xx/spi.h` containing the API definitions for use by applications.

### 20.2 API Functions

To use the module as a master, the user must call `SPI_masterInit()` to configure the SPI Master. This is followed by enabling the SPI module using `SPI_enable()`. The interrupts are then enabled (if needed). It is recommended to enable the SPI module before enabling the interrupts. A data transmit is then initiated using `SPI_transmitData()` and when the receive flag is set, the received data is read using `SPI_receiveData()` and this indicates that an RX/TX operation is complete.

To use the module as a slave, initialization is done using `SPI_slaveInit()` and this is followed by enabling the module using `SPI_enable()`. Following this, the interrupts may be enabled as needed. When the receive flag is set, data is first transmitted using `SPI_transmitData()` and this is followed by a data reception by `SPI_receiveData()`

The SPI API is broken into 3 groups of functions: those that deal with status and initialization, those that handle data, and those that manage interrupts.

The status and initialization of the SPI module are managed by

- `SPI_masterInit`
- `SPI_slaveInit`
- `SPI_disable`
- `SPI_enable`
- `SPI_masterChangeClock`
- `SPI_isBusy`

Data handling is done by

- `SPI_transmitData`

- SPI\_receiveData

Interrupts from the SPI module are managed using

- SPI\_disableInterrupt
- SPI\_enableInterrupt
- SPI\_getInterruptStatus
- SPI\_clearInterruptFlag

DMA related

- SPI\_getReceiveBufferAddressForDMA
- SPI\_getTransmitBufferAddressForDMA

## 20.3 Programming Example

The following example shows how to use the SPI API to configure the SPI module as a master device, and how to do a simple send of data.

```
//Initialize Master
returnValue = SPI_masterInit(USCI_A0_BASE, SMCLK, CLK_getSMClk(),
                             SPICLK, MSB_FIRST,
                             CLOCK_POLARITY_INACTIVITYHIGH
                             );

if(STATUS_FAIL == returnValue)
{
    return;
}

//Enable SPI module
SPI_enable(USCI_A0_BASE);

//Enable Receive interrupt
SPI_enableInterrupt(USCI_A0_BASE, UCRXIE);

//Configure port pins to reset slave

// Wait for slave to initialize
__delay_cycles(100);

// Initialize data values
transmitData = 0x00;

// USCI_A0 TX buffer ready?
while (!SPI_interruptStatus(USCI_A0_BASE, UCTXIFG));

//Transmit Data to slave
SPI_transmitData(USCI_A0_BASE, transmitData);

// CPU off, enable interrupts
__bis_SR_register(LPM0_bits + GIE);
}

//*****
//
// This is the USCI_B0 interrupt vector service routine.
//
```

```

//*****
#pragma vector=USCI_A0_VECTOR
__interrupt void USCI_A0_ISR(void)
{
    switch(__even_in_range(UCA0IV,4))
    {
        // Vector 2 - RXIFG
        case 2:
            // USCI_A0 TX buffer ready?
            while (!SPI_interruptStatus(USCI_A0_BASE, UCTXIFG));

            receiveData = SPI_receiveData(USCI_A0_BASE);

            // Increment data
            transmitData++;

            // Send next value
            SPI_transmitData(USCI_A0_BASE, transmitData);

            //Delay between transmissions for slave to process information
            __delay_cycles(40);

            break;
            default: break;
        }
    }
}

```



## 21 Timer

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### 21.1 Introduction

Timer is a 16-bit timer/counter with multiple capture/compare registers. Timer can support multiple capture/compares, PWM outputs, and interval timing. Timer also has extensive interrupt capabilities. Interrupts may be generated from the counter on overflow conditions and from each of the capture/compare registers.

This peripheral API handles Timer A and Timer B hardware peripheral.

Timer features include:

- Asynchronous 16-bit timer/counter with four operating modes
- Selectable and configurable clock source
- Up to seven configurable capture/compare registers
- Configurable outputs with pulse width modulation (PWM) capability
- Asynchronous input and output latching
- Interrupt vector register for fast decoding of all Timer interrupts

Timer can operate in 3 modes

- Continuous Mode
- Up Mode
- Down Mode

Timer Interrupts may be generated on counter overflow conditions and during capture compare events.

The timer may also be used to generate PWM outputs. PWM outputs can be generated by initializing the compare mode with `Timer_initCompare()` and the necessary parameters. The PWM may be customized by selecting a desired timer mode (continuous/up/upDown), duty cycle, output mode, timer period etc. The library also provides a simpler way to generate PWM using `Timer_generatePWM()` API. However the level of customization and the kinds of PWM generated are limited in this API. Depending on how complex the PWM is and what level of customization is required, the user can use `Timer_generatePWM()` or a combination of `Timer_initCompare()` and timer start APIs

The timer API provides a set of functions for dealing with the timer module. Functions are provided to configure and control the timer, along with functions to modify timer/counter values, and to manage interrupt handling for the timer.

Control is also provided over interrupt sources and events. Interrupts can be generated to indicate that an event has been captured.

This driver is contained in `driverlib/5xx_6xx/timer.c`, with `driverlib/5xx_6xx/timer.h` containing the API definitions for use by applications.

## 21.2 API Functions

The timer API is broken into three groups of functions: those that deal with timer configuration and control, those that deal with timer contents, and those that deal with interrupt handling.

Timer configuration and initialization is handled by

- `Timer_startContinuousMode()`,
- `Timer_startUpMode()`,
- `Timer_startUpDownMode()`,
- `Timer_initCapture()`,
- `Timer_initCompare()`,
- `Timer_clear()`,
- `Timer_stop()`

Timer outputs are handled by

- `Timer_getSynchronizedCaptureCompareInput()`,
- `Timer_getOutputForOutputModeOutBitValue()`,
- `Timer_setOutputForOutputModeOutBitValue()`,
- `Timer_generatePWM()`
- `Timer_getCaptureCompareCount()`
- `Timer_setCompareValue()`

The interrupt handler for the Timer interrupt is managed with

- `Timer_enableInterrupt()`,
- `Timer_disableInterrupt()`,
- `Timer_getInterruptStatus()`,
- `Timer_enableCaptureCompareInterrupt()`,
- `Timer_disableCaptureCompareInterrupt()`,
- `Timer_getCaptureCompareInterruptStatus()`,
- `Timer_clearCaptureCompareInterruptFlag()`
- `Timer_clearTimerInterruptFlag()`

## 21.3 Programming Example

The following example shows some timer operations using the APIs

```
{
    Timer_startUpMode(    __MSP430_BASEADDRESS_TIMERB0__,
                        TIMER_CLOCKSOURCE_SMCLK,
                        TIMER_CLOCKSOURCE_DIVIDER_1,
                        TIMER_PERIOD,
                        TIMER_TAIE_INTERRUPT_DISABLE,
                        TIMER_CAPTURECOMPARE_CCIE_INTERRUPT_ENABLE,
                        TIMER_DO_CLEAR
    )
}
```

```
        );

        __bis_SR_register(LPM0_bits + GIE);    // Enter LPM0, enable interrupts
        __no_operation();                      // For debugger
    }

    // Timer B0 interrupt service routine
    #pragma vector=TIMERB0_VECTOR
    __interrupt void TIMERB0_ISR (void)
    {
        P1OUT ^= 0x01;                          // Toggle P1.0 using exclusive-OR
    }
```





## 22 Tag Length Value

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### 22.1 Introduction

The TLV structure is a table stored in flash memory that contains device-specific information. This table is read-only and is write-protected. It contains important information for using and calibrating the device. A list of the contents of the TLV is available in the device-specific data sheet (in the Device Descriptors section), and an explanation on its functionality is available in the MSP430x5xx/MSP430x6xx Family User's Guide.

This driver is contained in `driverlib/5xx_6xx/tlv.c`, with `driverlib/5xx_6xx/tlv.h` containing the API definitions for use by applications.

### 22.2 API Functions

The APIs that help in querying the information in the TLV structure are listed

- `TLV_getInfo()` This function retrieves the value of a tag and the length of the tag.
- `TLV_getDeviceType()` This function retrieves the unique device ID from the TLV structure.
- `TLV_getMemory()` The returned value is zero if the end of the memory list is reached.
- `TLV_getPeripheral()` The returned value is zero if the specified tag value (peripheral) is not available in the device.
- `TLV_getInterrupt()` The returned value is zero if the specified interrupt vector is not defined.

### 22.3 Programming Example

The following example shows some tlv operations using the APIs

```
struct s_TLV_Die_Record * pDIEREC;
unsigned char bDieRecord_bytes;

TLV_getInfo(TLV_TAG_DIERECORD,
            0,
            &bDieRecord_bytes,
            (unsigned int **)&pDIEREC
            );
```



## 23 UART

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### 23.1 Introduction

The MSP430Ware library for UART mode features include:

- Odd, even, or non-parity
- Independent transmit and receive shift registers
- Separate transmit and receive buffer registers
- LSB-first or MSB-first data transmit and receive
- Built-in idle-line and address-bit communication protocols for multiprocessor systems
- Receiver start-edge detection for auto wake up from LPMx modes
- Status flags for error detection and suppression
- Status flags for address detection
- Independent interrupt capability for receive and transmit

The modes of operations supported by the UART and the library include

- UART mode
- Idle-line multiprocessor mode
- Address-bit multiprocessor mode
- UART mode with automatic baud-rate detection

In UART mode, the USCI transmits and receives characters at a bit rate asynchronous to another device. Timing for each character is based on the selected baud rate of the USCI. The transmit and receive functions use the same baud-rate frequency.

This driver is contained in `driverlib/5xx_6xx/uart.c`, with `driverlib/5xx_6xx/uart.h` containing the API definitions for use by applications.

### 23.2 API Functions

The UART API provides the set of functions required to implement an interrupt driven UART driver. The UART initialization with the various modes and features is done by the `UART_init()`. At the end of this function UART is initialized and stays disabled. `UART_enable()` enables the UART and the module is now ready for transmit and receive. It is recommended to initialize the UART via `UART_init()`, enable the required interrupts and then enable UART via `UART_enable()`.

The UART API is broken into three groups of functions: those that deal with configuration and control of the UART modules, those used to send and receive data, and those that deal with interrupt handling and those dealing with DMA.

Configuration and control of the UART are handled by the

- UART\_init()
- UART\_enable()
- UART\_disable()
- UART\_setDormant()
- UART\_resetDormant()

Sending and receiving data via the UART is handled by the

- UART\_transmitData()
- UART\_receiveData()
- UART\_transmitAddress()
- UART\_transmitBreak()

Managing the UART interrupts and status are handled by the

- UART\_enableInterrupt()
- UART\_disableInterrupt()
- UART\_getInterruptStatus()
- UART\_clearInterruptFlag()
- UART\_queryStatusFlags()

DMA related

- UART\_getReceiveBufferAddressForDMA()
- UART\_getTransmitBufferAddressForDMA()

## 23.3 Programming Example

The following example shows how to use the UART API to initialize the UART, transmit characters, and receive characters.

```
if ( STATUS_FAIL == UART_init ( __MSP430_BASEADDRESS_USCI_A0__,
                                UART_CLOCKSOURCE_SMCLK,
                                UCS_getSMCLK ( __MSP430_BASEADDRESS_UCS__ ),
                                BAUD_RATE,
                                UART_NO_PARITY,
                                UART_LSB_FIRST,
                                UART_ONE_STOP_BIT,
                                UART_MODE,
                                UART_OVERSAMPLING_BAUDRATE_GENERATION ) )
{
    return;
}

//Enable UART module for operation
UART_enable ( __MSP430_BASEADDRESS_USCI_A0__ );

//Enable Receive Interrupt
UART_enableInterrupt ( __MSP430_BASEADDRESS_USCI_A0__,
                       UCRXIE );

//Transmit data
```

```

UART_transmitData(__MSP430_BASEADDRESS_USCI_A0__,
                  transmitData++
                  );

// Enter LPM3, interrupts enabled
__bis_SR_register(LPM3_bits + GIE);
__no_operation();
}

//*****
//
// This is the USCI_A0 interrupt vector service routine.
//
//*****
#pragma vector=USCI_A0_VECTOR
__interrupt void USCI_A0_ISR(void)
{
    switch(__even_in_range(UCA0IV,4))
    {
        // Vector 2 - RXIFG
        case 2:
            // Echo back RXed character, confirm TX buffer is ready first

            // USCI_A0 TX buffer ready?
            while (!UART_interruptStatus(__MSP430_BASEADDRESS_USCI_A0__,
                                         UCTXIFG)
                   );

            //Receive echoed data
            receivedData = UART_receiveData(__MSP430_BASEADDRESS_USCI_A0__);

            //Transmit next data
            UART_transmitData(__MSP430_BASEADDRESS_USCI_A0__,
                              transmitData++
                              );

            break;
        default: break;
    }
}

```



## 24 Unified Clock System (UCS)

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### 24.1 Introduction

The UCS is based on five available clock sources (VLO, REFO, XT1, XT2, and DCO) providing signals to three system clocks (MCLK, SMCLK, ACLK). Different low power modes are achieved by turning off the MCLK, SMCLK, ACLK, and integrated LDO.

- VLO - Internal very-low-power low-frequency oscillator. 10 kHz ( $\pm 0.5/\text{°C}$ ,  $\pm 4/\text{V}$ )
- REFO - Reference oscillator. 32 kHz ( $\pm 1\%$ ,  $\pm 3\%$  over full temp range)
- XT1 (LFXT1, HFXT1) - Ultra-low-power oscillator, compatible with low-frequency 32768-Hz watch crystals and with standard XT1 (LFXT1, HFXT1) crystals, resonators, or external clock sources in the 4-MHz to 32-MHz range, including digital inputs. Most commonly used as 32-kHz watch crystal oscillator.
- XT2 - Optional high-frequency oscillator that can be used with standard crystals, resonators, or external clock sources in the 4-MHz to 32-MHz range, including digital inputs.
- DCO - Internal digitally-controlled oscillator (DCO) that can be stabilized by a frequency lock loop (FLL) that sets the DCO to a specified multiple of a reference frequency.

System Clocks and Functionality on the MSP430 MCLK Master Clock Services the CPU. Commonly sourced by DCO. Is available in Active mode only SMCLK Subsystem Master Clock Services 'fast' system peripherals. Commonly sourced by DCO. Is available in Active mode, LPM0 and LPM1 ACLK Auxiliary Clock Services 'slow' system peripherals. Commonly used for 32-kHz signal. Is available in Active mode, LPM0 to LPM3

System clocks of the MSP430x5xx generation are automatically enabled, regardless of the LPM mode of operation, if they are required for the proper operation of the peripheral module that they source. This additional flexibility of the UCS, along with improved fail-safe logic, provides a robust clocking scheme for all applications.

**Fail-Safe logic** The UCS fail-safe logic plays an important part in providing a robust clocking scheme for MSP430x5xx and MSP430x6xx applications. This feature hinges on the ability to detect an oscillator fault for the XT1 in both low- and high-frequency modes (XT1LFOFFG and XT1HFOFFG respectively), the high-frequency XT2 (XT2OFFG), and the DCO (DCOFFG). These flags are set and latched when the respective oscillator is enabled but not operating properly; therefore, they must be explicitly cleared in software

The oscillator fault flags on previous MSP430 generations are not latched and are asserted only as long as the failing condition exists. Therefore, an important difference between the families is that the fail-safe behavior in a 5xx-based MSP430 remains active until both the OFIFG and the respective fault flag are cleared in software.

This fail-safe behavior is implemented at the oscillator level, at the system clock level and, consequently, at the module level. Some notable highlights of this behavior are described below. For the full description of fail-safe behavior and conditions, see the MSP430x5xx/MSP430x6xx Family User's Guide (SLAU208).

- Low-frequency crystal oscillator 1 (LFXT1) The low-frequency (32768 Hz) crystal oscillator is the default reference clock to the FLL. An asserted XT1LFOFFG switches the FLL reference from the failing LFXT1 to the internal 32-kHz REFO. This can influence the DCO accuracy, because the FLL crystal ppm specification is typically tighter than the REFO accuracy over temperature and voltage of  $\pm 3\%$ .
- System Clocks (ACLK, SMCLK, MCLK) A fault on the oscillator that is sourcing a system clock switches the source from the failing oscillator to the DCO oscillator (DCOCLKDIV). This is true for all clock sources except the LFXT1. As previously described, a fault on the LFXT1 switches the source to the REFO. Since ACLK is the active clock in LPM3 there is a notable difference in the LPM3 current consumption when the REFO is the clock source ( $\sim 3 \mu\text{A}$  active) versus the LFXT1 ( $\sim 300 \text{ nA}$  active).
- Modules (WDT\_A) In watchdog mode, when SMCLK or ACLK fails, the clock source defaults to the VLOCLK.

This driver is contained in `driverlib/5xx_6xx/ucs.c`, with `driverlib/5xx_6xx/ucs.h` containing the API definitions for use by applications.

## 24.2 API Functions

The UCS API is broken into three groups of functions: those that deal with clock configuration and control

General UCS configuration and initialization is handled by

- `UCS_clockSignalInit()`,
- `UCS_initFLLSettle()`,
- `UCS_enableClockRequest()`,
- `UCS_disableClockRequest()`,
- `UCS_SMCLKOff()`,
- `UCS_SMCLKOn()`

External crystal specific configuration and initialization is handled by

- `UCS_setExternalClockSource()`,
- `UCS_LFXT1Start()`,
- `UCS_HFXT1Start()`,
- `UCS_bypassXT1()`,
- `UCS_LFXT1StartWithTimeout()`,
- `UCS_HFXT1StartWithTimeout()`,
- `UCS_bypassXT1WithTimeout()`,
- `UCS_XT1Off()`,
- `UCS_XT2Start()`,
- `UCS_XT2Off()`,
- `UCS_bypassXT2()`,
- `UCS_XT2StartWithTimeout()`,



- UCS\_bypassXT2WithTimeout()
- UCS\_clearAllOscFlagsWithTimeout()

UCS\_setExternalClockSource must be called if an external crystal XT1 or XT2 is used and the user intends to call UCS\_getMCLK, UCS\_getSMCLK or UCS\_getACLK APIs. If not, it is not necessary to invoke this API.

Failure to invoke UCS\_clockSignalInit() sets the clock signals to the default modes ACLK default mode - UCS\_XT1CLK\_SELECT SMCLK default mode - UCS\_DCOCLKDIV\_SELECT MCLK default mode - UCS\_DCOCLKDIV\_SELECT

Also fail-safe mode behavior takes effect when a selected mode fails.

The status and configuration query are done by

- UCS\_faultFlagStatus(),
- UCS\_clearFaultFlag(),
- UCS\_getACLK(),
- UCS\_getSMCLK(),
- UCS\_getMCLK()

## 24.3 Programming Example

The following example shows some UCS operations using the APIs

```
// Set DCO FLL reference = REFO
UCS_clockSignalInit(
    __MSP430_BASEADDRESS_UCS__,
    UCS_FLLREF,
    UCS_REFOCLK_SELECT,
    UCS_CLOCK_DIVIDER_1
);

// Set ACLK = REFO
UCS_clockSignalInit(
    __MSP430_BASEADDRESS_UCS__,
    UCS_ACLK,
    UCS_REFOCLK_SELECT,
    UCS_CLOCK_DIVIDER_1
);

// Set Ratio and Desired MCLK Frequency and initialize DCO
UCS_initFLLSettle(
    __MSP430_BASEADDRESS_UCS__,
    UCS_MCLK_DESIREDFREQUENCY_IN_KHZ,
    UCS_MCLK_FLLREF_RATIO
);

//Verify if the Clock settings are as expected
clockValue = UCS_getSMCLK (__MSP430_BASEADDRESS_UCS__);

while(1);
```



## 25 WatchDog Timer (WDT)

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### 25.1 Introduction

The Watchdog Timer (WDT) API provides a set of functions for using the MSP430Ware WDT modules. Functions are provided to initialize the Watchdog in either timer interval mode, or watchdog mode, with selectable clock sources and dividers to define the timer interval.

The WDT module can generate only 1 kind of interrupt in timer interval mode. If in watchdog mode, then the WDT module will assert a reset once the timer has finished.

This driver is contained in `driverlib/5xx_6xx/wdt.c`, with `driverlib/5xx_6xx/wdt.h` containing the API definitions for use by applications.

### 25.2 API Functions

The WDT API is one group that controls the WDT module.

- WDT\_hold
- WDT\_start
- WDT\_clearCounter
- WDT\_watchdogTimerInit
- WDT\_intervalTimerInit

### 25.3 Programming Example

The following example shows how to initialize and use the WDT API to interrupt about every 32 ms, toggling the LED in the ISR.

```
// Initialize WDT module in timer interval mode,
// with SMCLK as source at an interval of 32 ms.
WDT_intervalTimerInit (__MSP430_BASEADDRESS_WDT_A__,
                      WDT_CLOCKSOURCE_SMCLK,
                      WDT_CLOCKDIVIDER_32K);

// Enable Watchdog Interrupt
SFR_enableInterrupt (__MSP430_BASEADDRESS_SFR__,
                    WDTIE);

P1DIR |= 0x01; // Set P1.0 to output direction

__bis_SR_register(LPM0_bits + GIE); // Enter LPM0, enable interrupts
__no_operation(); // For debugger
```

---

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