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Liangniu SDK cross-compilation environment description

- Liangniu SDK supports **CMake + ARM GCC** compilation;
- with SEGGER JLink, it can be burned and the GDB debugging server can be
- started; use the Visual Studio Code editor to load **the Cortex-Debug** plug-in for online debugging;

The instructions here are based on windows10 x64 and Ubuntu 20.04 x64.

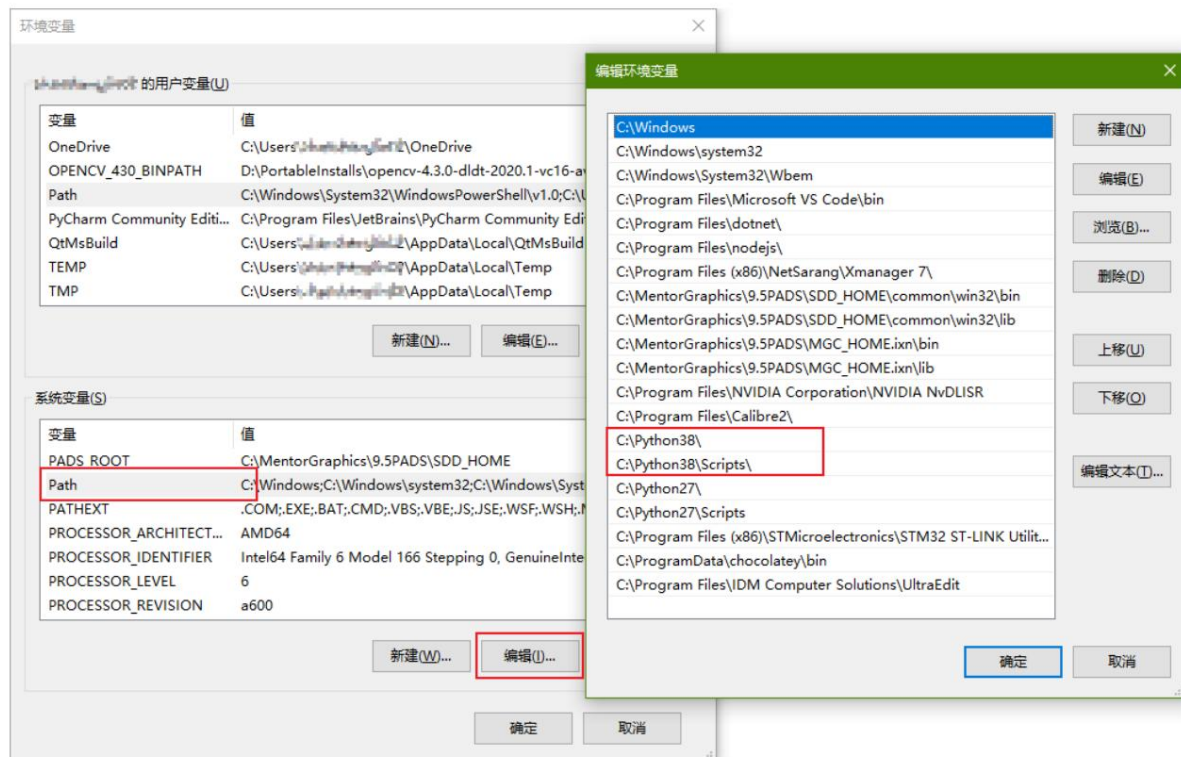
Software list

software	Introduction
Python3 (3.6 and above)	Python scripts are used in the build, and the SDK path cannot contain Chinese characters. Python2.x does not support it.
ARM GCC Compiler Suite	Choose ARM's official GNU Arm Embedded Toolchain: 10-2020-q4-major version.
CMake	Generate the corresponding Makefile file or build.ninja file according to the selected generator.
Ninja (recommended)	A build tool similar to Make that processes the build.ninja file generated by CMake much faster than Make .
Make (Linux version)	Read the Makefile generated by CMake and call the compiler suite to generate the target.
GNU MCU Eclipse Windows Build Tools (Windows version)	It is the windows version of GNU Make. It calls the GCC compilation suite to perform real compilation actions and generate executable image files.
SEGGER JLink	It can burn firmware and start the GDB debugging server. (Note that it is recommended to install V752d and below versions)
Visual Studio Code editor	Optional, but when debugging with gdb, this editor and additional plug-ins must be installed.

Software installation (Windows10 x64 example)

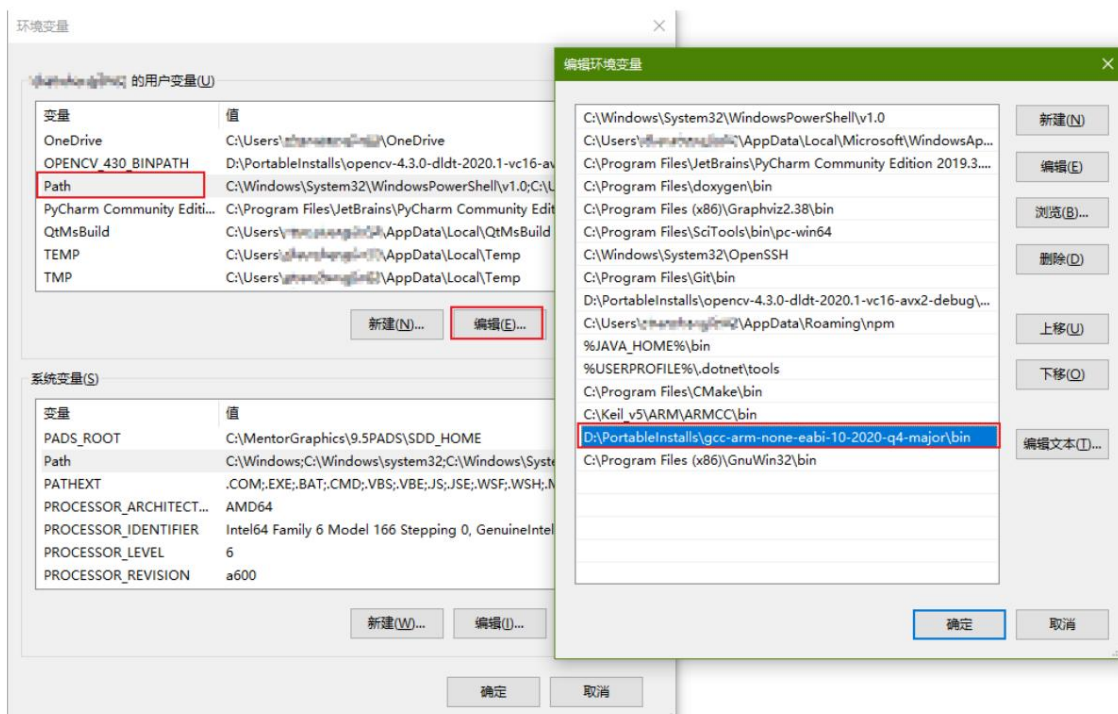
Python3

1. Installation: Double-click the Python3 installation package to install in the default way;
 2. **PATH** environment variable: Open the environment variable editor, edit the user or system environment variable PATH, and add the corresponding python3 installation path (can be placed after the Python2 path), An example is as follows:
 3. Enter the python3 installation path, copy python.exe and rename it to python3.exe .
- Enter python3 --version in the newly opened command line to check and confirm the version information;



ARM GCC Compiler Suite

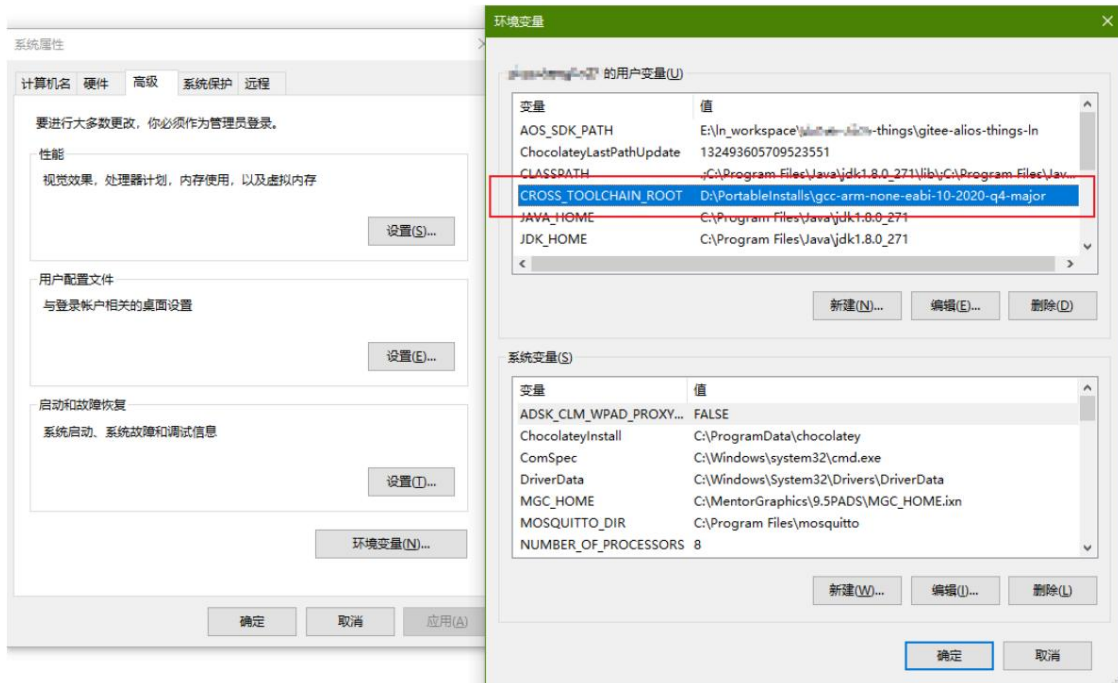
1. Unzip: **gcc-arm-none-eabi-10-2020-q4-major-win32.zip** is a green version, no installation is required, just unzip it to a certain directory, for example, unzip it to the D:\PortableInstalls directory;
2. **PATH** environment variable: Example is as follows



3. Check: Enter `arm-none-eabi-gcc --version` in the newly opened command line to confirm the version information.

breath;

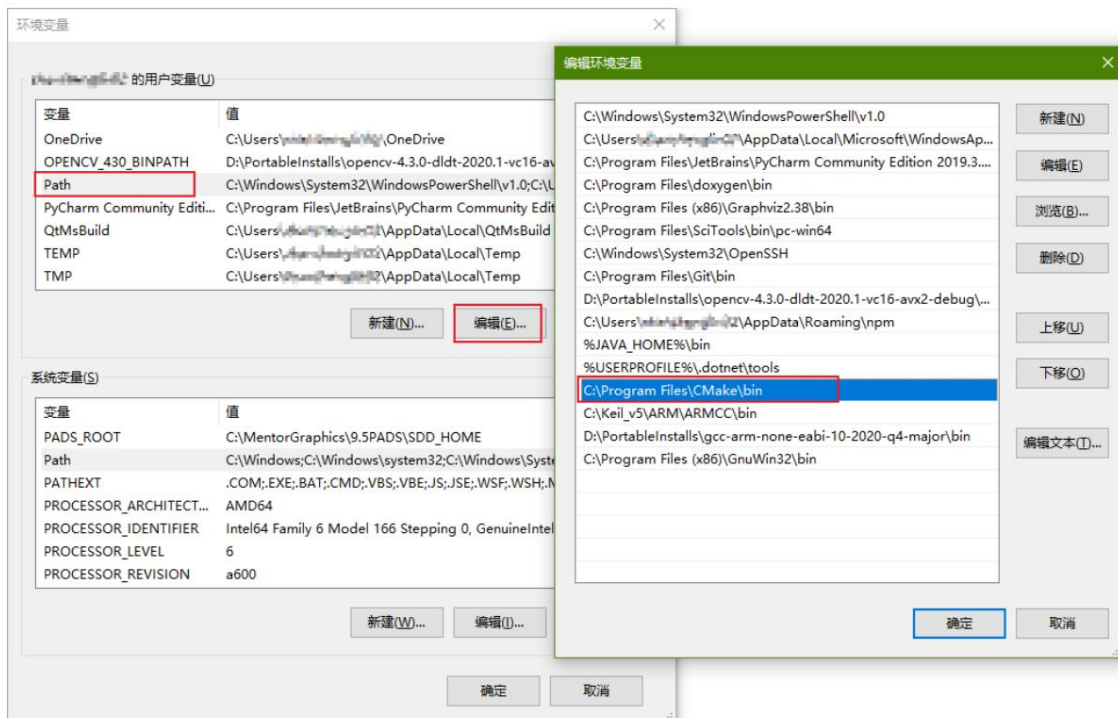
4. Add another environment variable **CROSS_TOOLCHAIN_ROOT**, its value is **D:\PortableInstalls\gcc-arm-none-eabi-10-2020-q4-major**, as shown below:



CMake

1. Installation: Double-click the installation package to install in the default

way; 2. **PATH** environment variable: Examples are as follows

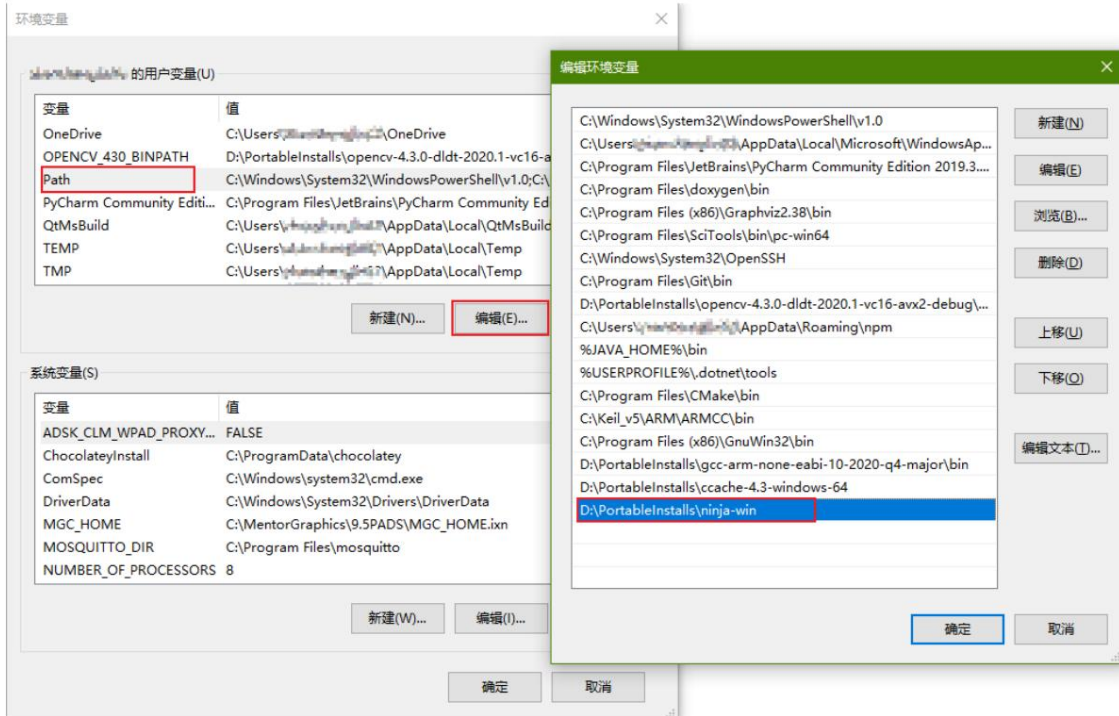


3. Check: Enter `cmake --version` in the newly opened command line to confirm the version information;

Ninja

1. Installation: Green version, just unzip it to a certain directory;

2. **PATH** environment variable: Examples are as follows:

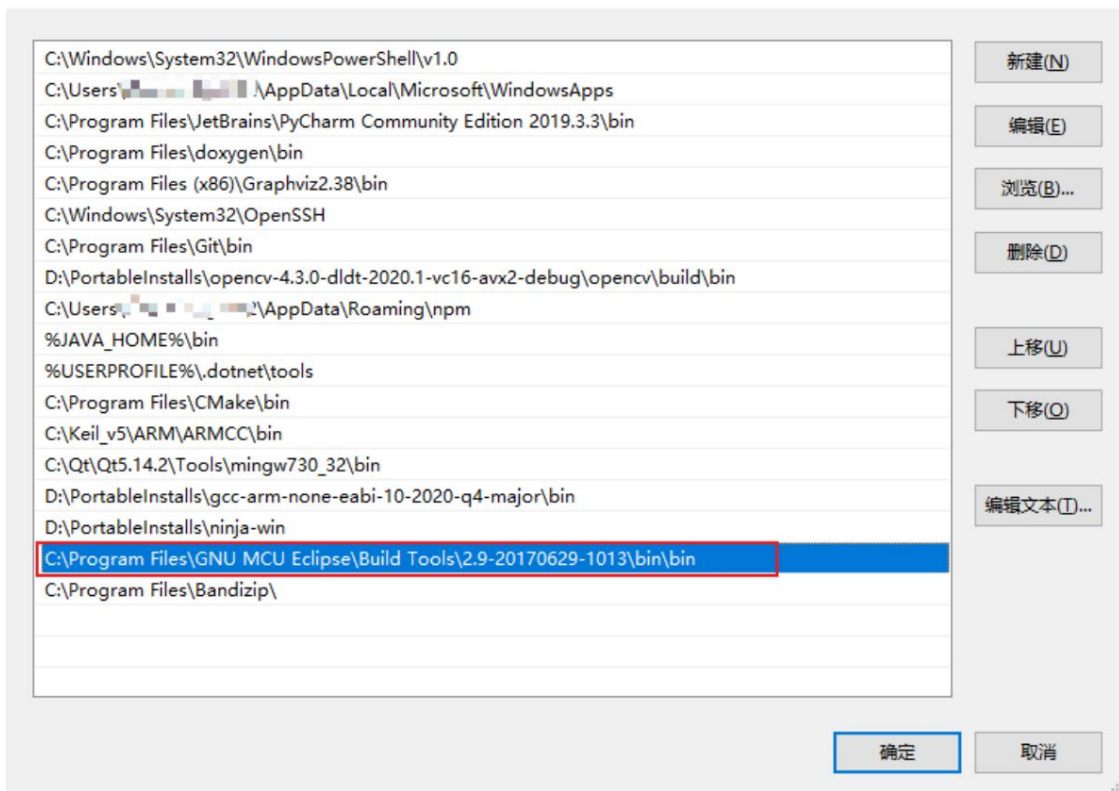


3. Check: Enter `ninja --version` in the newly opened command line to confirm the version information;

GNU MCU Eclipse Windows Build Tools

1. Installation: double-click to

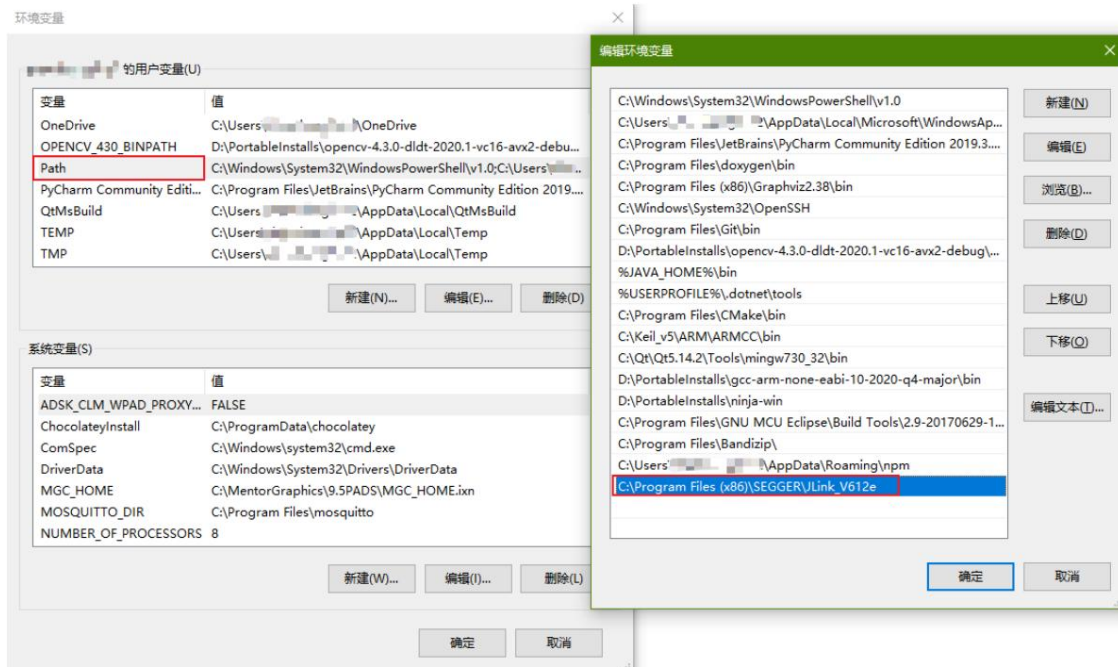
install; 2. **PATH** environment variable: as follows:



3. Check: Enter `make --version` in the newly opened command line to confirm the version information;

SEGGER JLink tool

1. Installation: Double-click to install, and the default option is to install;
2. **PATH** environment variable: as shown below:



3. Check: Enter JFlash.exe -? in the newly opened command line , if a window pops up.

Visual Studio Code editor

The Visual Studio Code editor is a lightweight and powerful source code editor that can achieve IDE-like effects with various plug-ins.

It is recommended to install the following plug-ins to edit source code and debug embedded programs:

1. **C/C++ IntelliSense**
2. **CMake**
3. **CMake Tools**
4. **Cortex-Debug** [and its configuration file refer to cortex-debug](#)

Software installation (Ubuntu 20.04 x64 example)

Install necessary software using a package manager

```
sudo apt-get install python3 cmake ninja-build make
```

Download other necessary software from the official website (Ubuntu version)

ARM GCC Compiler Suite

Select [gcc-arm-none-eabi-10-2020-q4-major-x86_64-linux.tar.bz2](#) from the download page

Unzip it to a directory and export the environment variables at the end of the ~/.bashrc file

```
CROSS_TOOLCHAIN_ROOT ŷ
```

```
1  # GCC ARM NONE EABI
2  export CROSS_TOOLCHAIN_ROOT=$HOME/PortableInstalls/gcc-arm-none-eabi-10-2020-q4-major
```

Open a new command line or enter source ~/.bashrc in the current command line to reload the environment variables.

SEGGER JLink tool

Select [v7.52d 64-bit DEB Installer](#) from the download page

Enter the command to install

```
sudo dpkg -i JLink_Linux_V752d_x86_64.deb
```

Visual Studio Code editor

Select .deb [64bit](#) from the [download page](#)

Enter the command to install

```
sudo dpkg -i code_1.59.1-1629375198_amd64.deb
```

Open vscode and install the following plug-ins:

1. **C/C++ IntelliSense**
2. **CMake**
3. **CMake Tools** 4.

Cortex-Debug. For its configuration file, please [refer to cortex-debug](#).