



MPLAB Harmony Core Help

MPLAB Harmony Integrated Software Framework

Driver Libraries Help

This section provides descriptions of the Driver libraries that are available in MPLAB Harmony.

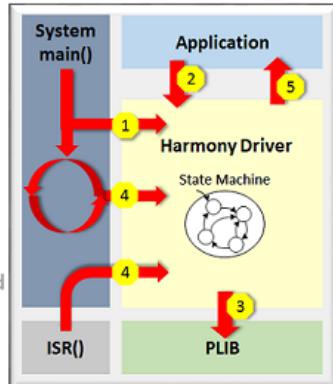
Introduction

This section provides descriptions of the Driver libraries that are available in MPLAB Harmony.

Description

MPLAB Harmony device drivers (usually referred to as "drivers") provide simple, highly abstracted C-language interfaces to peripherals and other resources. A driver's interface allows applications and other client modules to easily interact with the peripheral it controls using consistent usage models.

1. System Initializes Driver
 2. Application Calls Driver APIs
 3. Driver Starts Operation
 4. Interrupt Occurs and Runs Driver State Machine
 5. Driver finishes Operation and Notifies the Application
- Or
- System Runs the Driver State Machine



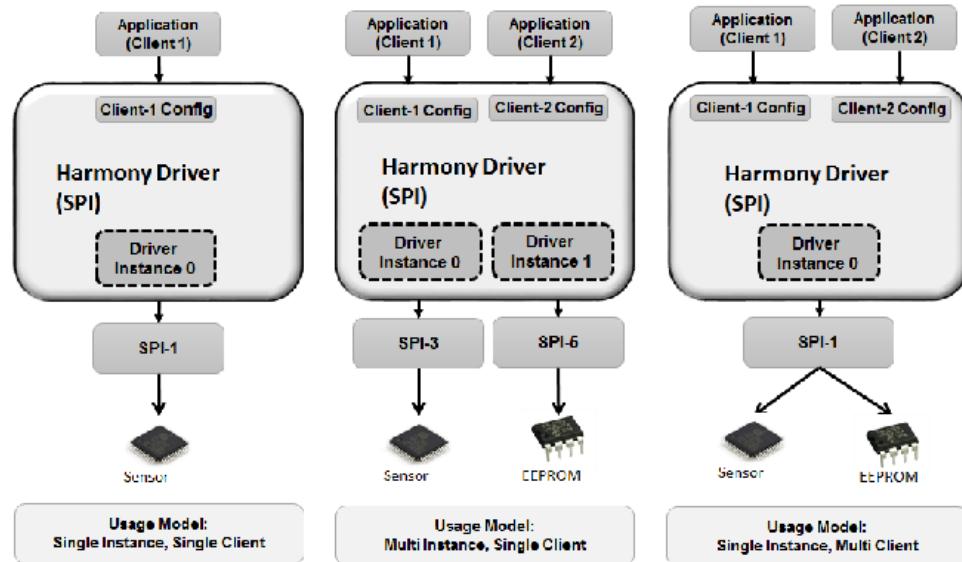
Harmony Driver Execution Flow

Harmony drivers provide:

- Same API for all the instances of a peripheral - This allows the application to remain the same when the peripheral instance is changed and across different platforms

USART Driver API	USART PLIB API
DRV_USART_WriteBufferAdd(...)	USART1_Write(...)
	USART2_Write(...)
DRV_USART_ReadBufferAdd(...)	USART1_Read(...)
	USART2_Read(...)
- Support for multiple clients - Seamlessly handle client specific differences. Drivers allow multiple clients to a driver instance. For example, there can be multiple application clients to a SPI driver instance having multiple SPI slaves. The SPI slave specific information such as clock phase, clock polarity, clock speed and chip select are all handled by the SPI driver based on the client that submitted the request
- Queue support - Drivers allow queuing of multiple requests. Each instance of a driver has a dedicated queue. The requests submitted by all the clients of the driver instance are queued in the driver instance queue. Queuing allows the application to submit requests before waiting for the driver to finish the previous requests. For each submitted request, the application can choose to get notified or poll the status of the submitted request using the handle provided by the driver for the submitted request
- Cache management - Drivers manage cache related operations on parts that have cache, thereby simplifying application development

Driver Usage Models:



- Single instance, single client - The driver manages a single instance of the peripheral and there is a single client (application) accessing the driver instance
- Multiple instances, single client (one client per driver instance) - The driver manages multiple instances of the peripheral and there is a single client to each instance of the driver. For example, the SPI driver instance 0 manages SPI peripheral instance 3 and SPI driver instance 1 manages SPI peripheral instance 5
- Single instance, multiple clients - Multiple clients to an instance of the driver. For example, there can be two application clients; one client interacting with SPI EEPROM and the second client interacting with SPI based temperature sensor, both interfaced to the same instance of SPI peripheral.

I2C Driver Library Help

This section describes the I²C driver library.

Introduction

This driver provides an interface to manage the data transfer operations using the I²C module.

Description

This driver library provides application ready routines to read and write data using the I²C protocol, thus minimizing developer's awareness of the working of the I²C protocol.

- Provides write, read and write-read transfers
- Support multi-client and multi-instance operation
- Provides data transfer events
- Supports Asynchronous and Synchronous modes of operation

Using the Library

This section describes the basic architecture of the I²C driver and provides information on how to use it.

Description

The I²C driver builds on top of the I²C peripheral library and provides write, read and write-read API's in blocking and non-blocking mode.

- Provides Write, Read and Write followed by Read API's.

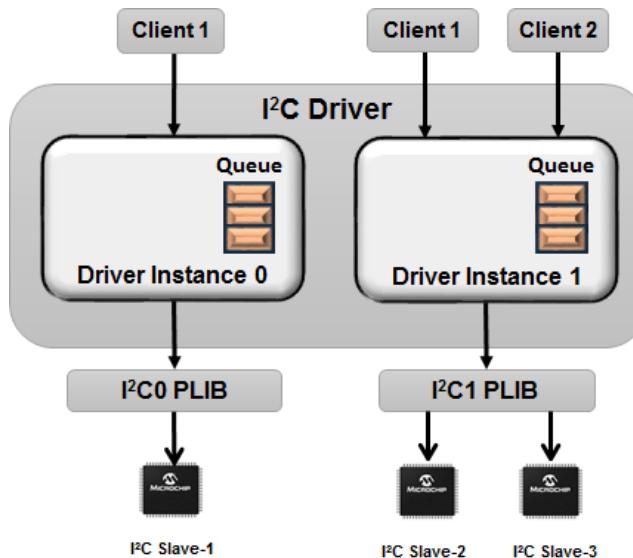
- Supports multiple slaves connected to the same I²C peripheral instance (multi-client mode).
- In *asynchronous* (non-blocking) mode, application can either register a callback to get notified once the data transfer is complete or can poll the status of the data transfer using the status related APIs.
- In *asynchronous* mode, application can queue more than one requests without waiting for the previous request to be completed. The number of requests that can be queued depends on the depth of the transfer queue configured using the MHC.
- The *asynchronous* mode is supported in both bare-meal and RTOS environment.
- The *synchronous* (blocking) mode of the driver provides a blocking behavior and is supported only in an RTOS environment.
- The *synchronous* mode of the driver does not support callback or queuing multiple requests. This is because the implementation is blocking in nature.

Abstraction Model

This section describes how the abstraction is modeled in software and introduces the library's interface.

Description

The following diagram illustrate the model used by the I²C Driver:



Note: Queue is not present in Synchronous mode of the driver.

How the Library Works

This section provides information on how the I²C driver Library works.

Description

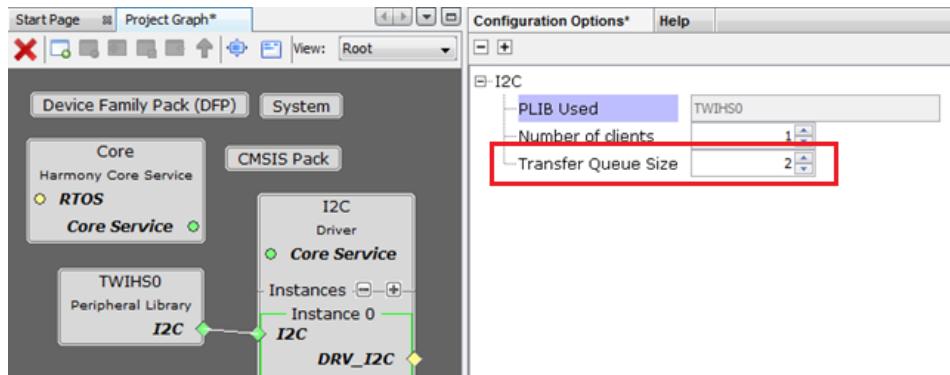
- The I²C driver is built on top of the I2C peripheral library
- The I²C driver registers a callback with the underlying I²C peripheral library to receive transfer related events from the peripheral library. The I²C driver callback is called by the peripheral library from the interrupt context
- Once the transfer is complete, the driver calls the callback registered by the application from the interrupt context or the application can poll the status of the transfer
- Each instance of the driver (in asynchronous/non-blocking mode) has a dedicated queue which can be configured using the MHC configuration options. The requests submitted by the clients are queued in the respective driver instance request queue
- The I²C driver is capable of supporting multiple instances of the I²C peripheral

Configuring the Library

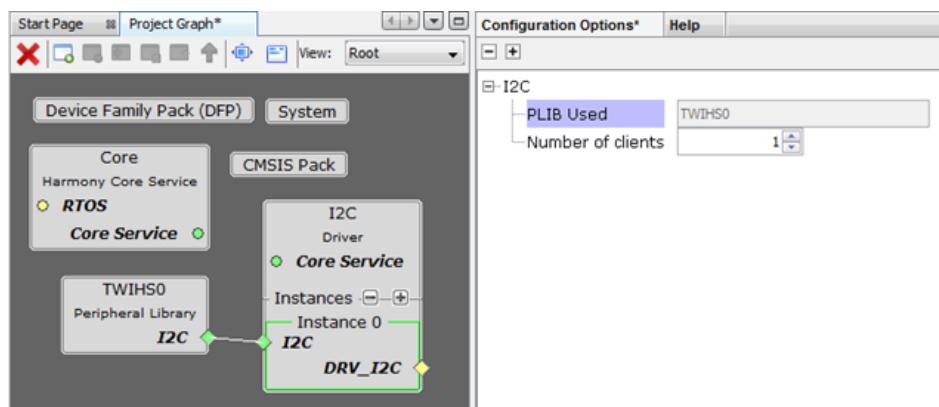
This section provides information on how to configure the I²C driver library.

Description

I²C Driver library should be configured via MHC. Below is the snapshot of the MHC configuration window for configuring the I²C driver in asynchronous and synchronous mode and a brief description of various configuration options.



Asynchronous Mode



Synchronous Mode

Common User Configuration for all Instances

- **Driver Mode:**
 - Allows User to select the mode of driver(Asynchronous or Synchronous). This setting is common for all the instances

Instance Specific User Configurations

- **PLIB Used:**
 - Indicates the underlying I²C peripheral library used by the driver
- **Number of clients:**
 - The total number of clients that can open the given I²C driver instance
- **Transfer Queue Size:**
 - Indicates the size of the transfer queue for the given I²C driver instance. Available only in Asynchronous mode

Building the Library

This section provides information on how the I²C Driver Library can be built.

Description



All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

Library Interface

a) System Functions

	Name	Description
≡	DRV_I2C_Initialize	Initializes the I2C instance for the specified driver index.
≡	DRV_I2C_Status	Gets the current status of the I2C driver module.

b) Core Client Functions

	Name	Description
≡	DRV_I2C_Open	Opens the specified I2C driver instance and returns a handle to it.
≡	DRV_I2C_Close	Closes an opened-instance of the I2C driver.
≡	DRV_I2C_TransferEventHandlerSet	Allows a client to identify a transfer event handling function for the driver to call back when queued transfers have finished.

c) Data Transfer Functions

	Name	Description
≡	DRV_I2C_ReadTransfer	This is a blocking function that performs a I2C read operation.
≡	DRV_I2C_ReadTransferAdd	Queues a read operation.
≡	DRV_I2C_WriteTransfer	This is a blocking function that performs a I2C write operation.
≡	DRV_I2C_WriteTransferAdd	Queues a write operation.
≡	DRV_I2C_WriteReadTransfer	This is a blocking function that performs a I2C write followed by a I2C read operation.
≡	DRV_I2C_WriteReadTransferAdd	Queues a write followed by read operation.
≡	DRV_I2C_TransferStatusGet	Returns the status of the write/read/write-read transfer request.
≡	DRV_I2C_ErrorGet	Gets the I2C hardware errors associated with the client.

d) Data Types and Constants

	Name	Description
	DRV_I2C_TRANSFER_HANDLE	Handle identifying a read, write or write followed by read transfer passed to the driver.
	DRV_I2C_TRANSFER_EVENT	Identifies the possible events that can result from a buffer add request.
	DRV_I2C_TRANSFER_EVENT_HANDLER	Pointer to a I2C Driver Transfer Event handler function
	DRV_I2C_TRANSFER_HANDLE_INVALID	Definition of an invalid transfer handle.

Description

This section describes the Application Programming Interface (API) functions of the I²C Driver Library.

Refer to each section for a detailed description.

a) System Functions

DRV_I2C_Initialize Function

Initializes the I2C instance for the specified driver index.

C

```
SYS_MODULE_OBJ DRV_I2C_Initialize(const SYS_MODULE_INDEX drvIndex, const SYS_MODULE_INIT * const init);
```

Returns

If successful, returns a valid handle to a driver instance object. Otherwise, returns [SYS_MODULE_OBJ_INVALID](#).

Description

This routine initializes the I2C driver instance for the specified driver index, making it ready for clients to open and use it. The initialization data is specified by the init parameter. The initialization may fail if the number of driver objects allocated are insufficient or if the specified driver instance is already initialized. The driver instance index is independent of the I2C peripheral instance it is associated with. For example, driver instance 0 can be assigned to I2C peripheral instance 2.

Remarks

This routine must be called before any other I2C routine is called. This routine should only be called once during system initialization.

Preconditions

None.

Example

```
// The following code snippet shows an example I2C driver initialization.

SYS_MODULE_OBJ objectHandle;

DRV_I2C_CLIENT_OBJ drvI2C0ClientObjPool[DRV_I2C_CLIENTS_NUMBER_IDX0] = {0};
DRV_I2C_TRANSFER_OBJ drvI2C0TransferObjPool[DRV_I2C_QUEUE_SIZE_IDX0] = {0};

DRV_I2C_PLIB_INTERFACE drvI2C0PLibAPI = {
    .read = (DRV_I2C_PLIB_READ)TWIHS0_Read,
    .write = (DRV_I2C_PLIB_WRITE)TWIHS0_Write,
    .writeRead = (DRV_I2C_PLIB_WRITE_READ)TWIHS0_WriteRead,
    .errorGet = (DRV_I2C_PLIB_ERROR_GET)TWIHS0_ErrorGet,
    .callbackRegister = (DRV_I2C_PLIB_CALLBACK_REGISTER)TWIHS0_CallbackRegister,
};

DRV_I2C_INIT drvI2C0InitData = {

    .i2cPlib = &drvI2C0PLibAPI,
    .numClients = DRV_I2C_CLIENTS_NUMBER_IDX0
    .clientObjPool = (uintptr_t)&drvI2C0ClientObjPool[0],
    .interruptI2C = DRV_I2C_INT_SRC_IDX0,
    .queueSize = DRV_I2C_QUEUE_SIZE_IDX0,
    .transferObj = (uintptr_t)&drvI2C0TransferObj[0],
    .clockSpeed = DRV_I2C_CLOCK_SPEED_IDX0,
};

objectHandle = DRV_I2C_Initialize(DRV_I2C_INDEX_0, (SYS_MODULE_INIT*)&drvI2C0InitData);
if (objectHandle == SYS_MODULE_OBJ_INVALID)
{
    // Handle error
}
```

Parameters

Parameters	Description
drvIndex	Identifier for the instance to be initialized
init	Pointer to the init data structure containing any data necessary to initialize the driver.

Function

[SYS_MODULE_OBJ DRV_I2C_Initialize](#)

```

(
const  SYS_MODULE_INDEX drvIndex,
const  SYS_MODULE_INIT * const init
)

```

DRV_I2C_Status Function

Gets the current status of the I2C driver module.

C

```
SYS_STATUS DRV_I2C_Status(const SYS_MODULE_OBJ object);
```

Returns

SYS_STATUS_READY - Initialization has succeeded and the I2C is ready for additional operations.

SYS_STATUS_UNINITIALIZED - Indicates that the driver is not initialized.

Description

This routine provides the current status of the I2C driver module.

Remarks

A driver can be opened only when its status is SYS_STATUS_READY.

Preconditions

Function [DRV_I2C_Initialize](#) should have been called before calling this function.

Example

```

SYS_MODULE_OBJ          object;      // Returned from DRV_I2C_Initialize
SYS_STATUS              i2cStatus;

i2cStatus = DRV_I2C_Status(object);
if (i2cStatus == SYS_STATUS_READY)
{
    // This means the driver can be opened using the
    // DRV_I2C_Open( ) function.
}

```

Parameters

Parameters	Description
object	Driver object handle, returned from the DRV_I2C_Initialize routine

Function

```
SYS_STATUS DRV_I2C_Status(const SYS_MODULE_OBJ object)
```

b) Core Client Functions

DRV_I2C_Open Function

Opens the specified I2C driver instance and returns a handle to it.

C

```
DRV_HANDLE DRV_I2C_Open(const SYS_MODULE_INDEX drvIndex, const DRV_IO_INTENT ioIntent);
```

Returns

If successful, the routine returns a valid open-instance handle (a number identifying both the caller and the module instance).

If an error occurs, the return value is [DRV_HANDLE_INVALID](#). Error can occur

- if the number of client objects allocated via [DRV_I2C_CLIENTS_NUMBER](#) is insufficient.
- if the client is trying to open the driver but driver has been opened exclusively by another client.
- if the driver instance being opened is not initialized or is invalid.
- if the client is trying to open the driver exclusively, but has already been opened in a non exclusive mode by another client.
- if the driver is not ready to be opened, typically when the initialize routine has not completed execution.

Description

This routine opens the specified I2C driver instance and provides a handle that must be provided to all other client-level operations to identify the caller and the instance of the driver. The [ioIntent](#) parameter defines how the client interacts with this driver instance.

Specifying a [DRV_IO_INTENT_EXCLUSIVE](#) will cause the driver to provide exclusive access to this client. The driver cannot be opened by any other client.

Remarks

The handle returned is valid until the [DRV_I2C_Close](#) routine is called.

Preconditions

Function [DRV_I2C_Initialize](#) must have been called before calling this function.

Example

```
DRV_HANDLE handle;

handle = DRV_I2C_Open(DRV_I2C_INDEX_0, DRV_IO_INTENT_EXCLUSIVE);
if (handle == DRV_HANDLE_INVALID)
{
    // Unable to open the driver
    // May be the driver is not initialized or the initialization
    // is not complete.
}
```

Parameters

Parameters	Description
drvIndex	Identifier for the object instance to be opened
ioIntent	Zero or more of the values from the enumeration DRV_IO_INTENT "ORed" together to indicate the intended use of the driver. See function description for details.

Function

```
DRV_HANDLE DRV_I2C_Open
(
const  SYS_MODULE_INDEX drvIndex,
const  DRV_IO_INTENT ioIntent
)
```

DRV_I2C_Close Function

Closes an opened-instance of the I2C driver.

C

```
void DRV_I2C_Close(const DRV_HANDLE handle);
```

Returns

None.

Description

This routine closes an opened-instance of the I2C driver, invalidating the handle. Any buffers in the driver queue that were submitted by this client will be removed. A new handle must be obtained by calling [DRV_I2C_Open](#) before the caller may use the

driver again.

Remarks

None.

Preconditions

[DRV_I2C_Open](#) must have been called to obtain a valid opened device handle.

Example

```
// 'handle', returned from the DRV_I2C_Open
DRV_I2C_Close(handle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
void DRV_I2C_Close( const DRV_HANDLE handle )
```

DRV_I2C_TransferEventHandlerSet Function

Allows a client to identify a transfer event handling function for the driver to call back when queued transfers have finished.

C

```
void DRV_I2C_TransferEventHandlerSet( const DRV_HANDLE handle, const
DRV_I2C_TRANSFER_EVENT_HANDLER eventHandler, const uintptr_t context);
```

Returns

None.

Description

This function allows a client to register a transfer event handling function with the driver to call back when queued transfers have finished. When a client calls either the [DRV_I2C_ReadTransferAdd](#), [DRV_I2C_WriteTransferAdd](#) or [DRV_I2C_WriteReadTransferAdd](#) function, it is provided with a handle identifying the transfer that was added to the driver's transfer queue. The driver will pass this handle back to the client by calling "eventHandler" function when the transfer has completed.

The event handler should be set before the client performs any "transfer add" operations that could generate events. The event handler once set, persists until the client closes the driver or sets another event handler (which could be a "NULL" pointer to indicate no callback).

Remarks

If the client does not want to be notified when the queued buffer transfer has completed, it does not need to register a callback. This function is thread safe when called in a RTOS application. This function is available only in the asynchronous mode.

Preconditions

[DRV_I2C_Open](#) must have been called to obtain a valid opened device handle.

Example

```
// myAppObj is an application specific state data object.
MY_APP_OBJ myAppObj;

uint8_t myBuffer[MY_BUFFER_SIZE];
DRV_I2C_TRANSFER_HANDLE transferHandle;

// myI2CHandle is the handle returned
// by the DRV_I2C_Open function.

// Client registers an event handler with driver. This is done once
```

```

DRV_I2C_TransferEventHandlerSet( myI2CHandle, APP_I2CTransferEventHandler, (uintptr_t)&myAppObj
);

DRV_I2C_ReadTransferAdd(myI2CHandle, slaveAddress, myBuffer, MY_BUFFER_SIZE, &transferHandle);

if(transferHandle == DRV_I2C_TRANSFER_HANDLE_INVALID)
{
    // Error handling here
}

// The registered event handler is called when the transfer is completed.

void APP_I2CTransferEventHandler(DRV_I2C_TRANSFER_EVENT event, DRV_I2C_TRANSFER_HANDLE handle,
uintptr_t context)
{
    // The context handle was set to an application specific
    // object. It is now retrievable easily in the event handler.
    MY_APP_OBJ* pMyAppObj = (MY_APP_OBJ *) context;

    switch(event)
    {
        case DRV_I2C_TRANSFER_EVENT_COMPLETE:
            // This means the data was transferred.
            break;

        case DRV_I2C_TRANSFER_EVENT_ERROR:
            // Error handling here.
            break;

        default:
            break;
    }
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine DRV_I2C_Open function.
eventHandler	Pointer to the event handler function.
context	The value of parameter will be passed back to the client unchanged, when the eventHandler function is called. It can be used to identify any client specific data object that identifies the instance of the client module (for example, it may be a pointer to the client module's state structure).

Function

```

void DRV_I2C_TransferEventHandlerSet
(
    const DRV_HANDLE handle,
    const DRV_I2C_TRANSFER_EVENT_HANDLER eventHandler,
    const uintptr_t context
)

```

c) Data Transfer Functions

DRV_I2C_ReadTransfer Function

This is a blocking function that performs a I2C read operation.

C

```
bool DRV_I2C_ReadTransfer(const DRV_HANDLE handle, uint16_t address, void* const buffer, const size_t size);
```

Returns

true - read is successful false - error has occurred

Description

This function does a blocking read operation. The function blocks till the read is complete or error has occurred during read. Function will return false to report failure. The failure will occur for the following reasons:

- Invalid input parameters
- Hardware error

Remarks

This function is thread safe in a RTOS application. This function should not be called from an interrupt context. This function is available only in the synchronous mode.

Preconditions

[DRV_I2C_Open](#) must have been called to obtain a valid opened device handle.

Example

```
uint8_t myRxBuffer[MY_RX_BUFFER_SIZE];

// myI2CHandle is the handle returned
// by the DRV_I2C_Open function.

// slaveAddress is address of I2C slave device
// to which data is to be written

if (DRV_I2C_ReadTransfer(myI2CHandle, slaveAddress, myRxBuffer, MY_RX_BUFFER_SIZE) == false)
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine DRV_I2C_Open function.
address	Slave Address
buffer	Destination buffer where read data is stored.
size	Size in bytes of data to be read.

Function

```
bool DRV_I2C_ReadTransfer(
    const DRV_HANDLE handle,
    uint16_t address,
    void* const buffer,
    const size_t size
)
```

DRV_I2C_ReadTransferAdd Function

Queues a read operation.

C

```
void DRV_I2C_ReadTransferAdd(const DRV_HANDLE handle, const uint16_t address, void * const
```

```
buffer, const size_t size, DRV_I2C_TRANSFER_HANDLE * const transferHandle);
```

Returns

None

Description

This function schedules a non-blocking read operation. The function returns with a valid transfer handle in the transferHandle argument if the read request was scheduled successfully. The function adds the request to the driver instance transfer queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. The function returns [DRV_I2C_TRANSFER_HANDLE_INVALID](#) in the transferHandle argument:

- if a buffer could not be allocated to the request
- if the input buffer pointer is NULL
- if the buffer size is 0
- if the driver handle is invalid

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_I2C_TRANSFER_EVENT_COMPLETE](#) event if the buffer was processed successfully or [DRV_I2C_TRANSFER_EVENT_ERROR](#) event if the buffer was not processed successfully.

Remarks

This function is thread safe in a RTOS application. It can be called from within the I2C Driver Transfer Event Handler that is registered by the client. It should not be called in the event handler associated with another I2C driver instance. It should not be called directly in an ISR. This function is available only in the asynchronous mode.

Preconditions

[DRV_I2C_Open](#) must have been called to obtain a valid opened device handle.

Example

```
uint8_t myBuffer[MY_BUFFER_SIZE];
DRV_I2C_TRANSFER_HANDLE transferHandle;

// myI2CHandle is the handle returned
// by the DRV_I2C_Open function.

// slaveAddress is address of I2C slave device
// to which data is to be written

DRV_I2C_ReadTransferAdd(myI2CHandle, slaveAddress, myBuffer, MY_BUFFER_SIZE, &transferHandle);

if(transferHandle == DRV_I2C_TRANSFER_HANDLE_INVALID)
{
    // Error handling here
}

// Event is received when the buffer is processed.
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine DRV_I2C_Open function.
address	Slave address
buffer	buffer where the read data will be stored.
size	Transfer size in bytes.
transferHandle	Pointer to an argument that will contain the return transfer handle. This is DRV_I2C_TRANSFER_HANDLE_INVALID if the request was not successful.

Function

```
void DRV_I2C_ReadTransferAdd(
    const DRV_HANDLE handle,
    const uint16_t address,
```

```

void * const buffer,
const size_t size,
DRV_I2C_TRANSFER_HANDLE * const transferHandle
)

```

DRV_I2C_WriteTransfer Function

This is a blocking function that performs a I2C write operation.

C

```
bool DRV_I2C_WriteTransfer(const DRV_HANDLE handle, uint16_t address, void* const buffer, const size_t size);
```

Returns

true - write is successful false - error has occurred

Description

This function does a blocking write operation. The function blocks till the write is complete or error has occurred during write. Function will return false to report failure. The failure will occur for the following reasons:

- Invalid input parameters

Remarks

This function is thread safe in a RTOS application. This function should not be called from an interrupt context. This function is available only in the synchronous mode.

Preconditions

[DRV_I2C_Open](#) must have been called to obtain a valid opened device handle.

Example

```

uint8_t myTxBuffer[MY_TX_BUFFER_SIZE];

// myI2CHandle is the handle returned
// by the DRV_I2C_Open function.

// slaveAddress is address of I2C slave device
// to which data is to be written

if (DRV_I2C_WriteTransfer(myI2CHandle, slaveAddress, myTxBuffer, MY_TX_BUFFER_SIZE) == false)
{
    // Error handling here
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine DRV_I2C_Open function.
address	Slave Address
buffer	Source buffer containing data to be written.
size	Size in bytes of data to be written.

Function

```

bool DRV_I2C_WriteTransfer(
const DRV_HANDLE handle,
uint16_t address,
void* const buffer,
const size_t size

```

)

DRV_I2C_WriteTransferAdd Function

Queues a write operation.

C

```
void DRV_I2C_WriteTransferAdd(const DRV_HANDLE handle, const uint16_t address, void * const
buffer, const size_t size, DRV_I2C_TRANSFER_HANDLE * const transferHandle);
```

Returns

None.

Description

This function schedules a non-blocking write operation. The function returns with a valid transfer handle in the transferHandle argument if the write request was scheduled successfully. The function adds the request to the driver instance transfer queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. On returning, the transferHandle parameter may be [DRV_I2C_TRANSFER_HANDLE_INVALID](#) for the following reasons:

- if a transfer buffer could not be allocated to the request
- if the input buffer pointer is NULL
- if the buffer size is 0

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_I2C_TRANSFER_EVENT_COMPLETE](#) event if the buffer was processed successfully or a [DRV_I2C_TRANSFER_EVENT_ERROR](#) event if the buffer was not processed successfully.

Remarks

This function is thread safe in a RTOS application. It can be called from within the I2C Driver Transfer Event Handler that is registered by this client. It should not be called in the event handler associated with another I2C driver instance. It should not otherwise be called directly in an ISR. This function is available only in the asynchronous mode.

Preconditions

[DRV_I2C_Open](#) must have been called to obtain a valid opened device handle.

Example

```
uint8_t myBuffer[MY_BUFFER_SIZE];
DRV_I2C_TRANSFER_HANDLE transferHandle;

// myI2CHandle is the handle returned
// by the DRV_I2C_Open function.

// slaveAddress is address of I2C slave device
// to which data is to be written

DRV_I2C_WriteTransferAdd(myI2CHandle, slaveAddress, myBuffer, MY_BUFFER_SIZE, &transferHandle);

if(transferHandle == DRV_I2C_TRANSFER_HANDLE_INVALID)
{
    // Error handling here
}

// Event is received when the buffer is processed.
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine DRV_I2C_Open function.
address	Slave address
buffer	Data to be written.

size	Transfer size in bytes.
transferHandle	Pointer to an argument that will contain the return transfer handle. This will be DRV_I2C_TRANSFER_HANDLE_INVALID if the function was not successful.

Function

```
void DRV_I2C_WriteTransferAdd(
    const DRV\_HANDLE handle,
    const uint16_t address,
    void * const buffer,
    const size_t size,
    DRV\_I2C\_TRANSFER\_HANDLE * const transferHandle
)
```

DRV_I2C_WriteReadTransfer Function

This is a blocking function that performs a I2C write followed by a I2C read operation.

C

```
bool DRV_I2C_WriteReadTransfer(const DRV\_HANDLE handle, uint16_t address, void* const
    writeBuffer, const size_t writeSize, void* const readBuffer, const size_t readSize);
```

Returns

true - transfer is successful false - error has occurred

Description

This function does a blocking write and read operation. The function blocks till the write and read is complete or error has occurred during data transfer. Function will return false to report failure. The failure will occur for the following reasons:

- Invalid input parameters
- Hardware error

Remarks

This function is thread safe in a RTOS application. This function should not be called from an interrupt context. This function is available only in the synchronous mode.

Preconditions

[DRV_I2C_Open](#) must have been called to obtain a valid opened device handle.

Example

```
uint8_t myTxBuffer[MY_TX_BUFFER_SIZE];
uint8_t myRxBuffer[MY_RX_BUFFER_SIZE];

// myI2CHandle is the handle returned
// by the DRV\_I2C\_Open function.

// slaveAddress is address of I2C slave device
// to which data is to be written

if (DRV_I2C_WriteReadTransfer(myI2CHandle, slaveAddress, myTxBuffer, MY_TX_BUFFER_SIZE,
    myRxBuffer, MY_RX_BUFFER_SIZE) == false)
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine DRV_I2C_Open function.

address	Slave Address
writeBuffer	Source buffer containing data to be written.
writeSize	Size in bytes of data to be written.
readBuffer	Destination buffer where read data is stored.
readSize	Size in bytes of data to be read.

Function

```
bool DRV_I2C_WriteReadTransfer (
    const DRV_HANDLE handle,
    uint16_t address,
    void* const writeBuffer,
    const size_t writeSize,
    void* const readBuffer,
    const size_t readSize
)
```

DRV_I2C_WriteReadTransfer Function

Queues a write followed by read operation.

C

```
void DRV_I2C_WriteReadTransferAdd(const DRV_HANDLE handle, const uint16_t address, void * const
writeBuffer, const size_t writeSize, void * const readBuffer, const size_t readSize,
DRV_I2C_TRANSFER_HANDLE * const transferHandle);
```

Returns

None.

Description

This function schedules a non-blocking write followed by read operation. The function returns with a valid transfer handle in the transferHandle argument if the write request was scheduled successfully. The function adds the request to the driver instance transfer queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. On returning, the transferHandle parameter may be [DRV_I2C_TRANSFER_HANDLE_INVALID](#) for the following reasons:

- if a buffer could not be allocated to the request
- if the input write or read buffer pointer is NULL
- if the write or read buffer size is 0

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_I2C_TRANSFER_EVENT_COMPLETE](#) event if the buffer was processed successfully or a [DRV_I2C_TRANSFER_EVENT_ERROR](#) event if the buffer was not processed successfully.

Remarks

This function is thread safe in a RTOS application. It can be called from within the I2C Driver Transfer Event Handler that is registered by this client. It should not be called in the event handler associated with another I2C driver instance. It should not otherwise be called directly in an ISR. This function is available only in the asynchronous mode.

Preconditions

[DRV_I2C_Open](#) must have been called to obtain a valid opened device handle.

Example

```
uint8_t myTxBuffer[MY_TX_BUFFER_SIZE];
uint8_t myRxBuffer[MY_RX_BUFFER_SIZE];
DRV_I2C_TRANSFER_HANDLE transferHandle;

// myI2CHandle is the handle returned
// by the DRV_I2C_Open function.
```

```

// slaveAddress is address of I2C slave device
// to which data is to be written

DRV_I2C_WriteReadTransferAdd(myI2CHandle, slaveAddress, myTxBuffer, MY_TX_BUFFER_SIZE,
myRxBuffer, MY_RX_BUFFER_SIZE, &transferHandle);

if(transferHandle == DRV_I2C_TRANSFER_HANDLE_INVALID)
{
    // Error handling here
}

// Event is received when the buffer is processed.

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine DRV_I2C_Open function.
address	Slave address
writeBuffer	Data to be written.
writeSize	Size of write buffer in bytes.
readBuffer	Buffer where data to be read is stored.
readSize	Size of the read buffer in bytes.
transferHandle	Pointer to an argument that will contain the return transfer handle. This will be DRV_I2C_TRANSFER_HANDLE_INVALID if the function was not successful.

Function

```

void DRV_I2C_WriteReadTransferAdd (
    const     DRV_HANDLE handle,
    const uint16_t address,
    void * const writeBuffer,
    const size_t writeSize,
    void * const readBuffer,
    const size_t readSize,
    DRV_I2C_TRANSFER_HANDLE * const transferHandle
)

```

DRV_I2C_TransferStatusGet Function

Returns the status of the write/read/write-read transfer request.

C

```
DRV_I2C_TRANSFER_EVENT DRV_I2C_TransferStatusGet(const DRV_I2C_TRANSFER_HANDLE transferHandle);
```

Returns

The success or error event of the transfer.

Description

This function can be used to poll the status of the queued transfer request if the application doesn't prefer to use the event handler (callback) function to get notified.

Remarks

This function is available only in the asynchronous mode.

Preconditions

[DRV_I2C_Open](#) must have been called to obtain a valid opened device handle.

Either the `DRV_I2C_ReadTransferAdd`, `DRV_I2C_WriteTransferAdd` or `DRV_I2C_WriteReadTransferAdd` function must have been called and a valid buffer handle returned.

Example

```
uint8_t myBuffer[MY_BUFFER_SIZE];
DRV_I2C_TRANSFER_HANDLE transferHandle;
DRV_I2C_TRANSFER_EVENT event;

// myI2CHandle is the handle returned
// by the DRV_I2C_Open function.

DRV_I2C_ReadTransferAdd(myI2CHandle, slaveAddress, myBuffer, MY_BUFFER_SIZE, &transferHandle);

if(transferHandle == DRV_I2C_TRANSFER_HANDLE_INVALID)
{
    // Error handling here
}

//Check the status of the transfer
//This call can be used to wait until the transfer is processed.

event = DRV_I2C_TransferStatusGet(transferHandle);
```

Parameters

Parameters	Description
transferHandle	Handle for the buffer of which the processed number of bytes to be obtained.

Function

```
DRV_I2C_TRANSFER_EVENT DRV_I2C_TransferStatusGet(
const DRV_I2C_TRANSFER_HANDLE transferHandle
)
```

DRV_I2C_ErrorGet Function

Gets the I2C hardware errors associated with the client.

C

```
DRV_I2C_ERROR DRV_I2C_ErrorGet(const DRV_HANDLE handle);
```

Returns

Errors occurred as listed by `DRV_I2C_ERROR`. This function reports I2C errors if occurred.

Description

This function returns the errors associated with the given client. The call to this function also clears all the associated error flags.

Remarks

The driver clears all the errors internally.

Preconditions

`DRV_I2C_Open` must have been called to obtain a valid opened device handle.

Example

```
// 'handle', returned from the DRV_I2C_Open

if (DRV_I2C_ErrorGet(handle) == DRV_I2C_ERROR_NACK)
{
    //Errors are cleared by the driver, take respective action
    //for the error case.
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine DRV_I2C_Open function.

Function

DRV_I2C_ERROR DRV_I2C_ErrorGet(const [DRV_HANDLE](#) handle)

d) Data Types and Constants

DRV_I2C_TRANSFER_HANDLE Type

Handle identifying a read, write or write followed by read transfer passed to the driver.

C

```
typedef uintptr_t DRV_I2C_TRANSFER_HANDLE;
```

Description

I2C Driver Transfer Handle

A transfer handle value is returned by a call to the [DRV_I2C_ReadTransferAdd](#)/ [DRV_I2C_WriteTransferAdd](#) or [DRV_I2C_WriteReadTransferAdd](#) functions. This handle is associated with the transfer passed into the function and it allows the application to track the completion of the data from (or into) that transfer. The transfer handle value returned from the "transfer add" function is returned back to the client by the "event handler callback" function registered with the driver.

The transfer handle assigned to a client request expires when the client has been notified of the completion of the buffer transfer (after event handler function that notifies the client returns) or after the transfer has been retired by the driver if no event handler callback was set.

Remarks

None

DRV_I2C_TRANSFER_EVENT Enumeration

Identifies the possible events that can result from a buffer add request.

C

```
typedef enum {
    DRV_I2C_TRANSFER_EVENT_PENDING = 0,
    DRV_I2C_TRANSFER_EVENT_COMPLETE = 1,
    DRV_I2C_TRANSFER_EVENT_HANDLE_EXPIRED = 2,
    DRV_I2C_TRANSFER_EVENT_ERROR = -1,
    DRV_I2C_TRANSFER_EVENT_HANDLE_INVALID = -2
} DRV_I2C_TRANSFER_EVENT;
```

Members

Members	Description
DRV_I2C_TRANSFER_EVENT_PENDING = 0	Transfer request is pending
DRV_I2C_TRANSFER_EVENT_COMPLETE = 1	All data from or to the buffer was transferred successfully.
DRV_I2C_TRANSFER_EVENT_HANDLE_EXPIRED = 2	Transfer Handle given is expired. It means transfer is completed but with or without error is not known.
DRV_I2C_TRANSFER_EVENT_ERROR = -1	There was an error while processing the buffer transfer request.

Description

I2C Driver Transfer Events

This enumeration identifies the possible events that can result from a buffer add request caused by the client calling either the [DRV_I2C_ReadTransferAdd](#), [DRV_I2C_WriteTransferAdd](#) or [DRV_I2C_WriteReadTransferAdd](#) functions.

Remarks

One of these values is passed in the "event" parameter of the event handling callback function that the client registered with the driver by calling the [DRV_I2C_TransferEventHandlerSet](#) function when a buffer transfer request is completed.

DRV_I2C_TRANSFER_EVENT_HANDLER Type

Pointer to a I2C Driver Transfer Event handler function

C

```
typedef void (* DRV_I2C_TRANSFER_EVENT_HANDLER)(DRV_I2C_TRANSFER_EVENT event,
DRV_I2C_TRANSFER_HANDLE transferHandle, uintptr_t context);
```

Returns

None.

Description

I2C Driver Transfer Event Handler Function Pointer

This data type defines the required function signature for the I2C driver buffer event handling callback function. A client must register a pointer using the buffer event handling function whose function signature (parameter and return value types) match the types specified by this function pointer in order to receive buffer related event calls back from the driver.

The parameters and return values are described here and a partial example implementation is provided.

Remarks

If the event is [DRV_I2C_TRANSFER_EVENT_COMPLETE](#), it means that the data was transferred successfully.

If the event is [DRV_I2C_TRANSFER_EVENT_ERROR](#), it means that the data was not transferred successfully.

The transferHandle parameter contains the transfer handle of the transfer that associated with the event. And transferHandle will be valid while the transfer request is in the queue and during callback, unless an error occurred. After callback returns, the driver will retire the transfer handle.

The context parameter contains the a handle to the client context, provided at the time the event handling function was registered using the [DRV_I2C_TransferEventHandlerSet](#) function. This context handle value is passed back to the client as the "context" parameter. It can be any value necessary to identify the client context or instance (such as a pointer to the client's data) instance of the client that made the buffer add request.

The event handler function executes in the peripheral's interrupt context. It is recommended of the application to not perform process intensive or blocking operations with in this function.

The [DRV_I2C_ReadTransferAdd](#), [DRV_I2C_WriteTransferAdd](#) and [DRV_I2C_WriteReadTransferAdd](#) functions can be called in the event handler to add a buffer to the driver queue. These functions can only be called to add buffers to the driver whose event handler is running. For example, I2C2 driver buffers cannot be added in I2C1 driver event handler.

Example

```
void APP_MyTransferEventHandler( DRV_I2C_TRANSFER_EVENT event,
                                DRV_I2C_TRANSFER_HANDLE transferHandle,
                                uintptr_t context )
{
    MY_APP_DATA_STRUCT* pAppData = (MY_APP_DATA_STRUCT*) context;

    switch(event)
    {
        case DRV_I2C_TRANSFER_EVENT_COMPLETE:
            // Handle the completed buffer.
            break;
    }
}
```

```

    case DRV_I2C_TRANSFER_EVENT_ERROR:
    default:

        // Handle error.
        break;
    }
}

```

Parameters

Parameters	Description
event	Identifies the type of event
transferHandle	Handle identifying the buffer to which the event relates
context	Value identifying the context of the application that registered the event handling function.

DRV_I2C_TRANSFER_HANDLE_INVALID Macro

Definition of an invalid transfer handle.

C

```
#define DRV_I2C_TRANSFER_HANDLE_INVALID
```

Description

I2C Driver Invalid Transfer Handle

This is the definition of an invalid transfer handle. An invalid transfer handle is returned by [DRV_I2C_ReadTransferAdd](#), [DRV_I2C_WriteTransferAdd](#) and [DRV_I2C_WriteReadTransferAdd](#) functions if the buffer add request was not successful.

Remarks

None

I2C EEPROM Driver Libraries Help

This section describes the I²C EEPROM based driver libraries.

AT24 Driver Library Help

This section describes the AT24 External EEPROM driver library.

Introduction

This driver provides an interface to access the external AT24 EEPROM over the I²C interface.

Description

This library provides a non-blocking interface to read and write to the external AT24 EEPROM. The library uses the I²C (or TWIHS) PLIB to interface with the AT24 EEPROM.

Key Features:

- Supports a single instance of the AT24 EEPROM and a single client to the driver
- Supports page writes
- Supports writes to random memory address and across page boundaries
- The library can be used in both bare-metal and RTOS environments

Using the Library

This section describes the basic architecture of the AT24 Library and provides information on how to use the library.

Description

The AT24 library provides non-blocking APIs to read and write to external AT24 EEPROM. It uses the I²C (or TWIHS) peripheral library to interface with the AT24 EEPROM.

- The library provides APIs to perform reads/writes from/to any EEPROM memory address, with number of bytes spanning multiple pages
- The library provides API to perform page write to EEPROM. Here, the memory start address must be aligned to the EEPROM page boundary
- Application can either register a callback to get notified once the data transfer is complete or can poll the status of the data transfer
- The library can be used in both bare-metal and RTOS environments

Abstraction Model

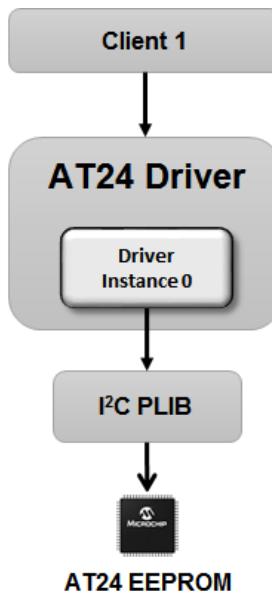
This library provides an abstraction of the AT24 Driver library.

Description

The AT24 library interface provides read and write functions that abstract out the internal workings of the AT24 driver and the underlying I²C (or TWIHS) protocol. The AT24 library supports a single instance of the AT24 EEPROM and a single client.

The client can be:

- Application - Directly access the AT24 EEPROM using the APIs provided by the AT24 library
- Memory Driver - Application can run a file system on the AT24 EEPROM by connecting it to the Memory Driver which can further be connected to the File System Service



How the Library Works

This section describes the basic architecture of the AT24 Driver Library and provides information on how the library works.

Description

- The AT24 Driver Library registers an event handler with the underlying I²C (or TWIHS) peripheral library. This event handler is

called by the PLIB from the interrupt context to notify the AT24 driver that the requested transfer is complete

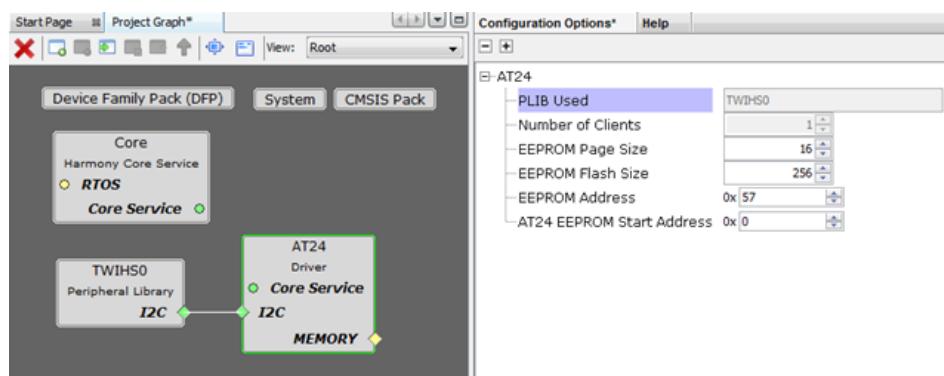
- The library's state machine is driven from the interrupt context. Once a transfer is complete a callback (if registered by the application) is given to the application from the interrupt context
- The library does not support queuing of more than one requests. The application must check and ensure that any previous request is completed before submitting a new one. This can be done either by polling the status of the data transfer or registering a callback

Configuring the Library

This section provides information on how to configure the AT24 Driver library.

Description

AT24 Driver library should be configured via MHC. Below is the snapshot of the MHC configuration window for configuring the AT24 driver and a brief description of various configuration options.



User Configurations:

- **PLIB Used:**
 - Indicates the I²C (or TWIHS) peripheral instance used by the AT24 driver
- **Number of Clients:**
 - Indicates maximum number of clients
 - Always set to one as it supports only a single client
- **EEPROM Page Size:**
 - Size of one page of EEPROM memory (in bytes)
- **EEPROM Flash Size:**
 - Total size of the EEPROM memory (in bytes)
- **EEPROM Address:**
 - The seventh bit of I²C slave address of the EEPROM
- **AT24 EEPROM Start Address:**
 - The EEPROM memory start address.
 - This is mainly used when the AT24 driver is connected to the Memory block driver

Building the Library

This section provides information on how the AT24 Driver Library can be built.

Description



All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

Library Interface**a) System Functions**

	Name	Description
≡	DRV_AT24_Initialize	Initializes the AT24 EEPROM device
≡	DRV_AT24_Status	Gets the current status of the AT24 driver module.

b) Core Client Functions

	Name	Description
≡	DRV_AT24_Open	Opens the specified AT24 driver instance and returns a handle to it.
≡	DRV_AT24_Close	Closes the opened-instance of the AT24 driver.
≡	DRV_AT24_EventHandlerSet	Allows a client to identify a transfer event handling function for the driver to call back when the requested transfer has finished.

c) Data Transfer Functions

	Name	Description
≡	DRV_AT24_Write	Writes 'n' bytes of data starting at the specified address.
≡	DRV_AT24_PageWrite	Writes one page of data starting at the specified address.
≡	DRV_AT24_Read	Reads 'n' bytes of data from the specified start address of EEPROM.
≡	DRV_AT24_TransferStatusGet	Gets the current status of the transfer request.

d) Block Interface Functions

	Name	Description
≡	DRV_AT24_GeometryGet	Returns the geometry of the device.

e) Data Types and Constants

	Name	Description
	DRV_AT24_EVENT_HANDLER	Pointer to a AT24 Driver Event handler function
	DRV_AT24_GEOMETRY	Defines the data type for AT24 EEPROM Geometry details.
	DRV_AT24_TRANSFER_STATUS	Defines the data type for AT24 Driver transfer status.

Description

This section describes the API functions of the AT24 Driver library.

Refer to each section for a detailed description.

a) System Functions***DRV_AT24_Initialize Function***

Initializes the AT24 EEPROM device

C

```
SYS_MODULE_OBJ DRV_AT24_Initialize(const SYS_MODULE_INDEX drvIndex, const SYS_MODULE_INIT *  
const init);
```

Returns

If successful, returns a valid handle to a driver instance object. Otherwise, returns [SYS_MODULE_OBJ_INVALID](#).

Description

This routine initializes the AT24 EEPROM device driver making it ready for clients to open and use. The initialization data is specified by the init parameter. It is a single instance driver, so this API should be called only once.

Remarks

This routine must be called before any other DRV_AT24 routine is called. This routine should only be called once during system initialization.

Preconditions

None.

Example

```
SYS_MODULE_OBJ sysObjDrvAT24;

DRV_AT24_PLIB_INTERFACE drvAT24PlibAPI = {
    .writeRead = (DRV_AT24_PLIB_WRITE_READ)TWIHS0_WriteRead,
    .write = (DRV_AT24_PLIB_WRITE)TWIHS0_Write,
    .read = (DRV_AT24_PLIB_READ)TWIHS0_Read,
    .isBusy = (DRV_AT24_PLIB_IS_BUSY)TWIHS0_IsBusy,
    .errorGet = (DRV_AT24_PLIB_ERROR_GET)TWIHS0_ErrorGet,
    .callbackRegister = (DRV_AT24_PLIB_CALLBACK_REGISTER)TWIHS0_CallbackRegister,
};

DRV_AT24_INIT drvAT24InitData = {
    .i2cPlib = &drvAT24PlibAPI,
    .slaveAddress = 0x57,
    .pageSize = DRV_AT24_EEPROM_PAGE_SIZE,
    .flashSize = DRV_AT24_EEPROM_FLASH_SIZE,
    .numClients = DRV_AT24_CLIENTS_NUMBER_IDX,
    .blockStartAddress = 0x0,
};

sysObjDrvAT24 = DRV_AT24_Initialize(DRV_AT24_INDEX, (SYS_MODULE_INIT *)&drvAT24InitData);
```

Parameters

Parameters	Description
drvIndex	Identifier for the instance to be initialized
init	Pointer to the init data structure containing any data necessary to initialize the driver.

Function

`SYS_MODULE_OBJ DRV_AT24_Initialize(const SYS_MODULE_INDEX drvIndex, const SYS_MODULE_INIT * const init)`

DRV_AT24_Status Function

Gets the current status of the AT24 driver module.

C

```
SYS_STATUS DRV_AT24_Status(const SYS_MODULE_INDEX drvIndex);
```

Returns

`SYS_STATUS_READY` - Indicates that the driver is ready and accept requests for new operations.
`SYS_STATUS_UNINITIALIZED` - Indicates the driver is not initialized.

Description

This routine provides the current status of the AT24 driver module.

Remarks

None.

Preconditions

Function [DRV_AT24_Initialize](#) should have been called before calling this function.

Example

```
SYS_STATUS status;

status = DRV_AT24_Status(DRV_AT24_INDEX);

if (status == SYS_STATUS_READY)
{
    // AT24 driver is initialized and ready to accept requests.
}
```

Parameters

Parameters	Description
drvIndex	Identifier for the instance used to initialize driver

Function

[SYS_STATUS DRV_AT24_Status\(const SYS_MODULE_INDEX drvIndex \)](#)

b) Core Client Functions

[DRV_AT24_Open Function](#)

Opens the specified AT24 driver instance and returns a handle to it.

C

```
DRV_HANDLE DRV\_AT24\_Open\( const SYS\_MODULE\_INDEX drvIndex, const DRV\_IO\_INTENT ioIntent \);
```

Returns

If successful, the routine returns a valid open-instance handle (a number identifying both the caller and the module instance).

If an error occurs, the return value is [DRV_HANDLE_INVALID](#). Error can occur

- if the driver has been already opened once and in use.
- if the driver instance being opened is not initialized or is invalid.

Description

This routine opens the specified AT24 driver instance and provides a handle that must be provided to all other client-level operations to identify the caller and the instance of the driver. The ioIntent parameter defines how the client interacts with this driver instance.

This driver is a single client driver, so [DRV_AT24_Open](#) API should be called only once until driver is closed.

Remarks

This driver ignores the ioIntent argument.

The handle returned is valid until the [DRV_AT24_Close](#) routine is called.

Preconditions

Function [DRV_AT24_Initialize](#) must have been called before calling this function.

Example

```
DRV_HANDLE handle;
```

```

handle = DRV_AT24_Open(DRV_AT24_INDEX, DRV_IO_INTENT_READWRITE);
if (handle == DRV_HANDLE_INVALID)
{
    // Unable to open the driver
    // May be the driver is not initialized
}

```

Parameters

Parameters	Description
drvIndex	Identifier for the object instance to be opened
ioIntent	Zero or more of the values from the enumeration DRV_IO_INTENT "ORed" together to indicate the intended use of the driver.

Function

```

DRV_HANDLE DRV_AT24_Open
(
const     SYS_MODULE_INDEX drvIndex,
const     DRV_IO_INTENT ioIntent
)

```

DRV_AT24_Close Function

Closes the opened-instance of the AT24 driver.

C

```
void DRV_AT24_Close(const DRV_HANDLE handle);
```

Returns

None.

Description

This routine closes opened-instance of the AT24 driver, invalidating the handle. A new handle must be obtained by calling [DRV_AT24_Open](#) before the caller may use the driver again.

Remarks

None.

Preconditions

[DRV_AT24_Open](#) must have been called to obtain a valid opened device handle.

Example

```

// 'handle', returned from the DRV_AT24_Open
DRV_AT24_Close(handle);

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
void DRV_AT24_Close(const DRV_HANDLE handle)
```

DRV_AT24_EventHandlerSet Function

Allows a client to identify a transfer event handling function for the driver to call back when the requested transfer has finished.

C

```
void DRV_AT24_EventHandlerSet(const DRV_HANDLE handle, const DRV_AT24_EVENT_HANDLER eventHandler, const uintptr_t context);
```

Returns

None.

Description

This function allows a client to register a transfer event handling function with the driver to call back when the requested transfer has finished.

The event handler should be set before the client submits any transfer requests that could generate events. The event handler once set, persists until the client closes the driver or sets another event handler (which could be a "NULL" pointer to indicate no callback).

Remarks

If the client does not want to be notified when the queued buffer transfer has completed, it does not need to register a callback.

Preconditions

`DRV_AT24_Open` must have been called to obtain a valid opened device handle.

Example

```
#define BUFFER_SIZE 256
#define MEM_ADDRESS 0x0

// myAppObj is an application specific state data object.
MY_APP_OBJ myAppObj;

uint8_t myBuffer[BUFFER_SIZE];

// myHandle is the handle returned from DRV_AT24_Open API.

// Client registers an event handler with driver. This is done once

DRV_AT24_EventHandlerSet( myHandle, APP_AT24TransferEventHandler, (uintptr_t)&myAppObj );

if (DRV_AT24_Read(myHandle, myBuffer, BUFFER_SIZE, MEM_ADDRESS) == false)
{
    // Error handling here
}

// The registered event handler is called when the request is complete.

void APP_AT24TransferEventHandler(DRV_AT24_TRANSFER_STATUS event, uintptr_t context)
{
    // The context handle was set to an application specific
    // object. It is now retrievable easily in the event handler.
    MY_APP_OBJ* pMyAppObj = (MY_APP_OBJ *) context;

    switch(event)
    {
        case DRV_AT24_TRANSFER_STATUS_COMPLETED:
            // This means the data was transferred.
            break;

        case DRV_AT24_TRANSFER_STATUS_ERROR:
            // Error handling here.
            break;

        default:
            break;
    }
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine.
eventHandler	Pointer to the event handler function.
context	The value of parameter will be passed back to the client unchanged, when the eventHandler function is called. It can be used to identify any client specific data object that identifies the instance of the client module (for example, it may be a pointer to the client module's state structure).

Function

```
void DRV_AT24_EventHandlerSet(
    const DRV_HANDLE handle,
    const DRV_AT24_EVENT_HANDLER eventHandler,
    const uintptr_t context
)
```

c) Data Transfer Functions

DRV_AT24_Write Function

Writes 'n' bytes of data starting at the specified address.

C

```
bool DRV_AT24_Write(const DRV_HANDLE handle, void* txData, uint32_t txDataLength, uint32_t address);
```

Returns

false

- if handle is not right
- if the pointer to the buffer to be written is NULL or number of bytes to write is zero
- if the driver is busy handling another transfer request

true

- if the write request is accepted.

Description

This function schedules a non-blocking write operation for writing txDataLength bytes of data starting from given address of EEPROM.

The requesting client should call [DRV_AT24_TransferStatusGet](#) API to know the current status of the request OR the requesting client can register a callback function with the driver to get notified of the status.

Remarks

None.

Preconditions

[DRV_AT24_Open](#) must have been called to obtain a valid opened device handle.

Example

```
#define BUFFER_SIZE 1024
#define MEM_ADDRESS 0x00

uint8_t writeBuffer[BUFFER_SIZE];

// myHandle is the handle returned from DRV\_AT24\_Open API.
```

```

// In the below example, the transfer status is polled. However, application can
// register a callback and get notified when the transfer is complete.

if (DRV_AT24_Write(myHandle, writeBuffer, BUFFER_SIZE, MEM_ADDRESS) != true)
{
    // Error handling here
}
else
{
    // Wait for write to be completed
    while(DRV_AT24_TransferStatusGet(myHandle) == DRV_AT24_TRANSFER_STATUS_BUSY);
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
txData	The source buffer containing data to be programmed into AT24 EEPROM
txDataLength	Total number of bytes to be written.
address	Memory start address from where the data should be written

Function

```
bool DRV_AT24_Write(const DRV_HANDLE handle, void* txData, uint32_t txDataLength, uint32_t address)
```

DRV_AT24_PageWrite Function

Writes one page of data starting at the specified address.

C

```
bool DRV_AT24_PageWrite(const DRV_HANDLE handle, void * txData, uint32_t address);
```

Returns

false

- if handle is not right
- if the pointer to the transmit data buffer is NULL
- if the driver is busy handling another transfer request

true

- if the write request is accepted.

Description

This function schedules a non-blocking write operation for writing one page of data starting from given address of EEPROM.

The requesting client should call [DRV_AT24_TransferStatusGet](#) API to know the current status of the request OR the requesting client can register a callback function with the driver to get notified of the status.

Remarks

None.

Preconditions

[DRV_AT24_Open](#) must have been called to obtain a valid opened device handle.

"address" provided must be page boundary aligned in order to avoid overwriting the data in the beginning of the page.

Example

```

#define BUFFER_SIZE 1024
#define MEM_ADDRESS 0x00

uint8_t writeBuffer[BUFFER_SIZE];

// myHandle is the handle returned from DRV\_AT24\_Open API.
// In the below example, the transfer status is polled. However, application can

```

```

// register a callback and get notified when the transfer is complete.

if (DRV_AT24_PageWrite(myHandle, writeBuffer, MEM_ADDRESS) != true)
{
    // Error handling here
}
else
{
    // Wait for write to be completed
    while(DRV_AT24_TransferStatusGet(myHandle) == DRV_AT24_TRANSFER_STATUS_BUSY);
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
txData	The source buffer containing data to be programmed into AT24 EEPROM
address	Memory start address from where the data should be written. It must be page boundary aligned in order to avoid overwriting the data in the beginning of the page.

Function

bool DRV_AT24_PageWrite(const **DRV_HANDLE** handle, void* txData, uint32_t address)

DRV_AT24_Read Function

Reads 'n' bytes of data from the specified start address of EEPROM.

C

```
bool DRV_AT24_Read(const DRV_HANDLE handle, void * rxData, uint32_t rxDataLength, uint32_t address);
```

Returns

false

- if handle is not right
- if the receive buffer pointer is NULL or number of bytes to read is zero
- if the driver is busy handling another transfer request

true

- if the read request is accepted.

Description

This function schedules a non-blocking read operation for the requested number of data bytes from given address of EEPROM.

The requesting client should call **DRV_AT24_TransferStatusGet** API to know the current status of the request OR the requesting client can register a callback function with the driver to get notified of the status.

Remarks

None.

Preconditions

DRV_AT24_Open must have been called to obtain a valid opened device handle.

Example

```

#define BUFFER_SIZE 1024
#define MEM_ADDRESS 0x00

uint8_t readBuffer[BUFFER_SIZE];

// myHandle is the handle returned from DRV_AT24_Open API.

// In the below example, the transfer status is polled. However, application can

```

```

// register a callback and get notified when the transfer is complete.

if (DRV_AT24_Read(myHandle, readBuffer, BUFFER_SIZE, MEM_ADDRESS) != true)
{
    // Error handling here
}
else
{
    // Wait for read to be completed
    while(DRV_AT24_TransferStatusGet(myHandle) == DRV_AT24_TRANSFER_STATUS_BUSY);
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
rxData	Buffer pointer into which the data read from the DRV_AT24 Flash memory will be placed.
rxDataLength	Total number of bytes to be read.
address	Memory start address from where the data should be read.

Function

bool DRV_AT24_Read(const [DRV_HANDLE](#) handle, void *rxData, uint32_t rxDataLength, uint32_t address)

[DRV_AT24_TransferStatusGet Function](#)

Gets the current status of the transfer request.

C

```
DRV_AT24_TRANSFER_STATUS DRV\_AT24\_TransferStatusGet(const DRV\_HANDLE handle);
```

Returns

One of the status element from the enum [DRV_AT24_TRANSFER_STATUS](#).

Description

This routine gets the current status of the transfer request.

Remarks

None.

Preconditions

[DRV_AT24_PageWrite](#) or [DRV_AT24_Read](#) must have been called to obtain the status of transfer.

Example

```

// myHandle is the handle returned from DRV\_AT24\_Open API.

if (DRV_AT24_TransferStatusGet(myHandle) == DRV_AT24_TRANSFER_STATUS_COMPLETED)
{
    // Operation Done
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

[DRV_AT24_TRANSFER_STATUS](#) [DRV_AT24_TransferStatusGet](#)(**const** [DRV_HANDLE](#) handle)

d) Block Interface Functions

DRV_AT24_GeometryGet Function

Returns the geometry of the device.

C

```
bool DRV_AT24_GeometryGet(const DRV_HANDLE handle, DRV_AT24_GEOMETRY * geometry);
```

Returns

false

- if handle is invalid

true

- if able to get the geometry details of the flash

Description

This API gives the following geometrical details of the DRV_AT24 Flash:

- Number of Read/Write/Erase Blocks and their size in each region of the device

Remarks

None.

Preconditions

[DRV_AT24_Open](#) must have been called to obtain a valid opened device handle.

Example

```
DRV_AT24_GEOMETRY eepromGeometry;
uint32_t readBlockSize, writeBlockSize, eraseBlockSize;
uint32_t nReadBlocks, nReadRegions, totalFlashSize;

// myHandle is the handle returned from DRV_AT24_Open API.

DRV_AT24_GeometryGet(myHandle, &eepromGeometry);

readBlockSize = eepromGeometry.readBlockSize;
nReadBlocks = eepromGeometry.readNumBlocks;
nReadRegions = eepromGeometry.readNumRegions;

writeBlockSize = eepromGeometry.writeBlockSize;
eraseBlockSize = eepromGeometry.eraseBlockSize;

totalFlashSize = readBlockSize * nReadBlocks * nReadRegions;
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
geometry	Pointer to flash device geometry table instance

Function

```
bool DRV_AT24_GeometryGet(const DRV_HANDLE handle, DRV_AT24_GEOMETRY *geometry)
```

e) Data Types and Constants

DRV_AT24_EVENT_HANDLER Type

Pointer to a AT24 Driver Event handler function

C

```
typedef void (* DRV_AT24_EVENT_HANDLER) (DRV_AT24_TRANSFER_STATUS event, uintptr_t context);
```

Returns

None.

Description

AT24 Driver Transfer Event Handler Function Pointer

This data type defines the required function signature for the AT24 driver event handling callback function. A client must register a pointer using the event handling function whose function signature (parameter and return value types) match the types specified by this function pointer in order to receive transfer related event calls back from the driver.

The parameters and return values are described here and a partial example implementation is provided.

Remarks

If the event is **DRV_AT24_TRANSFER_STATUS_COMPLETED**, it means that the data was transferred successfully.

If the event is **DRV_AT24_TRANSFER_STATUS_ERROR**, it means that the data was not transferred successfully.

The context parameter contains the handle to the client context, provided at the time the event handling function was registered using the [DRV_AT24_EventHandlerSet](#) function. This context handle value is passed back to the client as the "context" parameter. It can be any value necessary to identify the client context or instance (such as a pointer to the client's data) instance of the client that made the buffer add request.

The event handler function executes in the driver's interrupt context. It is recommended of the application to not perform process intensive or blocking operations with in this function.

The [DRV_AT24_Read](#), [DRV_AT24_Write](#) and [DRV_AT24_PageWrite](#) functions can be called in the event handler to submit a new request to the driver.

Example

```
void APP_MyTransferEventHandler( DRV_AT24_TRANSFER_STATUS event, uintptr_t context )
{
    MY_APP_DATA_STRUCT* pAppData = (MY_APP_DATA_STRUCT *) context;

    switch(event)
    {
        case DRV_AT24_TRANSFER_STATUS_COMPLETED:
            // Handle the transfer complete event.
            break;

        case DRV_AT24_TRANSFER_STATUS_ERROR:
        default:
            // Handle error.
            break;
    }
}
```

Parameters

Parameters	Description
event	Identifies the type of event
context	Value identifying the context of the application that registered the event handling function.

DRV_AT24_GEOMETRY Structure

Defines the data type for AT24 EEPROM Geometry details.

C

```
typedef struct {
    uint32_t readBlockSize;
    uint32_t readNumBlocks;
    uint32_t readNumRegions;
    uint32_t writeBlockSize;
    uint32_t writeNumBlocks;
    uint32_t writeNumRegions;
    uint32_t eraseBlockSize;
    uint32_t eraseNumBlocks;
    uint32_t eraseNumRegions;
    uint32_t blockStartAddress;
} DRV_AT24_GEOMETRY;
```

Description

DRV_AT24 Geometry data

This will be used to get the geometry details of the attached AT24 EEPROM device.

Remarks

None.

DRV_AT24_TRANSFER_STATUS Enumeration

Defines the data type for AT24 Driver transfer status.

C

```
typedef enum {
    DRV_AT24_TRANSFER_STATUS_BUSY,
    DRV_AT24_TRANSFER_STATUS_COMPLETED,
    DRV_AT24_TRANSFER_STATUS_ERROR
} DRV_AT24_TRANSFER_STATUS;
```

Members

Members	Description
DRV_AT24_TRANSFER_STATUS_BUSY	Transfer is being processed
DRV_AT24_TRANSFER_STATUS_COMPLETED	Transfer is successfully completed
DRV_AT24_TRANSFER_STATUS_ERROR	Transfer had error

Description

DRV_AT24 Transfer Status

This will be used to indicate the current transfer status of the AT24 EEPROM driver operations.

Remarks

None.

I2S Driver Library Help

This section describes the I2S Driver Library.

Introduction

This library provides an interface to manage the I2S Audio Protocol Interface Modes.

Description

The I2S Driver is connected to a hardware module that provides the actual I2S stream, on some MCUs this is a Serial Peripheral Interface (SPI), on others it may be an I2S Controller (I2SC), or Serial Synchronous Controller (SSC).

The I2S hardware peripheral is then interfaced to various devices such as codecs and Bluetooth modules to provide microcontroller-based audio solutions.

Using the Library

This topic describes the basic architecture of the I2S Driver Library and provides information and examples on its use.

Description

Interface Header File: `drv_i2s.h`

The interface to the I2S Driver Library is defined in the `drv_i2s.h` header file. Any C language source (`.c`) file that uses the I2S Driver Library should include `drv_i2s.h`.

Please refer to the [What is MPLAB Harmony?](#) section for how the driver interacts with the framework.

Example Applications:

This library is used by the following applications, among others:

- `audio/apps/audio_tone`
- `audio/apps/audio_tone_linkeddma`
- `audio/apps/microphone_loopback`

Abstraction Model

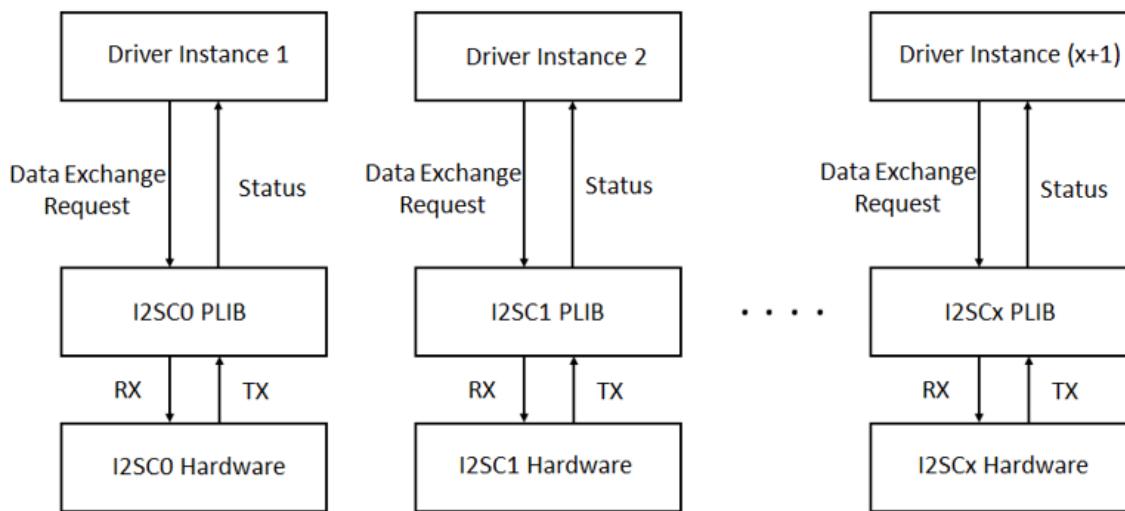
The I2S Driver provides a high level abstraction of the lower level (SPI/I2SC/SSC) I2S modules with a convenient C language interface. This topic describes how that abstraction is modeled in the software and introduces the I2S Driver Library interface.

Description

Different types of I2S capable PLIBs are available on various Microchip microcontrollers. Some have an internal buffer mechanism and some do not. The buffer depth varies across part families. The I2S Driver Library abstracts out these differences and provides a unified model for audio data transfer across different types of I2S modules.

Both the transmitter and receiver provide a buffer in the driver, which transmits and receives data to/from the hardware. The I2S Driver Library provides a set of interfaces to perform the read and the write. The following diagrams illustrate the abstraction model used by the I2S Driver Library. The I2SC Peripheral is used as an example of an I2S-capable PLIB.

I2S Driver Abstraction Model



The PLIBs currently provided, such as SSC and I2SC, only support an interrupt/DMA mode of operation. Polled mode of operation is not supported.

Library Overview

Refer to the Driver Library Overview section for information on how the driver operates in a system.

The I2S driver library provides an API interface to transfer/receive digital audio data using supported Audio protocols. The library interface routines are divided into various sub-sections, which address one of the blocks or the overall operation of the I2S Driver Library.

Library Interface Section	Description
System Interaction Functions	Provides device initialization and status functions.
Client Setup Functions	Provides open and close functions.
Data Transfer Functions	Provides data transfer functions.
Miscellaneous Functions	Provides driver miscellaneous functions such as get error functions, L/R clock sync, etc.
Data Types and Constants	These data types and constants are required while interacting and setting up the I2S Driver Library.

How the Library Works

The library provides interfaces to support:

- System Functionality
 - Client Functionality



Note: Not all modes are available on all devices. Please refer to the specific device data sheet to determine the supported modes.

System Access

This section provides information on system access.

Description

System Initialization

The system performs the initialization of the device driver with settings that affect only the instance of the device that is being initialized. During system initialization, each instance of the I2S module would be initialized with the following configuration settings (either passed dynamically at run time using [DRV_I2S_INIT](#) or by using Initialization Overrides) that are supported by the specific I2S device hardware:

- Device requested power state: one of the System Module Power States. For specific details please refer to [Data Types and Constants](#) in the [Library Interface](#) section.
- The actual peripheral ID enumerated as the PLIB level module ID (e.g., SPI_ID_2)
- Defining the respective interrupt sources for TX, RX, DMA TX Channel, DMA RX Channel and Error Interrupt

The [DRV_I2S_Initialize](#) API returns an object handle of the type [SYS_MODULE_OBJ](#). The object handle returned by the Initialize interface would be used by the other system interfaces such as [DRV_I2S_Deinitialize](#), [DRV_I2S_Status](#), [DRV_I2S_Tasks](#), and [DRV_I2S_TasksError](#).



Notes:

1. The system initialization setting only effect the instance of the peripheral that is being initialized.
2. Configuration of the dynamic driver for DMA mode(uses DMA channel for data transfer) or Non DMA mode can be performed by appropriately setting the 'dmaChannelTransmit' and 'dmaChannelReceive' variables of the [DRV_I2S_INIT](#) structure. For example the TX will be in DMA mode when 'dmaChannelTransmit' is initialized to a valid supported channel number from the enum [DMA_CHANNEL](#). TX will be in Non DMA mode when 'dmaChannelTransmit' is initialized to 'DMA_CHANNEL_NONE'.

Example:

```
DRV_I2S_INIT           init;
SYS_MODULE_OBJ         objectHandle;

/* I2S Driver Initialization Data */
DRV_I2S_INIT drvI2S0InitData =
{
    .i2sPlib = &drvI2S0PlibAPI,
    .interruptI2S = DRV_I2S_INT_SRC_IDX0,
    .numClients = DRV_I2S_CLIENTS_NUMBER_IDX0,
    .queueSize = DRV_I2S_QUEUE_SIZE_IDX0,
    .dmaChannelTransmit = DRV_I2S_XMIT_DMA_CH_IDX0,
    .dmaChannelReceive = DRV_I2S_RCV_DMA_CH_IDX0,
    .i2sTransmitAddress = (void *)&(SSC_REGS->SSC_THR),
    .i2sReceiveAddress = (void *)&(SSC_REGS->SSC_RHR),
    .interruptDMA = XDMAC IRQn,
    .dmaDataLength = DRV_I2S_DATA_LENGTH_IDX0,
};

sysObj.drvI2S0 = DRV_I2S_Initialize(DRV_I2S_INDEX_0, (SYS_MODULE_INIT *)&drvI2S0InitData);
```

Task Routine

There is no task routine, since polled mode is not currently supported.

Client Access

This section provides information on general client operation.

Description

General Client Operation

For the application to start using an instance of the module, it must call the [DRV_I2S_Open](#) function. This provides the settings required to open the I2S instance for operation.

For the various options available for [IO_INTENT](#), please refer to [Data Types and Constants](#) in the [Library Interface](#) section.

Example:

```
DRV_HANDLE handle;
handle = DRV_I2S_Open(drvObj->i2sDriverModuleIndex,
```

```

(DRV_IO_INTENT_WRITE | DRV_IO_INTENT_NONBLOCKING));
if (DRV_HANDLE_INVALID == handle)
{
    // Unable to open the driver
    // May be the driver is not initialized or the initialization
    // is not complete.
}

```

Client Operations - Buffered

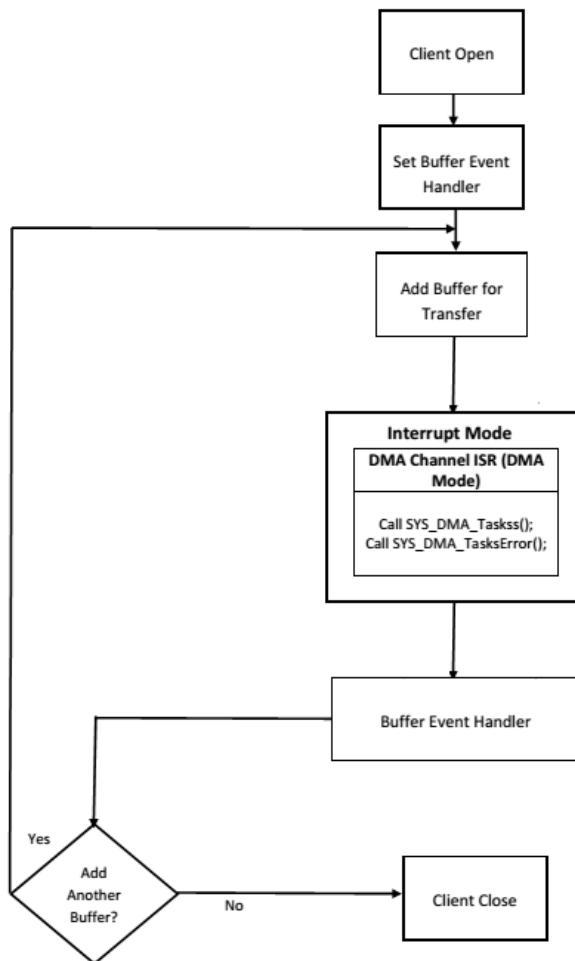
This section provides information on buffered client operations.

Description

Client Operations - Buffered

Client buffered operations provide a the typical audio interface. The functions DRV_I2S_BufferAddRead, DRV_I2S_BufferAddWrite, and DRV_I2S_BufferAddWriteRead are the buffered data operation functions. The buffered functions schedules non-blocking operations. The function adds the request to the hardware instance queues and returns a buffer handle. The requesting client also registers a callback event with the driver. The driver notifies the client with DRV_I2S_BUFFER_EVENT_COMPLETE, DRV_I2S_BUFFER_EVENT_ERROR or DRV_I2S_BUFFER_EVENT_ABORT events. The buffer add requests are processed from the I2S channel ISR in interrupt mode.

The following diagram illustrates the buffered data operations





It is not necessary to close and reopen the client between multiple transfers.

Note:

An application using the buffered functionality needs to perform the following steps:

1. The system should have completed necessary setup and initializations.
2. If DMA mode is desired, the DMA should be initialized by calling `SYS_DMA_Initialize`.
3. The necessary ports setup and remapping must be done for I2S lines: ADCDAT, DACDAT, BCLK, LRCK and MCLK (if required).
4. The driver object should have been initialized by calling `DRV_I2S_Initialize`. If DMA mode is desired, related attributes in the init structure must be set.
5. Open the driver using `DRV_I2S_Open` with the necessary ioIntent to get a client handle.
6. The necessary BCLK, LRCK, and MCLK should be set up so as to generate the required media bit rate.
7. The necessary Baud rate value should be set up by calling `DRV_I2S_BaudrateSet`.
8. The Register and event handler for the client handle should be set up by calling `DRV_I2S_BufferEventHandlerSet`.
9. Add a buffer to initiate the data transfer by calling
`DRV_I2S_BufferAddWrite`/`DRV_I2S_BufferAddRead`/`DRV_I2S_BufferAddWriteRead`.
10. When the DMA Channel has finished, the callback function registered in step 8 will be called.
11. Repeat step 9 through step 10 to handle multiple buffer transmission and reception.
12. When the client is done it can use `DRV_I2S_Close` to close the client handle.

Example:

```

// The following is an example for interrupt mode buffered transmit

#define SYS_I2S_DRIVER_INDEX DRV_I2S_1 // I2S Uses SPI Hardware
#define BUFFER_SIZE 1000
// I2S initialization structure.
// This should be populated with necessary settings.
// attributes dmaChannelTransmit/dmaChannelReceive
// and dmaInterruptTransmitSource/dmaInterruptReceiveSource
// must be set if DMA mode of operation is desired.

DRV_I2S_INIT i2sInit;
SYS_MODULE_OBJ sysObj; //I2S module object
DRV_HANDLE handle; //Client handle
uint32_t i2sClock; //BCLK frequency
uint32_t baudrate; //baudrate
uint16_t myAudioBuffer[BUFFER_SIZE]; //Audio buffer to be transmitted
DRV_I2S_BUFFER_HANDLE bufferHandle;
APP_DATA_S state; //Application specific state
uintptr_t contextHandle;

void SYS_Initialize ( void* data )
{
    // The system should have completed necessary setup and initializations.
    // Necessary ports setup and remapping must be done for I2S lines ADCDAT,
    // DACDAT, BCLK, LRCK and MCLK

    sysObj = DRV_I2S_Initialize(SYS_I2S_DRIVER_INDEX, (SYS_MODULE_INIT*)&i2sInit);
    if (SYS_MODULE_OBJ_INVALID == sysObj)
    {
        // Handle error
    }
}

void App_Task(void)
{
    switch(state)
    {
        case APP_STATE_INIT:
        {
            handle = DRV_I2S_Open(SYS_I2S_DRIVER_INDEX, (DRV_IO_INTENT_WRITE |
DRV_IO_INTENT_NONBLOCKING));
            if(handle != DRV_HANDLE_INVALID )

```

```
        {
            /* Update the state */
            state = APP_STATE_WAIT_FOR_READY;
        }
    }
break;

case APP_STATE_WAIT_FOR_READY:
{
    // Necessary clock settings must be done to generate
    // required MCLK, BCLK and LRCK
    DRV_I2S_BaudrateSet(handle, i2sClock, baudrate);

    /* Set the Event handler */
    DRV_I2S_BufferEventHandlerSet(handle, App_BufferEventHandler,
        contextHandle);

    /* Add a buffer to write*/
    DRV_I2S_WriteBufferAdd(handle, myAudioBuffer, BUFFER_SIZE,
        &bufferHandle);
    if(DRV_I2S_BUFFER_HANDLE_INVALID == bufferHandle)
    {
        // Error handling here
    }
    state = APP_STATE_IDLE;
}
break;

case APP_STATE_WAIT_FOR_DONE:
{
    state = APP_STATE_DONE;
}
break;

case APP_STATE_DONE:
{
    // Close done
    DRV_I2S_Close(handle);
}
break;

case APP_STATE_IDLE:
{
    // Do nothing
}
break;

default:
break;
}
}

void App_BufferEventHandler(DRV_I2S_BUFFER_EVENT event,
    DRV_I2S_BUFFER_HANDLE bufferHandle, uintptr_t contextHandle)
{
    uint8_t temp;

    if(DRV_I2S_BUFFER_EVENT_COMPLETE == event)
    {
        // Can set state = APP_STATE_WAIT_FOR_DONE;
        // Take Action as needed
    }
    else if(DRV_I2S_BUFFER_EVENT_ERROR == event)
    {
        // Take Action as needed
    }
    else if(DRV_I2S_BUFFER_EVENT_ABORT == event)
    {
```

```
    // Take Action as needed
}
else
{
    // Do nothing
}

void SYS_Tasks ( void )
{
    /* Call the application's tasks routine */
    APP_Tasks ( );
}
```

Client Operations - Non-buffered

This section provides information on non-buffered client operations.

Description

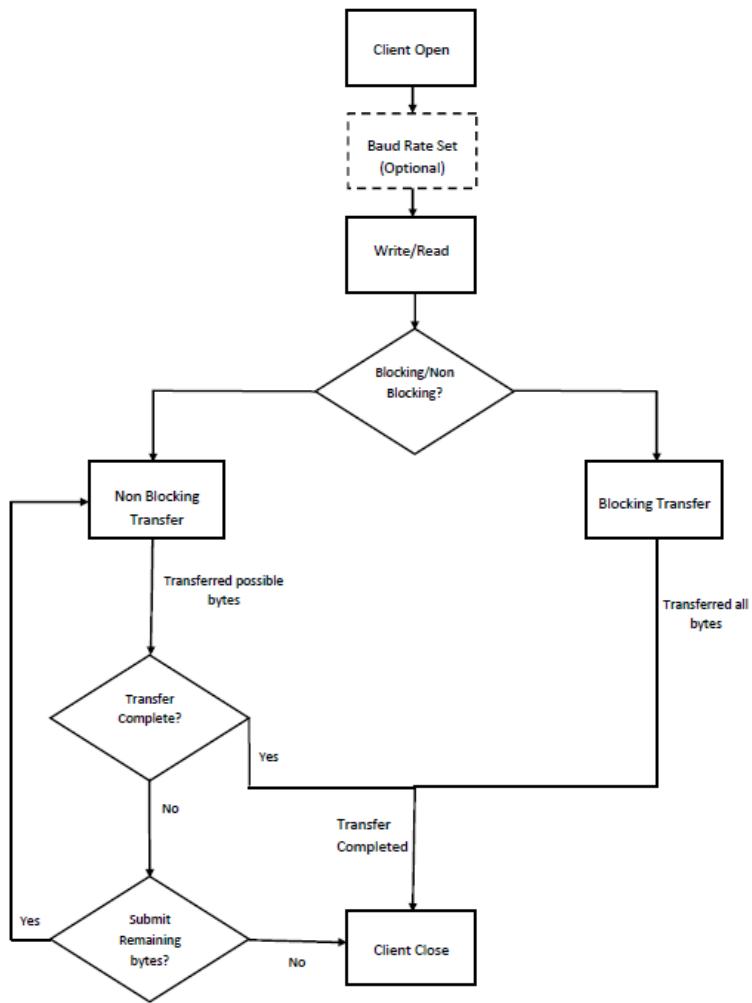
Client Operations - Non-buffered

Client non-buffered operations provide a basic interface for the driver operation. This interface could be used by applications which have do not have buffered data transfer requirements. The functions DRV_I2S_Read and DRV_I2S_Write are the non-buffered data operation functions. The non-buffered functions are blocking/non-blocking depending upon the mode (ioIntent) the client was opened. If the client was opened for blocking mode these functions will only return when (or will block until) the specified data operation is completed or if an error occurred. If the client was opened for non-blocking mode, these functions will return with the number of bytes that were actually accepted for operation. The function will not wait until the data operation has completed.



Note: Non-buffered functions do not support interrupt/DMA mode.

The following diagram illustrates the non-buffered data operations



Note: It is not necessary to close and reopen the client between multiple transfers.

An application using the non-buffered functionality needs to perform the following steps:

1. The system should have completed necessary setup and initializations.
2. The necessary ports setup and remapping must be done for I2S lines: ADCDAT, DACDAT, BCLK, LRCK and MCLK (if required).
3. The driver object should have been initialized by calling [DRV_I2S_Initialize](#).
4. Open the driver using [DRV_I2S_Open](#) with the necessary ioIntent to get a client handle.
5. The necessary BCLK, LRCK, and MCLK should be set up so as to generate the required media bit rate.
6. The necessary Baud rate value should be set up by calling [DRV_I2S_BaudrateSet](#).
7. The Transmit/Receive data should be set up by calling [DRV_I2S_Write](#)/[DRV_I2S_Read](#).
8. Repeat step 5 through step 7 to handle multiple buffer transmission and reception.
9. When the client is done it can use [DRV_I2S_Close](#) to close the client handle.

Example 1:

```

// The following is an example for a blocking transmit
#define SYS_I2S_DRIVER_INDEX DRV_I2S_1 // I2S Uses SPI Hardware
#define BUFFER_SIZE 1000
DRV_I2S_INIT i2sInit; //I2S initialization structure
//This should be populated with necessary settings
SYS_MODULE_OBJ sysObj; //I2S module object
APP_DATA_S state; //Application specific state
DRV_HANDLE handle; //Client handle
uint32_t i2sClock; //BCLK frequency
uint32_t baudrate; //baudrate
  
```

```

uint16_t myAudioBuffer[BUFFER_SIZE]; //Audio buffer to be transmitted
uint32_t count;

// The system should have completed necessary setup and initializations.
// Necessary ports setup and remapping must be done for
// I2S lines ADCDAT, DACDAT, BCLK, LRCK and MCLK

sysObj = DRV_I2S_Initialize(SYS_I2S_DRIVER_INDEX, (SYS_MODULE_INIT*)&i2sInit);
if (SYS_MODULE_OBJ_INVALID == sysObj)
{
    // Handle error
}
while(1)
{
    switch(state)
    {
        case APP_STATE_INIT:
        {
            handle = DRV_I2S_Open(SYS_I2S_DRIVER_INDEX, (DRV_IO_INTENT_WRITE | DRV_IO_INTENT_BLOCKING));
            if(handle != DRV_HANDLE_INVALID )
            {
                /* Update the state */
                state = APP_STATE_WAIT_FOR_READY;
            }
        }
        break;
        case APP_STATE_WAIT_FOR_READY:
        {
            // Necessary clock settings must be done to generate
            // required MCLK, BCLK and LRCK
            DRV_I2S_BaudrateSet(handle, i2sClock, baudrate);
            // Blocks here and transfer the buffer
            count = DRV_I2S_Write(handle, &myAudioBuffer,BUFFER_SIZE);
            if(count == DRV_I2S_WRITE_ERROR)
            {
                //Handle Error
            } else
            {
                // Transfer Done
                state = APP_STATE_DONE;
            }
        }
        break;
        case APP_STATE_DONE:
        {
            // Close done
            DRV_I2S_Close(handle);
        }
        break;
        default:
        break;
    }
}
}

```

Example 2:

```

// Following is an example for a non blocking transmit
#define SYS_I2S_DRIVER_INDEX DRV_I2S_1 //I2S Uses SPI Hardware
#define BUFFER_SIZE 1000
DRV_I2S_INIT i2sInit; //I2S initialization structure.
                    // This should be populated with necessary settings
SYS_MODULE_OBJ sysObj; //I2S module object
APP_DATA_S state; //Application specific state
DRV_HANDLE handle; //Client handle
uint32_t i2sClock; //BCLK frequency
uint32_t baudrate; //baudrate

```

```
uint16_t myAudioBuffer[BUFFER_SIZE]; //Audio buffer to be transmitted
uint32_t count,total,size;

total = 0;
size = BUFFER_SIZE;

// The system should have completed necessary setup and initializations.
// Necessary ports setup and remapping must be done for I2S lines ADCDAT,
// DACDAT, BCLK, LRCK and MCLK

sysObj = DRV_I2S_Initialize(SYS_I2S_DRIVER_INDEX, (SYS_MODULE_INIT*)&i2sInit);
if (SYS_MODULE_OBJ_INVALID == sysObj)
{
    // Handle error
}

while(1)
{
    switch(state)
    {
        case APP_STATE_INIT:
        {
            handle = DRV_I2S_Open(SYS_I2S_DRIVER_INDEX, (DRV_IO_INTENT_WRITE | DRV_IO_INTENT_NONBLOCKING));
            if(handle != DRV_HANDLE_INVALID )
            {
                /* Update the state */
                state = APP_STATE_WAIT_FOR_READY;
            }
        }
        break;
        case APP_STATE_WAIT_FOR_READY:
        {
            // Necessary clock settings must be done to generate
            // required MCLK, BCLK and LRCK
            DRV_I2S_BaudrateSet(handle, i2sClock, baudrate);
            // Transfer whatever possible number of bytes
            count = DRV_I2S_Write(handle, &myAudioBuffer,size);
            if(count == DRV_I2S_WRITE_ERROR)
            {
                //Handle Error
            } else
            {
                // 'count' bytes transferred
                state = APP_STATE_WAIT_FOR_DONE;
            }
        }
        break;
        case APP_STATE_WAIT_FOR_DONE:
        {
            // Can perform other Application tasks here
            // .....
            // .....
            // .....
            size = size - count;
            if(size!=0)
            {
                // Change the state so as to submit
                // another possible transmission
                state = APP_STATE_WAIT_FOR_READY;
            }
            else
            {
                // We are done
                state = APP_STATE_DONE;
            }
        }
        break;
        case APP_STATE_DONE:
```

```

    {
        if(DRV_I2S_CLOSE_FAILURE == DRV_I2S_Close(handle))
        {
            // Handle error
        }
        else
        {
            // Close done
        }
    }
break;
default:
break;
}
}

```

Configuring the Library

The configuration of the I2S Driver Library is based on the file `configurations.h`.

This header file contains the configuration selection for the I2S Driver Library. Based on the selections made, the I2S Driver Library may support the selected features. These configuration settings will apply to all instances of the I2S Driver Library.

This header can be placed anywhere; however, the path of this header needs to be present in the include search path for a successful build. Refer to the Applications Help section for more details.

System Configuration

Macros

Name	Description
<code>DRV_I2S_INDEX_x</code>	I2S Index selection
<code>DRV_I2S_CLIENTS_NUMBER_IDXx</code>	Sets up the maximum number of clients that can be connected to the driver
<code>DRV_I2S_QUEUE_DEPTH_COMBINED</code>	Number of entries of all queues in all instances of the driver.
<code>DRV_I2S_QUEUE_SIZE_IDXx</code>	Number of entries of all queues in all instances of the driver.
<code>DRV_I2S_DATA_LENGTH_IDXx</code>	Macro to define the data length for the I2S peripheral
<code>DRV_I2S_INT_SRC_IDXx</code>	Macro to define the interrupt source
<code>DRV_I2S_XMIT_DMA_CH_IDXx</code>	Macro to defines the I2S Driver Transmit DMA Channel
<code>DRV_I2S_RCV_DMA_CH_IDXx</code>	Macro to defines the I2S Driver Receive DMA Channel

Description

Configurations for driver instances, polled/interrupt mode, etc.

DRV_I2S_INDEX_x Macro

I2S Index selection

C

```
#define DRV_I2S_INDEX_x
```

Description

Index

I2S Index selection for the driver object reference. This macro defines the driver index.

Remarks

This index is required to make a reference to the driver object

Example

```
DRV_I2S_Initialize(DRV_I2S_INDEX_0, (SYS_MODULE_INIT *)&drvI2S0InitData);
```

DRV_I2S_CLIENTS_NUMBER_IDXx Macro

Sets up the maximum number of clients that can be connected to the driver

C

```
#define DRV_I2S_CLIENTS_NUMBER_IDXx
```

Description

I2S Client Count Configuration

Sets up the maximum number of clients that can be connected to the driver. It is recommended that this be set exactly equal to the number of expected clients. Client support consumes RAM memory space.

Remarks

None

DRV_I2S_QUEUE_DEPTH_COMBINED Macro

Number of entries of all queues in all instances of the driver.

C

```
#define DRV_I2S_QUEUE_DEPTH_COMBINED
```

Description

I2S Driver Buffer Queue Entries

This macro defined the number of entries of all queues in all instances of the driver.

Each hardware instance supports a buffer queue for transmit and receive operations. The size of queue is specified either in driver initialization (for dynamic build) or by macros (for static build). The hardware instance transmit buffer queue will queue transmit buffers submitted by the DRV_I2S_BufferAddWrite() function. The hardware instance receive buffer queue will queue receive buffers submitted by the DRV_I2S_BufferAddRead() function.

A buffer queue will contains buffer queue entries, each related to a BufferAdd request. This configuration macro defines total number of buffer entries that will be available for use between all I2S driver hardware instances. The buffer queue entries are allocated to individual hardware instances as requested by hardware instances. Once the request is processed, the buffer queue entry is free for use by other hardware instances.

The total number of buffer entries in the system determines the ability of the driver to service non blocking read and write requests. If a free buffer entry is not available, the driver will not add the request and will return an invalid buffer handle. More the number of buffer entries, greater the ability of the driver to service and add requests to its queue. A hardware instance additionally can queue up as many buffer entries as specified by its transmit and receive buffer queue size.

As an example, consider the case of static single client driver application where full duplex non blocking operation is desired without queuing, the minimum transmit queue depth and minimum receive queue depth should be 1. Hence the total number of buffer entries should be 2.

As an example, consider the case of a dynamic driver (say 2 instances) where instance 1 will queue up to 3 write requests and up to 2 read requests, and instance 2 will queue up to 2 write requests and up to 6 read requests, the value of this macro should be 13 (2 + 3 + 2 + 6).

Remarks

The maximum combined queue depth should not be greater than 0xFFFF (ie 65535)

DRV_I2S_QUEUE_SIZE_IDXx Macro

Number of entries of all queues in all instances of the driver.

C

```
#define DRV_I2S_QUEUE_SIZE_IDXx
```

Description

I2S Driver Buffer Queue Size

This macro defined the number of entries for either the transmit or receive queues.

The transmit buffer queue will queue transmit buffers submitted by the DRV_I2S_BufferAddWrite() function. The receive buffer queue will queue receive buffers submitted by the DRV_I2S_BufferAddRead() function.

DRV_I2S_DATA_LENGTH_IDXx Macro

Macro to define the data length for the I2S peripheral

C

```
#define DRV_I2S_DATA_LENGTH_IDXx
```

Description

Data Length

Macro to define the data length. This will override the dmaDataLength member of the [DRV_I2S_INIT](#) initialization data structure in the driver initialization routine. This value must match the setting in the PLIB.

Remarks

None.

DRV_I2S_INT_SRC_IDXx Macro

Macro to define the interrupt source

C

```
#define DRV_I2S_INT_SRC_IDXx
```

Description

Interrupt Source

Macro to define the interrupt source. This will override the interruptI2S member of the [DRV_I2S_INIT](#) initialization data structure in the driver initialization routine. This value should be set to the I2S module interrupt enumeration in the Interrupt PLIB for the microcontroller.

Remarks

None.

DRV_I2S_XMIT_DMA_CH_IDXx Macro

Macro to defines the I2S Driver Transmit DMA Channel

C

```
#define DRV_I2S_XMIT_DMA_CH_IDXx
```

Description

I2S Driver Transmit DMA Channel

Macro to define the I2S Receive DMA Channel. The DMA channel defined by this macro will override the dmaChannelTransmit member of the [DRV_I2S_INIT](#) initialization data structure in the driver initialization routine. This value should be set to the DMA channel in the DMA PLIB for the microcontroller.

Remarks

None.

DRV_I2S_RCV_DMA_CH_IDXx Macro

Macro to defines the I2S Driver Receive DMA Channel

C

```
#define DRV_I2S_RCV_DMA_CH_IDXx
```

Description

I2S Driver Receive DMA Channel

Macro to define the I2S Receive DMA Channel. The DMA channel defined by this macro will override the `dmaChannelReceive` member of the `DRV_I2S_INIT` initialization data structure in the driver initialization routine. This value should be set to the DMA channel in the DMA PLIB for the microcontroller.

Remarks

None.

Configuring MHC

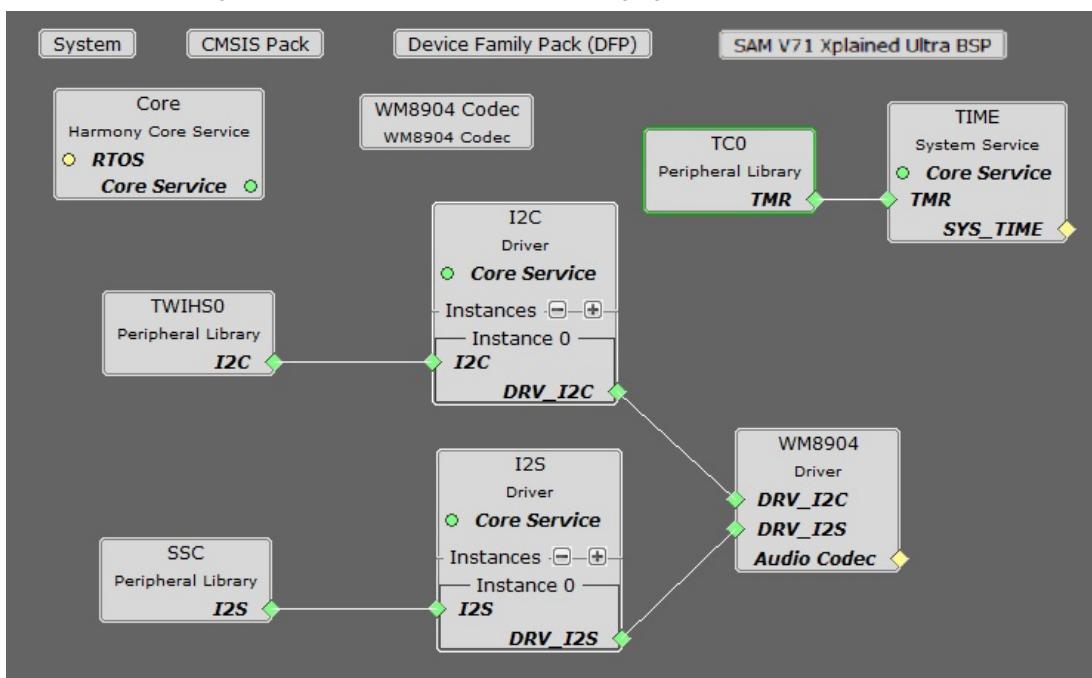
Provides examples on how to configure the MPLAB Harmony Configurator (MHC) for a specific driver.

Description

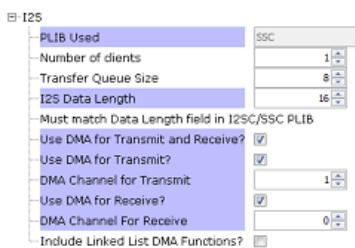
When building a new application, start by creating a 32-bit MPLAB Harmony 3 project in MPLAB X IDE by selecting *File > New Project*. Choose the Configuration name based on the BSP, and select the appropriate processor (such as ATSAME70Q21B).

In MHC, under Available Components select the appropriate BSP, such as SAM E70 Xplained Ultra. Under Audio->Templates, double-click on a codec template such as WM8904. Answer Yes to all questions.

You should end up with a project graph that looks like this, after rearranging the boxes:



Click on the I2S Driver component, Instance 0, and the following menu will be displayed in the Configurations Options:



PLIB Used will display the hardware peripheral instance connected to the I2S Driver, such as SPI0, SSC, or I2SC1.

Number of Clients indicates the maximum number of clients that can be connected to the I2S Driver.

Transfer Queue Size indicates number of buffers, of each transfer queue (transmit/receive).

I2S Data Length is the number of bits for one channel of audio (left or right). It must match the size of the PLIB.

Use DMA for Transmit and Receive should always be checked if using DMA, which is currently the only supported mode.

Use DMA for Transmit should be checked if sending data to a codec or Bluetooth module.

DMA Channel for Transmit indicates the DMA channel # assigned (done automatically when you connect the PLIB).

Use DMA for Receive should be checked if receiving data from a codec or Bluetooth module. However if you are only writing to the I2S stream, leaving this checked won't harm anything.

DMA Channel for Receive indicates the DMA channel # assigned (done automatically when you connect the PLIB).

Included Linked List DMA Functions should be checked if using the Linked DMA feature of some MCUs.

You can also bring in the I2S Driver by itself, by double clicking I2S under Harmony->Drivers in the Available Components list.

You will then need to add any additional needed components manually and connect them together.

Building the Library

This section lists the files that are available in the I2S Driver Library.

Description

The following three tables list and describe the header (.h) and source (.c) files that implement this library. The parent folder for these files is core/driver/i2s.

Interface File(s)

This table lists and describes the header files that must be included (i.e., using #include) by any code that uses this library.

Source File Name	Description
drv_i2s.h	This file provides the interface definitions of the I2S driver (generated via template core/driver/i2s/templates/drv_i2s.h.ftl)

Required File(s)

 **MHC** All of the required files listed in the following table are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

This table lists and describes the source and header files that must always be included in the MPLAB X IDE project to build this library.

Source File Name	Description
/src/drv_i2s.c	This file contains the core implementation of the I2S driver with DMA support (generated via template core/driver/i2s/templates/drv_i2s.c.ftl)

Optional File(s)

This table lists and describes the source and header files that may optionally be included if required for the desired implementation.

Source File Name	Description
N/A	

Module Dependencies

The I2S Driver Library depends on the following modules:

- SPI Peripheral Library, or
- SSC Peripheral Library
- I2SC Peripheral Library

Library Interface

a) System Interaction Functions

	Name	Description
≡	DRV_I2S_Initialize	Initializes the I2S instance for the specified driver index.
≡	DRV_I2S_Status	Gets the current status of the I2S driver module.

b) Client Setup Functions

	Name	Description
≡	DRV_I2S_Open	Opens the specified I2S driver instance and returns a handle to it.
≡	DRV_I2S_Close	Closes an opened-instance of the I2S driver.

c) Data Transfer Functions

	Name	Description
≡	DRV_I2S_ReadBufferAdd	Queues a read operation.
≡	DRV_I2S_WriteBufferAdd	Queues a write operation.
≡	DRV_I2S_WriteReadBufferAdd	Queues a write/read operation.
≡	DRV_I2S_BufferEventHandlerSet	Allows a client to identify a buffer event handling function for the driver to call back when queued buffer transfers have finished.
≡	DRV_I2S_ReadQueuePurge	Removes all buffer requests from the read queue.
≡	DRV_I2S_WriteQueuePurge	Removes all buffer requests from the write queue.
≡	DRV_I2S_ReadBuffer	This is a blocking function that reads data over I2S.
≡	DRV_I2S_WriteBuffer	This is a blocking function that writes data over I2S.
≡	DRV_I2S_BufferStatusGet	Returns the transmit/receive request status.
≡	DRV_I2S_BufferCompletedBytesGet	Returns the number of bytes that have been processed for the specified buffer request.

d) Miscellaneous Functions

	Name	Description
≡	DRV_I2S_ErrorGet	Gets the I2S hardware errors associated with the client.
≡	DRV_I2S_LRCLK_Sync	Synchronize to the start of the I2S LRCLK (left/right clock) signal
≡	DRV_I2S_SerialSetup	Sets the I2S serial communication settings dynamically.

e) Data Types and Constants

	Name	Description
	DRV_I2S_BUFFER_EVENT	Identifies the possible events that can result from a buffer add request.
	DRV_I2S_BUFFER_HANDLE	Handle identifying a read or write buffer passed to the driver.
	DRV_I2S_INIT	Defines the data required to initialize the I2S driver
	DRV_BAUDSET	This is type DRV_BAUDSET.
	DRV_I2S_DMA_WIDTH	This is type DRV_I2S_DMA_WIDTH.

	DRV_I2S_PLIB_INTERFACE	Defines the data required to initialize the I2S driver PLIB Interface.
	DRV_I2S_ERROR	Defines the data required to setup the I2S transfer
	DRV_I2S_SERIAL_SETUP	Defines the data required to dynamically set the serial settings.
	DRV_I2S_BUFFER_HANDLE_INVALID	Definition of an invalid buffer handle.
	DRV_I2S_LRCLK_GET	This is type DRV_I2S_LRCLK_GET .
	DRV_I2S_BUFFER_EVENT_HANDLER	Pointer to a I2S Driver Buffer Event handler function

Description

This section describes the Application Programming Interface (API) functions of the I2S Driver Library.

Refer to each section for a detailed description.

a) System Interaction Functions

DRV_I2S_Initialize Function

Initializes the I2S instance for the specified driver index.

C

```
SYS_MODULE_OBJ DRV_I2S_Initialize(const SYS_MODULE_INDEX index, const SYS_MODULE_INIT * const init);
```

Returns

If successful, returns a valid handle to a driver instance object. Otherwise, returns [SYS_MODULE_OBJ_INVALID](#).

Description

This routine initializes the I2S driver instance for the specified driver index, making it ready for clients to open and use it. The initialization data is specified by the init parameter. The initialization may fail if the number of driver objects allocated are insufficient or if the specified driver instance is already initialized. The driver instance index is independent of the I2S module ID. For example, driver instance 0 can be assigned to I2S2.

Remarks

This routine must be called before any other I2S routine is called.

This routine should only be called once during system initialization. This routine will NEVER block for hardware access.

Preconditions

None.

Example

```
// The following code snippet shows an example I2S driver initialization.

SYS_MODULE_OBJ objectHandle;

I2S_PLIB_API drvUsart0PlibAPI = {
{
    .readCallbackRegister = I2S1_ReadCallbackRegister,
    .read = I2S1_Read,
    .readIsBusy = I2S1_ReadIsBusy,
    .readCountGet = I2S1_ReadCountGet,
    .writeCallbackRegister = I2S1_WriteCallbackRegister,
    .write = I2S1_Write,
    .writeIsBusy = I2S1_WriteIsBusy,
    .writeCountGet = I2S1_WriteCountGet,
    .errorGet = I2S1_ErrorGet
}
};
```

```

DRV_I2S_INIT drvUsart0InitData =
{
    .i2sPlib = &drvUsart0PlibAPI,
    .interruptI2S = I2S1_IRQn,
    .queueSizeTransmit = DRV_I2S_XMIT_QUEUE_SIZE_IDX0,
    .queueSizeReceive = DRV_I2S_RCV_QUEUE_SIZE_IDX0,
    .dmaChannelTransmit = SYS_DMA_CHANNEL_NONE,
    .dmaChannelReceive = SYS_DMA_CHANNEL_NONE,
    .i2sTransmitAddress = I2S1_TRANSMIT_ADDRESS,
    .i2sReceiveAddress = I2S1_RECEIVE_ADDRESS,
    .interruptDMA = XDMAC_IRQn
};

objectHandle = DRV_I2S_Initialize(DRV_I2S_INDEX_1,
    (SYS_MODULE_INIT*)&drvUsart0InitData);
if (SYS_MODULE_OBJ_INVALID == objectHandle)
{
    // Handle error
}

```

Parameters

Parameters	Description
index	Identifier for the instance to be initialized
init	Pointer to the init data structure containing any data necessary to initialize the driver.

Function

```

SYS_MODULE_OBJ DRV_I2S_Initialize
(
    const SYS_MODULE_INDEX index,
    const SYS_MODULE_INIT * const init
)

```

DRV_I2S_Status Function

Gets the current status of the I2S driver module.

C

```
SYS_STATUS DRV_I2S_Status(SYS_MODULE_OBJ object);
```

Returns

SYS_STATUS_READY - Initialization have succeeded and the I2S is ready for additional operations

SYS_STATUS_DEINITIALIZED - Indicates that the driver has been deinitialized

Description

This routine provides the current status of the I2S driver module.

Remarks

A driver can opened only when its status is SYS_STATUS_READY.

Preconditions

Function [DRV_I2S_Initialize](#) should have been called before calling this function.

Example

```

SYS_MODULE_OBJ          object;      // Returned from DRV_I2S_Initialize
SYS_STATUS              i2sStatus;

i2sStatus = DRV_I2S_Status(object);
if (SYS_STATUS_READY == i2sStatus)

```

```
{
    // This means the driver can be opened using the
    // DRV_I2S_Open( ) function.
}
```

Parameters

Parameters	Description
object	Driver object handle, returned from the DRV_I2S_Initialize routine

Function

[SYS_STATUS DRV_I2S_Status\(SYS_MODULE_OBJ object \)](#)

b) Client Setup Functions

DRV_I2S_Open Function

Opens the specified I2S driver instance and returns a handle to it.

C

```
DRV_HANDLE DRV_I2S_Open(const SYS_MODULE_INDEX index, const DRV_IO_INTENT ioIntent);
```

Returns

If successful, the routine returns a valid open-instance handle (a number identifying both the caller and the module instance).

If an error occurs, the return value is [DRV_HANDLE_INVALID](#). Error can occur

- if the number of client objects allocated via [DRV_I2S_CLIENTS_NUMBER](#) is insufficient.
- if the client is trying to open the driver but driver has been opened exclusively by another client.
- if the driver peripheral instance being opened is not initialized or is invalid.
- if the client is trying to open the driver exclusively, but has already been opened in a non exclusive mode by another client.
- if the driver is not ready to be opened, typically when the initialize routine has not completed execution.

Description

This routine opens the specified I2S driver instance and provides a handle that must be provided to all other client-level operations to identify the caller and the instance of the driver. The [ioIntent](#) parameter defines how the client interacts with this driver instance.

Specifying a [DRV_IO_INTENT_EXCLUSIVE](#) will cause the driver to provide exclusive access to this client. The driver cannot be opened by any other client.

Remarks

The handle returned is valid until the [DRV_I2S_Close](#) routine is called. This routine will NEVER block waiting for hardware. If the requested intent flags are not supported, the routine will return [DRV_HANDLE_INVALID](#). This function is thread safe in a RTOS application.

Preconditions

Function [DRV_I2S_Initialize](#) must have been called before calling this function.

Example

```
DRV_HANDLE handle;

handle = DRV_I2S_Open(DRV_I2S_INDEX_0, DRV_IO_INTENT_EXCLUSIVE);
if (DRV_HANDLE_INVALID == handle)
{
    // Unable to open the driver
    // May be the driver is not initialized or the initialization
    // is not complete.
}
```

Parameters

Parameters	Description
index	Identifier for the object instance to be opened
intent	Zero or more of the values from the enumeration DRV_IO_INTENT "ORed" together to indicate the intended use of the driver. See function description for details.

Function

```
DRV_HANDLE DRV_I2S_Open
(
const  SYS_MODULE_INDEX index,
const  DRV_IO_INTENT ioIntent
)
```

DRV_I2S_Close Function

Closes an opened-instance of the I2S driver.

C

```
void DRV_I2S_Close(const DRV_HANDLE handle);
```

Returns

None.

Description

This routine closes an opened-instance of the I2S driver, invalidating the handle. Any buffers in the driver queue that were submitted by this client will be removed. A new handle must be obtained by calling [DRV_I2S_Open](#) before the caller may use the driver again.

Remarks

None.

Preconditions

[DRV_I2S_Open](#) must have been called to obtain a valid opened device handle.

Example

```
// 'handle', returned from the DRV_I2S_Open
DRV_I2S_Close(handle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
void DRV_I2S_Close( DRV_Handle handle )
```

c) Data Transfer Functions

DRV_I2S_ReadBufferAdd Function

Queues a read operation.

C

```
void DRV_I2S_ReadBufferAdd(const DRV_HANDLE handle, void * buffer, const size_t size,
DRV_I2S_BUFFER_HANDLE * const bufferHandle);
```

Returns

The buffer handle is returned in the bufferHandle argument. This is [DRV_I2S_BUFFER_HANDLE_INVALID](#) if the request was not successful.

Description

This function schedules a non-blocking read operation. The function returns with a valid buffer handle in the bufferHandle argument if the read request was scheduled successfully. The function adds the request to the hardware instance receive queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. The function returns [DRV_I2S_BUFFER_HANDLE_INVALID](#) in the bufferHandle argument:

- if a buffer could not be allocated to the request
- if the input buffer pointer is NULL
- if the buffer size is 0
- if the read queue size is full or queue depth is insufficient.
- if the driver handle is invalid

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_I2S_BUFFER_EVENT_COMPLETE](#) event if the buffer was processed successfully or [DRV_I2S_BUFFER_EVENT_ERROR](#) event if the buffer was not processed successfully.

Remarks

This function is thread safe in a RTOS application. It can be called from within the I2S Driver Buffer Event Handler that is registered by the client. It should not be called in the event handler associated with another I2S driver instance. It should not be called directly in an ISR.

Preconditions

[DRV_I2S_Open](#) must have been called to obtain a valid opened device handle.

Example

```
MY_APP_OBJ myAppObj;
uint8_t mybuffer[MY_BUFFER_SIZE];
DRV_I2S_BUFFER_HANDLE bufferHandle;

// myI2SHandle is the handle returned
// by the DRV_I2S_Open function.

DRV_I2S_ReadBufferAdd(myI2SHandle, myBuffer, MY_BUFFER_SIZE,
&bufferHandle);

if(DRV_I2S_BUFFER_HANDLE_INVALID == bufferHandle)
{
    // Error handling here
}

// Event is received when the buffer is processed.
```

Parameters

Parameters	Description
handle	Handle of the communication channel as returned by the DRV_I2S_Open function.
buffer	Buffer where the received data will be stored.
size	Buffer size in bytes.
bufferHandle	Pointer to an argument that will contain the return buffer handle.

Function

```
void DRV_I2S_ReadBufferAdd
(
```

```
const DRV_HANDLE handle,
void * buffer,
const size_t size,
DRV_I2S_BUFFER_HANDLE * bufferHandle
)
```

DRV_I2S_WriteBufferAdd Function

Queues a write operation.

C

```
void DRV_I2S_WriteBufferAdd(const DRV_HANDLE handle, void * buffer, const size_t size,
DRV_I2S_BUFFER_HANDLE * bufferHandle);
```

Returns

The bufferHandle parameter will contain the return buffer handle. This will be [DRV_I2S_BUFFER_HANDLE_INVALID](#) if the function was not successful.

Description

This function schedules a non-blocking write operation. The function returns with a valid buffer handle in the bufferHandle argument if the write request was scheduled successfully. The function adds the request to the driver instance transmit queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. On returning, the bufferHandle parameter may be [DRV_I2S_BUFFER_HANDLE_INVALID](#) for the following reasons:

- if a buffer could not be allocated to the request
- if the input buffer pointer is NULL
- if the client opened the driver for read-only
- if the buffer size is 0
- if the transmit queue is full or the queue depth is insufficient

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_I2S_BUFFER_EVENT_COMPLETE](#) event if the buffer was processed successfully or a [DRV_I2S_BUFFER_EVENT_ERROR](#) event if the buffer was not processed successfully.

Remarks

This function is thread safe in a RTOS application. It can be called from within the I2S Driver Buffer Event Handler that is registered by this client. It should not be called in the event handler associated with another I2S driver instance. It should not otherwise be called directly in an ISR.

Preconditions

[DRV_I2S_Open](#) must have been called to obtain a valid opened device handle.

Example

```
MY_APP_OBJ myAppObj;
uint8_t mybuffer[MY_BUFFER_SIZE];
DRV_I2S_BUFFER_HANDLE bufferHandle;

// myI2SHandle is the handle returned
// by the DRV_I2S_Open function.

DRV_I2S_WriteBufferAdd(myI2SHandle, myBuffer, MY_BUFFER_SIZE,
&bufferHandle);

if(DRV_I2S_BUFFER_HANDLE_INVALID == bufferHandle)
{
    // Error handling here
}

// Event is received when
// the buffer is processed.
```

Parameters

Parameters	Description
handle	Handle of the communication channel as return by the DRV_I2S_Open function.
buffer	Data to be transmitted.
size	Buffer size in bytes.
bufferHandle	Pointer to an argument that will contain the return buffer handle.

Function

```
void DRV_I2S_WriteBufferAdd
(
    const DRV_HANDLE handle,
    void * buffer,
    size_t size,
    DRV_I2S_BUFFER_HANDLE * bufferHandle
);
```

DRV_I2S_WriteReadBufferAdd Function

Queues a write/read operation.

C

```
void DRV_I2S_WriteReadBufferAdd(const DRV_HANDLE handle, void * transmitBuffer, void * receiveBuffer, size_t size, DRV_I2S_BUFFER_HANDLE * bufferHandle);
```

Returns

The bufferHandle parameter will contain the return buffer handle. This will be [DRV_I2S_BUFFER_HANDLE_INVALID](#) if the function was not successful.

Description

This function schedules a non-blocking write-read operation. The function returns with a valid buffer handle in the bufferHandle argument if the write-read request was scheduled successfully. The function adds the request to the hardware instance queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. The function returns [DRV_I2S_BUFFER_HANDLE_INVALID](#):

- if a buffer could not be allocated to the request
- if the input buffer pointer is NULL
- if the client opened the driver for read only or write only
- if the buffer size is 0
- if the queue is full or the queue depth is insufficient

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_I2S_BUFFER_EVENT_COMPLETE](#) event if the buffer was processed successfully or [DRV_I2S_BUFFER_EVENT_ERROR](#) event if the buffer was not processed successfully.

Remarks

This function is thread safe in a RTOS application. It can be called from within the I2S Driver Buffer Event Handler that is registered by this client. It should not be called in the event handler associated with another I2S driver instance. It should not otherwise be called directly in an ISR.

This function is useful when there is valid read expected for every I2S write. The transmit and receive size must be same.

Preconditions

[DRV_I2S_Open](#) must have been called to obtain a valid opened device handle.

Parameters

Parameters	Description
handle	Handle of the communication channel as return by the DRV_I2S_Open function.
transmitBuffer	Data to be transmitted.
receiveBuffer	Will hold data that is received.
size	Buffer size in bytes (same for both buffers)
bufferHandle	Pointer to an argument that will contain the return buffer handle.

Function

```
void DRV_I2S_BufferAddWriteRead(const DRV_HANDLE handle,
void *transmitBuffer, void *receiveBuffer,
size_t size, DRV_I2S_BUFFER_HANDLE *bufferHandle)
```

DRV_I2S_BufferEventHandlerSet Function

Allows a client to identify a buffer event handling function for the driver to call back when queued buffer transfers have finished.

C

```
void DRV_I2S_BufferEventHandlerSet(const DRV_HANDLE handle, const DRV_I2S_BUFFER_EVENT_HANDLER
eventHandler, const uintptr_t context);
```

Returns

None.

Description

This function allows a client to register a buffer event handling function with the driver to call back when queued buffer transfers have finished. When a client calls either the [DRV_I2S_ReadBufferAdd](#) or [DRV_I2S_WriteBufferAdd](#) function, it is provided with a handle identifying the buffer that was added to the driver's buffer queue. The driver will pass this handle back to the client by calling "eventHandler" function when the buffer transfer has completed.

The event handler should be set before the client performs any "buffer add" operations that could generate events. The event handler once set, persists until the client closes the driver or sets another event handler (which could be a "NULL" pointer to indicate no callback).

Remarks

If the client does not want to be notified when the queued buffer transfer has completed, it does not need to register a callback. This function is thread safe when called in a RTOS application.

Preconditions

[DRV_I2S_Open](#) must have been called to obtain a valid opened device handle.

Example

```
// myAppObj is an application specific state data object.
MY_APP_OBJ myAppObj;

uint8_t mybuffer[MY_BUFFER_SIZE];
DRV_I2S_BUFFER_HANDLE bufferHandle;

// myI2SHandle is the handle returned
// by the DRV_I2S_Open function.

// Client registers an event handler with driver. This is done once

DRV_I2S_BufferEventHandlerSet( myI2SHandle, APP_I2SBufferEventHandler,
                               (uintptr_t)&myAppObj );

DRV_I2S_ReadBufferAdd(myI2SHandle, myBuffer, MY_BUFFER_SIZE,
                      &bufferHandle);
```

```

if(DRV_I2S_BUFFER_HANDLE_INVALID == bufferHandle)
{
    // Error handling here
}

// Event is received when the buffer is processed.

void APP_I2SBufferEventHandler(DRV_I2S_BUFFER_EVENT event,
                               DRV_I2S_BUFFER_HANDLE handle, uintptr_t context)
{
    // The context handle was set to an application specific
    // object. It is now retrievable easily in the event handler.
    MY_APP_OBJ myAppObj = (MY_APP_OBJ *) context;

    switch(event)
    {
        case DRV_I2S_BUFFER_EVENT_COMPLETE:
            // This means the data was transferred.
            break;

        case DRV_I2S_BUFFER_EVENT_ERROR:
            // Error handling here.
            break;

        default:
            break;
    }
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine.
eventHandler	Pointer to the event handler function.
context	The value of parameter will be passed back to the client unchanged, when the eventHandler function is called. It can be used to identify any client specific data object that identifies the instance of the client module (for example, it may be a pointer to the client module's state structure).

Function

```

void DRV_I2S_BufferEventHandlerSet
(
    const DRV_HANDLE handle,
    const DRV_I2S_BUFFER_EVENT_HANDLER eventHandler,
    const uintptr_t context
)

```

DRV_I2S_ReadQueuePurge Function

Removes all buffer requests from the read queue.

C

```
bool DRV_I2S_ReadQueuePurge(const DRV_HANDLE handle);
```

Returns

True - Read queue purge is successful. False - Read queue purge has failed.

Description

This function removes all the buffer requests from the read queue. The client can use this function to purge the queue on timeout or to remove unwanted stalled buffer requests or in any other use case.

Remarks

This function is thread safe when used in an RTOS environment. Avoid this function call from within the callback.

Preconditions

[DRV_I2S_Open](#) must have been called to obtain a valid opened device handle.

Example

```
// myI2SHandle is the handle returned by the DRV_I2S_Open function.
// Use DRV_I2S_ReadBufferAdd to queue read requests

// Application timeout function, where remove queued buffers.
void APP_TimeOut(void)
{
    if(false == DRV_I2S_ReadQueuePurge(myI2SHandle))
    {
        //Couldn't purge the read queue, try again.
    }
    else
    {
        //Queue purge successful.
    }
}
```

Parameters

Parameters	Description
handle	Handle of the communication channel as returned by the DRV_I2S_Open function.

Function

bool DRV_I2S_ReadQueuePurge(const [DRV_HANDLE](#) handle)

DRV_I2S_WriteQueuePurge Function

Removes all buffer requests from the write queue.

C

```
bool DRV_I2S_WriteQueuePurge(const DRV\_HANDLE handle);
```

Returns

True - Write queue purge is successful. False - Write queue purge has failed.

Description

This function removes all the buffer requests from the write queue. The client can use this function to purge the queue on timeout or to remove unwanted stalled buffer requests or in any other use case.

Remarks

This function is thread safe when used in an RTOS environment. Avoid this function call from within the callback.

Preconditions

[DRV_I2S_Open](#) must have been called to obtain a valid opened device handle.

Example

```
// myI2SHandle is the handle returned by the DRV_I2S_Open function.
// Use DRV_I2S_WriteBufferAdd to queue write requests

// Application timeout function, where remove queued buffers.
void APP_TimeOut(void)
{
    if(false == DRV_I2S_WriteQueuePurge(myI2SHandle))
    {
```

```

        //Couldn't purge the write queue, try again.
    }
    else
    {
        //Queue purge successful.
    }
}

```

Parameters

Parameters	Description
handle	Handle of the communication channel as returned by the DRV_I2S_Open function.

Function

bool [DRV_I2S_WriteQueuePurge](#)(const [DRV_HANDLE](#) handle)

DRV_I2S_ReadBuffer Function

This is a blocking function that reads data over I2S.

C

```
bool DRV\_I2S\_ReadBuffer(const DRV\_HANDLE handle, void * buffer, const size_t size);
```

Returns

true - read is successful false - error has occurred

Description

This function does a blocking read operation. The function blocks till the data read is complete or error has occurred during read. Function will return false to report failure. The failure will occur for the following reasons:

- if the handle is invalid
- if the input buffer pointer is NULL
- if the buffer size is 0
- Hardware errors

Remarks

This function is thread safe in a RTOS application. This function should not be called from an interrupt context.

Preconditions

[DRV_I2S_Open](#) must have been called to obtain a valid opened device handle.

Example

```

MY_APP_OBJ myAppObj;
uint8_t myBuffer[MY_BUFFER_SIZE];

// myI2SHandle is the handle returned
// by the DRV\_I2S\_Open function.

if (DRV\_I2S\_ReadBuffer(myI2SHandle, myBuffer, MY_BUFFER_SIZE) == false)
{
    // Error handling here
}

```

Parameters

Parameters	Description
handle	Handle of the communication channel as return by the DRV_I2S_Open function.
buffer	Pointer to the receive buffer.
size	Buffer size in bytes.

Function

```
bool DRV_I2S_ReadBuffer
(
    const DRV_HANDLE handle,
    void * buffer,
    const size_t size
);
```

DRV_I2S_WriteBuffer Function

This is a blocking function that writes data over I2S.

C

```
bool DRV_I2S_WriteBuffer(const DRV_HANDLE handle, void * buffer, const size_t size);
```

Returns

true - write is successful false - error has occurred

Description

This function does a blocking write operation. The function blocks till the data write is complete. Function will return false to report failure. The failure will occur for the following reasons:

- if the handle is invalid
- if the input buffer pointer is NULL
- if the buffer size is 0

Remarks

This function is thread safe in a RTOS application. This function should not be called from an interrupt context.

Preconditions

[DRV_I2S_Open](#) must have been called to obtain a valid opened device handle.

Example

```
MY_APP_OBJ myAppObj;
uint8_t myBuffer[MY_BUFFER_SIZE];

// myI2SHandle is the handle returned
// by the DRV_I2S_Open function.

if (DRV_I2S_WriteBuffer(myI2SHandle, myBuffer, MY_BUFFER_SIZE) == false)
{
    // Error: Verify the input parameters
}
```

Parameters

Parameters	Description
handle	Handle of the communication channel as return by the DRV_I2S_Open function.
buffer	Pointer to the data to be transmitted.
size	Buffer size in bytes.

Function

```
bool DRV_I2S_WriteBuffer
(
    const DRV_HANDLE handle,
    void * buffer,
    const size_t size
);
```

);

DRV_I2S_BufferStatusGet Function

Returns the transmit/receive request status.

C

```
DRV_I2S_BUFFER_EVENT DRV_I2S_BufferStatusGet( const DRV_I2S_BUFFER_HANDLE bufferHandle );
```

Returns

The success or error event of the buffer.

Description

This function can be used to poll the status of the queued buffer request if the application doesn't prefer to use the event handler (callback) function to get notified.

Remarks

This function returns error event if the buffer handle is invalid.

Preconditions

DRV_I2S_Open must have been called to obtain a valid opened device handle.

Either the DRV_I2S_ReadBufferAdd or DRV_I2S_WriteBufferAdd function must have been called and a valid buffer handle returned.

Example

```
// myAppObj is an application specific object.
MY_APP_OBJ myAppObj;

uint8_t mybuffer[MY_BUFFER_SIZE];
DRV_I2S_BUFFER_HANDLE bufferHandle;
DRV_I2S_BUFFER_EVENT event;

// myI2SHandle is the handle returned
// by the DRV_I2S_Open function.

// Client registers an event handler with driver. This is done once

DRV_I2S_BufferEventHandlerSet( myI2SHandle, APP_I2SBufferEventHandle,
                               (uintptr_t)&myAppObj );

DRV_I2S_ReadBufferAdd( myI2SHandle, myBuffer, MY_BUFFER_SIZE,
                      bufferHandle);

if(DRV_I2S_BUFFER_HANDLE_INVALID == bufferHandle)
{
    // Error handling here
}

//Check the status of the buffer
//This call can be used to wait until the buffer is processed.
event = DRV_I2S_BufferStatusGet(bufferHandle);
```

Parameters

Parameters	Description
bufferHandle	Handle for the buffer of which the processed number of bytes to be obtained.

Function

```
DRV_I2S_BUFFER_EVENT DRV_I2S_BufferStatusGet
(
    const DRV_I2S_BUFFER_HANDLE bufferHandle
```

)

DRV_I2S_BufferCompletedBytesGet Function

Returns the number of bytes that have been processed for the specified buffer request.

C

```
size_t DRV_I2S_BufferCompletedBytesGet(DRV_I2S_BUFFER_HANDLE bufferHandle);
```

Returns

Returns the number of bytes that have been processed for this buffer.

Returns [DRV_I2S_BUFFER_HANDLE_INVALID](#) for an invalid or an expired buffer handle.

Description

The client can use this function, in a case where the buffer is terminated due to an error, to obtain the number of bytes that have been processed. Or in any other use case. This function can be used for non-DMA buffer transfers only. It cannot be used when the I2S driver is configured to use DMA.

Remarks

This function is expected to work in non-DMA mode only. This function is thread safe when used in a RTOS application. If called from the callback, it must not call an OSAL mutex or critical section.

Preconditions

[DRV_I2S_Open](#) must have been called to obtain a valid opened device handle.

Either the [DRV_I2S_ReadBufferAdd](#) or [DRV_I2S_WriteBufferAdd](#) function must have been called and a valid buffer handle returned.

Example

```
// myAppObj is an application specific object.
MY_APP_OBJ myAppObj;

uint8_t mybuffer[MY_BUFFER_SIZE];
DRV_I2S_BUFFER_HANDLE bufferHandle;

// myI2SHandle is the handle returned
// by the DRV_I2S_Open function.

// Client registers an event handler with driver. This is done once

DRV_I2S_BufferEventHandlerSet( myI2SHandle, APP_I2SBufferEventHandler,
                               (uintptr_t)&myAppObj );

DRV_I2S_ReadBufferAdd( myI2SHandle, myBuffer, MY_BUFFER_SIZE,
                      bufferHandle);

if(DRV_I2S_BUFFER_HANDLE_INVALID == bufferHandle)
{
    // Error handling here
}

// Event Processing Technique. Event is received when
// the buffer is processed.

void APP_I2SBufferEventHandler( DRV_I2S_BUFFER_EVENT event,
                                DRV_I2S_BUFFER_HANDLE bufferHandle, uintptr_t contextHandle )
{
    // The context handle was set to an application specific
    // object. It is now retrievable easily in the event handler.
    MY_APP_OBJ myAppObj = (MY_APP_OBJ *) contextHandle;
    size_t processedBytes;
```

```

switch(event)
{
    case DRV_I2S_BUFFER_EVENT_COMPLETE:
        // This means the data was transferred.
        break;

    case DRV_I2S_BUFFER_EVENT_ERROR:
        // Error handling here.
        // We can find out how many bytes have been processed in this
        // buffer request prior to the error.
        processedBytes= DRV_I2S_BufferCompletedBytesGet(bufferHandle);
        break;

    default:
        break;
}
}

```

Parameters

Parameters	Description
bufferhandle	Handle for the buffer of which the processed number of bytes to be obtained.

Function

```

size_t DRV_I2S_BufferCompletedBytesGet
(
    DRV_I2S_BUFFER_HANDLE bufferHandle
);

```

d) Miscellaneous Functions

DRV_I2S_ErrorGet Function

Gets the I2S hardware errors associated with the client.

C

```
DRV_I2S_ERROR DRV_I2S_ErrorGet(const DRV_HANDLE handle);
```

Returns

Errors occurred as listed by [DRV_I2S_ERROR](#). This function reports multiple I2S errors if occurred.

Description

This function returns the errors associated with the given client. The call to this function also clears all the associated error flags.

Remarks

I2S errors are normally associated with the receiver. The driver clears all the errors internally and only returns the occurred error information for the client.

Preconditions

[DRV_I2S_Open](#) must have been called to obtain a valid opened device handle.

Example

```

// 'handle', returned from the DRV_I2S_Open

if (DRV_I2S_ERROR_OVERRUN & DRV_I2S_ErrorGet(handle))
{
    //Errors are cleared by the driver, take respective action
    //for the overrun error case.
}

```

}

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
DRV_I2S_ERROR DRV_I2S_ErrorGet( const DRV_HANDLE handle )
```

DRV_I2S_LRCLK_Sync Function

Synchronize to the start of the I2S LRCLK (left/right clock) signal

C

```
bool DRV_I2S_LRCLK_Sync( const DRV_HANDLE handle, const uint32_t sample_rate );
```

Returns

true if the function was successful, false if a timeout occurred (no transitions seen)

Description

This function waits until low-tohigh transition of the I2S LRCLK (left/right clock) signal (high-low if Left-Justified format, this is determined by the PLIB). In the case where this signal is generated from a codec or other external source, this allows the caller to synchronize calls to the DMA with the LRCLK signal so the left/right channel association is valid.

Remarks

None.

Preconditions

None.

Example

```
// myI2SHandle is the handle returned
// by the DRV_I2S_Open function.

DRV_I2S_LRCLK_Sync(myI2SHandle, 48000);
```

Function

```
uint32_t DRV_I2S_LRCLK_Sync( const DRV_HANDLE handle, const uint32_t sample_rate );
```

DRV_I2S_SerialSetup Function

Sets the I2S serial communication settings dynamically.

C

```
bool DRV_I2S_SerialSetup( const DRV_HANDLE handle, DRV_I2S_SERIAL_SETUP * setup );
```

Returns

true - Serial setup was updated successfully. false - Failure while updating serial setup.

Description

This function sets the I2S serial communication settings dynamically.

Remarks

None.

Preconditions

`DRV_I2S_Open` must have been called to obtain a valid opened device handle. The I2S transmit or receive transfer status should not be busy.

Example

```
// 'handle', returned from the DRV_I2S_Open

DRV_I2S_SERIAL_SETUP setup = {
    115200,
    DRV_I2S_DATA_8_BIT,
    DRV_I2S_PARITY_ODD,
    DRV_I2S_STOP_1_BIT
};

DRV_I2S_SerialSetup(handle, &setup);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
setup	Pointer to the structure containing the serial setup.

Function

```
bool DRV_I2S_SerialSetup(const DRV_HANDLE handle,
    DRV_I2S_SERIAL_SETUP * setup)
```

e) Data Types and Constants

DRV_I2S_BUFFER_EVENT Enumeration

Identifies the possible events that can result from a buffer add request.

C

```
typedef enum {
    DRV_I2S_BUFFER_EVENT_COMPLETE,
    DRV_I2S_BUFFER_EVENT_ERROR,
    DRV_I2S_BUFFER_EVENT_ABORT
} DRV_I2S_BUFFER_EVENT;
```

Members

Members	Description
DRV_I2S_BUFFER_EVENT_COMPLETE	All data from or to the buffer was transferred successfully.
DRV_I2S_BUFFER_EVENT_ERROR	There was an error while processing the buffer transfer request.

Description

I2S Driver Buffer Events

This enumeration identifies the possible events that can result from a buffer add request caused by the client calling either the `DRV_I2S_ReadBufferAdd` or `DRV_I2S_WriteBufferAdd` functions.

Remarks

One of these values is passed in the "event" parameter of the event handling callback function that the client registered with the driver by calling the `DRV_I2S_BufferEventHandlerSet` function when a buffer transfer request is completed.

DRV_I2S_BUFFER_HANDLE Type

Handle identifying a read or write buffer passed to the driver.

C

```
typedef uintptr_t DRV_I2S_BUFFER_HANDLE;
```

Description

I2S Driver Buffer Handle

A buffer handle value is returned by a call to the [DRV_I2S_ReadBufferAdd](#) or [DRV_I2S_WriteBufferAdd](#) functions. This handle is associated with the buffer passed into the function and it allows the application to track the completion of the data from (or into) that buffer. The buffer handle value returned from the "buffer add" function is returned back to the client by the "event handler callback" function registered with the driver.

The buffer handle assigned to a client request expires when the client has been notified of the completion of the buffer transfer (after event handler function that notifies the client returns) or after the buffer has been retired by the driver if no event handler callback was set.

Remarks

None

DRV_I2S_INIT Structure

Defines the data required to initialize the I2S driver

C

```
typedef struct {
    DRV_I2S_PLIB_INTERFACE * i2sPlib;
    INT_SOURCE interruptI2S;
    uintptr_t clientObjPool;
    size_t numClients;
    uintptr_t transferObjPool;
    size_t queueSize;
    SYS_DMA_CHANNEL dmaChannelTransmit;
    SYS_DMA_CHANNEL dmaChannelReceive;
    void * i2sTransmitAddress;
    void * i2sReceiveAddress;
    INT_SOURCE interruptDMA;
    uint8_t dmaDataLength;
} DRV_I2S_INIT;
```

Members

Members	Description
DRV_I2S_PLIB_INTERFACE * i2sPlib;	Identifies the PLIB API set to be used by the driver to access the <ul style="list-style-type: none"> • peripheral.
INT_SOURCE interruptI2S;	Interrupt source ID for the I2S interrupt.
uintptr_t clientObjPool;	Memory Pool for Client Objects
size_t numClients;	Number of clients
uintptr_t transferObjPool;	Queue for Transfer Objects
size_t queueSize;	Driver Queue Size
SYS_DMA_CHANNEL dmaChannelTransmit;	I2S transmit DMA channel.
SYS_DMA_CHANNEL dmaChannelReceive;	I2S receive DMA channel.
void * i2sTransmitAddress;	I2S transmit register address used for DMA operation.
void * i2sReceiveAddress;	I2S receive register address used for DMA operation.

INT_SOURCE interruptDMA;	Interrupt source ID for DMA interrupt.
uint8_t dmaDataLength;	DMA data length from I2S or SSC PLIB

Description

I2S Driver Initialization Data

This data type defines the data required to initialize or the I2S driver.

Remarks

None.

DRV_BAUDSET Type

C

```
typedef void (* DRV_BAUDSET)(const uint32_t);
```

Description

This is type DRV_BAUDSET.

DRV_I2S_DMA_WIDTH Enumeration

C

```
typedef enum {
    DRV_I2S_DMA_WIDTH_8_BIT = 0,
    DRV_I2S_DMA_WIDTH_16_BIT = 1
} DRV_I2S_DMA_WIDTH;
```

Description

This is type DRV_I2S_DMA_WIDTH.

DRV_I2S_PLIB_INTERFACE Structure

Defines the data required to initialize the I2S driver PLIB Interface.

C

```
typedef struct {
    DRV_BAUDSET setBaud;
    DRV_I2S_LRCLK_GET I2S_LRCLK_Get;
} DRV_I2S_PLIB_INTERFACE;
```

Members

Members	Description
DRV_BAUDSET setBaud;	I2S PLIB baud rate set function

Description

I2S Driver PLIB Interface Data

This data type defines the data required to initialize the I2S driver PLIB Interface.

Remarks

None.

DRV_I2S_ERROR Enumeration

Defines the data required to setup the I2S transfer

C

```
typedef enum {
    DRV_I2S_ERROR_NONE = 0,
    DRV_I2S_ERROR_OVERRUN = 1
} DRV_I2S_ERROR;
```

Description

I2S Driver Setup Data

This data type defines the data required to setup the I2S transfer. The data is passed to the [DRV_I2S_TransferSetup](#) API to setup the I2S peripheral settings dynamically.

Remarks

None.

DRV_I2S_SERIAL_SETUP Type

Defines the data required to dynamically set the serial settings.

C

```
typedef struct _DRV_I2S_SERIAL_SETUP DRV_I2S_SERIAL_SETUP;
```

Description

I2S Driver Serial Setup Data

This data type defines the data required to dynamically set the serial settings for the specific I2S driver instance.

Remarks

This structure is implementation specific. It is fully defined in `drv_i2s_definitions.h`.

DRV_I2S_BUFFER_HANDLE_INVALID Macro

Definition of an invalid buffer handle.

C

```
#define DRV_I2S_BUFFER_HANDLE_INVALID
```

Description

I2S Driver Invalid Buffer Handle

This is the definition of an invalid buffer handle. An invalid buffer handle is returned by [DRV_I2S_ReadBufferAdd](#) and [DRV_I2S_WriteBufferAdd](#) functions if the buffer add request was not successful.

Remarks

None

DRV_I2S_LRCLK_GET Type

C

```
typedef uint32_t (* DRV_I2S_LRCLK_GET)();
```

Description

This is type DRV_I2S_LRCLK_GET.

DRV_I2S_BUFFER_EVENT_HANDLER Type

Pointer to a I2S Driver Buffer Event handler function

C

```
typedef void (* DRV_I2S_BUFFER_EVENT_HANDLER)(DRV_I2S_BUFFER_EVENT event, DRV_I2S_BUFFER_HANDLE
bufferHandle, uintptr_t context);
```

Returns

None.

Description

I2S Driver Buffer Event Handler Function Pointer

This data type defines the required function signature for the I2S driver buffer event handling callback function. A client must register a pointer using the buffer event handling function whose function signature (parameter and return value types) match the types specified by this function pointer in order to receive buffer related event calls back from the driver.

The parameters and return values are described here and a partial example implementation is provided.

Remarks

If the event is DRV_I2S_BUFFER_EVENT_COMPLETE, it means that the data was transferred successfully.

If the event is DRV_I2S_BUFFER_EVENT_ERROR, it means that the data was not transferred successfully. The [DRV_I2S_BufferCompletedBytesGet](#) function can be called to find out how many bytes were processed.

The bufferHandle parameter contains the buffer handle of the buffer that associated with the event. And bufferHandle will be valid while the buffer request is in the queue and during callback, unless an error occurred. After callback returns, the driver will retire the buffer handle.

The context parameter contains the a handle to the client context, provided at the time the event handling function was registered using the [DRV_I2S_BufferEventHandlerSet](#) function. This context handle value is passed back to the client as the "context" parameter. It can be any value necessary to identify the client context or instance (such as a pointer to the client's data) instance of the client that made the buffer add request.

The event handler function executes in the peripheral's interrupt context when the driver is configured for interrupt mode operation. It is recommended of the application to not perform process intensive or blocking operations with in this function.

The [DRV_I2S_ReadBufferAdd](#) and [DRV_I2S_WriteBufferAdd](#) functions can be called in the event handler to add a buffer to the driver queue. These functions can only be called to add buffers to the driver whose event handler is running. For example, I2S2 driver buffers cannot be added in I2S1 driver event handler.

Example

```
void APP_MyBufferEventHandler( DRV_I2S_BUFFER_EVENT event,
                               DRV_I2S_BUFFER_HANDLE bufferHandle,
                               uintptr_t context )
{
    MY_APP_DATA_STRUCT pAppData = (MY_APP_DATA_STRUCT) context;

    switch(event)
    {
        case DRV_I2S_BUFFER_EVENT_COMPLETE:
            // Handle the completed buffer.
            break;

        case DRV_I2S_BUFFER_EVENT_ERROR:
        default:
            // Handle error.
            break;
    }
}
```

}

Parameters

Parameters	Description
event	Identifies the type of event
bufferHandle	Handle identifying the buffer to which the event relates
context	Value identifying the context of the application that registered the event handling function.

Memory Driver Library Help

This section describes the Memory driver library.

Introduction

This driver provides an interface to use Memory Driver to communicate with various media devices like QSPI_FLASH, EEPROM_FLASH, NVM_FLASH etc..

Description

The Memory driver is a multi-client multi-instance buffer model based block driver interface which can be used to communicate with various media devices.

Key Features of Memory Driver:

1. It works in both Asynchronous and Synchronous modes of operation.
2. It works in both Bare Metal and RTOS environment.
3. It can be used to communicate with Different Media's via common Media Interface.
 1. Media which can be accessed directly by Peripheral Libraries (NVM).
 2. Media which can be accessed by protocol drivers which in-turn connect to respective peripheral Libraries (SST26 Driver --> QSPI peripheral library)

Using the Library

This section describes the basic architecture of the Memory Driver and provides information on how it works.

Description

The Memory driver can be used to communicate with various media devices using common interface functions. The library interface functions can be used in two different modes.

Modes supported:

1. Asynchronous mode - Bare-metal and RTOS.
2. Synchronous mode - RTOS.

It can be used in multiple ways:

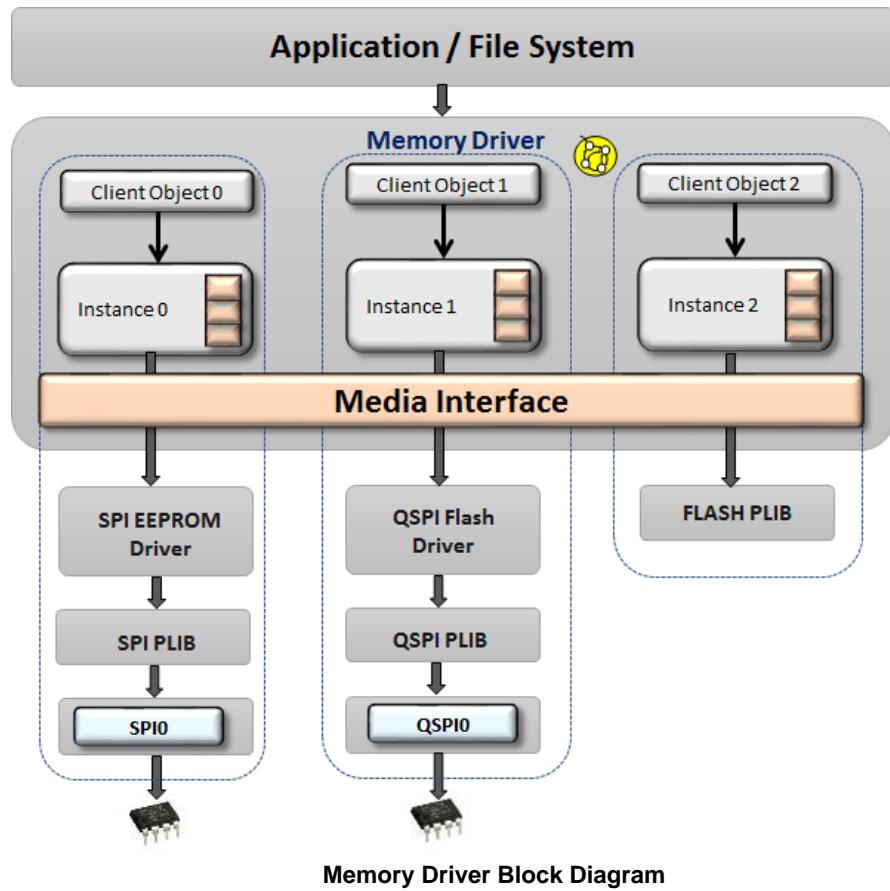
1. Application can directly use the Memory driver API's to perform Media operations.
2. Application can use File System service layer and perform file operations.
3. It can be interfaced with Middleware's like USB.

Abstraction Model

This section describes how the abstraction is modeled in software and introduces the library's interface.

Description

The Memory driver provides abstraction to communicate with different media devices via a common Media Interface ([DRV_MEMORY_DEVICE_INTERFACE](#)).



Note: Queue is not present in Synchronous mode of the driver.

How the Library Works

This section describes the basic architecture of the Memory driver library and provides an example on how to initialize the driver.

Description

The memory driver library is a multi-client, multi-instance buffer queue model based block driver interface.

Memory Driver Common Features:

- Each instance of the driver has its own buffer queue which allows the capability to not block other media operations
- Each instance of the driver can either have File-system as client or an application as client
- Every transfer request expects data in blocks. Block details (**Size and number of blocks**) can be retrieved by [DRV_MEMORY_GeometryGet\(\)](#)
- Driver provides feature to register call back for transfer complete event, which can be used by clients to get notified
- When the Memory driver is connected to the File System, the buffer queue is disabled as it is a blocking interface

Overview on behavior of memory driver in below two modes:

Asynchronous Mode	Synchronous Mode
Works in both Bare-Metal and RTOS environment	Works only in RTOS Environment

Provides Non-Blocking behavior.	Provides Blocking behavior. Application thread gets blocked on a semaphore until transfer request is completed.
API's to be used <code>DRV_MEMORY_AsyncXxx()</code>	API's to be used <code>DRV_MEMORY_SyncXxx()</code>
API's return with a valid handle which can be used to check whether transfer request is accepted	API's return true or false to indicate whether the whole transfer is completed.
Bare-Metal: A dedicated task routine <code>DRV_MEMORY_Tasks()</code> is called from <code>SYS_Tasks()</code> to process the data from the instance queue.	As the Driver works in complete blocking behavior there is no task routine generated.
RTOS: A dedicated thread is created for task routine <code>DRV_MEMORY_Tasks()</code> to process the data from the instance queue.	
A Client specific handler will be called to indicate the status of transfer.	A Client specific handler will be called to indicate the status of transfer before returning from API. Although the return type of API also can be used to identify the status of transfer.

How to plugin Media's to Memory Driver

The `DRV_MEMORY_INIT` data structure allows a Media driver Or Media peripheral library to be plugged into the Memory block driver.

Any media that needs to be plugged into the Memory block driver needs to implement the interface (function pointer signatures) specified by the `DRV_MEMORY_DEVICE_INTERFACE` type.

```
static uint8_t gDrvMemory0EraseBuffer[DRV_SST26_ERASE_BUFFER_SIZE] __attribute__((aligned(32)));

static DRV_MEMORY_CLIENT_OBJECT gDrvMemory0ClientObject[DRV_MEMORY_CLIENTS_NUMBER_IDX0] = { 0 };

static DRV_MEMORY_BUFFER_OBJECT gDrvMemory0BufferObject[DRV_MEMORY_BUFFER_QUEUE_SIZE_IDX0] = { 0 };

const DRV_MEMORY_DEVICE_INTERFACE drvMemory0DeviceInterface = {
    .Open          = DRV_SST26_Open,
    .Close         = DRV_SST26_Close,
    .Status        = DRV_SST26_Status,
    .SectorErase   = DRV_SST26_SectorErase,
    .Read          = DRV_SST26_Read,
    .PageWrite     = DRV_SST26_PageWrite,
    .EventHandlerSet = NULL,
    .GeometryGet   = (GEOMETRY_GET)DRV_SST26_GeometryGet,
    .TransferStatusGet = (TRANSFER_STATUS_GET)DRV_SST26_TransferStatusGet
};

const DRV_MEMORY_INIT drvMemory0InitData =
{
    .memDevIndex          = DRV_SST26_INDEX,
    .memoryDevice         = &drvMemory0DeviceInterface,
    .isMemDevInterruptEnabled = false,
    .isFsEnabled          = true,
    .deviceMediaType      = (uint8_t)SYS_FS_MEDIA_TYPE_SPIFLASH,
    .ewBuffer              = &gDrvMemory0EraseBuffer[0],
    .clientObjPool         = (uintptr_t)&gDrvMemory0ClientObject[0],
    .bufferObj             = (uintptr_t)&gDrvMemory0BufferObject[0],
    .queueSize              = DRV_MEMORY_BUFFER_QUEUE_SIZE_IDX0,
    .nClientsMax           = DRV_MEMORY_CLIENTS_NUMBER_IDX0
};

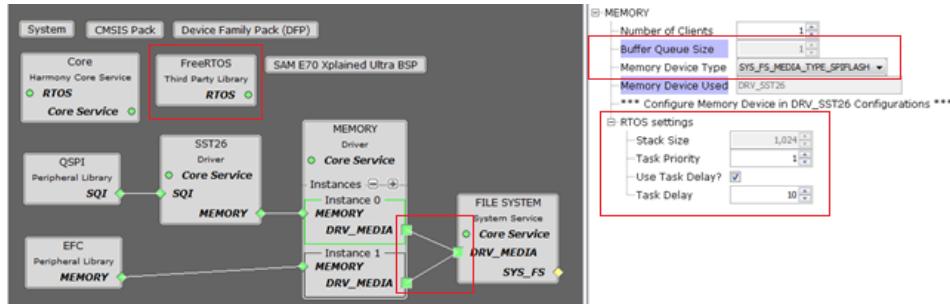
sysObj.drvMemory0 = DRV_MEMORY_Initialize((SYS_MODULE_INDEX)DRV_MEMORY_INDEX_0,
(SYS_MODULE_INIT *)&drvMemory0InitData);
```

Configuring the Library

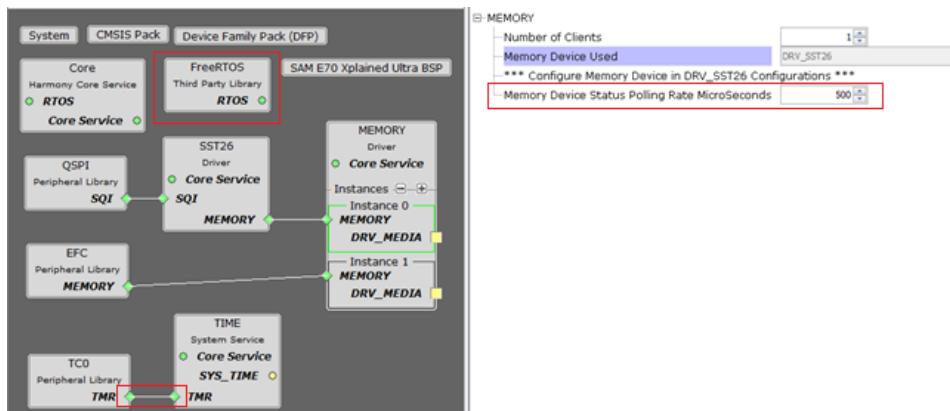
This section provides information on how to configure the Memory driver.

Description

The Memory driver library should be configured through the MHC. The following figures show the MHC configuration window for the Memory driver and brief description.



Asynchronous Mode with RTOS and File-System



Synchronous Mode with RTOS and without File System

Common User Configuration for all Instances

- **Driver Mode:**
 - Allows User to select the mode of driver(Asynchronous or Synchronous). This setting is common for all the instances.

Instance Specific User Configurations

- **Number Of Clients:**
 - Specifies number of clients to access the specific instance of the driver
- **Buffer Queue Size:**
 - Specifies maximum number of requests to be buffered in queue
 - When Connected to File system this value is set to 1 and non modifiable
 - This Configuration is displayed only in Asynchronous mode
- **Memory Device Type:**
 - Specifies the type of the device connected when the File system is connected to this instance
- **Memory Device Used:**
 - Specifies the Media device connected
- **Memory Device Status Polling Rate Microseconds:**

- Specifies the interval to poll for the transfer status
- Option is displayed only in synchronous mode and when Memory device used does not support interrupt mode
- RTOS Settings:**
 - This configuration is displayed only in asynchronous mode
- Stack Size:**
 - Specifies the number of bytes to be allocated on the stack
- Task Priority:**
 - Specifies priority for the Memory driver task thread
- Task Delay:**
 - Specifies delay to sleep for the Memory task thread after every call.

Building the Library

This section provides information on how the Memory Driver Library can be built.

Description



All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

Library Interface

a) System Functions

	Name	Description
≡	DRV_MEMORY_Initialize	Initializes the Memory instance for the specified driver index
≡	DRV_MEMORY_Status	Gets the current status of the Memory driver module.
≡	DRV_MEMORY_Tasks	Maintains the Memory driver's internal state machine.

b) Core Client Functions

	Name	Description
≡	DRV_MEMORY_Open	Opens the specified Memory driver instance and returns a handle to it
≡	DRV_MEMORY_Close	Closes an opened-instance of the Memory driver
≡	DRV_MEMORY_TransferHandlerSet	Allows a client to identify an event handling function for the driver to call back when queued operation has completed.

c) Block Operation Functions

	Name	Description
≡	DRV_MEMORY_AsyncErase	Erase the specified number of memory blocks from the specified block start. Each block is equal to sector size of the memory device attached.
≡	DRV_MEMORY_AsyncEraseWrite	Erase and Write blocks of data in the sectors where the block start belongs.
≡	DRV_MEMORY_AsyncRead	Reads nblocks of data from the specified block start.
≡	DRV_MEMORY_AsyncWrite	Writes nblocks of data starting at the specified block start.
≡	DRV_MEMORY_SyncErase	Erase the specified number of memory blocks from the specified block start. Each block is equal to sector size of the memory device attached.
≡	DRV_MEMORY_Erase	This routine provides interface to the file system to perform a media erase operation in synchronous mode of the Memory driver.
≡	DRV_MEMORY_SyncEraseWrite	Erase and Write blocks of data in the sectors where the block start belongs.
≡	DRV_MEMORY_EraseWrite	This routine provides interface to the file system to perform a media erase-write operation in synchronous mode of the Memory driver.
≡	DRV_MEMORY_SyncRead	Reads nblock of data from the specified block start.

≡	DRV_MEMORY_Read	This routine provides interface to the file system to perform a media read operation in synchronous mode of the Memory driver.
≡	DRV_MEMORY_SyncWrite	Writes nblock of data starting at the specified block start.
≡	DRV_MEMORY_Write	This routine provides interface to the file system to perform a media write operation in synchronous mode of the Memory driver.
≡	DRV_MEMORY_CommandStatusGet	Gets the current status of the command.
≡	DRV_MEMORY_TransferStatusGet	Gets the current status of the transfer request on attached device.

d) Media Interface Functions

	Name	Description
≡	DRV_MEMORY_AddressGet	Returns the Memory media start address
≡	DRV_MEMORY_GeometryGet	Returns the geometry of the memory device.
≡	DRV_MEMORY_IsAttached	Returns the physical attach status of the Media.
≡	DRV_MEMORY_IsWriteProtected	Returns the write protect status of the Memory.

e) Data Types and Constants

	Name	Description
	DRV_MEMORY_COMMAND_HANDLE	Handle to identify commands queued in the driver.
	DRV_MEMORY_COMMAND_HANDLE_INVALID	This value defines the Memory Driver's Invalid Command Handle.
	DRV_MEMORY_COMMAND_STATUS	Memory Driver command Status
	DRV_MEMORY_DEVICE_INTERFACE	Memory Device API.
	DRV_MEMORY_DEVICE_OPEN	Function pointer typedef to open the attached media
	DRV_MEMORY_DEVICE_CLOSE	Function pointer typedef to close the attached media
	DRV_MEMORY_DEVICE_SECTOR_ERASE	Function pointer typedef to erase a sector from attached media
	DRV_MEMORY_DEVICE_STATUS	Function pointer typedef to get the status of the attached media
	DRV_MEMORY_DEVICE_READ	Function pointer typedef to read from the attached media
	DRV_MEMORY_DEVICE_PAGE_WRITE	Function pointer typedef to write a page to the attached media
	DRV_MEMORY_DEVICE_EVENT_HANDLER_SET	Function pointer typedef to set the event handler with attached media
	DRV_MEMORY_DEVICE_GEOMETRY_GET	Function pointer typedef to get the Geometry details from attached media
	DRV_MEMORY_DEVICE_TRANSFER_STATUS_GET	Function pointer typedef to get the transfer Status from attached media
	DRV_MEMORY_EVENT	Identifies the possible events that can result from a request.
	DRV_MEMORY_EVENT_HANDLER	Function pointer typedef for event handler to be sent to attached media
	DRV_MEMORY_INIT	Memory Driver Initialization Data
	DRV_MEMORY_TRANSFER_HANDLER	Pointer to a Memory Driver Event handler function
	MEMORY_DEVICE_GEOMETRY	Memory Device Geometry Table.
	MEMORY_DEVICE_TRANSFER_STATUS	Memory Device Transfer Status.

Description

This section describes the Application Programming Interface (API) functions of the Memory driver library.

Refer to each section for a detailed description.

a) System Functions

DRV_MEMORY_Initialize Function

Initializes the Memory instance for the specified driver index

C

```
SYS_MODULE_OBJ DRV_MEMORY_Initialize(const SYS_MODULE_INDEX drvIndex, const SYS_MODULE_INIT * const init);
```

Returns

If successful, returns a valid handle to a driver instance object. Otherwise it returns [SYS_MODULE_OBJ_INVALID](#).

Description

This routine initializes the Memory driver instance for the specified driver index, making it ready for clients to open and use it.

Remarks

This routine must be called before any other Memory routine is called.

This routine should only be called once during system initialization.

This routine will NEVER block for hardware access. If the operation requires time to allow the hardware to initialize, it will be reported by the [DRV_MEMORY_Status](#) operation. The system must use [DRV_MEMORY_Status](#) to find out when the driver is in the ready state.

Preconditions

None.

Example

```
// This code snippet shows an example of initializing the Memory Driver
// with SST26 serial flash device attached and File system Enabled.

SYS_MODULE_OBJ objectHandle;

static uint8_t gDrvMemory0EraseBuffer[DRV_MEMORY_ERASE_BUFFER_SIZE_IDX0]
__attribute__((aligned(32)));

static DRV_MEMORY_CLIENT_OBJECT gDrvMemory0ClientObject[DRV_MEMORY_CLIENTS_NUMBER_IDX0] = { 0 };

static DRV_MEMORY_BUFFER_OBJECT gDrvMemory0BufferObject[DRV_MEMORY_BUFFER_QUEUE_SIZE_IDX0] = { 0 };

const DRV_MEMORY_DEVICE_INTERFACE drvMemory0DeviceAPI = {
    .Open          = DRV_SST26_Open,
    .Close         = DRV_SST26_Close,
    .Status        = DRV_SST26_Status,
    .SectorErase   = DRV_SST26_SectorErase,
    .Read          = DRV_SST26_Read,
    .PageWrite     = DRV_SST26_PageWrite,
    .GeometryGet   = (DRV_MEMORY_DEVICE_GEOMETRY_GET)DRV_SST26_GeometryGet,
    .TransferStatusGet = (DRV_MEMORY_DEVICE_TRANSFER_STATUS_GET)DRV_SST26_TransferStatusGet
};

const DRV_MEMORY_INIT drvMemory0InitData =
{
    .memDevIndex      = DRV_SST26_INDEX,
    .memoryDevice     = &drvMemory0DeviceAPI,
    .isFsEnabled       = true,
    .deviceMediaType  = (uint8_t)SYS_FS_MEDIA_TYPE_SPIFLASH,
    .ewBuffer          = &gDrvMemory0EraseBuffer[0],
    .clientObjPool    = (uintptr_t)&gDrvMemory0ClientObject[0],
    .bufferObj         = (uintptr_t)&gDrvMemory0BufferObject[0],
    .queueSize         = DRV_MEMORY_BUFFER_QUEUE_SIZE_IDX0,
    .nClientsMax      = DRV_MEMORY_CLIENTS_NUMBER_IDX0
};
```

```

};

//usage of DRV_MEMORY_INDEX_0 indicates usage of Flash-related APIs
objectHandle = DRV_MEMORY_Initialize((SYS_MODULE_INDEX)DRV_MEMORY_INDEX_0, (SYS_MODULE_INIT
*)&drvMemory0InitData);

if (SYS_MODULE_OBJ_INVALID == objectHandle)
{
    // Handle error
}

```

Parameters

Parameters	Description
drvIndex	Identifier for the instance to be initialized
init	Pointer to a data structure containing any data necessary to initialize the driver.

Function

```

SYS_MODULE_OBJ DRV_MEMORY_Initialize
(
const    SYS_MODULE_INDEX drvIndex,
const    SYS_MODULE_INIT * const init
);

```

DRV_MEMORY_Status Function

Gets the current status of the Memory driver module.

C

```
SYS_STATUS DRV_MEMORY_Status(SYS_MODULE_OBJ object);
```

Returns

SYS_STATUS_READY - Indicates that the driver is ready and accept requests for new operations.
 SYS_STATUS_UNINITIALIZED - Indicates the driver is not initialized.
 SYS_STATUS_BUSY - Indicates the driver is in busy state.

Description

This routine provides the current status of the Memory driver module.

Remarks

This routine will NEVER block waiting for hardware.

Preconditions

Function [DRV_MEMORY_Initialize](#) should have been called before calling this function.

Example

```

SYS_MODULE_OBJ      object;      // Returned from DRV_MEMORY_Initialize
SYS_STATUS         MEMORYStatus;

MEMORYStatus = DRV_MEMORY_Status(object);

```

Parameters

Parameters	Description
object	Driver object handle, returned from the DRV_MEMORY_Initialize routine

Function

```
SYS_STATUS DRV_MEMORY_Status( SYS_MODULE_OBJ object );
```

DRV_MEMORY_Tasks Function

Maintains the Memory driver's internal state machine.

C

```
void DRV_MEMORY_Tasks(SYS_MODULE_OBJ object);
```

Returns

None.

Description

This routine maintains the driver's internal state machine.

Initial state is put to process Queue so that driver can accept transfer requests(open, erase, read, write, etc) from client.

This routine is also responsible for checking the status of Erase and Write transfer requests and notify the client through transferHandler registered if any.

The state of driver will be busy until transfer is completed. Once transfer is done the state goes back to Process state until new requests is received.

Remarks

This routine is generated only in Asynchronous mode.

This routine should not be called directly by application.

- For Bare Metal it will be called by the system Task routine (SYS_Tasks).
- For RTOS a separate Thread will be created for this task and will be called in the thread context.

Preconditions

The [DRV_MEMORY_Initialize](#) routine must have been called for the specified Memory driver instance.

Example

```
SYS_MODULE_OBJ object;           // Returned from DRV_MEMORY_Initialize

void SYS_Tasks ( void )
{
    DRV_Memory_Tasks (object);
    // Do other tasks
}
```

Parameters

Parameters	Description
object	Driver object handle, returned from the DRV_MEMORY_Initialize routine

Function

```
void DRV_MEMORY_Tasks( SYS_MODULE_OBJ object );
```

b) Core Client Functions

DRV_MEMORY_Open Function

Opens the specified Memory driver instance and returns a handle to it

C

```
DRV_HANDLE DRV_MEMORY_Open(const SYS_MODULE_INDEX drvIndex, const DRV_IO_INTENT ioIntent);
```

Returns

If successful, the routine returns a valid open-instance handle (a number identifying both the caller and the module instance).

If an error occurs, `DRV_HANDLE_INVALID` is returned. Errors can occur under the following circumstances:

- if the attached media device is not ready or the geometry get fails.
- if the number of client objects allocated via `DRV_MEMORY_CLIENTS_NUMBER` is insufficient
- if the client is trying to open the driver but driver has been opened exclusively by another client
- if the client is trying to open the driver exclusively, but has already been opened in a non exclusive mode by another client.
- if the driver hardware instance being opened is not initialized or is invalid
- if the attached memory device open or geometry read fails for first time.

Description

This routine opens the specified Memory driver instance and provides a handle.

When `Open` is called for the first time for specified Memory driver instance it opens the attached media device and reads the geometry details.

This handle returned must be provided to all other client-level operations to identify the caller and the instance of the driver.

Remarks

The handle returned is valid until the `DRV_MEMORY_Close` routine is called.

This routine will NEVER block wait for hardware. If the driver has already been opened, it cannot be opened again.

Preconditions

Function `DRV_MEMORY_Initialize` must have been called before calling this function.

Example

```
DRV_HANDLE handle;

handle = DRV_MEMORY_Open(DRV_MEMORY_INDEX_0);
if (DRV_HANDLE_INVALID == handle)
{
    // Unable to open the driver
}
```

Parameters

Parameters	Description
<code>drvIndex</code>	Identifier for the instance to be opened
<code>ioIntent</code>	Zero or more of the values from the enumeration <code>DRV_IO_INTENT</code> "ORed" together to indicate the intended use of the driver

Function

```
DRV_HANDLE DRV_MEMORY_Open
(
const  SYS_MODULE_INDEX drvIndex,
const  DRV_IO_INTENT ioIntent
);
```

DRV_MEMORY_Close Function

Closes an opened-instance of the Memory driver

C

```
void DRV_MEMORY_Close(const DRV_HANDLE handle);
```

Returns

None

Description

This routine closes an opened-instance of the Memory driver, invalidating the handle.

Remarks

After calling this routine, the handle passed in "handle" must not be used with any of the remaining driver routines. A new handle must be obtained by calling [DRV_MEMORY_Open](#) before the caller may use the driver again. Usually there is no need for the driver client to verify that the Close operation has completed.

Preconditions

[DRV_MEMORY_Open](#) must have been called to obtain a valid opened device handle.

Example

```
DRV_HANDLE handle; // Returned from DRV_MEMORY_Open

DRV_MEMORY_Close(handle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
void DRV_MEMORY_Close( const DRV_HANDLE handle );
```

DRV_MEMORY_TransferHandlerSet Function

Allows a client to identify an event handling function for the driver to call back when queued operation has completed.

C

```
void DRV_MEMORY_TransferHandlerSet( const DRV_HANDLE handle, const void * transferHandler, const
uintptr_t context );
```

Returns

None.

Description

This function allows a client to set an event handling function for the driver to call back when queued operation has completed.

When a client calls a read, write, erase or a erasewrite function, it is provided with a handle identifying the command that was added to the driver's buffer queue. The driver will pass this handle back to the client by calling "transferHandler" function when the queued operation has completed.

The event handler should be set before the client performs any operations that could generate events. The event handler once set, persists until the client closes the driver or sets another event handler (which could be a "NULL" pointer to indicate no callback).

Remarks

If the client does not want to be notified when the queued operation has completed, it does not need to register a callback.

Used in Asynchronous Mode of operation.

Preconditions

The [DRV_MEMORY_Open\(\)](#) routine must have been called to obtain a valid opened device handle.

Example

```
DRV_MEMORY_COMMAND_HANDLE commandHandle;

// memoryHandle is the handle returned by the DRV_MEMORY_Open function.
// Client registers an event handler with driver

// Event is received when the erase request is completed.
```

```

void appTransferHandler
(
    DRV_MEMORY_EVENT event,
    DRV_MEMORY_COMMAND_HANDLE commandHandle,
    uintptr_t context
)
{
    switch(event)
    {
        case DRV_MEMORY_EVENT_COMMAND_COMPLETE:
            xfer_done = true;
            break;
        case DRV_MEMORY_EVENT_COMMAND_ERROR:
            // Handle Error
            break;
        default:
            break;
    }
}

DRV_MEMORY_TransferHandlerSet(memoryHandle, appTransferHandler, (uintptr_t)NULL);

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
transferHandler	Pointer to the event handler function implemented by the user
context	The value of parameter will be passed back to the client unchanged, when the transferHandler function is called. It can be used to identify any client specific data object that identifies the instance of the client module (for example, it may be a pointer to the client module's state structure).

Function

```

void DRV_MEMORY_TransferHandlerSet
(
    const DRV_HANDLE handle,
    const void * transferHandler,
    const uintptr_t context
);

```

c) Block Operation Functions

DRV_MEMORY_AsyncErase Function

Erase the specified number of memory blocks from the specified block start.

Each block is equal to sector size of the memory device attached.

C

```

void DRV_MEMORY_AsyncErase(const DRV_HANDLE handle, DRV_MEMORY_COMMAND_HANDLE * commandHandle,
                           uint32_t blockStart, uint32_t nBlock);

```

Returns

The command handle is returned in the commandHandle argument. It Will be [DRV_MEMORY_COMMAND_HANDLE_INVALID](#) if the request was not queued.

Description

This function schedules a non-blocking sector erase operation on attached memory device.

The function returns with a valid erase handle in the commandHandle argument if the erase request was scheduled successfully. The function adds the request to the hardware instance queue and returns immediately.

The function returns [DRV_MEMORY_COMMAND_HANDLE_INVALID](#) in the commandHandle argument under the following circumstances:

- if a buffer object could not be allocated to the request
- if the client opened the driver for read only
- if the number of blocks to be erased is either zero or more than the number of blocks actually available
- if the erase queue size is full or queue depth is insufficient
- if the driver handle is invalid

If the requesting client registered a transfer handler callback with the driver will issue a [DRV_MEMORY_EVENT_COMMAND_COMPLETE](#) event if the erase operation was successful or [DRV_MEMORY_EVENT_COMMAND_ERROR](#) event if the erase operation was not successful.

If the requesting client has not registered any transfer handler callback with the driver, he can call [DRV_MEMORY_CommandStatusGet\(\)](#) API to know the current status of the request.

Remarks

None.

Preconditions

The [DRV_MEMORY_Open\(\)](#) must have been called with [DRV_IO_INTENT_WRITE](#) or [DRV_IO_INTENT_READWRITE](#) as a parameter to obtain a valid opened device handle.

Example

```

// Use DRV\_MEMORY\_GeometryGet\(\) to find the write region geometry.
uint32_t blockStart = 0;
uint32_t nBlocks = 10;
bool xfer_done = false;

// memoryHandle is the handle returned by the DRV\_MEMORY\_Open function.

// Event is received when the erase request is completed.
void appTransferHandler
(
    DRV_MEMORY_EVENT event,
    DRV_MEMORY_COMMAND_HANDLE commandHandle,
    uintptr_t context
)
{
    switch(event)
    {
        case DRV_MEMORY_EVENT_COMMAND_COMPLETE:
            xfer_done = true;
            break;
        case DRV_MEMORY_EVENT_COMMAND_ERROR:
            // Handle Error
            break;
        default:
            break;
    }
}

DRV_MEMORY_TransferHandlerSet(memoryHandle, appTransferHandler, (uintptr_t)NULL);

DRV_MEMORY_AsyncErase( memoryHandle, &commandHandle, blockStart, nBlock );

if(DRV_MEMORY_COMMAND_HANDLE_INVALID == commandHandle)
{
    // Error handling here
}

// Wait for erase to be completed
while(!xfer_done);

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the return buffer handle
blockStart	Block start from where the blocks should be erased.
nBlock	Total number of blocks to be erased.

Function

```
void DRV_MEMORY_AsyncErase
(
    const DRV_HANDLE handle,
    DRV_MEMORY_COMMAND_HANDLE *commandHandle,
    uint32_t blockStart,
    uint32_t nBlock
);
```

DRV_MEMORY_AsyncEraseWrite Function

Erase and Write blocks of data in the sectors where the block start belongs.

C

```
void DRV_MEMORY_AsyncEraseWrite(const DRV_HANDLE handle, DRV_MEMORY_COMMAND_HANDLE *commandHandle, void * sourceBuffer, uint32_t blockStart, uint32_t nBlock);
```

Returns

The command handle is returned in the commandHandle argument. It Will be [DRV_MEMORY_COMMAND_HANDLE_INVALID](#) if the request was not queued.

Description

This function combines the step of erasing a sector and then writing the page. The application can use this function if it wants to avoid having to explicitly delete a sector in order to update the pages contained in the sector.

This function schedules a non-blocking operation to erase and write blocks of data into attached device memory.

The function returns with a valid command handle in the commandHandle argument if the write request was scheduled successfully. The function adds the request to the hardware instance queue and returns immediately.

While the request is in the queue, the application buffer is owned by the driver and should not be modified.

The function returns [DRV_MEMORY_COMMAND_HANDLE_INVALID](#) in the commandHandle argument under the following circumstances:

- if a buffer could not be allocated to the request
- if the sourceBuffer pointer is NULL
- if the client opened the driver for read only
- if the number of blocks to be written is either zero or more than the number of blocks actually available
- if the driver handle is invalid

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_MEMORY_EVENT_COMMAND_COMPLETE](#) event if the buffer was processed successfully or [DRV_MEMORY_EVENT_COMMAND_ERROR](#) event if the buffer was not processed successfully.

If the requesting client has not registered any transfer handler callback with the driver, he can call [DRV_MEMORY_CommandStatusGet\(\)](#) API to know the current status of the request.

Remarks

None.

Preconditions

The [DRV_MEMORY_Open\(\)](#) must have been called with [DRV_IO_INTENT_WRITE](#) or [DRV_IO_INTENT_READWRITE](#) as a

parameter to obtain a valid opened device handle.

Example

```

#define BUFFER_SIZE      4096
uint8_t buffer[BUFFER_SIZE];

// Use DRV_MEMORY_GeometryGet () to find the write region geometry.
uint32_t blockStart = 0x0;
uint32_t nBlock = BUFFER_SIZE / block_size; // block_size for write geometry
DRV_MEMORY_COMMAND_HANDLE commandHandle;

// memoryHandle is the handle returned by the DRV_MEMORY_Open function.
// Client registers an event handler with driver

// Event is received when the erase request is completed.
void appTransferHandler
(
    DRV_MEMORY_EVENT event,
    DRV_MEMORY_COMMAND_HANDLE commandHandle,
    uintptr_t context
)
{
    switch(event)
    {
        case DRV_MEMORY_EVENT_COMMAND_COMPLETE:
            xfer_done = true;
            break;
        case DRV_MEMORY_EVENT_COMMAND_ERROR:
            // Handle Error
            break;
        default:
            break;
    }
}

DRV_MEMORY_TransferHandlerSet(memoryHandle, appTransferHandler, (uintptr_t)NULL);

DRV_MEMORY_AsyncEraseWrite(memoryHandle, &commandHandle, &myBuffer, blockStart, nBlock);

if(DRV_MEMORY_COMMAND_HANDLE_INVALID == commandHandle)
{
    // Error handling here
}

// Wait for erase to be completed
while(!xfer_done);

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the return command handle. If NULL, then command handle is not returned.
sourceBuffer	The source buffer containing data to be programmed into media device memory
blockStart	Write block start where the write should begin.
nBlock	Total number of blocks to be written.

Function

```

void DRV_MEMORY_AsyncEraseWrite
(
    const    DRV_HANDLE handle,
    DRV_MEMORY_COMMAND_HANDLE * commandHandle,
    void * sourceBuffer,

```

```
    uint32_t blockStart,
    uint32_t nBlock
);
```

DRV_MEMORY_AsyncRead Function

Reads nblocks of data from the specified block start.

C

```
void DRV_MEMORY_AsyncRead(const DRV_HANDLE handle, DRV_MEMORY_COMMAND_HANDLE * commandHandle,
void * targetBuffer, uint32_t blockStart, uint32_t nBlock);
```

Returns

The command handle is returned in the commandHandle argument. It will be [DRV_MEMORY_COMMAND_HANDLE_INVALID](#) if the request was not successful.

Description

This function schedules a non-blocking read operation for reading blocks of data from the memory device attached.

The function returns with a valid command handle in the commandHandle argument if the request was scheduled successfully.

The function adds the request to the hardware instance queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified.

The function returns [DRV_MEMORY_COMMAND_HANDLE_INVALID](#) in the commandHandle argument under the following circumstances:

- if a buffer object could not be allocated to the request
- if the target buffer pointer is NULL
- if the client opened the driver for write only
- if the number of blocks to be read is either zero or more than the number of blocks actually available
- if the driver handle is invalid

Remarks

None.

Preconditions

[DRV_MEMORY_Open\(\)](#) must have been called with [DRV_IO_INTENT_READ](#) or [DRV_IO_INTENT_READWRITE](#) as the ioIntent to obtain a valid opened device handle.

Example

```
uint8_t readBuffer[BUFFER_SIZE];

// Use DRV_MEMORY_GeometryGet () to find the read region geometry.
// Find the block address from which to read data.
uint32_t blockStart = 0x0;
uint32_t nBlock = BUFFER_SIZE;
DRV_MEMORY_COMMAND_HANDLE commandHandle;
bool xfer_done = false;

// memoryHandle is the handle returned by the DRV_MEMORY_Open function.

// Event is received when the write request is completed.
void appTransferHandler(
{
    DRV_MEMORY_EVENT event,
    DRV_MEMORY_COMMAND_HANDLE commandHandle,
    uintptr_t context
}
{
    switch(event)
    {
        case DRV_MEMORY_EVENT_COMMAND_COMPLETE:
```

```

        xfer_done = true;
        break;
    case DRV_MEMORY_EVENT_COMMAND_ERROR:
        // Handle Error
        break;
    default:
        break;
    }
}

DRV_MEMORY_TransferHandlerSet(memoryHandle, appTransferHandler, (uintptr_t)NULL);

DRV_MEMORY_AsyncRead(memoryHandle, &commandHandle, &readBuffer, blockStart, nBlock);

if (DRV_MEMORY_COMMAND_HANDLE_INVALID == commandHandle)
{
    // Error handling here
}

while (!xfer_done);

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the command handle
targetBuffer	Buffer into which the data read from the media device memory will be placed
blockStart	Block start from where the data should be read.
nBlock	Total number of blocks to be read.

Function

```

void DRV_MEMORY_AsyncRead
(
    const DRV_HANDLE handle,
    DRV_MEMORY_COMMAND_HANDLE *commandHandle,
    void *targetBuffer,
    uint32_t blockStart,
    uint32_t nBlock
);

```

DRV_MEMORY_AsyncWrite Function

Writes nblocks of data starting at the specified block start.

C

```

void DRV_MEMORY_AsyncWrite(const DRV_HANDLE handle, DRV_MEMORY_COMMAND_HANDLE * commandHandle,
void * sourceBuffer, uint32_t blockStart, uint32_t nBlock);

```

Returns

The command handle is returned in the commandHandle argument. It will be **DRV_MEMORY_COMMAND_HANDLE_INVALID** if the request was not successful.

Description

This function schedules a non-blocking write operation for writing blocks of data into attached devices memory.

The function returns with a valid command handle in the commandHandle argument if the write request was scheduled successfully.

The function adds the request to the hardware instance queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified.

The function returns `DRV_MEMORY_COMMAND_HANDLE_INVALID` in the `commandHandle` argument under the following circumstances:

- if a buffer object could not be allocated to the request
- if the source buffer pointer is `NULL`
- if the client opened the driver for read only
- if the number of blocks to be written is either zero or more than the number of blocks actually available
- if the driver handle is invalid

If the requesting client registered an event callback with the driver, the driver will issue a `DRV_MEMORY_EVENT_COMMAND_COMPLETE` event if the buffer was processed successfully or `DRV_MEMORY_EVENT_COMMAND_ERROR` event if the buffer was not processed successfully.

If the requesting client has not registered any transfer handler callback with the driver, he can call `DRV_MEMORY_CommandStatusGet()` API to know the current status of the request.

Remarks

None.

Preconditions

`DRV_MEMORY_Open()` routine must have been called to obtain a valid opened device handle.

The memory address location which has to be written, must have been erased before using the `DRV_MEMORY_xxxErase()` routine.

Example

```

#define BUFFER_SIZE      4096
uint8_t writeBuffer[BUFFER_SIZE];

// Use DRV_MEMORY_GeometryGet () to find the write region geometry.
uint32_t blockStart = 0x0;
uint32_t nBlock = BUFFER_SIZE / block_size; // block_size for write geometry
bool xfer_done = false;

DRV_MEMORY_COMMAND_HANDLE commandHandle;

// memoryHandle is the handle returned by the DRV_MEMORY_Open function.

// Event is received when the write request is completed.
void appTransferHandler
(
    DRV_MEMORY_EVENT event,
    DRV_MEMORY_COMMAND_HANDLE commandHandle,
    uintptr_t context
)
{
    switch(event)
    {
        case DRV_MEMORY_EVENT_COMMAND_COMPLETE:
            xfer_done = true;
            break;
        case DRV_MEMORY_EVENT_COMMAND_ERROR:
            // Handle Error
            break;
        default:
            break;
    }
}

DRV_MEMORY_TransferHandlerSet(memoryHandle, appTransferHandler, (uintptr_t)NULL);

DRV_MEMORY_AsyncErase(memoryHandle, &commandHandle, blockStart, nBlock);

if(DRV_MEMORY_COMMAND_HANDLE_INVALID == commandHandle)
{
    // Error handling here
}

```

```

// Wait for erase to be completed
while(!xfer_done);

DRV_MEMORY_AsyncWrite(memoryHandle, &commandHandle, &writeBuffer, blockStart, nBlock);

if(DRV_MEMORY_COMMAND_HANDLE_INVALID == commandHandle)
{
    // Error handling here
}

// Wait for write to be completed
while(!xfer_done);

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the return buffer handle
sourceBuffer	The source buffer containing data to be programmed into media device memory
blockStart	Block start from where the data should be written to.
nBlock	Total number of blocks to be written.

Function

```

void DRV_MEMORY_AsyncWrite
(
    const DRV_HANDLE handle,
    DRV_MEMORY_COMMAND_HANDLE *commandHandle,
    void *sourceBuffer,
    uint32_t blockStart,
    uint32_t nBlock
);

```

DRV_MEMORY_SyncErase Function

Erase the specified number of memory blocks from the specified block start.

Each block is equal to sector size of the memory device attached.

C

```
bool DRV_MEMORY_SyncErase(const DRV_HANDLE handle, uint32_t blockStart, uint32_t nBlock);
```

Returns

true:

- If the transfer request is successfully completed.

false:

- If the client opened the driver for read only
- If the number of blocks to be erased is either zero or more than the number of blocks actually available
- If the driver handle is invalid

Description

This function schedules a blocking sector erase operation on attached memory device.

Remarks

None.

Preconditions

The [DRV_MEMORY_Open\(\)](#) must have been called with DRV_IO_INTENT_WRITE or DRV_IO_INTENT_READWRITE as a

parameter to obtain a valid opened device handle.

Example

```
// Use DRV_MEMORY_GeometryGet () to find the erase region geometry.
uint32_t blockStart = 0;
uint32_t nBlocks = 10;

// memoryHandle is the handle returned by the DRV_MEMORY_Open function.

if(DRV_MEMORY_SyncErase( memoryHandle, blockStart, nBlock ) == false)
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
blockStart	block start from where the blocks should be erased.
nBlock	Total number of blocks to be erased.

Function

```
bool DRV_MEMORY_SyncErase
(
    const DRV_HANDLE handle,
    uint32_t blockStart,
    uint32_t nBlock
);
```

DRV_MEMORY_Erase Function

This routine provides interface to the file system to perform a media erase operation in synchronous mode of the Memory driver.

C

```
void DRV_MEMORY_Erase(const DRV_HANDLE handle, SYS_MEDIA_BLOCK_COMMAND_HANDLE * commandHandle,
    uint32_t blockStart, uint32_t nBlock);
```

Returns

The buffer handle is returned in the commandHandle argument. It will be [DRV_MEMORY_COMMAND_HANDLE_INVALID](#) if the request was not successful.

Description

This function is internally used by the file system.

Remarks

This function is internally used by the file system.

Preconditions

The [DRV_MEMORY_Open](#) must have been called to obtain a valid opened device handle.

Example

None.

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the return buffer handle

blockStart	Start block address of SD Card where the writes should begin.
nBlock	Total number of blocks to be written.

Function

```
void DRV_MEMORY_Erase
(
    const DRV_HANDLE handle,
    SYS_MEDIA_BLOCK_COMMAND_HANDLE* commandHandle,
    void* sourceBuffer,
    uint32_t blockStart,
    uint32_t nBlock
)
```

DRV_MEMORY_SyncEraseWrite Function

Erase and Write blocks of data in the sectors where the block start belongs.

C

```
bool DRV_MEMORY_SyncEraseWrite(const DRV_HANDLE handle, void * sourceBuffer, uint32_t
blockStart, uint32_t nBlock);
```

Returns

true:

- If the transfer request is successfully completed.

false:

- If the sourceBuffer pointer is NULL
- If the client opened the driver for read only
- If the number of blocks to be written is either zero or more than the number of blocks actually available
- If the driver handle is invalid

Description

This function combines the step of erasing a sector and then writing the page. The application can use this function if it wants to avoid having to explicitly delete a sector in order to update the pages contained in the sector.

This function schedules a blocking operation to erase and write blocks of data into attached device memory.

Remarks

None.

Preconditions

The [DRV_MEMORY_Open\(\)](#) must have been called with DRV_IO_INTENT_WRITE or DRV_IO_INTENT_READWRITE as a parameter to obtain a valid opened device handle.

Example

```
#define BUFFER_SIZE 4096

uint8_t buffer[BUFFER_SIZE];

// Use DRV_MEMORY_GeometryGet () to find the write region geometry.
uint32_t blockStart = 0x0;
uint32_t nBlock = BUFFER_SIZE / block_size; // block_size for write geometry

// memoryHandle is the handle returned by the DRV_MEMORY_Open function.

if(DRV_MEMORY_SyncEraseWrite(memoryHandle, &myBuffer, blockStart, nBlock) == false)
{
    // Error handling here
```

}

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
sourceBuffer	The source buffer containing data to be programmed into media device memory
blockStart	block start where the write should begin.
nBlock	Total number of blocks to be written.

Function

```
bool DRV_MEMORY_SyncEraseWrite
(
    const DRV_HANDLE handle,
    void *sourceBuffer,
    uint32_t blockStart,
    uint32_t nBlock
);
```

DRV_MEMORY_EraseWrite Function

This routine provides interface to the file system to perform a media erase-write operation in synchronous mode of the Memory driver.

C

```
void DRV_MEMORY_EraseWrite(const DRV_HANDLE handle, SYS_MEDIA_BLOCK_COMMAND_HANDLE *commandHandle, void * sourceBuffer, uint32_t blockStart, uint32_t nBlock);
```

Returns

The buffer handle is returned in the commandHandle argument. It will be [DRV_MEMORY_COMMAND_HANDLE_INVALID](#) if the request was not successful.

Description

This function is internally used by the file system.

Remarks

This function is internally used by the file system.

Preconditions

The [DRV_MEMORY_Open](#) must have been called to obtain a valid opened device handle.

Example

None.

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the return buffer handle
sourceBuffer	The source buffer containing data to be programmed to the SD Card.
blockStart	Start block address of SD Card where the writes should begin.
nBlock	Total number of blocks to be written.

Function

```
void DRV_MEMORY_EraseWrite
(
```

```
const DRV_HANDLE handle,
SYS_MEDIA_BLOCK_COMMAND_HANDLE* commandHandle,
void* sourceBuffer,
uint32_t blockStart,
uint32_t nBlock
)
```

DRV_MEMORY_SyncRead Function

Reads nblock of data from the specified block start.

C

```
bool DRV_MEMORY_SyncRead(const DRV_HANDLE handle, void * targetBuffer, uint32_t blockStart,
uint32_t nBlock);
```

Returns

true:

- If the transfer request is successfully completed.

false:

- If the target buffer pointer is NULL
- If the client opened the driver for write only
- If the number of blocks to be read is either zero or more than the number of blocks actually available
- If the driver handle is invalid

Description

This function schedules a blocking read operation for reading blocks of data from the memory device attached.

Remarks

None.

Preconditions

DRV_MEMORY_Open() must have been called with DRV_IO_INTENT_READ or DRV_IO_INTENT_READWRITE as the ioIntent to obtain a valid opened device handle.

Example

```
#define BUFFER_SIZE 4096
uint8_t readBuffer[BUFFER_SIZE];

// Use DRV_MEMORY_GeometryGet () to find the read region geometry.
uint32_t blockStart = 0x0;
uint32_t nBlock = BUFFER_SIZE / block_size; // block_size for read geometry

// memoryHandle is the handle returned by the DRV_MEMORY_Open function.

if(DRV_MEMORY_SyncRead(memoryHandle, &readBuffer, blockStart, nBlock) == false)
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
targetBuffer	Buffer into which the data read from the media device memory will be placed
blockStart	Block start from where the data should be read.
nBlock	Total number of blocks to be read.

Function

```
bool DRV_MEMORY_SyncRead
(
    const DRV_HANDLE handle,
    void *targetBuffer,
    uint32_t blockStart,
    uint32_t nBlock
);
```

DRV_MEMORY_Read Function

This routine provides interface to the file system to perform a media read operation in synchronous mode of the Memory driver.

C

```
void DRV_MEMORY_Read(const DRV_HANDLE handle, SYS_MEDIA_BLOCK_COMMAND_HANDLE * commandHandle,
                     void * targetBuffer, uint32_t blockStart, uint32_t nBlock);
```

Returns

The buffer handle is returned in the commandHandle argument. It will be [DRV_MEMORY_COMMAND_HANDLE_INVALID](#) if the request was not successful.

Description

This function is internally used by the file system.

Remarks

This function is internally used by the file system.

Preconditions

The [DRV_MEMORY_Open](#) must have been called to obtain a valid opened device handle.

Example

None.

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the return buffer handle
sourceBuffer	The source buffer containing data to be programmed to the SD Card.
blockStart	Start block address of SD Card where the writes should begin.
nBlock	Total number of blocks to be written.

Function

```
void DRV_MEMORY_Read
(
    const DRV_HANDLE handle,
    SYS_MEDIA_BLOCK_COMMAND_HANDLE* commandHandle,
    void* sourceBuffer,
    uint32_t blockStart,
    uint32_t nBlock
)
```

DRV_MEMORY_SyncWrite Function

Writes nblock of data starting at the specified block start.

C

```
bool DRV_MEMORY_SyncWrite(const DRV_HANDLE handle, void * sourceBuffer, uint32_t blockStart,
                           uint32_t nBlock);
```

Returns

true:

- If the transfer request is successfully completed.

false:

- If the source buffer pointer is NULL
- If the client opened the driver for read only
- If the number of blocks to be written is either zero or more than the number of blocks actually available
- If the driver handle is invalid

Description

This function schedules a blocking write operation for writing blocks of data into attached devices memory.

Remarks

None.

Preconditions

DRV_MEMORY_Open() routine must have been called to obtain a valid opened device handle.

The memory block which has to be written, must have been erased before using the DRV_MEMORY_xxxErase() routine.

Example

```
#define BUFFER_SIZE 4096
uint8_t writeBuffer[BUFFER_SIZE];

// Use DRV_MEMORY_GeometryGet () to find the write region geometry.
uint32_t blockStart = 0x0;
uint32_t nBlock = BUFFER_SIZE / block_size; // block_size for write geometry

// memoryHandle is the handle returned by the DRV_MEMORY_Open function.

if(DRV_MEMORY_SyncErase(memoryHandle, blockStart, nBlock) == false)
{
    // Error handling here
}

if(DRV_MEMORY_SyncWrite(memoryHandle, &writeBuffer, blockStart, nBlock) == false)
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
sourceBuffer	The source buffer containing data to be programmed into media device memory
blockStart	Block start from where the data should be written to.
nBlock	Total number of blocks to be written.

Function

```
bool DRV_MEMORY_SyncWrite
(
```

```
const DRV_HANDLE handle,
void *sourceBuffer,
uint32_t blockStart,
uint32_t nBlock
);
```

DRV_MEMORY_Write Function

This routine provides interface to the file system to perform a media write operation in synchronous mode of the Memory driver.

C

```
void DRV_MEMORY_Write(const DRV_HANDLE handle, SYS_MEDIA_BLOCK_COMMAND_HANDLE * commandHandle,
void * sourceBuffer, uint32_t blockStart, uint32_t nBlock);
```

Returns

The buffer handle is returned in the commandHandle argument. It will be [DRV_MEMORY_COMMAND_HANDLE_INVALID](#) if the request was not successful.

Description

This function is internally used by the file system.

Remarks

This function is internally used by the file system.

Preconditions

The [DRV_MEMORY_Open](#) must have been called to obtain a valid opened device handle.

Example

None.

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the return buffer handle
sourceBuffer	The source buffer containing data to be programmed to the SD Card.
blockStart	Start block address of SD Card where the writes should begin.
nBlock	Total number of blocks to be written.

Function

```
void DRV_MEMORY_Write
(
const DRV_HANDLE handle,
SYS_MEDIA_BLOCK_COMMAND_HANDLE* commandHandle,
void* sourceBuffer,
uint32_t blockStart,
uint32_t nBlock
)
```

DRV_MEMORY_CommandStatusGet Function

Gets the current status of the command.

C

```
DRV_MEMORY_COMMAND_STATUS DRV_MEMORY_CommandStatusGet(const DRV_HANDLE handle, const
DRV_MEMORY_COMMAND_HANDLE commandHandle);
```

Returns

DRV_MEMORY_COMMAND_COMPLETED

- If the transfer request is completed

DRV_MEMORY_COMMAND_QUEUED

- If the command is Queued and waiting to be processed.

DRV_MEMORY_COMMAND_IN_PROGRESS

- If the current transfer request is still being processed

DRV_MEMORY_COMMAND_ERROR_UNKNOWN

- If the handle is invalid

- If the status read request fails

Description

This routine gets the current status of the buffer. The application must use this routine where the status of a scheduled buffer needs to polled on.

The function may return [DRV_MEMORY_COMMAND_HANDLE_INVALID](#) in a case where the buffer handle has expired. A buffer handle expires when the internal buffer object is re-assigned to another erase or write request. It is recommended that this function be called regularly in order to track the buffer status correctly.

The application can alternatively register an event handler to receive write or erase operation completion events.

Remarks

Used in Async mode of operation.

Preconditions

[DRV_MEMORY_Open\(\)](#) must have been called to obtain a valid opened device handle.

Example

```
// memoryHandle is the handle returned by the DRV_MEMORY_Open function.
// commandHandle is the handle returned by any read/write/erase block operation.

if (DRV_MEMORY_COMMAND_COMPLETED == DRV_MEMORY_CommandStatusGet(memoryHandle, commandHandle))
{
    // Operation Done
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the command handle

Function

```
DRV_MEMORY_COMMAND_STATUS DRV_MEMORY_CommandStatusGet
(
const DRV_HANDLE handle,
const DRV_MEMORY_COMMAND_HANDLE commandHandle
);
```

DRV_MEMORY_TransferStatusGet Function

Gets the current status of the transfer request on attached device.

C

```
MEMORY_DEVICE_TRANSFER_STATUS DRV_MEMORY_TransferStatusGet(const DRV_HANDLE handle);
```

Returns

MEMORY_DEVICE_TRANSFER_ERROR_UNKNOWN

- If the handle is invalid
- If the status read request fails

MEMORY_DEVICE_TRANSFER_BUSY

- If the current transfer request is still being processed

MEMORY_DEVICE_TRANSFER_COMPLETED

- If the transfer request is completed

Description

This routine gets the current status of the transfer request. The application must use this routine where the status of a scheduled request needs to be polled on.

The application can alternatively register a transfer handler to receive the transfer completion events.

Remarks

This routine will block for hardware access.

Used in Async mode of operation.

Preconditions

`DRV_MEMORY_Open()` must have been called to obtain a valid opened device handle.

Example

```
// memoryHandle is the handle returned by the DRV_MEMORY_Open function.

if (MEMORY_DEVICE_TRANSFER_COMPLETED == DRV_MEMORY_TransferStatusGet(memoryHandle))
{
    // Operation Done
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function

Function

```
MEMORY_DEVICE_TRANSFER_STATUS DRV_MEMORY_TransferStatusGet
(
    const DRV_HANDLE handle
);
```

d) Media Interface Functions**DRV_MEMORY_AddressGet Function**

Returns the Memory media start address

C

```
uintptr_t DRV_MEMORY_AddressGet(const DRV_HANDLE handle);
```

Returns

Start address of the Memory Media if the handle is valid otherwise NULL.

Description

This function returns the Memory Media start address.

Remarks

None.

Preconditions

The [DRV_MEMORY_Open\(\)](#) routine must have been called to obtain a valid opened device handle.

Example

```
uintptr_t startAddress;
startAddress = DRV_MEMORY_AddressGet(drvMEMORYHandle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function

Function

```
uintptr_t DRV_MEMORY_AddressGet
(
    const DRV_HANDLE handle
);
```

DRV_MEMORY_GeometryGet Function

Returns the geometry of the memory device.

C

```
SYS_MEDIA_GEOMETRY * DRV_MEMORY_GeometryGet(const DRV_HANDLE handle);
```

Returns

[SYS_MEDIA_GEOMETRY](#) - Pointer to structure which holds the media geometry information.

Description

This API gives the following geometrical details of the attached memory device:

- Media Property
- Number of Read/Write/Erase regions in the memory device
- Number of Blocks and their size in each region of the device

Remarks

Refer `sys_media.h` for definition of [SYS_MEDIA_GEOMETRY](#).

Preconditions

The [DRV_MEMORY_Open\(\)](#) routine must have been called to obtain a valid opened device handle.

Example

```
SYS_MEDIA_GEOMETRY geometry;
uint32_t readBlockSize, writeBlockSize, eraseBlockSize;
uint32_t nReadBlocks, nReadRegions, totalFlashSize;

if (true != DRV_MEMORY_GeometryGet(&geometry))
{
    // Handle Error
```

```

}

readBlockSize  = geometry.geometryTable[0].blockSize;
nReadBlocks  = geometry.geometryTable[0].numBlocks;
nReadRegions = geometry.numReadRegions;

writeBlockSize = geometry.geometryTable[1].blockSize;
eraseBlockSize = geometry.geometryTable[2].blockSize;

totalFlashSize = readBlockSize * nReadBlocks * nReadRegions;

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function

Function

```

SYS_MEDIA_GEOMETRY * DRV_MEMORY_GeometryGet
(
    const DRV_HANDLE handle
);

```

DRV_MEMORY_IsAttached Function

Returns the physical attach status of the Media.

C

```
bool DRV_MEMORY_IsAttached(const DRV_HANDLE handle);
```

Returns

Returns false if the handle is invalid otherwise returns true.

Description

This function returns the physical attach status of the Media device.

Remarks

None.

Preconditions

The [DRV_MEMORY_Open\(\)](#) routine must have been called to obtain a valid opened device handle.

Example

```

bool isMEMORYAttached;
isMEMORYAttached = DRV_MEMORY_IsAttached(drvMEMORYHandle);

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function

Function

```

bool DRV_MEMORY_IsAttached
(
    const DRV_HANDLE handle
);

```

DRV_MEMORY_IsWriteProtected Function

Returns the write protect status of the Memory.

C

```
bool DRV_MEMORY_IsWriteProtected(const DRV_HANDLE handle);
```

Returns

True - If the memory is write protected. False - If the memory is not write protected.

Description

This function returns the write protect status of the Memory.

Remarks

None.

Preconditions

The [DRV_MEMORY_Open\(\)](#) routine must have been called to obtain a valid opened device handle.

Example

```
bool isWriteProtected;
isWriteProtected = DRV_MEMORY_IsWriteProtected(drvMEMORYHandle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function

Function

```
bool DRV_MEMORY_IsWriteProtected
(
const DRV_HANDLE handle
);
```

e) Data Types and Constants

DRV_MEMORY_COMMAND_HANDLE Type

Handle to identify commands queued in the driver.

C

```
typedef SYS_MEDIA_BLOCK_COMMAND_HANDLE DRV_MEMORY_COMMAND_HANDLE;
```

Description

A command handle is returned by a call to the Read, Write, Erase or EraseWrite functions. This handle allows the application to track the completion of the operation. This command handle is also returned to the client along with the event that has occurred with respect to the command. This allows the application to connect the event to a specific command in case where multiple commands are queued.

The command handle associated with the command request expires when the client has been notified of the completion of the command (after event handler function that notifies the client returns) or after the command has been retired by the driver if no event handler callback was set.

Remarks

Refer sys_media.h for definition of [SYS_MEDIA_BLOCK_COMMAND_HANDLE](#).

DRV_MEMORY_COMMAND_HANDLE_INVALID Macro

This value defines the Memory Driver's Invalid Command Handle.

C

```
#define DRV_MEMORY_COMMAND_HANDLE_INVALID SYS_MEDIA_BLOCK_COMMAND_HANDLE_INVALID
```

Description

This value defines the Memory Driver's Invalid Command Handle. This value is returned by read/write/erase/erasewrite routines when the command request was not accepted.

Remarks

Refer sys_media.h for definition of [SYS_MEDIA_BLOCK_COMMAND_HANDLE_INVALID](#).

DRV_MEMORY_COMMAND_STATUS Enumeration

Memory Driver command Status

C

```
typedef enum {
    DRV_MEMORY_COMMAND_COMPLETED = SYS_MEDIA_COMMAND_COMPLETED,
    DRV_MEMORY_COMMAND_QUEUED = SYS_MEDIA_COMMAND_QUEUED,
    DRV_MEMORY_COMMAND_IN_PROGRESS = SYS_MEDIA_COMMAND_IN_PROGRESS,
    DRV_MEMORY_COMMAND_ERROR_UNKNOWN = SYS_MEDIA_COMMAND_UNKNOWN
} DRV_MEMORY_COMMAND_STATUS;
```

Members

Members	Description
DRV_MEMORY_COMMAND_COMPLETED = SYS_MEDIA_COMMAND_COMPLETED	Done OK and ready
DRV_MEMORY_COMMAND_QUEUED = SYS_MEDIA_COMMAND_QUEUED	Scheduled but not started
DRV_MEMORY_COMMAND_IN_PROGRESS = SYS_MEDIA_COMMAND_IN_PROGRESS	Currently being in transfer
DRV_MEMORY_COMMAND_ERROR_UNKNOWN = SYS_MEDIA_COMMAND_UNKNOWN	Unknown Command

Description

Specifies the status of the command for the read, write, erase and erasewrite operations.

Remarks

Refer sys_media.h for SYS_MEDIA_XXX definitions.

DRV_MEMORY_DEVICE_INTERFACE Structure

Memory Device API.

C

```
typedef struct {
    DRV_MEMORY_DEVICE_OPEN Open;
    DRV_MEMORY_DEVICE_CLOSE Close;
}
```

```

DRV_MEMORY_DEVICE_SECTOR_ERASE SectorErase;
DRV_MEMORY_DEVICE_STATUS Status;
DRV_MEMORY_DEVICE_READ Read;
DRV_MEMORY_DEVICE_PAGE_WRITE PageWrite;
DRV_MEMORY_DEVICE_EVENT_HANDLER_SET EventHandlerSet;
DRV_MEMORY_DEVICE_GEOMETRY_GET GeometryGet;
DRV_MEMORY_DEVICE_TRANSFER_STATUS_GET TransferStatusGet;
} DRV_MEMORY_DEVICE_INTERFACE;

```

Description

This Data Structure is used by attached media to populate the required device functions for media transactions.
This will be used in memory driver init structure.

Remarks

None.

DRV_MEMORY_DEVICE_OPEN Type

C

```
typedef DRV_HANDLE (* DRV_MEMORY_DEVICE_OPEN)(const SYS_MODULE_INDEX drvIndex, const
DRV_IO_INTENT ioIntent);
```

Description

Function pointer typedef to open the attached media

DRV_MEMORY_DEVICE_CLOSE Type

C

```
typedef void (* DRV_MEMORY_DEVICE_CLOSE)(const DRV_HANDLE handle);
```

Description

Function pointer typedef to close the attached media

DRV_MEMORY_DEVICE_SECTOR_ERASE Type

C

```
typedef bool (* DRV_MEMORY_DEVICE_SECTOR_ERASE)(const DRV_HANDLE handle, uint32_t address);
```

Description

Function pointer typedef to erase a sector from attached media

DRV_MEMORY_DEVICE_STATUS Type

C

```
typedef SYS_STATUS (* DRV_MEMORY_DEVICE_STATUS)(const SYS_MODULE_INDEX drvIndex);
```

Description

Function pointer typedef to get the status of the attached media

DRV_MEMORY_DEVICE_READ Type

C

```
typedef bool (* DRV_MEMORY_DEVICE_READ)(const DRV_HANDLE handle, void *rx_data, uint32_t rx_data_length, uint32_t address);
```

Description

Function pointer typedef to read from the attached media

DRV_MEMORY_DEVICE_PAGE_WRITE Type

C

```
typedef bool (* DRV_MEMORY_DEVICE_PAGE_WRITE)(const DRV_HANDLE handle, void *tx_data, uint32_t address);
```

Description

Function pointer typedef to write a page to the attached media

DRV_MEMORY_DEVICE_EVENT_HANDLER_SET Type

C

```
typedef void (* DRV_MEMORY_DEVICE_EVENT_HANDLER_SET)(const DRV_HANDLE handle, DRV_MEMORY_EVENT_HANDLER eventHandler, uintptr_t context);
```

Description

Function pointer typedef to set the event handler with attached media

DRV_MEMORY_DEVICE_GEOMETRY_GET Type

C

```
typedef bool (* DRV_MEMORY_DEVICE_GEOMETRY_GET)(const DRV_HANDLE handle, MEMORY_DEVICE_GEOMETRY *geometry);
```

Description

Function pointer typedef to get the Geometry details from attached media

DRV_MEMORY_DEVICE_TRANSFER_STATUS_GET Type

C

```
typedef uint32_t (* DRV_MEMORY_DEVICE_TRANSFER_STATUS_GET)(const DRV_HANDLE handle);
```

Description

Function pointer typedef to get the transfer Status from attached media

DRV_MEMORY_EVENT Enumeration

Identifies the possible events that can result from a request.

C

```
typedef enum {
    DRV_MEMORY_EVENT_COMMAND_COMPLETE = SYS_MEDIA_EVENT_BLOCK_COMMAND_COMPLETE,
    DRV_MEMORY_EVENT_COMMAND_ERROR = SYS_MEDIA_EVENT_BLOCK_COMMAND_ERROR
} DRV_MEMORY_EVENT;
```

Members

Members	Description
DRV_MEMORY_EVENT_COMMAND_COMPLETE = SYS_MEDIA_EVENT_BLOCK_COMMAND_COMPLETE	Operation has been completed successfully.
DRV_MEMORY_EVENT_COMMAND_ERROR = SYS_MEDIA_EVENT_BLOCK_COMMAND_ERROR	There was an error during the operation

Description

This enumeration identifies the possible events that can result from a read, write, erase or erasewrite request caused by the client.

Remarks

One of these values is passed in the "event" parameter of the event handling callback function that client registered with the driver by calling the [DRV_MEMORY_TransferHandlerSet](#) function when a request is completed.

Refer sys_media.h for SYS_MEDIA_XXX definitions.

DRV_MEMORY_EVENT_HANDLER Type

C

```
typedef void (* DRV_MEMORY_EVENT_HANDLER)(MEMORY_DEVICE_TRANSFER_STATUS status, uintptr_t context);
```

Description

Function pointer typedef for event handler to be sent to attached media

DRV_MEMORY_INIT Structure

Memory Driver Initialization Data

C

```
typedef struct {
    SYS_MODULE_INDEX memDevIndex;
    const DRV_MEMORY_DEVICE_INTERFACE * memoryDevice;
    bool isMemDevInterruptEnabled;
    uint32_t memDevStatusPollUs;
    bool isFsEnabled;
    uint8_t deviceMediaType;
    uint8_t * ewBuffer;
    uintptr_t clientObjPool;
    uintptr_t bufferObj;
    size_t queueSize;
    size_t nClientsMax;
} DRV_MEMORY_INIT;
```

Members

Members	Description
SYS_MODULE_INDEX memDevIndex;	Attached Memory Device index
const DRV_MEMORY_DEVICE_INTERFACE * memoryDevice;	Flash Device functions

bool isMemDevInterruptEnabled;	Flag to indicate if attached memory device configured to interrupt mode
uint32_t memDevStatusPollUs;	Number of milliseconds to poll for transfer status check
bool isFsEnabled;	FS enabled
uint8_t deviceMediaType;	Memory Device Type
uint8_t * ewBuffer;	Erase Write Buffer pointer
uintptr_t clientObjPool;	Memory pool for Client Objects
uintptr_t bufferObj;	Pointer to Buffer Objects array
size_t queueSize;	Buffer Queue Size
size_t nClientsMax;	Maximum number of clients

Description

This data type defines the data required to initialize the Memory Driver.

Remarks

Not all initialization features are available for all devices. Please refer to the attached media device capabilities.

DRV_MEMORY_TRANSFER_HANDLER Type

Pointer to a Memory Driver Event handler function

C

```
typedef SYS_MEDIA_EVENT_HANDLER DRV_MEMORY_TRANSFER_HANDLER;
```

Returns

None.

Description

This data type defines the required function signature for the Memory event handling callback function. A client must register a pointer to an event handling function whose function signature (parameter and return value types) match the types specified by this function pointer in order to receive event calls back from the driver.

The parameters and return values are described here and a partial example implementation is provided.

Remarks

If the event is DRV_MEMORY_EVENT_COMMAND_COMPLETE, it means that the requested operation was completed successfully.

If the event is DRV_MEMORY_EVENT_COMMAND_ERROR, it means that the scheduled operation was not completed successfully.

The context parameter contains the handle to the client context, provided at the time the event handling function was registered using the [DRV_MEMORY_TransferHandlerSet](#) function. This context handle value is passed back to the client as the "context" parameter. It can be any value necessary to identify the client context or instance (such as a pointer to the client's data) instance of the client that made the read/write/erase request.

Used in Asynchronous mode of operation.

Refer [sys_media.h](#) for definition of [SYS_MEDIA_EVENT_HANDLER](#).

Example

```
void appTransferHandler
(
    DRV_MEMORY_EVENT event,
    DRV_MEMORY_COMMAND_HANDLE commandHandle,
    uintptr_t context
)
{
    switch(event)
    {
        case DRV_MEMORY_EVENT_COMMAND_COMPLETE:
            xfer_done = true;
    }
}
```

```

        break;
    case DRV_MEMORY_EVENT_COMMAND_ERROR:
        // Handle Error
        break;
    default:
        break;
}
}

```

Parameters

Parameters	Description
event	Identifies the type of event
commandHandle	Handle returned from the Read/Write/Erase/EraseWrite requests
context	Value identifying the context of the application that registered the event handling function

MEMORY_DEVICE_GEOMETRY Structure

Memory Device Geometry Table.

C

```

typedef struct {
    uint32_t read_blockSize;
    uint32_t read_numBlocks;
    uint32_t numReadRegions;
    uint32_t write_blockSize;
    uint32_t write_numBlocks;
    uint32_t numWriteRegions;
    uint32_t erase_blockSize;
    uint32_t erase_numBlocks;
    uint32_t numEraseRegions;
    uint32_t blockStartAddress;
} MEMORY_DEVICE_GEOMETRY;

```

Description

This Data Structure is used by Memory driver to get the media geometry details.

The Media attached to memory driver needs to fill in this data structure when GEOMETRY_GET is called.

Remarks

None.

MEMORY_DEVICE_TRANSFER_STATUS Enumeration

Memory Device Transfer Status.

C

```

typedef enum {
    MEMORY_DEVICE_TRANSFER_BUSY,
    MEMORY_DEVICE_TRANSFER_COMPLETED,
    MEMORY_DEVICE_TRANSFER_ERROR_UNKNOWN
} MEMORY_DEVICE_TRANSFER_STATUS;

```

Members

Members	Description
MEMORY_DEVICE_TRANSFER_BUSY	Transfer being processed
MEMORY_DEVICE_TRANSFER_COMPLETED	Transfer is successfully completed
MEMORY_DEVICE_TRANSFER_ERROR_UNKNOWN	Transfer had error

Description

This Data structure is used to indicate the current transfer status of the attached media.

Remarks

None.

SDMMC Driver Library

This section describes the SD Card driver library.

Introduction

The SDMMC driver provides the necessary interfaces to interact with an SD or eMMC card. It provides the necessary abstraction for the higher layer.

Description

The SDMMC driver is a multi-client multi-instance buffer model based block driver interface which can be used to communicate with SD or eMMC cards.

Key Features of the SDMMC driver:

1. Supports Asynchronous (non-blocking) mode of operation.
2. It works in both Bare Metal and RTOS environment.

Note: Support for eMMC card is currently not available.

Using the Library

This section describes the basic architecture of the SDMMC driver and provides information on how it works.

Description

The SDMMC driver can be used to communicate with SD Cards.

Modes supported:

- Asynchronous mode - Bare-metal and RTOS.

It can be used in multiple ways:

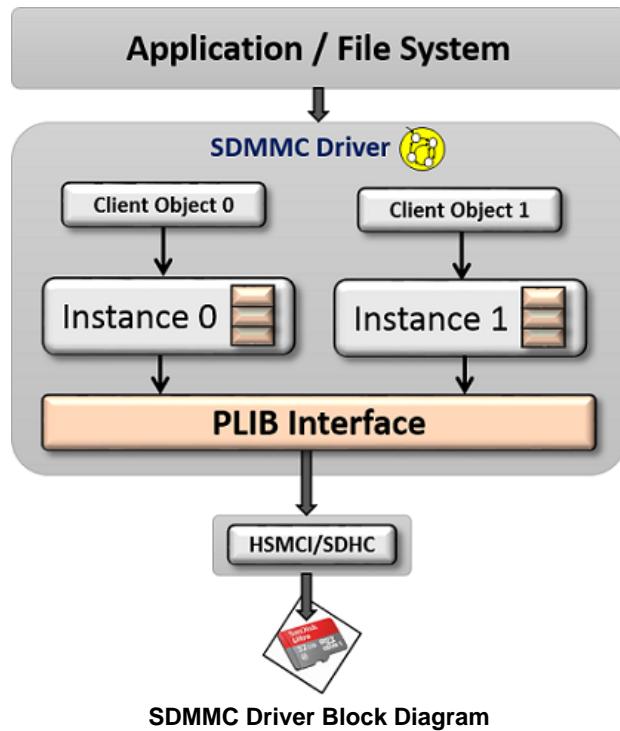
1. Application can directly use the SDMMC driver API's to perform Read/Write operations.
2. Application can use File System service layer and perform file operations on the SD/eMMC Card.
3. It can be interfaced with Middleware's like USB.

Abstraction Model

This section describes how the abstraction is modeled in software and introduces the library's interface.

Description

The SDMMC driver provides abstraction to communicate with SD/eMMC card through the HSMCI or SDHC peripheral library interface.



SDMMC Driver Block Diagram

How the Library Works

This section describes the basic architecture of the SDMMC driver Library.

Description

The SDMMC driver is a multi-client, multi-instance buffer queue model based block driver interface.

SDMMC Driver Features:

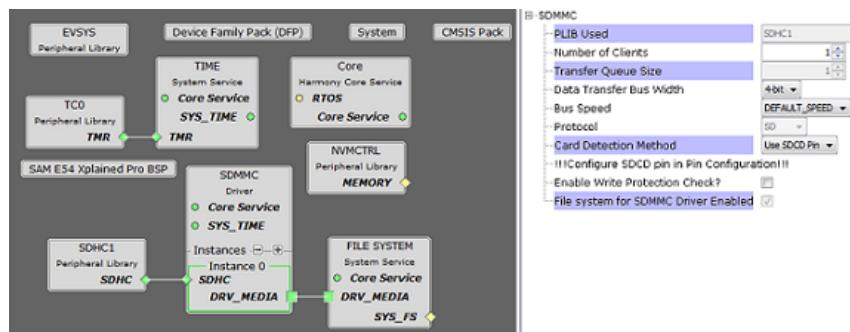
- Driver has a buffer queue which allows the capability of accepting multiple requests
- Driver can either have File-system as client or Application or USB as client
- Every transfer request expects data in blocks. Block details (**Size and number of blocks**) can be retrieved by `DRV_SDMMC_GeometryGet()`
- Driver provides feature to register call back for transfer complete event, which can be used by clients to get notified
- When SDMMC driver is connected to File System buffer queue is disabled as File system is blocking interface
- Works in both Bare-Metal and RTOS environment in Asynchronous mode
 - **Bare-Metal:**
 - A dedicated task routine `DRV_SDMMC_Tasks()` is called from `SYS_Tasks()` to process the data from the instance queue
 - **RTOS:**
 - A dedicated thread is created for task routine `DRV_SDMMC_Tasks()` to process the data from the instance queue
- API's return with a valid handle which can be used to check whether transfer request is accepted or not
- A Client specific handler will be called to indicate the status of transfer

Configuring the Library

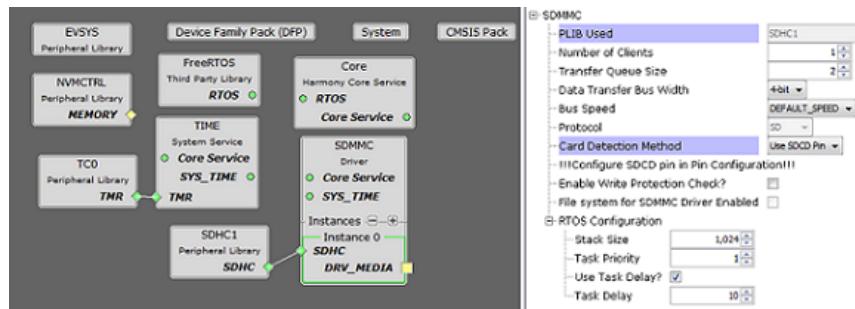
This section provides information on how to configure the SDMMC driver.

Description

The SDMMC driver library should be configured through the MHC. The following figures show the MHC configuration window for the SDMMC driver and brief description.



Asynchronous Mode with File-System



Asynchronous Mode with RTOS and without File-System

Common User Configuration for all Instances

- **Driver Mode:**
 - Allows User to select the mode of driver(Asynchronous or Synchronous). This setting is common for all the instances.
 - Only Asynchronous mode is supported for now

Instance Specific User Configurations

- **PLIB Used:**
 - Specifies the peripheral library used by the SDMMC driver. This can either be the HSMCI PLIB or the SDHC PLIB.
- **Number of Clients:**
 - Specifies number of clients that can access the specific instance of the driver
- **Transfer Queue Size:**
 - Specifies maximum number of requests that can be queued
 - When connected to file system this value is set to 1 and is non modifiable
- **Data Transfer Bus Width:**
 - Specifies the Bus width to be used for data transfer (1-Bit, 4-Bit)
- **Bus Speed:**
 - Specifies Bus Speed to be used for Communication with SD-card (DEFAULT_SPEED, HIGH_SPEED)
 - Standard SD-Cards only support Default Speed
 - SD-Cards with High Capacity support Both Default and High Speed
- **Protocol:**
 - Specifies whether SD or eMMC protocol is enabled in the SDMMC driver. Currently only SD protocol is supported.
- **Card Detection Method:**
 - Specifies the card detection method used by the SDMMC driver. Either SDCCD pin or Polling method can be used to detect insertion/removal of SD Card
- **Polling Interval (ms):**
 - If the Card Detection Method is selected as "Use Polling", then this option specifies the rate at which the SDMMC driver checks for SD Card insertion/removal
- **File system for SDMMC Driver Enabled:**

- Indicates whether SDMMC driver will register its services with the file system or not.
- This option is automatically checked when the file system is connected to the SDMMC driver.
- **RTOS Configuration:**
 - **Stack Size:**
 - Maximum Stack size to be allocated for the SDMMC Driver
 - **Task Priority:**
 - Specifies Priority for the SDMMC driver task thread
 - **Use Task Delay?**
 - Specifies if the task delay should be enabled for the SDMMC task routine or not. In an RTOS environment, this option must be enabled to allow all the RTOS threads to run in a co-operative manner.
 - **Task Delay:**
 - Specifies Delay to put the SDMMC task Thread in blocked state after each call to the driver task routine. This allows other threads in the system to run.

Building the Library

This section provides information on how the SDMMC Driver Library can be built.

Description

Description



MHC *All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.*

Library Interface

a) System Functions

	Name	Description
≡	DRV_SDMMC_Initialize	Initializes the SD Card driver.
≡	DRV_SDMMC_Status	Provides the current status of the SD Card driver module.
≡	DRV_SDMMC_Tasks	Maintains the driver's state machine.

b) Core Client Functions

	Name	Description
≡	DRV_SDMMC_Open	Opens the specified SD Card driver instance and returns a handle to it.
≡	DRV_SDMMC_Close	Closes an opened-instance of the SD Card driver.
≡	DRV_SDMMC_EventHandlerSet	Allows a client to identify an event handling function for the driver to call back when queued operation has completed.

c) Block Operation Functions

	Name	Description
≡	DRV_SDMMC_AsyncRead	Reads blocks of data from the specified block address of the SD Card.
≡	DRV_SDMMC_AsyncWrite	Writes blocks of data starting at the specified address of the SD Card.
≡	DRV_SDMMC_CommandStatus	Gets the current status of the command.

d) Status Functions

	Name	Description
≡	DRV_SDMMC_GeometryGet	Returns the geometry of the device.
≡	DRV_SDMMC_IsAttached	Returns the physical attach status of the SD Card.
≡	DRV_SDMMC_IsWriteProtected	Returns the write protect status of the SDMMC.

e) Data Types and Constants

	Name	Description
	DRV_SDMMC_COMMAND_HANDLE	Handle identifying commands queued in the driver.
	DRV_SDMMC_COMMAND_STATUS	Identifies the possible events that can result from a request.
	DRV_SDMMC_EVENT	Identifies the possible events that can result from a request.
	DRV_SDMMC_EVENT_HANDLER	Pointer to a SDMMCDriver Event handler function
	DRV_SDMMC_COMMAND_HANDLE_INVALID	SDMMC Driver's Invalid Command Handle.

Description

This section describes the Application Programming Interface (API) functions of the SDMMC Driver Library.

Refer to each section for a detailed description.

a) System Functions

DRV_SDMMC_Initialize Function

Initializes the SD Card driver.

C

```
SYS_MODULE_OBJ DRV_SDMMC_Initialize(const SYS_MODULE_INDEX index, const SYS_MODULE_INIT* const init);
```

Returns

If successful, returns a valid handle to a driver object. Otherwise, it returns [SYS_MODULE_OBJ_INVALID](#).

Description

This routine initializes the SD Card driver, making it ready for clients to open and use the driver.

Remarks

This routine must be called before any other SD Card routine is called. This routine should only be called once during system initialization.

This routine will NEVER block for hardware access. The system must use [DRV_SDMMC_Status](#) to find out when the driver is in the ready state.

Preconditions

None.

Example

```
DRV_SDMMC_INIT      init;
SYS_MODULE_OBJ      objectHandle;

// Populate the SD Card initialization structure

objectHandle = DRV_SDMMC_Initialize(DRV_SDMMC_INDEX_0, (SYS_MODULE_INIT*)&init);
if (objectHandle == SYS_MODULE_OBJ_INVALID)
{
    // Handle error
}
```

Parameters

Parameters	Description
drvIndex	Index for the driver instance to be initialized

init	Pointer to a data structure containing any data necessary to initialize the driver. This pointer may be null if no data is required because static overrides have been provided.
------	--

Function

```
SYS_MODULE_OBJ DRV_SDMMC_Initialize (
const   SYS_MODULE_INDEX index,
const   SYS_MODULE_INIT* const init
);
```

DRV_SDMMC_Status Function

Provides the current status of the SD Card driver module.

C

```
SYS_STATUS DRV_SDMMC_Status(SYS_MODULE_OBJ object);
```

Returns

SYS_STATUS_READY - Indicates that the driver is busy with a previous system level operation and cannot start another Note Any value greater than SYS_STATUS_READY is also a normal running state in which the driver is ready to accept new operations.

SYS_STATUS_UNINITIALIZED - Driver is not initialized.

Description

This routine provides the current status of the SD Card driver module.

Remarks

None.

Preconditions

Function [DRV_SDMMC_Initialize](#) must have been called before calling this

Example

```
SYS_MODULE_OBJ          object;      // Returned from DRV_SDMMC_Initialize
SYS_STATUS             status;

status = DRV_SDMMC_Status(object);

if (status == SYS_STATUS_READY)
{
    // Driver is initialized and ready to accept requests
}
```

Parameters

Parameters	Description
object	Driver object handle, returned from the DRV_SDMMC_Initialize routine

Function

```
SYS_STATUS DRV_SDMMC_Status (
    SYS_MODULE_OBJ object
);
```

DRV_SDMMC_Tasks Function

Maintains the driver's state machine.

C

```
void DRV_SDMMC_Tasks(SYS_MODULE_OBJ object);
```

Returns

None

Description

This routine is used to maintain the driver's internal state machine.

Remarks

This routine is normally not called directly by an application. It is called by the system's Tasks routine (SYS_Tasks).

Preconditions

The [DRV_SDMMC_Initialize](#) routine must have been called for the specified SDMMC driver instance.

Example

```
SYS_MODULE_OBJ object; // Returned from DRV_SDMMC_Initialize

while (true)
{
    DRV_SDMMC_Tasks (object);

    // Do other tasks
}
```

Parameters

Parameters	Description
object	Object handle for the specified driver instance (returned from DRV_SDMMC_Initialize)

Function

```
void DRV_SDMMC_Tasks (
    SYS_MODULE_OBJ object
);
```

b) Core Client Functions**DRV_SDMMC_Open Function**

Opens the specified SD Card driver instance and returns a handle to it.

C

```
DRV_HANDLE DRV_SDMMC_Open(const SYS_MODULE_INDEX drvIndex, const DRV_IO_INTENT intent);
```

Returns

If successful, the routine returns a valid open-instance handle (a number identifying both the caller and the module instance).

If an error occurs, the return value is [DRV_HANDLE_INVALID](#).

Description

This routine opens the specified SD Card driver instance and provides a handle that must be provided to all other client-level operations to identify the caller and the instance of the driver.

Remarks

The handle returned is valid until the [DRV_SDMMC_Close](#) routine is called.

Preconditions

Function `DRV_SDMMC_Initialize` must have been called before calling this function.

Example

```
DRV_HANDLE handle;

handle = DRV_SDMMC_Open (DRV_SDMMC_INDEX_0, DRV_IO_INTENT_EXCLUSIVE);

if (handle == DRV_HANDLE_INVALID)
{
    // Unable to open the driver
}
```

Parameters

Parameters	Description
drvIndex	Identifier for the object instance to be opened
intent	Zero or more of the values from the enumeration <code>DRV_IO_INTENT</code> "ORed" together to indicate the intended use of the driver

Function

```
DRV_HANDLE DRV_SDMMC_Open (
const    SYS_MODULE_INDEX drvIndex,
const    DRV_IO_INTENT   intent
);
```

DRV_SDMMC_Close Function

Closes an opened-instance of the SD Card driver.

C

```
void DRV_SDMMC_Close(DRV_HANDLE handle);
```

Returns

None

Description

This routine closes an opened-instance of the SD Card driver, invalidating the handle.

Remarks

After calling this routine, the handle passed in "handle" must not be used with any of the remaining driver routines. A new handle must be obtained by calling `DRV_SDMMC_Open` before the caller may use the driver again.

If any requests were queued by the client, the driver will remove those requests from the queue and issue a `DRV_SDMMC_EVENT_COMMAND_ERROR` event, (if an event handler is registered by the client) before the client is closed.

Preconditions

The `DRV_SDMMC_Initialize` routine must have been called for the specified SD Card driver instance.

`DRV_SDMMC_Open` must have been called to obtain a valid opened device handle.

Example

```
DRV_HANDLE handle; // Returned from DRV_SDMMC_Open

DRV_SDMMC_Close (handle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
void DRV_SDMMC_Close (
    DRV_HANDLE handle
);
```

DRV_SDMMC_EventHandlerSet Function

Allows a client to identify an event handling function for the driver to call back when queued operation has completed.

C

```
void DRV_SDMMC_EventHandlerSet(const DRV_HANDLE handle, const void* eventHandler, const
uintptr_t context);
```

Returns

None.

Description

This function allows a client to identify an event handling function for the driver to call back when queued operation has completed. When a client queues a request for a read or a write operation, it is provided with a handle identifying the buffer that was added to the driver's buffer queue. The driver will pass this handle back to the client by calling "eventHandler" function when the queued operation has completed.

The event handler should be set before the client performs any read or write operations that could generate events. The event handler once set, persists until the client closes the driver or sets another event handler (which could be a "NULL" pointer to indicate no callback).

Remarks

If the client does not want to be notified when the queued operation has completed, it does not need to register a callback.

Preconditions

The `DRV_SDMMC_Initialize` routine must have been called for the specified SDMMC driver instance.

The `DRV_SDMMC_Open` routine must have been called to obtain a valid opened device handle.

Example

```
// myAppObj is an application specific state data object.
MY_APP_OBJ myAppObj;

uint8_t myBuffer[MY_BUFFER_SIZE];
uint32_t blockStart, nBlock;
DRV_SDMMC_COMMAND_HANDLE commandHandle;

// drvSDMMCHandle is the handle returned
// by the DRV_SDMMC_Open function.

// Client registers an event handler with driver. This is done once.

DRV_SDMMC_EventHandlerSet(drvSDMMCHandle, APP_SDMMCEventHandler, (uintptr_t)&myAppObj);

DRV_SDMMC_AsyncRead(drvSDMMCHandle, &commandHandle, &myBuffer[0], blockStart, nBlock);

if(commandHandle == DRV_SDMMC_COMMAND_HANDLE_INVALID)
{
    // Error handling here
}

// Event Processing Technique. Event is received when operation is done.

void APP_SDMMCEventHandler(
    DRV_SDMMC_EVENT event,
    DRV_SDMMC_COMMAND_HANDLE handle,
```

```

        uintptr_t context
    )
{
    // The context handle was set to an application specific
    // object. It is now retrievable easily in the event handler.

    MY_APP_OBJ myAppObj = (MY_APP_OBJ* ) context;

    switch(event)
    {
        case DRV_SDMMC_EVENT_COMMAND_COMPLETE:

            // This means the data was transferred successfully
            break;

        case DRV_SDMMC_EVENT_COMMAND_ERROR:

            // Error handling here
            break;

        default:
            break;
    }
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
eventHandler	Pointer to the event handler function implemented by the user
context	The value of parameter will be passed back to the client unchanged, when the eventHandler function is called. It can be used to identify any client specific data object that identifies the instance of the client module (for example, it may be a pointer to the client module's state structure).

Function

```

void DRV_SDMMC_EventHandlerSet (
    const     DRV_HANDLE handle,
    const void* eventHandler,
    const uintptr_t context
);

```

c) Block Operation Functions

DRV_SDMMC_AsyncRead Function

Reads blocks of data from the specified block address of the SD Card.

C

```

void DRV_SDMMC_AsyncRead(DRV_HANDLE handle, DRV_SDMMC_COMMAND_HANDLE* commandHandle, void*
targetBuffer, uint32_t blockstart, uint32_t nBlock);

```

Returns

The buffer handle is returned in the commandHandle argument. It will be [DRV_SDMMC_COMMAND_HANDLE_INVALID](#) if the request was not successful.

Description

This function schedules a non-blocking read operation for reading blocks of data from the SD Card. The function returns with a

valid buffer handle in the commandHandle argument if the read request was scheduled successfully. The function adds the request to the hardware instance queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. The function returns [DRV_SDMMC_COMMAND_HANDLE_INVALID](#) in the commandHandle argument under the following circumstances:

- if the driver handle is invalid
- if the target buffer pointer is NULL
- if the number of blocks to be read is zero or more than the actual number of blocks available
- if a buffer object could not be allocated to the request

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_SDMMC_EVENT_COMMAND_COMPLETE](#) event if the buffer was processed successfully or [DRV_SDMMC_EVENT_COMMAND_ERROR](#) event if the buffer was not processed successfully.

Remarks

None.

Preconditions

The [DRV_SDMMC_Initialize](#) routine must have been called for the specified SDMMC driver instance. [DRV_SDMMC_Open](#) must have been called and a valid handle must have been obtained.

Example

```
uint8_t myBuffer[MY_BUFFER_SIZE];

// address should be block aligned.
uint32_t blockStart = 0x00;
uint32_t nBlock = 2;
DRV_SDMMC_COMMAND_HANDLE commandHandle;
MY_APP_OBJ myAppObj;

// mySDMMCHandle is the handle returned
// by the DRV_SDMMC_Open function.

DRV_SDMMC_AsyncRead(mySDMMCHandle, &commandHandle, &myBuffer[0], blockStart, nBlock);

if(commandHandle == DRV_SDMMC_COMMAND_HANDLE_INVALID)
{
    // Error handling here
}
else
{
    // Read Successfully queued
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the return buffer handle
targetBuffer	Buffer into which the data read from the SD Card will be placed
blockStart	Start block address of the SD Card from where the read should begin.
nBlock	Total number of blocks to be read.

Function

```
void DRV_SDMMC_AsyncRead (
    const DRV_HANDLE handle,
    DRV_SDMMC_COMMAND_HANDLE* commandHandle,
    void* targetBuffer,
    uint32_t blockStart,
    uint32_t nBlock
);
```

DRV_SDMMC_AsyncWrite Function

Writes blocks of data starting at the specified address of the SD Card.

C

```
void DRV_SDMMC_AsyncWrite(DRV_HANDLE handle, DRV_SDMMC_COMMAND_HANDLE* commandHandle, void* sourceBuffer, uint32_t blockStart, uint32_t nBlock);
```

Returns

The buffer handle is returned in the commandHandle argument. It will be [DRV_SDMMC_COMMAND_HANDLE_INVALID](#) if the request was not successful.

Description

This function schedules a non-blocking write operation for writing blocks of data to the SD Card. The function returns with a valid buffer handle in the commandHandle argument if the write request was scheduled successfully. The function adds the request to the hardware instance queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. The function returns [DRV_SDMMC_COMMAND_HANDLE_INVALID](#) in the commandHandle argument under the following circumstances:

- if the driver handle is invalid
- if the source buffer pointer is NULL
- if the number of blocks to write is zero or more than the actual number of blocks available
- if a buffer object could not be allocated to the request

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_SDMMC_EVENT_COMMAND_COMPLETE](#) event if the buffer was processed successfully or [DRV_SDMMC_EVENT_COMMAND_ERROR](#) event if the buffer was not processed successfully.

Remarks

None.

Preconditions

The [DRV_SDMMC_Initialize](#) routine must have been called for the specified SDMMC driver instance.

[DRV_SDMMC_Open](#) routine must have been called to obtain a valid opened device handle.

Example

```
uint8_t myBuffer[MY_BUFFER_SIZE];

// address should be block aligned.
uint32_t blockStart = 0x00;
uint32_t nBlock = 2;
DRV_SDMMC_COMMAND_HANDLE commandHandle;
MY_APP_OBJ myAppObj;

// mySDMMCHandle is the handle returned
// by the DRV_SDMMC_Open function.

// Client registers an event handler with driver

DRV_SDMMC_EventHandlerSet(mySDMMCHandle, APP_SDMMCEventHandler, (uintptr_t)&myAppObj);

DRV_SDMMC_AsyncWrite(mySDMMCHandle, &commandHandle, &myBuffer[0], blockStart, nBlock);

if(commandHandle == DRV_SDMMC_COMMAND_HANDLE_INVALID)
{
    // Error handling here
}

// Event is received when
// the buffer is processed.
```

```

void APP_SDMMCEventHandler(
    DRV_SDMMC_EVENT event,
    DRV_SDMMC_COMMAND_HANDLE commandHandle,
    uintptr_t contextHandle
)
{
    // contextHandle points to myAppObj.

    switch(event)
    {
        case DRV_SDMMC_EVENT_COMMAND_COMPLETE:

            // This means the data was transferred successfully
            break;

        case DRV_SDMMC_EVENT_COMMAND_ERROR:

            // Error handling here
            break;

        default:
            break;
    }
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the return buffer handle
sourceBuffer	The source buffer containing data to be programmed to the SD Card.
blockStart	Start block address of SD Card where the writes should begin.
nBlock	Total number of blocks to be written.

Function

```

void DRV_SDMMC_AsyncWrite (
    const DRV_HANDLE handle,
    DRV_SDMMC_COMMAND_HANDLE* commandHandle,
    void* sourceBuffer,
    uint32_t blockStart,
    uint32_t nBlock
);

```

DRV_SDMMC_CommandStatus Function

Gets the current status of the command.

C

```

DRV_SDMMC_COMMAND_STATUS DRV_SDMMC_CommandStatus(const DRV_HANDLE handle, const
DRV_SDMMC_COMMAND_HANDLE commandHandle);

```

Returns

A [DRV_SDMMC_COMMAND_STATUS](#) value describing the current status of the command. Returns [DRV_SDMMC_COMMAND_ERROR_UNKNOWN](#) if the client handle or the command handle is not valid.

Description

This routine gets the current status of the command. The application must use this routine where the status of a scheduled command needs to be polled on. The function may return [DRV_SDMMC_COMMAND_ERROR_UNKNOWN](#) in a case where the command handle has expired. A command handle expires when the internal buffer object is re-assigned to another read or write

request. It is recommended that this function be called regularly in order to track the command status correctly. The application can alternatively register an event handler to receive read or write operation completion events.

Remarks

This routine will not block for hardware access and will immediately return the current status.

Preconditions

The `DRV_SDMMC_Initialize` routine must have been called.

The `DRV_SDMMC_Open` must have been called to obtain a valid opened device handle.

Example

```
DRV_HANDLE handle;           // Returned from DRV_SDMMC_Open
DRV_SDMMC_COMMAND_HANDLE commandHandle;
DRV_SDMMC_COMMAND_STATUS status;

status = DRV_SDMMC_CommandStatus(handle, commandHandle);
if(status == DRV_SDMMC_COMMAND_COMPLETED)
{
    // Operation Done
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
DRV_SDMMC_COMMAND_STATUS DRV_SDMMC_CommandStatus (
const DRV_HANDLE handle,
const DRV_SDMMC_COMMAND_HANDLE commandHandle
);
```

d) Status Functions

DRV_SDMMC_GeometryGet Function

Returns the geometry of the device.

C

```
SYS_MEDIA_GEOMETRY* DRV_SDMMC_GeometryGet(const DRV_HANDLE handle);
```

Returns

`SYS_MEDIA_GEOMETRY` - Pointer to structure which holds the media geometry information.

Description

This API gives the following geometrical details of the SD Card.

- Media Property
- Number of Read/Write/Erase regions in the SD Card
- Number of Blocks and their size in each region of the device

Remarks

None.

Preconditions

The `DRV_SDMMC_Initialize` routine must have been called for the specified SDMMC driver instance.

The [DRV_SDMMC_Open](#) routine must have been called to obtain a valid opened device handle.

Example

```
SYS_MEDIA_GEOMETRY* SDMMCGeometry;
uint32_t readBlockSize, writeBlockSize, eraseBlockSize;
uint32_t nReadBlocks, nReadRegions, totalSize;

SDMMCGeometry = DRV_SDMMC_GeometryGet(SDMMCOpenHandle1);

readBlockSize = SDMMCGeometry->geometryTable->blockSize;
nReadBlocks = SDMMCGeometry->geometryTable->numBlocks;
nReadRegions = SDMMCGeometry->numReadRegions;

writeBlockSize = (SDMMCGeometry->geometryTable +1)->blockSize;
eraseBlockSize = (SDMMCGeometry->geometryTable +2)->blockSize;

totalSize = readBlockSize * nReadBlocks * nReadRegions;
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function

Function

```
SYS_MEDIA_GEOMETRY* DRV_SDMMC_GeometryGet (
const DRV_HANDLE handle
);
```

DRV_SDMMC_IsAttached Function

Returns the physical attach status of the SD Card.

C

```
bool DRV_SDMMC_IsAttached(const DRV_HANDLE handle);
```

Returns

Returns false if the handle is invalid otherwise returns the attach status of the SD Card. Returns true if the SD Card is attached and initialized by the SDMMC driver otherwise returns false.

Description

This function returns the physical attach status of the SD Card.

Remarks

None.

Preconditions

The [DRV_SDMMC_Initialize](#) routine must have been called for the specified SDMMC driver instance.

The [DRV_SDMMC_Open](#) routine must have been called to obtain a valid opened device handle.

Example

```
// drvSDMMCHandle is the handle returned
// by the DRV\_SDMMC\_Open function.

bool isSDMMCAttached;
isSDMMCAttached = DRV_SDMMC_isAttached(drvSDMMCHandle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function

Function

```
bool DRV_SDMMC_IsAttached (
    const DRV_HANDLE handle
);
```

DRV_SDMMC_IsWriteProtected Function

Returns the write protect status of the SDMMC.

C

```
bool DRV_SDMMC_IsWriteProtected(const DRV_HANDLE handle);
```

Returns

Returns true if the attached SD Card is write protected. Returns false if the handle is not valid, or if the SD Card is not write protected, or if the write protection check is not enabled.

Description

This function returns the physical write status of the SDMMC. This function returns true if the SD Card is write protected otherwise it returns false.

Remarks

None.

Preconditions

The [DRV_SDMMC_Initialize](#) routine must have been called for the specified SDMMC driver instance.

The [DRV_SDMMC_Open](#) routine must have been called to obtain a valid opened device handle.

Example

```
bool isWriteProtected;
isWriteProtected = DRV_SDMMC_IsWriteProtected(drvSDMMCHandle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function

Function

```
bool DRV_SDMMC_IsWriteProtected (
    const DRV_HANDLE handle
);
```

e) Data Types and Constants

DRV_SDMMC_COMMAND_HANDLE Type

Handle identifying commands queued in the driver.

C

```
typedef SYS_MEDIA_BLOCK_COMMAND_HANDLE DRV_SDMMC_COMMAND_HANDLE;
```

Description

SDMMC Driver command handle.

A command handle is returned by a call to the Read or Write functions. This handle allows the application to track the completion of the operation. This command handle is also returned to the client along with the event that has occurred with respect to the command. This allows the application to connect the event to a specific command in case where multiple commands are queued. The command handle associated with the command request expires when the client has been notified of the completion of the command (after event handler function that notifies the client returns) or after the command has been retired by the driver if no event handler callback was set.

Remarks

None.

DRV_SDMMC_COMMAND_STATUS Enumeration

Identifies the possible events that can result from a request.

C

```
typedef enum {
    DRV_SDMMC_COMMAND_COMPLETED = SYS_MEDIA_COMMAND_COMPLETED,
    DRV_SDMMC_COMMAND_QUEUED = SYS_MEDIA_COMMAND_QUEUED,
    DRV_SDMMC_COMMAND_IN_PROGRESS = SYS_MEDIA_COMMAND_IN_PROGRESS,
    DRV_SDMMC_COMMAND_ERROR_UNKNOWN = SYS_MEDIA_COMMAND_UNKNOWN
} DRV_SDMMC_COMMAND_STATUS;
```

Members

Members	Description
DRV_SDMMC_COMMAND_COMPLETED = SYS_MEDIA_COMMAND_COMPLETED	Done OK and ready
DRV_SDMMC_COMMAND_QUEUED = SYS_MEDIA_COMMAND_QUEUED	Scheduled but not started
DRV_SDMMC_COMMAND_IN_PROGRESS = SYS_MEDIA_COMMAND_IN_PROGRESS	Currently being in transfer
DRV_SDMMC_COMMAND_ERROR_UNKNOWN = SYS_MEDIA_COMMAND_UNKNOWN	Unknown Command

Description

SDMMC Driver Events

This enumeration identifies the possible status values of a read or write buffer request submitted to the driver.

Remarks

One of these values is returned by the [DRV_SDMMC_CommandStatus](#) routine.

DRV_SDMMC_EVENT Enumeration

Identifies the possible events that can result from a request.

C

```
typedef enum {
    DRV_SDMMC_EVENT_COMMAND_COMPLETE = SYS_MEDIA_EVENT_BLOCK_COMMAND_COMPLETE,
    DRV_SDMMC_EVENT_COMMAND_ERROR = SYS_MEDIA_EVENT_BLOCK_COMMAND_ERROR
} DRV_SDMMC_EVENT;
```

Members

Members	Description
DRV_SDMMC_EVENT_COMMAND_COMPLETE = SYS_MEDIA_EVENT_BLOCK_COMMAND_COMPLETE	Operation has been completed successfully.

DRV_SDMMC_EVENT_COMMAND_ERROR =
SYS_MEDIA_EVENT_BLOCK_COMMAND_ERROR

There was an error during the operation

Description

SDMMC Driver Events

This enumeration identifies the possible events that can result from a read or a write request issued by the client.

Remarks

One of these values is passed in the "event" parameter of the event handling callback function that client registered with the driver by calling the [DRV_SDMMC_EventHandlerSet](#) function when a request is completed.

DRV_SDMMC_EVENT_HANDLER Type

Pointer to a SDMMCDriver Event handler function

C

```
typedef SYS_MEDIA_EVENT_HANDLER DRV_SDMMC_EVENT_HANDLER;
```

Returns

None.

Description

SDMMC Driver Event Handler Function Pointer

This data type defines the required function signature for the SDMMC event handling callback function. A client must register a pointer to an event handling function whose function signature (parameter and return value types) match the types specified by this function pointer in order to receive event calls back from the driver.

The parameters and return values are described here and a partial example implementation is provided.

Remarks

If the event is DRV_SDMMC_EVENT_COMMAND_COMPLETE, it means that the write or a read operation was completed successfully.

If the event is DRV_SDMMC_EVENT_COMMAND_ERROR, it means that the operation was not completed successfully.

The context parameter contains the handle to the client context, provided at the time the event handling function was registered using the [DRV_SDMMC_EventHandlerSet](#) function. This context handle value is passed back to the client as the "context" parameter. It can be any value necessary to identify the client context or instance (such as a pointer to the client's data) instance of the client that made the read/write request.

Example

```
void APP_MySDMMCEventHandler
(
    DRV_SDMMC_EVENT event,
    DRV_SDMMC_COMMAND_HANDLE commandHandle,
    uintptr_t context
)
{
    MY_APP_DATA_STRUCT* pAppData = (MY_APP_DATA_STRUCT* ) context;

    switch(event)
    {
        case DRV_SDMMC_EVENT_COMMAND_COMPLETE:
            // Handle the completed buffer.
            break;

        case DRV_SDMMC_EVENT_COMMAND_ERROR:
        default:
            // Handle error.
            break;
    }
}
```

```

    }
}

```

Parameters

Parameters	Description
event	Identifies the type of event
commandHandle	Handle returned from the Read/Write requests
context	Value identifying the context of the application that registered the event handling function

DRV_SDMMC_COMMAND_HANDLE_INVALID Macro

SDMMC Driver's Invalid Command Handle.

C

```
#define DRV_SDMMC_COMMAND_HANDLE_INVALID SYS_MEDIA_BLOCK_COMMAND_HANDLE_INVALID
```

Description

SDMMC Driver Invalid Command Handle.

This value defines the SDMMC Driver Invalid Command Handle. This value is returned by read or write routines when the command request was not accepted.

Remarks

None.

SD Card (SPI) Driver Library

This section describes the SD (Secure Digital) Card driver (SDSPI) library.

Introduction

The SDSPI driver provides the necessary interfaces to interact with an SD card interfaced over SPI peripheral library. It provides the necessary abstraction for the higher layers.

Description

This driver library provides application ready routines to read and write to the SD Card, thus minimizing developer's awareness of working of the SD Card protocol.

- Supports asynchronous (non-blocking) and synchronous (blocking) mode of operation
- Supports both DMA and non-DMA modes
- The driver API interface can be used directly by the application to read/write directly from the SD Card Or the SDSPI driver can be used with a file system

Using the Library

This section describes the basic architecture of the SDSPI driver Library and provides information on how to use the library.

Description

The SDSPI driver builds on top of the SPI peripheral library and provides direct access to the SD Card. It also confirms to the media block layer interface which allows it to register its services with the file system's media block driver interface.

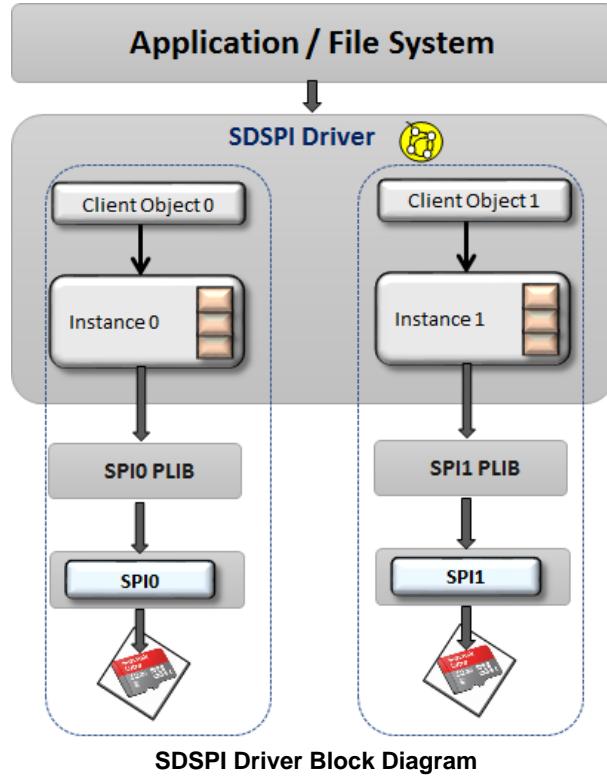
- The driver supports both asynchronous (non-blocking) and synchronous (blocking) behavior
- The application can access the SD Card either by using the SDSPI APIs or by using the File System APIs

Abstraction Model

This section describes how the abstraction is modeled in software and introduces the library's interface.

Description

The SDSPI driver provides abstraction to communicate with SD-Card through SPI peripheral library.



Note:

- Driver instance specific queue is not present in synchronous mode of the driver

How the Library Works

This section describes the basic architecture of the SDSPI Driver Library and provides information on how it works.

Description

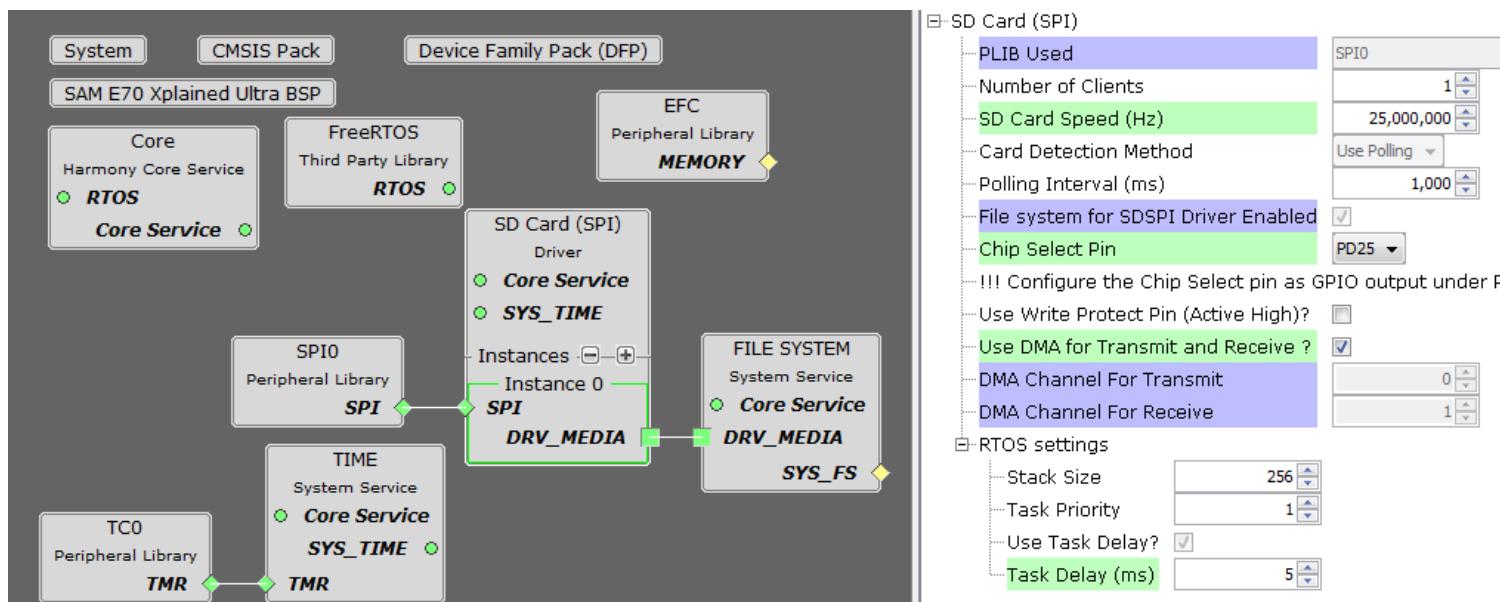
- The SDSPI driver Library registers an event handler with the underlying SPI peripheral library. This event handler is called by the PLIB from the interrupt context to notify the SDSPI driver that the requested transfer is complete
- If DMA is enabled, the SDSPI Driver registers an event handler with the DMA peripheral library. This event handler is called by the DMA PLIB from the interrupt context once the DMA transfer is complete
- The SD Card driver state machine checks for SD Card attach/detach status using command-response mechanism. Once a SD Card is detected, the state machine initializes the SD Card making it ready for the client to submit read/write requests. After the SD Card is initialized, the state machine periodically checks if the SD Card is still connected using command/response mechanism. The rate at which the SD card driver checks for the SD Card attach/detach event can be specified via an MHC configuration option. In case RTOS is enabled, the RTOS Task Delay value for the SDSPI Driver task also affects the rate at which the SD Card attach/detach is checked.
- In Asynchronous mode, the SD Card driver state machine checks the driver instance queue for any pending requests. If a request is pending, then the corresponding request is executed. Once the request is execution is complete, a callback is given to the application if it is registered by the application client. In Synchronous mode, the application request is executed in blocking mode, which means it is executed in the context of the caller/application thread.

Configuring the Library

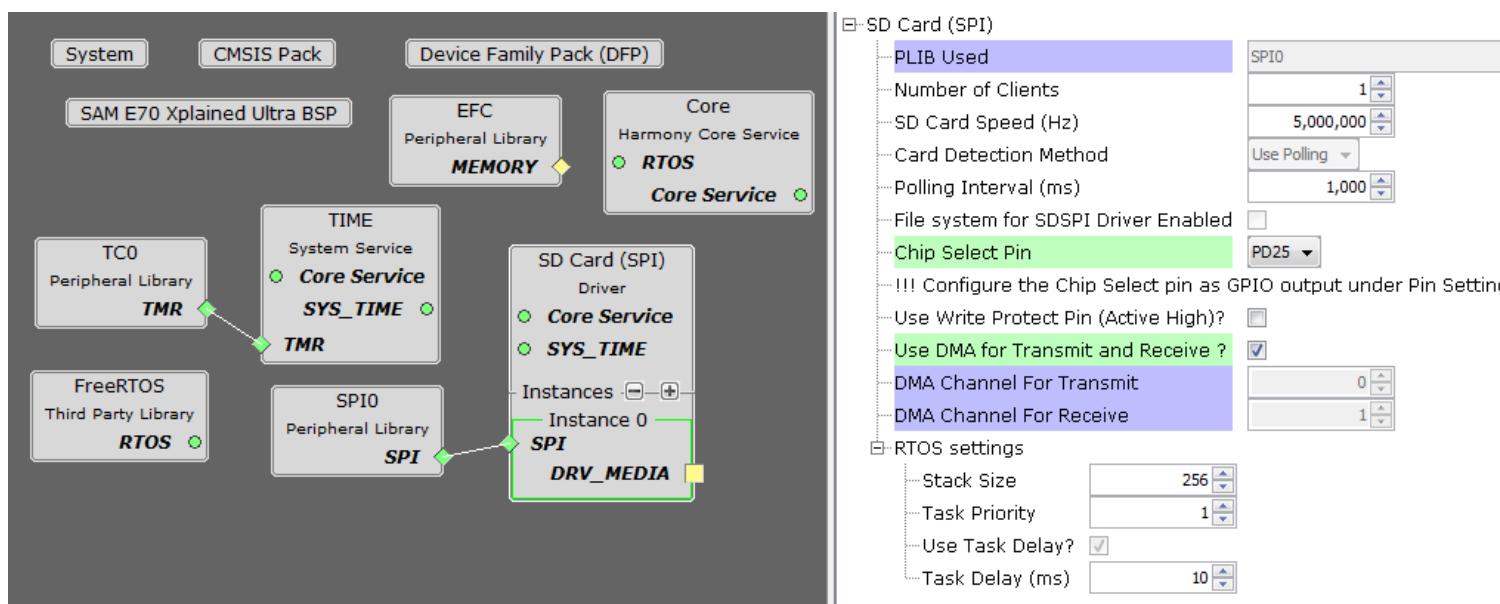
This section provides information on how to configure the SDSPI Driver library.

Description

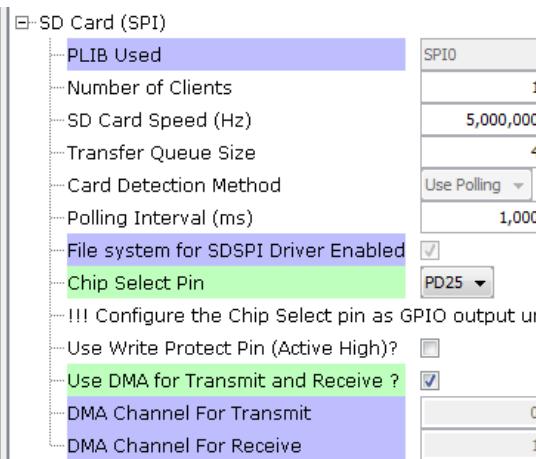
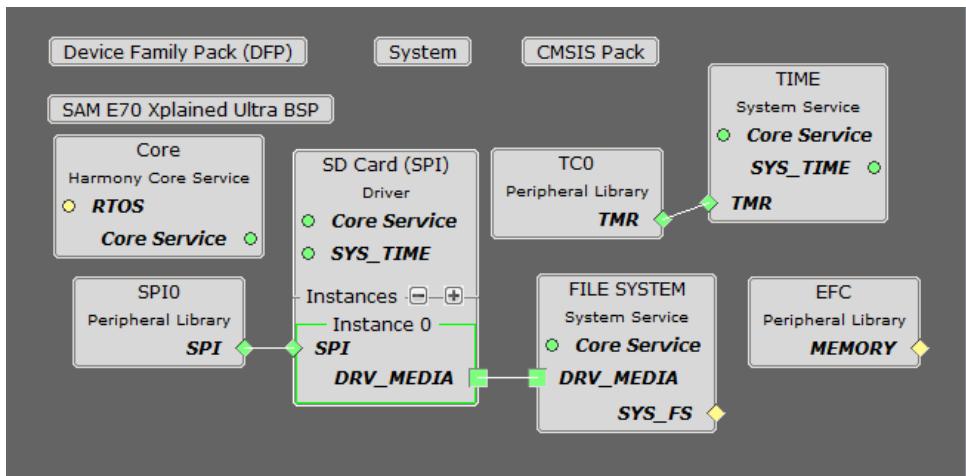
The SDSPI driver library should be configured through the MHC. The following figures show the MHC configuration window for the SDHC driver and brief description.



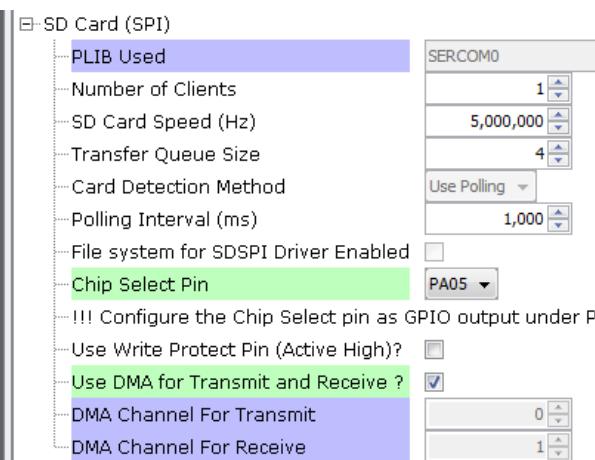
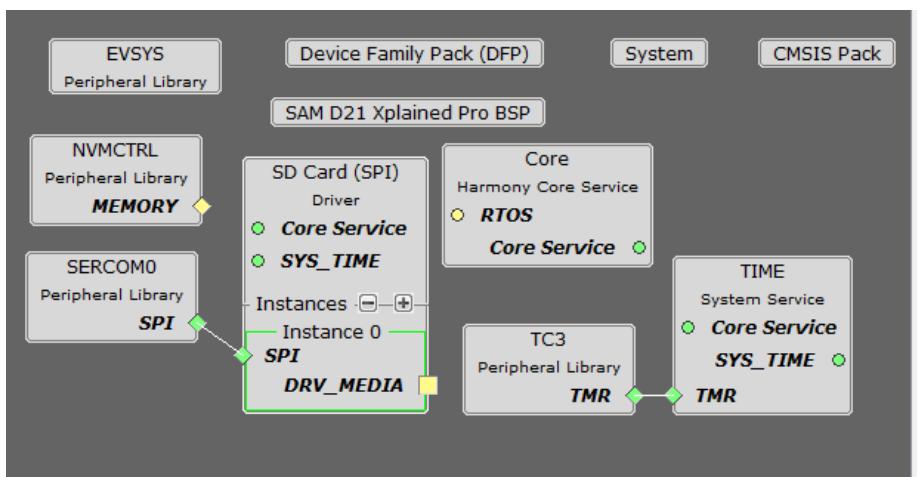
Synchronous Mode with File-System



Synchronous Mode without File-System



Asynchronous Mode with File-System



Asynchronous Mode without File-System

Common User Configuration for all Instances

- Driver Mode:**
 - Allows User to select the mode of driver(Asynchronous or Synchronous).This setting is common for all the instances

Instance Specific User Configurations

- PLIB Used:**
 - Indicates the SPI peripheral instance used by the SDSPI driver
- Number of Clients:**
 - Indicates the number of clients to the given SDSPI driver instance
- SD Card Speed (Hz):**
 - The maximum SPI speed at which the SDSPI driver interacts with the SD Card
 - SDSPI driver overrides the SPI PLIB clock speed settings
- Card Detection Method:**
 - Card detection method used. For SDSPI driver command-response based polling method is used for card insertion/removal
- Polling Interval (ms):**
 - Rate at which the SDSPI driver checks for card insertion and removal
- File System For SDSPI Driver Enabled:**
 - Indicates whether SDSPI driver will register its services with the file system or not
 - This option is automatically checked when the file system is connected to the SDSPI driver
- Chip Select Pin:**

- The SD Card chip select pin
- **Use Write Protect Pin (Active High)?**
 - Enable write protection check. The selected write protect pin must be configured as GPIO input under the Pin Settings window
- **Use DMA for Transmit and Receive?:**
 - Enable/disable SDSPI driver to use DMA
- **DMA Channel For Transmit:**
 - Indicates the DMA channel the SDSPI driver will use for transmission
- **DMA Channel For Receive:**
 - Indicates the DMA channel the SDSPI driver will use for reception
- **RTOS Settings:**
 - **Stack Size:**
 - The stack size of the SDSPI RTOS thread
 - **Task Priority:**
 - The priority of the SDSPI RTOS thread
 - **Use Task Delay?:**
 - Indicates whether the Task Delay is used to yield the SDSPI RTOS thread
 - **Task Delay (ms):**
 - Indicates the amount of time for which the SDSPI RTOS thread is put in blocked state by the scheduler before it is run again
 - This inturn controls the rate at which the SDSPI driver checks for the SD Card attach/detach status

Note: The Time System Service is used by the SDSPI driver to maintain the SD Card protocol timings, and hence must be enabled.

Building the Library

This section provides information on how the SDSPI Driver Library can be built.

Description



All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

Library Interface

a) System Functions

	Name	Description
≡◊	DRV_SDSPI_Initialize	Initializes the SD Card driver.
≡◊	DRV_SDSPI_Status	Provides the current status of the SDSPI driver module.
≡◊	DRV_SDSPI_Tasks	Maintains the driver's state machine.

b) Core Client Functions

	Name	Description
≡◊	DRV_SDSPI_Open	Opens the specified SD Card driver instance and returns a handle to it.
≡◊	DRV_SDSPI_Close	Closes an opened-instance of the SD Card driver.
≡◊	DRV_SDSPI_EventHandlerSet	Allows a client to identify an event handling function for the driver to call back when queued operation has completed. For the synchronous SDSPI driver, the event handler is only used by the file system.

c) Data Transfer Functions

	Name	Description
≡	DRV_SDSPI_AsyncRead	Reads blocks of data from the specified block address of the SD Card.
≡	DRV_SDSPI_SyncRead	Reads blocks of data from the specified block address of the SD Card.
≡	DRV_SDSPI_Read	This routine provides interface to the file system to perform a media read operation in synchronous mode of the SDSPI driver.
≡	DRV_SDSPI_SyncWrite	Writes blocks of data starting at the specified address of the SD Card.
≡	DRV_SDSPI_AsyncWrite	Writes blocks of data starting at the specified address of the SD Card.
≡	DRV_SDSPI_Write	This routine provides interface to the file system to perform a media write operation in synchronous mode of the SDSPI driver.
≡	DRV_SDSPI_CommandStatusGet	Gets the current status of the command. For synchronous mode, the command status is only used by the file system.

d) Status Functions

	Name	Description
≡	DRV_SDSPI_IsAttached	Returns the physical attach status of the SD Card.
≡	DRV_SDSPI_IsWriteProtected	Returns the write protect status of the SD Card.
≡	DRV_SDSPI_GeometryGet	Returns the geometry of the device.

e) Data Types and Constants

	Name	Description
	DRV_SDSPI_COMMAND_HANDLE	This is type DRV_SDSPI_COMMAND_HANDLE.
	DRV_SDSPI_COMMAND_STATUS	This is type DRV_SDSPI_COMMAND_STATUS.
	DRV_SDSPI_EVENT	Identifies the possible events that can result from a request.
	DRV_SDSPI_EVENT_HANDLER	Pointer to a SDSPI Driver Event handler function
	DRV_SDSPI_COMMAND_HANDLE_INVALID	SDSPI Driver's Invalid Command Handle.

Description

This section describes the API functions of the SDSPI Driver library.

Refer to each section for a detailed description.

a) System Functions

DRV_SDSPI_Initialize Function

Initializes the SD Card driver.

C

```
SYS_MODULE_OBJ DRV_SDSPI_Initialize(const SYS_MODULE_INDEX drvIndex, const SYS_MODULE_INIT *  
const init);
```

Returns

If successful, returns a valid handle to a driver object. Otherwise, it returns [SYS_MODULE_OBJ_INVALID](#).

Description

This routine initializes the SD Card driver, making it ready for clients to open and use the driver.

Remarks

This routine must be called before any other SD Card routine is called.

This routine should only be called once during system initialization.

The system must use [DRV_SDSPI_Status](#) to find out when the driver is in the ready state.

Preconditions

None.

Example

```

DRV_SDSPI_INIT      drvSDSPI0InitData;
SYS_MODULE_OBJ      objectHandle;

DRV_SDSPI_PLIB_INTERFACE drvSDSPI0plibAPI = {
    // SPI PLIB WriteRead function
    .writeRead = (DRV_SDSPI_WITEREAD)SPI0_WriteRead,
    // SPI PLIB Write function
    .write = (DRV_SDSPI_WRITE)SPI0_Write,
    // SPI PLIB Read function
    .read = (DRV_SDSPI_READ)SPI0_Read,
    // SPI PLIB Transfer Status function
    .isBusy = (DRV_SDSPI_IS_BUSY)SPI0_IsBusy,
    // SPI PLIB Transfer Setup function
    .transferSetup = (DRV_SDSPI_SETUP)SPI0_TransferSetup,
    // SPI PLIB Callback Register
    .callbackRegister = (DRV_SDSPI_CALLBACK_REGISTER)SPI0_CallbackRegister,
};

DRV_SDSPI_INIT drvSDSPI0InitData = {
    // SD Card SPI PLIB API interface
    .spiplib          = &drvSDSPI0plibAPI,
    .remapDataBits   = drvSDSPI0remapDataBits,
    .remapClockPolarity = drvSDSPI0remapClockPolarity,
    .remapClockPhase = drvSDSPI0remapClockPhase,
    // SDSPI Number of clients
    .numClients       = DRV_SDSPI_CLIENTS_NUMBER_IDX0,
    // SDSPI Client Objects Pool
    .clientObjPool    = (uintptr_t)&drvSDSPI0ClientObjPool[0],
    .chipSelectPin   = DRV_SDSPI_CHIP_SELECT_PIN_IDX0,
    .SDSPISpeedHz    = DRV_SDSPI_SPEED_HZ_IDX0,
    .writeProtectPin = SYS_PORT_PIN_NONE,
    .isFsEnabled      = DRV_SDSPI_REGISTER_WITH_FS_IDX0,
    // DMA Channel for Transmit
    .txDMAChannel    = DRV_SDSPI_XMIT_DMA_CH_IDX0,
    // DMA Channel for Receive
    .rxDMAChannel    = DRV_SDSPI_RCV_DMA_CH_IDX0,
    // SPI Transmit Register
    .txAddress        = (void *)(&(SPI0_REGS->SPI_TDR)),
    // SPI Receive Register
    .rxAddress        = (void *)(&(SPI0_REGS->SPI_RDR)),
};

objectHandle = DRV_SDSPI_Initialize(DRV_SDSPI_INDEX_0, (SYS_MODULE_INIT *)&drvSDSPI0InitData);
if (objectHandle == SYS_MODULE_OBJ_INVALID)
{
    // Handle error
}

```

Parameters

Parameters	Description
drvIndex	Index for the driver instance to be initialized
init	Pointer to a data structure containing any data necessary to initialize the driver.

Function

```

SYS_MODULE_OBJ DRV_SDSPI_Initialize
(
    const    SYS_MODULE_INDEX drvIndex,
    const    SYS_MODULE_INIT * const init

```

)

DRV_SDSPI_Status Function

Provides the current status of the SDSPI driver module.

C

```
SYS_STATUS DRV_SDSPI_Status(const SYS_MODULE_OBJ object);
```

Returns

SYS_STATUS_READY - Indicates that the driver has been initialized and is ready to accept requests from the client.

SYS_STATUS_UNINITIALIZED - Indicates that the driver has not been initialized.

Description

This routine provides the current status of the SDSPI driver module.

Remarks

This operation can be used to determine if the driver is initialized or not.

Preconditions

Function [DRV_SDSPI_Initialize](#) must have been called before calling this

Example

```
SYS_MODULE_OBJ          object;      // Returned from DRV_SDSPI_Initialize
SYS_STATUS              status;

status = DRV_SDSPI_Status(object);

if (status == SYS_STATUS_READY)
{
    // Driver is initialized and ready.
}
```

Parameters

Parameters	Description
object	Driver object handle, returned from the DRV_SDSPI_Initialize routine

Function

```
SYS_STATUS DRV_SDSPI_Status
(
    SYS_MODULE_OBJ object
)
```

DRV_SDSPI_Tasks Function

Maintains the driver's state machine.

C

```
void DRV_SDSPI_Tasks(SYS_MODULE_OBJ object);
```

Returns

None

Description

This routine is used to maintain the driver's internal state machine. For synchronous driver, the task routine periodically checks for SD card attach/detach event and initializes the SD card.

Remarks

This routine is normally not called directly by an application. For synchronous driver with RTOS, this routine is called from a separate RTOS thread.

Preconditions

The [DRV_SDSPI_Initialize](#) routine must have been called for the specified SDSPI driver instance.

Example

```
//sysObj.drvSDSPI0 is returned by the driver initialization routine

//For synchronous driver
while(1)
{
    DRV_SDSPI_Tasks(sysObj.drvSDSPI0);

    // Yield and allow other threads to run
    vTaskDelay(100 / portTICK_PERIOD_MS);
}
```

Parameters

Parameters	Description
object	Object handle for the specified driver instance (returned from DRV_SDSPI_Initialize)

Function

```
void DRV_SDSPI_Tasks
(
    SYS_MODULE_OBJ object
)
```

b) Core Client Functions

DRV_SDSPI_Open Function

Opens the specified SD Card driver instance and returns a handle to it.

C

```
DRV_HANDLE DRV_SDSPI_Open(const SYS_MODULE_INDEX drvIndex, const DRV_IO_INTENT ioIntent);
```

Returns

If successful, the routine returns a valid open-instance handle (a number identifying both the caller and the module instance). If an error occurs, the return value is [DRV_HANDLE_INVALID](#).

Description

This routine opens the specified SD Card driver instance and provides a handle that must be provided to all other client-level operations to identify the caller and the instance of the driver.

Remarks

The handle returned is valid until the [DRV_SDSPI_Close](#) routine is called. This routine may block for other client-level operations to complete.

Preconditions

Function [DRV_SDSPI_Initialize](#) must have been called before calling this function.

Example

```
DRV_HANDLE handle;

handle = DRV_SDSPI_Open (DRV_SDSPI_INDEX_0, DRV_IO_INTENT_EXCLUSIVE);

if (handle == DRV_HANDLE_INVALID)
{
    // Unable to open the driver
}
```

Parameters

Parameters	Description
drvIndex	Identifier for the object instance to be opened
ioIntent	Zero or more of the values from the enumeration DRV_IO_INTENT "ORed" together to indicate the intended use of the driver. Supports only DRV_IO_INTENT_EXCLUSIVE .

Function

```
DRV_HANDLE DRV_SDSPI_Open
(
    const SYS_MODULE_INDEX drvIndex,
    const DRV_IO_INTENT ioIntent
)
```

DRV_SDSPI_Close Function

Closes an opened-instance of the SD Card driver.

C

```
void DRV_SDSPI_Close(const DRV_HANDLE handle);
```

Returns

None

Description

This routine closes an opened-instance of the SD Card driver, invalidating the handle.

Remarks

After calling this routine, the handle passed in "handle" must not be used with any of the remaining driver routines. A new handle must be obtained by calling [DRV_SDSPI_Open](#) before the caller may use the driver again. This routine may block for other client-level operations to complete.

Usually there is no need for the driver client to verify that the Close operation has completed.

Preconditions

The [DRV_SDSPI_Initialize](#) routine must have been called for the specified SD Card driver instance.

[DRV_SDSPI_Open](#) must have been called to obtain a valid opened device handle.

Example

```
DRV_HANDLE handle; // Returned from DRV_SDSPI_Open

DRV_SDSPI_Close (handle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
void DRV_SDSPI_Close
(
const DRV_HANDLE handle
)
```

DRV_SDSPI_EventHandlerSet Function

Allows a client to identify an event handling function for the driver to call back when queued operation has completed. For the synchronous SDSPI driver, the event handler is only used by the file system.

C

```
void DRV_SDSPI_EventHandlerSet(const DRV_HANDLE handle, const void * eventHandler, const
uintptr_t context);
```

Returns

None.

Description

This function allows a client to identify an event handling function for the driver to call back when queued operation has completed. When a client queues a request for a read or a write operation, it is provided with a handle identifying the buffer that was added to the driver's buffer queue. The driver will pass this handle back to the client by calling "eventHandler" function when the queued operation has completed.

The event handler should be set before the client performs any read or write operations that could generate events. The event handler once set, persists until the client closes the driver or sets another event handler (which could be a "NULL" pointer to indicate no callback).

Remarks

If the client does not want to be notified when the queued operation has completed, it does not need to register a callback. This API may not be used in applications using the SDSPI Driver in synchronous mode.

Preconditions

The [DRV_SDSPI_Initialize](#) routine must have been called for the specified SDSPI driver instance.

The [DRV_SDSPI_Open](#) routine must have been called to obtain a valid opened device handle.

Example

None.

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
eventHandler	Pointer to the event handler function implemented by the user
context	The value of parameter will be passed back to the client unchanged, when the eventHandler function is called. It can be used to identify any client specific data object that identifies the instance of the client module (for example, it may be a pointer to the client module's state structure).

Function

```
void DRV_SDSPI_EventHandlerSet
(
const DRV_HANDLE handle,
const void * eventHandler,
const uintptr_t context
)
```

c) Data Transfer Functions

DRV_SDSPI_AsyncRead Function

Reads blocks of data from the specified block address of the SD Card.

C

```
void DRV_SDSPI_AsyncRead(const DRV_HANDLE handle, DRV_SDSPI_COMMAND_HANDLE* commandHandle,  
void* targetBuffer, uint32_t blockStart, uint32_t nBlocks);
```

Returns

The buffer handle is returned in the commandHandle argument. It will be [DRV_SDSPI_COMMAND_HANDLE_INVALID](#) if the request was not successful.

Description

This function schedules a non-blocking read operation for reading blocks of data from the SD Card. The function returns with a valid buffer handle in the commandHandle argument if the read request was scheduled successfully. The function adds the request to the hardware instance queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. The function returns [DRV_SDSPI_COMMAND_HANDLE_INVALID](#) in the commandHandle argument under the following circumstances:

- if the driver handle is invalid
- if the target buffer pointer is NULL
- if the number of blocks to be read is zero or more than the actual number of blocks available.
- Error during the read operation

Remarks

None.

Preconditions

The [DRV_SDSPI_Initialize](#) routine must have been called for the specified SDSPI driver instance.

[DRV_SDSPI_Open](#) must have been called to obtain a valid opened device handle.

Example

```
uint8_t myBuffer[MY_BUFFER_SIZE];  
  
// address should be block aligned.  
uint32_t blockStart = 0x00;  
uint32_t nBlock = 2;  
DRV_SDSPI_COMMAND_HANDLE commandHandle;  
MY_APP_OBJ myAppObj;  
  
// mySDSPIHandle is the handle returned  
// by the DRV_SDSPI_Open function.  
  
// Client registers an event handler with driver  
DRV_SDSPI_EventHandlerSet(mySDSPIHandle, APP_SDSPIEventHandler, (uintptr_t)&myAppObj);  
  
DRV_SDSPI_AsyncRead(mySDSPIHandle, &commandHandle, &myBuffer[0], blockStart, nBlock);  
  
if(commandHandle == DRV_SDMMC_COMMAND_HANDLE_INVALID)  
{  
    // Error handling here  
}  
else  
{  
    // Read Successfully queued  
}
```

```

// Event is received when
// the buffer is processed.

void APP_SD SPIEvent Handler(
    DRV_SD SPI_EVENT event,
    DRV_SD SPI_COMMAND_HANDLE commandHandle,
    uintptr_t contextHandle
)
{
    // contextHandle points to myAppObj.

    switch(event)
    {
        case DRV_SD SPI_EVENT_COMMAND_COMPLETE:

            // This means the data was transferred successfully
            break;

        case DRV_SD SPI_EVENT_COMMAND_ERROR:

            // Error handling here
            break;

        default:
            break;
    }
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the return buffer handle
targetBuffer	Buffer into which the data read from the SD Card will be placed
blockStart	Starting block address of the SD Card from where the read should begin.
nBlock	Total number of blocks to be read.

Function

```

void DRV_SD SPI_AsyncRead (
    const DRV_HANDLE handle,
    DRV_SD SPI_COMMAND_HANDLE* commandHandle,
    void* targetBuffer,
    uint32_t blockStart,
    uint32_t nBlocks
)

```

DRV_SD SPI_SyncRead Function

Reads blocks of data from the specified block address of the SD Card.

C

```

bool DRV_SD SPI_SyncRead(const DRV_HANDLE handle, void* targetBuffer, uint32_t blockStart,
uint32_t nBlock);

```

Returns

true - If the request was executed successfully.
 false - If there was an error executing the request.

Description

This function performs a blocking read operation to read blocks of data from the SD Card. The function returns true if the request was successfully executed; returns false otherwise. The function returns false under following conditions:

- if the driver handle is invalid
- if the target buffer pointer is NULL
- if the number of blocks to be read is zero or more than the actual number of blocks available.
- Error during the read operation

Remarks

None.

Preconditions

The [DRV_SDSPI_Initialize](#) routine must have been called for the specified SDSPI driver instance.

[DRV_SDSPI_Open](#) must have been called to obtain a valid opened device handle.

Example

```
#define MY_BUFFER_SIZE 1024
uint8_t myBuffer[MY_BUFFER_SIZE];

// Address must be block aligned.
uint32_t blockStart = 0x00;
uint32_t nBlock = 2;

// mySDSPIHandle is the handle returned by the DRV_SDSPI_Open function.

if (DRV_SDSPI_SyncRead(mySDSPIHandle, myBuffer, blockStart, nBlock) == true)
{
    // Read successful
}
else
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
targetBuffer	Buffer into which the data read from the SD Card will be placed
blockStart	Starting block address of the SD Card from where the read should begin.
nBlock	Total number of blocks to be read.

Function

```
bool DRV_SDSPI_SyncRead (
    const DRV_HANDLE handle,
    void* targetBuffer,
    uint32_t blockStart,
    uint32_t nBlock
)
```

DRV_SDSPI_Read Function

This routine provides interface to the file system to perform a media read operation in synchronous mode of the SDSPI driver.

C

```
void DRV_SDSPI_Read(const DRV_HANDLE handle, DRV_SDSPI_COMMAND_HANDLE* commandHandle, void*
targetBuffer, uint32_t blockstart, uint32_t nBlock);
```

Returns

The buffer handle is returned in the commandHandle argument. It will be [DRV_SDSPI_COMMAND_HANDLE_INVALID](#) if the request was not successful.

Description

This function is internally used by the file system.

Remarks

This function is internally used by the file system.

Preconditions

The [DRV_SDSPI_Initialize](#) routine must have been called.

The [DRV_SDSPI_Open](#) must have been called to obtain a valid opened device handle.

Example

None.

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the return buffer handle
targetBuffer	Buffer into which the data read from the SD Card will be placed
blockStart	Start block address of the SD Card from where the read should begin.
nBlock	Total number of blocks to be read.

Function

```
void DRV_SDSPI_Read
(
    const DRV_HANDLE handle,
    DRV_SDSPI_COMMAND_HANDLE* commandHandle,
    void* targetBuffer,
    uint32_t blockStart,
    uint32_t nBlock
)
```

DRV_SDSPI_SyncWrite Function

Writes blocks of data starting at the specified address of the SD Card.

C

```
bool DRV_SDSPI_SyncWrite(const DRV_HANDLE handle, void* sourceBuffer, uint32_t blockStart,
    uint32_t nBlock);
```

Returns

true - If the request was executed successfully.

false - If there was an error executing the request.

Description

This function performs a blocking write operation to write blocks of data to the SD Card. The function returns true if the request was successfully executed. The function returns false under the following circumstances:

- if the driver handle is invalid
- if the source buffer pointer is NULL
- if the number of blocks to be written is either zero or more than the number of blocks actually available

- if the SD card is write-protected
- if there was an error during the SD card write operation

Remarks

None.

Preconditions

The [DRV_SDSPI_Initialize](#) routine must have been called for the specified SDSPI driver instance.

[DRV_SDSPI_Open](#) routine must have been called to obtain a valid opened device handle.

Example

```
#define MY_BUFFER_SIZE          1024
uint8_t myBuffer[MY_BUFFER_SIZE];

// Address must be block aligned.
uint32_t blockStart = 0x00;
uint32_t nBlock = 2;

// mySDSPIHandle is the handle returned by the DRV_SDSPI_Open function.

if (DRV_SDSPI_SyncWrite(mySDSPIHandle, myBuffer, blockStart, nBlock) == true)
{
    // Write is successful
}
else
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
sourceBuffer	The source buffer containing data to be written to the SD Card.
blockStart	Starting block address of SD Card where the writes should begin.
nBlock	Total number of blocks to be written.

Function

```
bool DRV_SDSPI_SyncWrite(
    const DRV_HANDLE handle,
    void* sourceBuffer,
    uint32_t blockStart,
    uint32_t nBlock
)
```

DRV_SDSPI_AsyncWrite Function

Writes blocks of data starting at the specified address of the SD Card.

C

```
void DRV_SDSPI_AsyncWrite(const DRV_HANDLE handle, DRV_SDSPI_COMMAND_HANDLE* commandHandle,
    void* sourceBuffer, uint32_t blockStart, uint32_t nBlocks);
```

Returns

The buffer handle is returned in the commandHandle argument. It will be [DRV_SDSPI_COMMAND_HANDLE_INVALID](#) if the request was not queued successfully.

Description

This function performs a non-blocking write operation to write blocks of data to the SD Card. The function returns with a valid buffer handle in the commandHandle argument if the write request was scheduled successfully. The function adds the request to the hardware instance queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. The function returns [DRV_SDSPI_COMMAND_HANDLE_INVALID](#) in the commandHandle argument under the following circumstances:

- if the driver handle is invalid
- if the source buffer pointer is NULL
- if the number of blocks to be written is either zero or more than the number of blocks actually available
- if the SD card is write-protected
- if there was an error during the SD card write operation

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_SDSPI_EVENT_COMMAND_COMPLETE](#) event if the buffer was processed successfully or [DRV_SDSPI_EVENT_COMMAND_ERROR](#) event if the buffer was not processed successfully.

Remarks

None.

Preconditions

The [DRV_SDSPI_Initialize](#) routine must have been called for the specified SDSPI driver instance.

[DRV_SDSPI_Open](#) routine must have been called to obtain a valid opened device handle.

Example

```
uint8_t myBuffer[MY_BUFFER_SIZE];

// address should be block aligned.
uint32_t blockStart = 0x00;
uint32_t nBlock = 2;
DRV_SDSPI_COMMAND_HANDLE commandHandle;
MY_APP_OBJ myAppObj;

// mySDSPIHandle is the handle returned
// by the DRV_SDSPI_Open function.

// Client registers an event handler with driver
DRV_SDSPI_EventHandlerSet(mySDSPIHandle, APP_SDSPIEventHandler, (uintptr_t)&myAppObj);

DRV_SDSPI_AsyncWrite(mySDSPIHandle, &commandHandle, &myBuffer[0], blockStart, nBlock);

if(commandHandle == DRV_SDSPI_COMMAND_HANDLE_INVALID)
{
    // Error handling here
}

// Event is received when
// the buffer is processed.

void APP_SDSPIEventHandler(
    DRV_SDSPI_EVENT event,
    DRV_SDSPI_COMMAND_HANDLE commandHandle,
    uintptr_t contextHandle
)
{
    // contextHandle points to myAppObj.

    switch(event)
    {
        case DRV_SDSPI_EVENT_COMMAND_COMPLETE:

            // This means the data was transferred successfully
            break;
    }
}
```

```

    case DRV_SDSPI_EVENT_COMMAND_ERROR:
        // Error handling here
        break;

    default:
        break;
}
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function
commandHandle	Pointer to an argument that will contain the return buffer handle
sourceBuffer	The source buffer containing data to be written to the SD Card.
blockStart	Starting block address of SD Card where the writes should begin.
nBlock	Total number of blocks to be written.

Function

```

void DRV_SDSPI_AsyncWrite(
    const DRV_HANDLE handle,
    DRV_SDSPI_COMMAND_HANDLE* commandHandle,
    void* sourceBuffer,
    uint32_t blockStart,
    uint32_t nBlocks
)

```

DRV_SDSPI_Write Function

This routine provides interface to the file system to perform a media write operation in synchronous mode of the SDSPI driver.

C

```

void DRV_SDSPI_Write(const DRV_HANDLE handle, DRV_SDSPI_COMMAND_HANDLE* commandHandle, void*
sourceBuffer, uint32_t blockStart, uint32_t nBlock);

```

Returns

The buffer handle is returned in the commandHandle argument. It will be [DRV_SDSPI_COMMAND_HANDLE_INVALID](#) if the request was not successful.

Description

This function is internally used by the file system.

Remarks

This function is internally used by the file system.

Preconditions

The [DRV_SDSPI_Initialize](#) routine must have been called.

The [DRV_SDSPI_Open](#) must have been called to obtain a valid opened device handle.

Example

None.

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function

commandHandle	Pointer to an argument that will contain the return buffer handle
sourceBuffer	The source buffer containing data to be programmed to the SD Card.
blockStart	Start block address of SD Card where the writes should begin.
nBlock	Total number of blocks to be written.

Function

```
void DRV_SDSPI_Write
(
    const DRV_HANDLE handle,
    DRV_SDSPI_COMMAND_HANDLE* commandHandle,
    void* sourceBuffer,
    uint32_t blockStart,
    uint32_t nBlock
)
```

DRV_SDSPI_CommandStatusGet Function

Gets the current status of the command. For synchronous mode, the command status is only used by the file system.

C

```
DRV_SDSPI_COMMAND_STATUS DRV_SDSPI_CommandStatusGet(const DRV_HANDLE handle, const
DRV_SDSPI_COMMAND_HANDLE commandHandle);
```

Returns

A [DRV_SDSPI_COMMAND_STATUS](#) value describing the current status of the command. Returns [DRV_SDSPI_COMMAND_ERROR_UNKNOWN](#) if the client handle or the command handle is not valid.

Description

This routine gets the current status of the command. The application must use this routine where the status of a scheduled command needs to be polled on. The function may return [DRV_SDSPI_COMMAND_HANDLE_INVALID](#) in a case where the command handle has expired. A command handle expires when the internal buffer object is re-assigned to another read or write request. It is recommended that this function be called regularly in order to track the command status correctly.

The application can alternatively register an event handler to receive read or write operation completion events.

Remarks

This API may not be used in applications using the SDSPI Driver in synchronous mode.

Preconditions

The [DRV_SDSPI_Initialize](#) routine must have been called.

The [DRV_SDSPI_Open](#) must have been called to obtain a valid opened device handle.

A read or write request must have been submitted to the SDSPI driver.

Example

None.

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
commandHandle	Handle to the command whose status is to be known.

Function

```
DRV_SDSPI_COMMAND_STATUS DRV_SDSPI_CommandStatusGet
(
    const DRV_HANDLE handle,
```

```
const     DRV_SDSPI_COMMAND_HANDLE commandHandle
)
```

d) Status Functions

DRV_SDSPI_IsAttached Function

Returns the physical attach status of the SD Card.

C

```
bool DRV_SDSPI_IsAttached(const DRV_HANDLE handle);
```

Returns

true - If the SD Card is attached and initialized by the SDSPI driver.

false - If the handle is invalid

Description

This function returns the physical attach status of the SD Card.

Remarks

None.

Preconditions

The [DRV_SDSPI_Initialize](#) routine must have been called for the specified SDSPI driver instance.

The [DRV_SDSPI_Open](#) routine must have been called to obtain a valid opened device handle.

Example

```
bool isSDSPIAttached;

// mySDSPIHandle is the handle returned by the DRV_SDSPI_Open function.
isSDSPIAttached = DRV_SDSPI_IsAttached(mySDSPIHandle);

if (isSDSPIAttached == true)
{
    // SD Card is attached and initialized by the SDSPI driver.
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function

Function

```
bool DRV_SDSPI_IsAttached
(
const     DRV_HANDLE handle
)
```

DRV_SDSPI_IsWriteProtected Function

Returns the write protect status of the SD Card.

C

```
bool DRV_SDSPI_IsWriteProtected(const DRV_HANDLE handle);
```

Returns

true - If the attached SD Card is write protected. If the configured write protect GPIO pin is read High by the driver then the card is write protected. The status of the write protect GPIO pin is read by the driver during the media (SD Card) initialization.
 false - If the handle is not valid, or if the SD Card is not write protected.

Description

This function returns true if the SD Card is write protected otherwise it returns false.

Remarks

None.

Preconditions

The [DRV_SDSPI_Initialize](#) routine must have been called for the specified SDSPI driver instance.
 The [DRV_SDSPI_Open](#) routine must have been called to obtain a valid opened device handle.

Example

```
bool isWriteProtected;
// mySDSPIHandle is the handle returned by the DRV_SDSPI_Open function.
isWriteProtected = DRV_SDSPI_IsWriteProtected(mySDSPIHandle);

if (isWriteProtected == true)
{
    //SD Card is write protected.
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function

Function

```
bool DRV_SDSPI_IsWriteProtected
(
const    DRV_HANDLE handle
)
```

DRV_SDSPI_GeometryGet Function

Returns the geometry of the device.

C

```
SYS_MEDIA_GEOMETRY * DRV_SDSPI_GeometryGet(const DRV_HANDLE handle);
```

Returns

[SYS_MEDIA_GEOMETRY](#) - Pointer to structure which holds the media geometry information.

Description

This API gives the following geometrical details of the SD Card.

- Media Property
- Number of Read/Write/Erase regions in the SD Card
- Number of Blocks and their size in each region of the device

Remarks

Refer to the "system/system_media.h" for the declaration of the [SYS_MEDIA_GEOMETRY](#) structure.

Preconditions

The `DRV_SDSPI_Initialize` routine must have been called for the specified SDSPI driver instance.

The `DRV_SDSPI_Open` routine must have been called to obtain a valid opened device handle.

Example

```

SYS_MEDIA_GEOMETRY * SDSPIGeometry;
uint32_t readBlockSize, writeBlockSize, eraseBlockSize;
uint32_t nReadBlocks, nReadRegions, totalSize;

// mySDSPIHandle is the handle returned by the DRV_SDSPI_Open function.
SDSPIGeometry = DRV_SDSPI_GeometryGet(mySDSPIHandle);

readBlockSize = SDSPIGeometry->geometryTable->blockSize;
nReadBlocks = SDSPIGeometry->geometryTable->numBlocks;
nReadRegions = SDSPIGeometry->numReadRegions;

writeBlockSize = (SDSPIGeometry->geometryTable +1)->blockSize;
eraseBlockSize = (SDSPIGeometry->geometryTable +2)->blockSize;

totalSize = readBlockSize * nReadBlocks * nReadRegions;

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open function

Function

```

SYS_MEDIA_GEOMETRY* DRV_SDSPI_GeometryGet
(
  const DRV_HANDLE handle
)

```

e) Data Types and Constants

DRV_SDSPI_COMMAND_HANDLE Type

C

```
typedef SYS_MEDIA_BLOCK_COMMAND_HANDLE DRV_SDSPI_COMMAND_HANDLE;
```

Description

This is type `DRV_SDSPI_COMMAND_HANDLE`.

DRV_SDSPI_COMMAND_STATUS Enumeration

C

```

typedef enum {
  DRV_SDSPI_COMMAND_COMPLETED = SYS_MEDIA_COMMAND_COMPLETED,
  DRV_SDSPI_COMMAND_QUEUED = SYS_MEDIA_COMMAND_QUEUED,
  DRV_SDSPI_COMMAND_IN_PROGRESS = SYS_MEDIA_COMMAND_IN_PROGRESS,
  DRV_SDSPI_COMMAND_ERROR_UNKNOWN = SYS_MEDIA_COMMAND_UNKNOWN
} DRV_SDSPI_COMMAND_STATUS;

```

Members

Members	Description
DRV_SDSPI_COMMAND_COMPLETED = SYS_MEDIA_COMMAND_COMPLETED	Done OK and ready
DRV_SDSPI_COMMAND_QUEUED = SYS_MEDIA_COMMAND_QUEUED	Scheduled but not started
DRV_SDSPI_COMMAND_IN_PROGRESS = SYS_MEDIA_COMMAND_IN_PROGRESS	Currently being in transfer
DRV_SDSPI_COMMAND_ERROR_UNKNOWN = SYS_MEDIA_COMMAND_UNKNOWN	Unknown Command

Description

This is type DRV_SDSPI_COMMAND_STATUS.

DRV_SDSPI_EVENT Enumeration

Identifies the possible events that can result from a request.

C

```
typedef enum {
    DRV_SDSPI_EVENT_COMMAND_COMPLETE = SYS_MEDIA_EVENT_BLOCK_COMMAND_COMPLETE,
    DRV_SDSPI_EVENT_COMMAND_ERROR = SYS_MEDIA_EVENT_BLOCK_COMMAND_ERROR
} DRV_SDSPI_EVENT;
```

Members

Members	Description
DRV_SDSPI_EVENT_COMMAND_COMPLETE = SYS_MEDIA_EVENT_BLOCK_COMMAND_COMPLETE	Operation has been completed successfully.
DRV_SDSPI_EVENT_COMMAND_ERROR = SYS_MEDIA_EVENT_BLOCK_COMMAND_ERROR	There was an error during the operation

Description

SDSPI Driver Events

This enumeration identifies the possible events that can result from a read or a write request issued by the client.

Remarks

One of these values is passed in the "event" parameter of the event handling callback function that client registered with the driver by calling the [DRV_SDSPI_EventHandlerSet](#) function when a request is completed.

DRV_SDSPI_EVENT_HANDLER Type

Pointer to a SDSPI Driver Event handler function

C

```
typedef SYS_MEDIA_EVENT_HANDLER DRV_SDSPI_EVENT_HANDLER;
```

Returns

None.

Description

SDSPI Driver Event Handler Function Pointer

This data type defines the required function signature for the SDSPI event handling callback function. A client must register a pointer to an event handling function whose function signature (parameter and return value types) match the types specified by

this function pointer in order to receive event calls back from the driver.

The parameters and return values are described here and a partial example implementation is provided.

Remarks

If the event is DRV_SDSPI_EVENT_COMMAND_COMPLETE, it means that the write or a erase operation was completed successfully.

If the event is DRV_SDSPI_EVENT_COMMAND_ERROR, it means that the scheduled operation was not completed successfully.

The context parameter contains the handle to the client context, provided at the time the event handling function was registered using the [DRV_SDSPI_EventHandlerSet](#) function. This context handle value is passed back to the client as the "context" parameter. It can be any value necessary to identify the client context or instance (such as a pointer to the client's data) instance of the client that made the read/write/erase request.

Example

```
void APP_MySDSPIEventHandler
(
    DRV_SDSPI_EVENT event,
    DRV_SDSPI_COMMAND_HANDLE commandHandle,
    uintptr_t context
)
{
    MY_APP_DATA_STRUCT* pAppData = (MY_APP_DATA_STRUCT*) context;

    switch(event)
    {
        case DRV_SDSPI_EVENT_COMMAND_COMPLETE:

            // Handle the completed buffer.
            break;

        case DRV_SDSPI_EVENT_COMMAND_ERROR:
        default:

            // Handle error.
            break;
    }
}
```

Parameters

Parameters	Description
event	Identifies the type of event
commandHandle	Handle returned from the Read/Write requests
context	Value identifying the context of the application that registered the event handling function

DRV_SDSPI_COMMAND_HANDLE_INVALID Macro

SDSPI Driver's Invalid Command Handle.

C

```
#define DRV_SDSPI_COMMAND_HANDLE_INVALID SYS_MEDIA_BLOCK_COMMAND_HANDLE_INVALID
```

Description

SDSPI Driver Invalid Command Handle.

This value defines the SDSPI Driver Invalid Command Handle. This value is returned by read or write routines when the command request was not accepted.

Remarks

None.

SPI EEPROM Driver Libraries Help

This section describes the SPI EEPROM based driver libraries.

AT25 Driver Library Help

This section describes the AT25 External EEPROM driver library.

Introduction

This driver provides an interface to access the external AT25 EEPROM over the SPI interface.

Description

This library provides a non-blocking interface to read and write to the external AT25 EEPROM. The library uses the SPI peripheral library (PLIB) to interface with the AT25 EEPROM.

Key Features:

- Supports a single instance of the AT25 EEPROM and a single client to the driver
- Supports page writes
- Supports writes to random memory address and across page boundaries
- The library interface is compliant to the block media interface expected by the Memory Driver. This allows running a file system on the AT25 EEPROM using the Memory Driver and the File System Service
- The library can be used in both bare-metal and RTOS environments

Using the Library

This section describes the basic architecture of the AT25 Library and provides information on how to use the library.

Description

The AT25 library provides non-blocking APIs to read and write to external AT25 EEPROM. It uses the SPI peripheral library to interface with the AT25 EEPROM.

- The library provides APIs to perform reads/writes from/to any EEPROM memory address, with number of bytes spanning multiple pages
- The library provides API to perform page write to EEPROM. Here, the memory start address must be aligned to the EEPROM page boundary
- Application can either register a callback to get notified once the data transfer is complete or can poll the status of the data transfer
- The library interface complies to the block driver interface expected by the Memory Driver. This allows application to run a file system on the AT25 EEPROM media using the Memory Driver and the File System Service
- The library can be used in both bare-metal and RTOS environments

Abstraction Model

This library provides a low-level abstraction of the AT25 EEPROM Driver Library with a convenient C language interface.

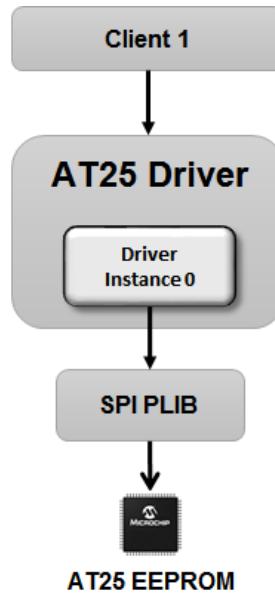
Description

The AT25 library interface provides read and write functions that abstract out the internal workings of the AT25 driver and the underlying SPI protocol. The AT25 library supports a single instance of the AT25 EEPROM and a single client.

The client can be:

- Application - Directly access the AT25 EEPROM using the APIs provided by the AT25 library
- Memory Driver - Application can run a file system on the AT25 EEPROM by connecting it to the Memory Driver which can

further be connected to the File System Service



How the Library Works

This section provides information on how the AT25 driver library works.

Description

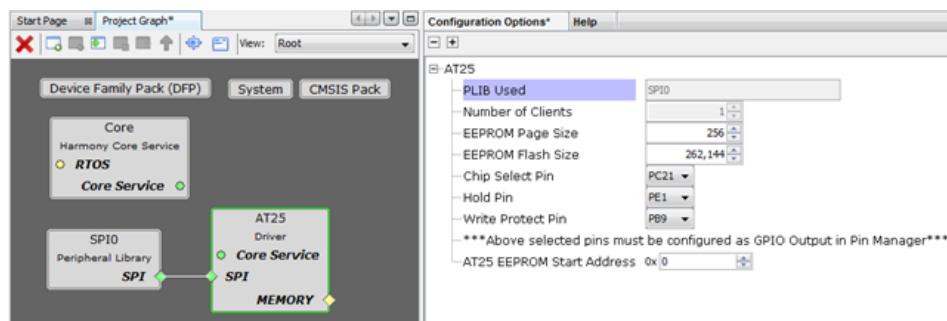
- The AT25 Driver Library registers an event handler with the underlying SPI peripheral library (PLIB). This event handler is called by the PLIB from the interrupt context to notify the AT25 driver that the requested transfer is complete
- The library's state machine is driven from the interrupt context. Once a transfer is complete a callback (if registered by the application) is given to the application from the interrupt context
- The library does not support queuing of more than one requests. The application must check and ensure that any previous request is completed before submitting a new one. This can be done either by polling the status of the data transfer or registering a callback

Configuring the Library

This section provides information on how to configure the AT25 Driver library.

Description

AT25 Driver library should be configured via the MHC. Below is the snapshot of the MHC configuration window for configuring the AT25 driver and a brief description of various configuration options.



User Configurations:

- **PLIB Used:**
 - Indicates the SPI peripheral instance used by the AT25 driver
- **Number of Clients:**
 - Indicates maximum number of clients
 - Always set to one as it supports only a single client
- **EEPROM Page Size:**
 - Size of one page of EEPROM memory (in bytes)
- **EEPROM Flash Size:**
 - Total size of the EEPROM memory (in bytes)
 - Depending on the specified EEPROM Flash Size, the driver will generate the appropriate number of address bits (8-bit, 16-bit or 24-bit), thereby allowing it to communicate with EEPROM of different sizes in the AT25 family
- **Chip Select Pin:**
 - EEPROM chip select pin (active low)
 - This pin must be configured as GPIO output in "Pin Settings" configuration
- **Hold Pin:**
 - EEPROM hold pin (active low)
 - This pin must be configured as GPIO output in "Pin Settings" configuration
- **Write Protect Pin:**
 - EEPROM write protect pin (active low).
 - This pin must be configured as GPIO output in "Pin Settings" configuration.
 - The AT25 driver keeps the Write Protect pin in logic high state, which means writes are always allowed
- **AT25 EEPROM Start Address:**
 - The EEPROM memory start address.
 - This is mainly used when the AT25 driver is connected to the Memory Block Driver

Building the Library

This section provides information on how the AT25 Driver Library can be built.

Description



All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

Library Interface

a) System Functions

	Name	Description
≡	DRV_AT25_Initialize	Initializes the AT25 EEPROM device
≡	DRV_AT25_Status	Gets the current status of the AT25 driver module.

b) Core Client Functions

	Name	Description
≡	DRV_AT25_Open	Opens the specified AT25 driver instance and returns a handle to it.
≡	DRV_AT25_Close	Closes the opened-instance of the AT25 driver.
≡	DRV_AT25_EventHandlerSet	Allows a client to identify a transfer event handling function for the driver to call back when the requested transfer has finished.

c) Data Transfer Functions

	Name	Description
≡	DRV_AT25_Read	Reads 'n' bytes of data from the specified start address of EEPROM.
≡	DRV_AT25_Write	Writes 'n' bytes of data starting at the specified address.
≡	DRV_AT25_PageWrite	Writes one page of data starting at the specified address.
≡	DRV_AT25_TransferStatusGet	Gets the current status of the transfer request.

d) Block Interface Functions

	Name	Description
≡	DRV_AT25_GeometryGet	Returns the geometry of the device.

e) Data Types and Constants

	Name	Description
	DRV_AT25_GEOMETRY	Defines the data type for AT25 EEPROM Geometry details.
	DRV_AT25_TRANSFER_STATUS	Defines the data type for AT25 Driver transfer status.
	DRV_AT25_EVENT_HANDLER	Pointer to a AT25 Driver Event handler function

Description

This section describes the API functions of the AT25 Driver library.

Refer to each section for a detailed description.

a) System Functions

DRV_AT25_Initialize Function

Initializes the AT25 EEPROM device

C

```
SYS_MODULE_OBJ DRV_AT25_Initialize(const SYS_MODULE_INDEX drvIndex, const SYS_MODULE_INIT *  
const init);
```

Returns

If successful, returns a valid handle to a driver instance object. Otherwise, returns [SYS_MODULE_OBJ_INVALID](#).

Description

This routine initializes the AT25 EEPROM device driver making it ready for clients to open and use. The initialization data is specified by the init parameter. It is a single instance driver, so this API should be called only once.

Remarks

This routine must be called before any other DRV_AT25 routine is called. This routine should only be called once during system initialization.

Preconditions

None.

Example

```
SYS_MODULE_OBJ sysObjDrvAT25;  
  
DRV_AT25_PLIB_INTERFACE drvAT25PlibAPI = {  
    .writeRead = (DRV_AT25_PLIB_WRITE_READ)SPI0_WriteRead,  
    .write = (DRV_AT25_PLIB_WRITE)SPI0_Write,  
    .read = (DRV_AT25_PLIB_READ)SPI0_Read,  
    .isBusy = (DRV_AT25_PLIB_IS_BUSY)SPI0_IsBusy,
```

```

.callbackRegister = (DRV_AT25_PLIB_CALLBACK_REGISTER)SPI0_CallbackRegister,
};

DRV_AT25_INIT drvAT25InitData = {
    .spiPlib = &drvAT25PlibAPI,
    .numClients = DRV_AT25_CLIENTS_NUMBER_IDX,
    .pageSize = DRV_AT25_EEPROM_PAGE_SIZE,
    .flashSize = DRV_AT25_EEPROM_FLASH_SIZE,
    .blockStartAddress = 0x0,
    .chipSelectPin = DRV_AT25_CHIP_SELECT_PIN_IDX,
    .holdPin = DRV_AT25_HOLD_PIN_IDX,
    .writeProtectPin = DRV_AT25_WP_PIN_IDX,
};

sysObjDrvAT25 = DRV_AT25_Initialize(DRV_AT25_INDEX, (SYS_MODULE_INIT *)&drvAT25InitData);

```

Parameters

Parameters	Description
drvIndex	Identifier for the instance to be initialized.
init	Pointer to the init data structure containing any data necessary to initialize the driver.

Function

```

SYS_MODULE_OBJ DRV_AT25_Initialize(
    const SYS_MODULE_INDEX drvIndex,
    const SYS_MODULE_INIT * const init
)

```

DRV_AT25_Status Function

Gets the current status of the AT25 driver module.

C

```
SYS_STATUS DRV_AT25_Status(const SYS_MODULE_INDEX drvIndex);
```

Returns

SYS_STATUS_READY - Indicates that the driver is ready and accept requests for new operations.

SYS_STATUS_UNINITIALIZED - Indicates the driver is not initialized.

Description

This routine provides the current status of the AT25 driver module.

Remarks

None.

Preconditions

Function [DRV_AT25_Initialize](#) should have been called before calling this function.

Example

```

SYS_STATUS status;

status = DRV_AT25_Status(DRV_AT25_INDEX);

```

Parameters

Parameters	Description
drvIndex	Identifier for the instance used to initialize driver

Function

`SYS_STATUS DRV_AT25_Status(const SYS_MODULE_INDEX drvIndex)`

b) Core Client Functions

DRV_AT25_Open Function

Opens the specified AT25 driver instance and returns a handle to it.

C

`DRV_HANDLE DRV_AT25_Open(const SYS_MODULE_INDEX drvIndex, const DRV_IO_INTENT ioIntent);`

Returns

If successful, the routine returns a valid open-instance handle (a number identifying both the caller and the module instance).

If an error occurs, the return value is `DRV_HANDLE_INVALID`. Error can occur

- if the driver has been already opened once and in use.
- if the driver instance being opened is not initialized or is invalid.

Description

This routine opens the specified AT25 driver instance and provides a handle that must be provided to all other client-level operations to identify the caller and the instance of the driver. The `ioIntent` parameter defines how the client interacts with this driver instance.

This driver is a single client driver, so `DRV_AT25_Open` API should be called only once until driver is closed.

Remarks

This driver ignores the `ioIntent` argument.

The handle returned is valid until the `DRV_AT25_Close` routine is called.

Preconditions

Function `DRV_AT25_Initialize` must have been called before calling this function.

Example

```
DRV_HANDLE handle;

handle = DRV_AT25_Open(DRV_AT25_INDEX, DRV_IO_INTENT_READWRITE);
if (handle == DRV_HANDLE_INVALID)
{
    // Unable to open the driver
    // May be the driver is not initialized
}
```

Parameters

Parameters	Description
<code>drvIndex</code>	Identifier for the object instance to be opened
<code>ioIntent</code>	Zero or more of the values from the enumeration <code>DRV_IO_INTENT</code> "ORed" together to indicate the intended use of the driver.

Function

```
DRV_HANDLE DRV_AT25_Open
(
    const SYS_MODULE_INDEX drvIndex,
    const DRV_IO_INTENT ioIntent
)
```

DRV_AT25_Close Function

Closes the opened-instance of the AT25 driver.

C

```
void DRV_AT25_Close(const DRV_HANDLE handle);
```

Returns

None.

Description

This routine closes opened-instance of the AT25 driver, invalidating the handle. A new handle must be obtained by calling [DRV_AT25_Open](#) before the caller may use the driver again.

Remarks

None.

Preconditions

[DRV_AT25_Open](#) must have been called to obtain a valid opened device handle.

Example

```
// 'handle', returned from the DRV_AT25_Open
DRV_AT25_Close(handle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
void DRV_AT25_Close( const DRV_Handle handle )
```

DRV_AT25_EventHandlerSet Function

Allows a client to identify a transfer event handling function for the driver to call back when the requested transfer has finished.

C

```
void DRV_AT25_EventHandlerSet(const DRV_HANDLE handle, const DRV_AT25_EVENT_HANDLER
eventHandler, const uintptr_t context);
```

Returns

None.

Description

This function allows a client to register a transfer event handling function with the driver to call back when the requested transfer has finished.

The event handler should be set before the client submits any transfer requests that could generate events. The event handler once set, persists until the client closes the driver or sets another event handler (which could be a "NULL" pointer to indicate no callback).

Remarks

If the client does not want to be notified when the queued buffer transfer has completed, it does not need to register a callback.

Preconditions

[DRV_AT25_Open](#) must have been called to obtain a valid opened device handle.

Example

```

#define BUFFER_SIZE 256
#define MEM_ADDRESS 0x00

// myAppObj is an application specific state data object.
MY_APP_OBJ myAppObj;

uint8_t myBuffer[BUFFER_SIZE];

// myHandle is the handle returned from DRV_AT25_Open API.

// Client registers an event handler with driver. This is done once

DRV_AT25_EventHandlerSet( myHandle, APP_AT25TransferEventHandler, (uintptr_t)&myAppObj );

if (DRV_AT25_Read(myHandle, myBuffer, BUFFER_SIZE, MEM_ADDRESS) == false)
{
    // Error handling here
}

// The registered event handler is called when the request is complete.

void APP_AT25TransferEventHandler(DRV_AT25_TRANSFER_STATUS event, uintptr_t context)
{
    // The context handle was set to an application specific
    // object. It is now retrievable easily in the event handler.
    MY_APP_OBJ* pMyAppObj = (MY_APP_OBJ *) context;

    switch(event)
    {
        case DRV_AT25_TRANSFER_STATUS_COMPLETED:
            // This means the data was transferred.
            break;

        case DRV_AT25_TRANSFER_STATUS_ERROR:
            // Error handling here.
            break;

        default:
            break;
    }
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine.
eventHandler	Pointer to the event handler function.
context	The value of parameter will be passed back to the client unchanged, when the eventHandler function is called. It can be used to identify any client specific data object that identifies the instance of the client module (for example, it may be a pointer to the client module's state structure).

Function

```

void DRV_AT25_EventHandlerSet(
    const DRV_HANDLE handle,
    const DRV_AT25_EVENT_HANDLER eventHandler,
    const uintptr_t context
)

```

c) Data Transfer Functions

DRV_AT25_Read Function

Reads 'n' bytes of data from the specified start address of EEPROM.

C

```
bool DRV_AT25_Read(const DRV_HANDLE handle, void * rxData, uint32_t rxDataLength, uint32_t address);
```

Returns

false

- if handle is invalid
- if the pointer to the receive buffer is NULL or number of bytes to read is 0
- if the driver is busy handling another transfer request

true

- if the read request is accepted.

Description

This function schedules a non-blocking read operation for the requested number of data bytes from the given address of the EEPROM.

The requesting client should call [DRV_AT25_TransferStatusGet](#) API to know the current status of the request OR the requesting client can register a callback function with the driver to get notified of the status.

Remarks

None.

Preconditions

[DRV_AT25_Open](#) must have been called to obtain a valid opened device handle.

Example

```
#define BUFFER_SIZE 1024
#define MEM_ADDRESS 0x00

uint8_t readBuffer[BUFFER_SIZE];

// myHandle is the handle returned from DRV_AT25_Open API.
// In the below example, the transfer status is polled. However, application can
// register a callback and get notified when the transfer is complete.

if (DRV_AT25_Read(myHandle, readBuffer, BUFFER_SIZE, MEM_ADDRESS) != true)
{
    // Error handling here
}
else
{
    // Wait for read to be completed
    while(DRV_AT25_TransferStatusGet(myHandle) == DRV_AT25_TRANSFER_STATUS_BUSY);
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
rxData	Buffer pointer into which the data read from the DRV_AT25 Flash memory will be placed.

rxDataLength	Total number of bytes to be read.
address	Memory start address from where the data should be read.

Function

```
bool DRV_AT25_Read(const DRV_HANDLE handle, void *rxData, uint32_t rxDataLength, uint32_t address )
```

DRV_AT25_Write Function

Writes 'n' bytes of data starting at the specified address.

C

```
bool DRV_AT25_Write(const DRV_HANDLE handle, void * txData, uint32_t txDataLength, uint32_t address );
```

Returns

false

- if handle is invalid
- if the pointer to transmit buffer is NULL or number of bytes to write is 0
- if the driver is busy handling another transfer request

true

- if the write request is accepted.

Description

This function schedules a non-blocking write operation for writing txDataLength bytes of data starting from given address of EEPROM.

The requesting client should call [DRV_AT25_TransferStatusGet](#) API to know the current status of the request OR the requesting client can register a callback function with the driver to get notified of the status.

Remarks

None.

Preconditions

[DRV_AT25_Open](#) must have been called to obtain a valid opened device handle.

Example

```
#define PAGE_SIZE 256
#define BUFFER_SIZE 1024
#define MEM_ADDRESS 0x00

uint8_t writeBuffer[BUFFER_SIZE];

// myHandle is the handle returned from DRV_AT25_Open API.
// In the below example, the transfer status is polled. However, application can
// register a callback and get notified when the transfer is complete.

if (DRV_AT25_Write(myHandle, writeBuffer, BUFFER_SIZE, MEM_ADDRESS) != true)
{
    // Error handling here
}
else
{
    // Wait for write to be completed
    while(DRV_AT25_TransferStatusGet(myHandle) == DRV_AT25_TRANSFER_STATUS_BUSY);
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

txData	The source buffer containing data to be programmed into AT25 EEPROM
txDataLength	Total number of bytes to be written.
address	Memory start address from where the data should be written

Function

```
bool DRV_AT25_Write(const DRV_HANDLE handle, void *txData, uint32_t txDataLength, uint32_t address)
```

DRV_AT25_PageWrite Function

Writes one page of data starting at the specified address.

C

```
bool DRV_AT25_PageWrite(const DRV_HANDLE handle, void * txData, uint32_t address);
```

Returns

false

- if handle is invalid
- if the pointer to the transmit data is NULL
- if the driver is busy handling another transfer request

true

- if the write request is accepted.

Description

This function schedules a non-blocking write operation for writing one page of data starting from the given address of the EEPROM.

The requesting client should call [DRV_AT25_TransferStatusGet](#) API to know the current status of the request OR the requesting client can register a callback function with the driver to get notified of the status.

Remarks

None.

Preconditions

[DRV_AT25_Open](#) must have been called to obtain a valid opened device handle.

"address" provided must be page boundary aligned in order to avoid overwriting the data in the beginning of the page.

Example

```
#define PAGE_SIZE 256
#define MEM_ADDRESS 0x0

uint8_t writeBuffer[PAGE_SIZE];

// myHandle is the handle returned from DRV_AT25_Open API.
// In the below example, the transfer status is polled. However, application can
// register a callback and get notified when the transfer is complete.

if (DRV_AT25_PageWrite(myHandle, writeBuffer, MEM_ADDRESS) != true)
{
    // Error handling here
}
else
{
    // Wait for write to be completed
    while(DRV_AT25_TransferStatusGet(myHandle) == DRV_AT25_TRANSFER_STATUS_BUSY);
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
txData	The source buffer containing data to be written to the AT25 EEPROM
address	Write memory start address from where the data should be written. It must be page boundary aligned in order to avoid overwriting the data in the beginning of the page.

Function

```
bool DRV_AT25_PageWrite(const DRV_HANDLE handle, void *txData, uint32_t address)
```

DRV_AT25_TransferStatusGet Function

Gets the current status of the transfer request.

C

```
DRV_AT25_TRANSFER_STATUS DRV_AT25_TransferStatusGet(const DRV_HANDLE handle);
```

Returns

One of the status element from the enum [DRV_AT25_TRANSFER_STATUS](#).

Description

This routine gets the current status of the transfer request.

Remarks

None.

Preconditions

[DRV_AT25_PageWrite](#), [DRV_AT25_Write](#) or [DRV_AT25_Read](#) must have been called to obtain the status of transfer.

Example

```
// myHandle is the handle returned from DRV_AT25_Open API.

if (DRV_AT25_TransferStatusGet(myHandle) == DRV_AT25_TRANSFER_STATUS_COMPLETED)
{
    // Operation Done
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
DRV_AT25_TRANSFER_STATUS DRV_AT25_TransferStatusGet(const DRV_HANDLE handle)
```

d) Block Interface Functions

DRV_AT25_GeometryGet Function

Returns the geometry of the device.

C

```
bool DRV_AT25_GeometryGet(const DRV_HANDLE handle, DRV_AT25_GEOMETRY * geometry);
```

Returns

- false
- if handle is invalid
- true
- if able to get the geometry details of the flash

Description

This API gives the following geometrical details of the DRV_AT25 Flash:

- Number of Read/Write/Erase Blocks and their size in each region of the device

Remarks

None.

Preconditions

[DRV_AT25_Open](#) must have been called to obtain a valid opened device handle.

Example

```
DRV_AT25_GEOMETRY eepromGeometry;
uint32_t readBlockSize, writeBlockSize, eraseBlockSize;
uint32_t nReadBlocks, nReadRegions, totalFlashSize;

// myHandle is the handle returned from DRV\_AT25\_Open API.

DRV_AT25_GeometryGet(myHandle, &eepromGeometry);

readBlockSize = eepromGeometry.readBlockSize;
nReadBlocks = eepromGeometry.readNumBlocks;
nReadRegions = eepromGeometry.readNumRegions;

writeBlockSize = eepromGeometry.writeBlockSize;
eraseBlockSize = eepromGeometry.eraseBlockSize;

totalFlashSize = readBlockSize * nReadBlocks * nReadRegions;
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
geometry	Pointer to flash device geometry table instance

Function

bool DRV_AT25_GeometryGet(const [DRV_HANDLE](#) handle, [DRV_AT25_GEOMETRY](#) *geometry)

e) Data Types and Constants

[DRV_AT25_GEOMETRY](#) Structure

Defines the data type for AT25 EEPROM Geometry details.

C

```
typedef struct {
    uint32_t readBlockSize;
    uint32_t readNumBlocks;
    uint32_t readNumRegions;
    uint32_t writeBlockSize;
    uint32_t writeNumBlocks;
```

```

    uint32_t writeNumRegions;
    uint32_t eraseBlockSize;
    uint32_t eraseNumBlocks;
    uint32_t eraseNumRegions;
    uint32_t blockStartAddress;
} DRV_AT25_GEOMETRY;

```

Description

DRV_AT25 Geometry data

This will be used to get the geometry details of the attached AT25 EEPROM device.

Remarks

None.

DRV_AT25_TRANSFER_STATUS Enumeration

Defines the data type for AT25 Driver transfer status.

C

```

typedef enum {
    DRV_AT25_TRANSFER_STATUS_BUSY,
    DRV_AT25_TRANSFER_STATUS_COMPLETED,
    DRV_AT25_TRANSFER_STATUS_ERROR
} DRV_AT25_TRANSFER_STATUS;

```

Members

Members	Description
DRV_AT25_TRANSFER_STATUS_BUSY	Transfer is being processed
DRV_AT25_TRANSFER_STATUS_COMPLETED	Transfer is successfully completed
DRV_AT25_TRANSFER_STATUS_ERROR	Transfer had error

Description

DRV_AT25 Transfer Status

This will be used to indicate the current transfer status of the AT25 EEPROM driver operations.

Remarks

None.

DRV_AT25_EVENT_HANDLER Type

Pointer to a AT25 Driver Event handler function

C

```

typedef void (* DRV_AT25_EVENT_HANDLER)(DRV_AT25_TRANSFER_STATUS event, uintptr_t context);

```

Returns

None.

Description

AT25 Driver Transfer Event Handler Function Pointer

This data type defines the required function signature for the AT25 driver event handling callback function. A client must register a pointer using the event handling function whose function signature (parameter and return value types) match the types specified by this function pointer in order to receive transfer related event calls back from the driver.

The parameters and return values are described here and a partial example implementation is provided.

Remarks

If the event is DRV_AT25_TRANSFER_STATUS_COMPLETED, it means that the data was transferred successfully.

If the event is DRV_AT25_TRANSFER_STATUS_ERROR, it means that the data was not transferred successfully.

The context parameter contains the handle to the client context, provided at the time the event handling function was registered using the [DRV_AT25_EventHandlerSet](#) function. This context handle value is passed back to the client as the "context" parameter. It can be any value necessary to identify the client context or instance (such as a pointer to the client's data) instance of the client that made the buffer add request.

The event handler function executes in the driver's interrupt context. It is recommended of the application to not perform process intensive or blocking operations with in this function.

The [DRV_AT25_Read](#), [DRV_AT25_Write](#) and [DRV_AT25_PageWrite](#) functions can be called in the event handler to submit a request to the driver.

Example

```
void APP_MyTransferEventHandler( DRV_AT25_TRANSFER_STATUS event, uintptr_t context )
{
    MY_APP_DATA_STRUCT* pAppData = (MY_APP_DATA_STRUCT*) context;

    switch(event)
    {
        case DRV_AT25_TRANSFER_STATUS_COMPLETED:
            // Handle the transfer complete event.
            break;

        case DRV_AT25_TRANSFER_STATUS_ERROR:
        default:
            // Handle error.
            break;
    }
}
```

Parameters

Parameters	Description
event	Identifies the type of event
context	Value identifying the context of the application that registered the event handling function.

SPI Driver Library Help

This section describes the SPI driver library.

Introduction

This driver provides an interface to manage the Serial Peripheral Interface (SPI) module.

Description

The SPI Driver is a multi-client, multi-instance buffer model based driver interface which can be used to communicate with various slave devices like EEPROM, ADC etc.

Key Features of SPI Driver:

- Multi Client:** Each instance of SPI driver can have multiple clients. This means the SPI driver supports multiple slaves connected to the same SPI bus.
- Multi Instance:** Provides interface to manage multiple instances of SPI peripheral.
- Supports Asynchronous and Synchronous modes of operation.
- Supports Bare Metal and RTOS environments.

5. Supports DMA.

Using the Library

This section describes the basic architecture of the SPI Driver Library and provides information on its use.

Description

The SPI Driver can be used in 2 different modes:

1. Asynchronous Mode.
2. Synchronous Mode.

The following table describes which function is supported in which mode of SPI Driver:

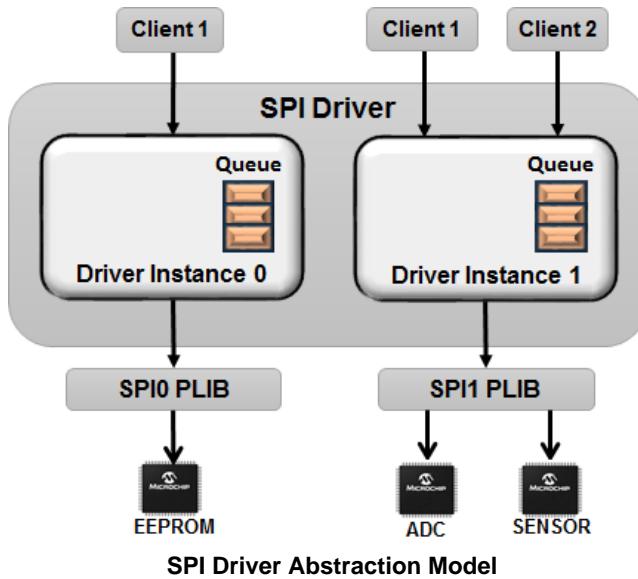
Functions	Asynchronous Mode	Synchronous Mode
DRV_SPI_Initialize	Yes	Yes
DRV_SPI_Status	Yes	Yes
DRV_SPI_Open	Yes	Yes
DRV_SPI_Close	Yes	Yes
DRV_SPI_TransferSetup	Yes	Yes
DRV_SPI_WriteReadTransferAdd	Yes	No
DRV_SPI_WriteTransferAdd	Yes	No
DRV_SPI_ReadTransferAdd	Yes	No
DRV_SPI_TransferEventHandlerSet	Yes	No
DRV_SPI_TransferStatusGet	Yes	No
DRV_SPI_WriteTransfer	No	Yes
DRV_SPI_ReadTransfer	No	Yes
DRV_SPI_WriteReadTransfer	No	Yes

Abstraction Model

This section describes how the abstraction is modeled in software and introduces the library's interface.

Description

The SPI driver provides interface to use multiple SPI Peripherals (via SPI PLIB instances) connected with one or multiple slave devices.



Note: Queue is not present in Synchronous mode of the driver.

Asynchronous Mode

This section describes how to use SPI Driver in Asynchronous mode.

Description

Asynchronous mode of SPI driver allows user to use the library in non-blocking manner. This mode is supported in both RTOS and Bare-Metal environments. Transfer APIs of this mode return a transfer handle. Application can check the transfer completion status in two ways:

1. **Callback:** Callback can be registered with the driver using [DRV_SPI_TransferEventHandlerSet](#) API and it needs to be registered prior to calling the transfer API. Here is the example of SPI write using callback:

```

DRV_SPI_TRANSFER_HANDLE transferHandle1;
DRV_SPI_TRANSFER_SETUP setup;
DRV_HANDLE drvSPIHandle;
uint8_t writeData[] = "SPI Driver Async Mode Callback";

void SpiEventHandler (DRV_SPI_TRANSFER_EVENT event, DRV_SPI_TRANSFER_HANDLE transferHandle,
uintptr_t context )
{
    if (event == DRV_SPI_TRANSFER_EVENT_COMPLETE)
    {
        if(transferHandle == transferHandle1)
        {
            // transfer1 is completed
        }
    }
    else
    {
        // transfer1 had error.
    }
}

// SPI Driver Initialization is done in MHC generated code

/* Setup structure for SPI transfer */
setup.baudRateInHz = 600000;
setup.clockPhase = DRV_SPI_CLOCK_PHASE_VALID_LEADING_EDGE;
setup.clockPolarity = DRV_SPI_CLOCK_POLARITY_IDLE_LOW;
setup.dataBits = DRV_SPI_DATA_BITS_8;
setup(chipSelect = SYS_PORT_PIN_PD16;

```

```

setup.csPolarity = DRV_SPI_CS_POLARITY_ACTIVE_LOW;

/* Open the SPI Driver*/
drvSPIHandle = DRV_SPI_Open( DRV_SPI_INDEX_0, DRV_IO_INTENT_READWRITE);

if(drvSPIHandle != DRV_HANDLE_INVALID)
{
    if(DRV_SPI_TransferSetup(drvSPIHandle, &setup) == true)
    {
        // setup is successful
    }
    DRV_SPI_TransferEventHandlerSet(drvSPIHandle, SpiEventHandler, (uintptr_t)NULL);
}

DRV_SPI_WriteTransferAdd(drvSPIHandle, &writeData, sizeof(writeData), &transferHandle1 );
if(transferHandle1 == DRV_SPI_TRANSFER_HANDLE_INVALID)
{
    /* transfer request was not successful, try again */
}
else
{
    /* transfer request was successful, callback function
    "SpiEventHandler" will be called when transfer is completed. */
}

```

2. **Polling:** Data transfer status polling can be done using [DRV_SPI_TransferStatusGet](#) API. Here is the example of SPI write using status polling:

```

DRV_SPI_TRANSFER_HANDLE transferHandle1;
DRV_SPI_TRANSFER_SETUP setup;
DRV_HANDLE             drvSPIHandle;
uint8_t                writeData[] = "SPI Driver Async Mode Polling";

// SPI Driver Initialization is done in MHC generated code

/* Setup structure for SPI transfer */
setup.baudRateInHz = 600000;
setup.clockPhase = DRV_SPI_CLOCK_PHASE_VALID.LEADING_EDGE;
setup.clockPolarity = DRV_SPI_CLOCK_POLARITY_IDLE_LOW;
setup.dataBits = DRV_SPI_DATA_BITS_8;
setup.chipSelect = SYS_PORT_PIN_PD16;
setup.csPolarity = DRV_SPI_CS_POLARITY_ACTIVE_LOW;

/* Open the SPI Driver*/
drvSPIHandle = DRV_SPI_Open( DRV_SPI_INDEX_0, DRV_IO_INTENT_READWRITE);

if(drvSPIHandle != DRV_HANDLE_INVALID)
{
    if(DRV_SPI_TransferSetup(drvSPIHandle, &setup) == true)
    {
        // setup is successful
    }
}

DRV_SPI_WriteTransferAdd(drvSPIHandle, &writeData, sizeof(writeData), &transferHandle1 );
if(transferHandle1 == DRV_SPI_TRANSFER_HANDLE_INVALID)
{
    /* transfer request was not successful, try again */
}
else
{
    /* transfer request was successful, transfer status can be
    polled anytime using DRV_SPI_TransferStatusGet API */
}

if (DRV_SPI_TransferStatusGet(transferHandle1) == DRV_SPI_TRANSFER_EVENT_COMPLETE)
{

```

```
    // transfer1 is completed successfully
}
```

Synchronous mode

This chapter describes how to use SPI Driver in Synchronous mode.

Description

Synchronous mode of SPI driver allows user to use the library in blocking manner. This mode is supported only in RTOS environment. Transfer APIs of this mode block until transfer is complete and return true or false depending on transfer status. Here is the example of SPI write in synchronous mode:

```
DRV_SPI_TRANSFER_SETUP    setup;
DRV_HANDLE                 drvSPIHandle;
uint8_t                     writeData[] = "SPI Driver Async Mode";

// SPI Driver Initialization is done in MHC generated code

/* Setup structure for SPI transfer */
setup.baudRateInHz = 600000;
setup.clockPhase = DRV_SPI_CLOCK_PHASE_VALID.LEADING_EDGE;
setup.clockPolarity = DRV_SPI_CLOCK_POLARITY_IDLE_LOW;
setup.dataBits = DRV_SPI_DATA_BITS_8;
setup.chipSelect = SYS_PORT_PIN_PD16;
setup.csPolarity = DRV_SPI_CS_POLARITY_ACTIVE_LOW;

/* Open the SPI Driver*/
drvSPIHandle = DRV_SPI_Open( DRV_SPI_INDEX_0, DRV_IO_INTENT_READWRITE);

if(drvSPIHandle != DRV_HANDLE_INVALID)
{
    if(DRV_SPI_TransferSetup(drvSPIHandle, &setup) == true)
    {
        // setup is successful
    }
}

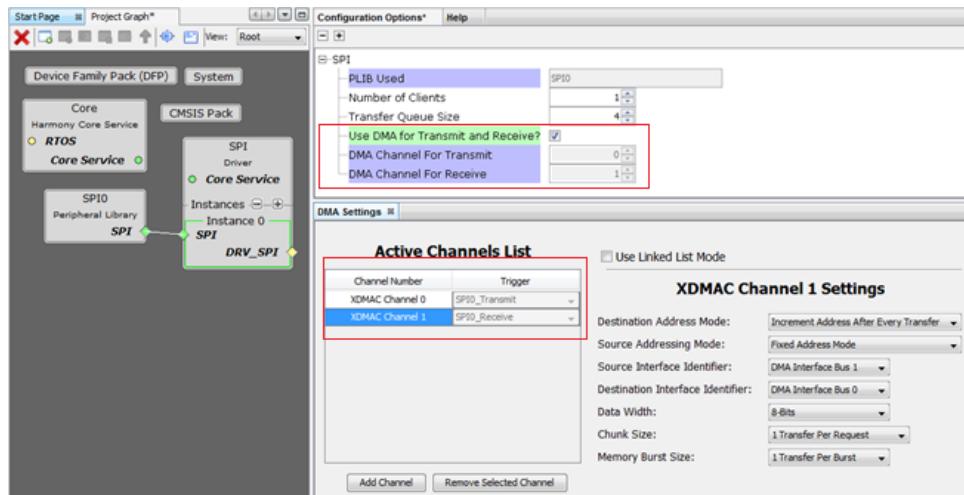
if(DRV_SPI_WriteTransfer(drvSPIHandle, &writeData, sizeof(writeData)) == true)
{
    // transfer is completed successfully
}
```

Configuring the Library

This section provides information on how to configure SPI Driver library.

Description

SPI Driver library should be configured via MHC. Below is the Snapshot of the MHC configuration window for SPI driver and brief description.



Common User Configuration for all the Driver Instances:

- **Driver Mode:**
 - Allows User to select the mode of driver (Asynchronous or Synchronous). This setting is common for all the instances

Driver Instance Specific User Configurations

- **Number Of Clients:**
 - Specify number of clients for the specific instance of the driver
- **Transfer Queue Size:**
 - In Asynchronous mode, specify maximum number of transfer requests which can be queued for the specific instance of the driver
 - In Synchronous mode, buffer Queuing is disabled
- **Use DMA for Transmit and Receive:**
 - This option is used if DMA mode is intended for specific instance
 - **DMA Channel For Transmit**
 - DMA Channel used for transmission is auto allocated based on availability in DMA Configuration
 - **DMA Channel For Receive**
 - DMA Channel used for Receiving is auto allocated based on availability in DMA Configuration

Building the Library

This section provides information on how the SPI Driver Library can be built.

Description



All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

Library Interface

a) System Functions

	Name	Description
≡	DRV_SPI_Initialize	Initializes the SPI instance for the specified driver index.
≡	DRV_SPI_Status	Gets the current status of the SPI driver module.

b) Client Setup Functions

	Name	Description
≡	DRV_SPI_Open	Opens the specified SPI driver instance and returns a handle to it.
≡	DRV_SPI_Close	Closes an opened-instance of the SPI driver.
≡	DRV_SPI_TransferSetup	Sets the dynamic configuration of the driver including chip select pin.
≡	DRV_SPI_TransferEventHandlerSet	Allows a client to set a transfer event handling function for the driver to call back when queued transfer has finished.

c) Transfer Functions

	Name	Description
≡	DRV_SPI_ReadTransfer	This is a blocking function that receives data over SPI.
≡	DRV_SPI_WriteTransfer	This is a blocking function that transmits data over SPI.
≡	DRV_SPI_WriteReadTransfer	This is a blocking function that transmits and receives data over SPI.
≡	DRV_SPI_ReadTransferAdd	Queues a read operation.
≡	DRV_SPI_WriteTransferAdd	Queues a write operation.
≡	DRV_SPI_WriteReadTransferAdd	Queues a write-read transfer operation.

d) Transfer Status Functions

	Name	Description
≡	DRV_SPI_TransferStatusGet	Returns transfer add request status.

e) Data Types and Constants

	Name	Description
	DRV_SPI_CLOCK_PHASE	Identifies SPI Clock Phase Options
	DRV_SPI_CLOCK_POLARITY	Identifies SPI Clock Polarity Options
	DRV_SPI_CS_POLARITY	Identifies SPI Chip Select Polarity Options
	DRV_SPI_DATA_BITS	Identifies SPI bits per transfer
	DRV_SPI_TRANSFER_SETUP	Defines the data required to setup the SPI transfer
	DRV_SPI_TRANSFER_EVENT	Identifies the possible events that can result from a transfer add request.
	DRV_SPI_TRANSFER_HANDLE	Handle identifying the transfer request queued.
	DRV_SPI_TRANSFER_EVENT_HANDLER	Pointer to a SPI Driver Transfer Event handler function
	DRV_SPI_TRANSFER_HANDLE_INVALID	Definition of an invalid transfer handle.

Description

This section describes the API functions of the SPI Driver library.

Refer to each section for a detailed description.

a) System Functions

DRV_SPI_Initialize Function

Initializes the SPI instance for the specified driver index.

C

```
SYS_MODULE_OBJ DRV_SPI_Initialize(const SYS_MODULE_INDEX index, const SYS_MODULE_INIT * const init);
```

Returns

If successful, returns a valid handle to a driver instance object. Otherwise, returns [SYS_MODULE_OBJ_INVALID](#).

Description

This routine initializes the SPI driver instance for the specified driver index, making it ready for clients to open and use it. The initialization data is specified by the init parameter. The initialization may fail if the number of driver objects allocated are insufficient or if the specified driver instance is already initialized. The driver instance index is independent of the SPI module ID. For example, driver instance 0 can be assigned to SPI2.

Remarks

- This routine must be called before any other SPI routine is called.
- This routine must only be called once during system initialization.
- This routine will NEVER block for hardware access.

Preconditions

None.

Example

```
// The following code snippet shows an example SPI driver initialization.

SYS_MODULE_OBJ    objectHandle;

const DRV_SPI_PLIB_INTERFACE drvSPI0PlibAPI = {

    // SPI PLIB Setup
    .setup = (DRV_SPI_PLIB_SETUP)SPI0_TransferSetup,

    // SPI PLIB WriteRead function
    .writeRead = (DRV_SPI_PLIB_WRITE_READ)SPI0_WriteRead,

    // SPI PLIB Transfer Status function
    .isBusy = (DRV_SPI_PLIB_IS_BUSY)SPI0_IsBusy,

    // SPI PLIB Callback Register
    .callbackRegister = (DRV_SPI_PLIB_CALLBACK_REGISTER)SPI0_CallbackRegister,
};

const DRV_SPI_INIT drvSPI0InitData = {

    // SPI PLIB API
    .spiPlib = &drvSPI0PlibAPI,

    .remapDataBits = drvSPI0remapDataBits,
    .remapClockPolarity = drvSPI0remapClockPolarity,
    .remapClockPhase = drvSPI0remapClockPhase,

    /// SPI Number of clients
    .numClients = DRV_SPI_CLIENTS_NUMBER_IDX0,

    // SPI Client Objects Pool
    .clientObjPool = (uintptr_t)&drvSPI0ClientObjPool[0],

    // DMA Channel for Transmit
    .dmaChannelTransmit = DRV_SPI_XMIT_DMA_CH_IDX0,

    // DMA Channel for Receive
    .dmaChannelReceive = DRV_SPI_RCV_DMA_CH_IDX0,

    // SPI Transmit Register
    .spiTransmitAddress = (void *)&(SPI0_REGS->SPI_TDR),

    // SPI Receive Register
    .spiReceiveAddress = (void *)&(SPI0_REGS->SPI_RDR),

    // Interrupt source is DMA
}
```

```

.interruptSource = XDMAC_IRQn,

// SPI Queue Size
.queueSize = DRV_SPI_QUEUE_SIZE_IDX0,

// SPI Transfer Objects Pool
.transferObjPool = (uintptr_t)&drvSPI0TransferObjPool[0],
};

objectHandle = DRV_SPI_Initialize(DRV_SPI_INDEX_0, (SYS_MODULE_INIT*)&drvSPI0InitData);
if (objectHandle == SYS_MODULE_OBJ_INVALID)
{
    // Handle error
}

```

Parameters

Parameters	Description
index	Identifier for the instance to be initialized
init	Pointer to the init data structure containing any data necessary to initialize the driver.

Function

```

SYS_MODULE_OBJ DRV_SPI_Initialize
(
const     SYS_MODULE_INDEX index,
const     SYS_MODULE_INIT * const init
)

```

DRV_SPI_Status Function

Gets the current status of the SPI driver module.

C

```
SYS_STATUS DRV_SPI_Status(SYS_MODULE_OBJ object);
```

Returns

- SYS_STATUS_READY - Initialization have succeeded and the SPI is ready for additional operations
- SYS_STATUS_DEINITIALIZED - Indicates that the driver has been deinitialized

Description

This routine provides the current status of the SPI driver module.

Remarks

A driver can be opened only when its status is SYS_STATUS_READY.

Preconditions

Function `DRV_SPI_Initialize` should have been called before calling this function.

Example

```

SYS_MODULE_OBJ      object;      // Returned from DRV_SPI_Initialize
SYS_STATUS         spiStatus;

spiStatus = DRV_SPI_Status(object);
if (spiStatus == SYS_STATUS_READY)
{
    // This means now the driver can be opened using the
    // DRV_SPI_Open() function.
}

```

```
}
```

Parameters

Parameters	Description
object	Driver object handle, returned from the DRV_SPI_Initialize routine

Function

```
SYS_STATUS DRV_SPI_Status( SYS_MODULE_OBJ object )
```

b) Client Setup Functions

DRV_SPI_Open Function

Opens the specified SPI driver instance and returns a handle to it.

C

```
DRV_HANDLE DRV_SPI_Open(const SYS_MODULE_INDEX index, const DRV_IO_INTENT ioIntent);
```

Returns

If successful, the routine returns a valid open-instance handle (a number identifying both the caller and the module instance).

If an error occurs, the return value is [DRV_HANDLE_INVALID](#). Error can occur

- if the number of client objects allocated via [DRV_SPI_CLIENTS_NUMBER](#) is insufficient.
- if the client is trying to open the driver but driver has been opened exclusively by another client.
- if the driver peripheral instance being opened is not initialized or is invalid.
- if the client is trying to open the driver exclusively, but has already been opened in a non exclusive mode by another client.
- if the driver is not ready to be opened, typically when the initialize routine has not completed execution.

Description

This routine opens the specified SPI driver instance and provides a handle that must be provided to all other client-level operations to identify the caller and the instance of the driver. The [ioIntent](#) parameter defines how the client interacts with this driver instance.

Specifying a [DRV_IO_INTENT_EXCLUSIVE](#) will cause the driver to provide exclusive access to this client. The driver cannot be opened by any other client.

Remarks

- The handle returned is valid until the [DRV_SPI_Close](#) routine is called.
- This routine will NEVER block waiting for hardware.

Preconditions

Function [DRV_SPI_Initialize](#) must have been called before calling this function.

Example

```
DRV_HANDLE handle;

handle = DRV_SPI_Open(DRV_SPI_INDEX_0, DRV_IO_INTENT_EXCLUSIVE);
if (handle == DRV_HANDLE_INVALID)
{
    // Unable to open the driver
    // May be the driver is not initialized or the initialization
    // is not complete.
}
```

Parameters

Parameters	Description
index	Identifier for the object instance to be opened
intent	Zero or more of the values from the enumeration DRV_IO_INTENT "ORed" together to indicate the intended use of the driver. See function description for details.

Function

```
DRV_HANDLE DRV_SPI_Open
(
const  SYS_MODULE_INDEX index,
const  DRV_IO_INTENT ioIntent
)
```

DRV_SPI_Close Function

Closes an opened-instance of the SPI driver.

C

```
void DRV_SPI_Close(const DRV_HANDLE handle);
```

Returns

None.

Description

This routine closes an opened-instance of the SPI driver, invalidating the handle. User should make sure that there is no transfer request pending before calling this API. A new handle must be obtained by calling [DRV_SPI_Open](#) before the caller may use the driver again.

Remarks

None.

Preconditions

[DRV_SPI_Open](#) must have been called to obtain a valid opened device handle.

Example

```
// 'handle', returned from the DRV_SPI_Open

DRV_SPI_Close(handle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
void DRV_SPI_Close( DRV_Handle handle )
```

DRV_SPI_TransferSetup Function

Sets the dynamic configuration of the driver including chip select pin.

C

```
bool DRV_SPI_TransferSetup(DRV_HANDLE handle, DRV_SPI_TRANSFER_SETUP * setup);
```

Returns

None.

Description

This function is used to update any of the [DRV_SPI_TRANSFER_SETUP](#) parameters for the selected client of the driver dynamically. For single client scenario, if GPIO has to be used for chip select, then calling this API with appropriate GPIO pin information becomes mandatory. For multi client scenario where different clients need different setup like baud rate, clock settings, chip select etc, then also calling this API is mandatory.

Note that all the elements of setup structure must be filled appropriately before using this API.

Remarks

None.

Preconditions

[DRV_SPI_Open](#) must have been called to obtain a valid opened device handle.

Example

```
// mySPIHandle is the handle returned by the DRV_SPI_Open function.
DRV_SPI_TRANSFER_SETUP setup;

setup.baudRateInHz = 10000000;
setup.clockPhase = DRV_SPI_CLOCK_PHASE_TRAILING_EDGE;
setup.clockPolarity = DRV_SPI_CLOCK_POLARITY_IDLE_LOW;
setup.dataBits = DRV_SPI_DATA_BITS_16;
setup.chipSelect = SYS_PORT_PIN_PC5;
setup.csPolarity = DRV_SPI_CS_POLARITY_ACTIVE_LOW;

DRV_SPI_TransferSetup ( mySPIHandle, &setup );
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
*setup	A structure containing the new configuration settings

Function

bool DRV_SPI_TransferSetup ([DRV_HANDLE](#) handle, [DRV_SPI_TRANSFER_SETUP](#) * setup)

DRV_SPI_TransferEventHandlerSet Function

Allows a client to set a transfer event handling function for the driver to call back when queued transfer has finished.

C

```
void DRV_SPI_TransferEventHandlerSet(const DRV\_HANDLE handle, const
DRV\_SPI\_TRANSFER\_EVENT\_HANDLER eventHandler, uintptr\_t context);
```

Returns

None.

Description

This function allows a client to register a transfer event handling function with the driver to call back when queued transfer has finished. When a client calls either the [DRV_SPI_ReadTransferAdd](#) or [DRV_SPI_WriteTransferAdd](#) or [DRV_SPI_WriteReadTransferAdd](#) function, it is provided with a handle identifying the transfer request that was added to the driver's queue. The driver will pass this handle back to the client by calling "eventHandler" function when the transfer has completed.

The event handler should be set before the client performs any "transfer add" operations that could generate events. The event handler once set, persists until the client closes the driver or sets another event handler (which could be a "NULL" pointer to indicate no callback).

Remarks

If the client does not want to be notified when the queued transfer request has completed, it does not need to register a callback.

Preconditions

[DRV_SPI_Open](#) must have been called to obtain a valid open instance handle.

Example

```
// myAppObj is an application specific state data object.
MY_APP_OBJ myAppObj;

uint8_t myTxBuffer[MY_TX_BUFFER_SIZE];
uint8_t myRxBuffer[MY_RX_BUFFER_SIZE];
DRV_SPI_TRANSFER_HANDLE transferHandle;

// mySPIHandle is the handle returned by the DRV_SPI_Open function.

// Client registers an event handler with driver. This is done once

DRV_SPI_TransferEventHandlerSet( mySPIHandle, APP_SPITransferEventHandler,
                                  (uintptr_t)&myAppObj );

DRV_SPI_WriteReadTransferAdd(mySPIHandle, myTxBuffer,
                             MY_TX_BUFFER_SIZE, myRxBuffer,
                             MY_RX_BUFFER_SIZE, &transferHandle);

if(transferHandle == DRV_SPI_TRANSFER_HANDLE_INVALID)
{
    // Error handling here
}

// Event is received when the transfer is completed.

void APP_SPITransferEventHandler(DRV_SPI_TRANSFER_EVENT event,
                                  DRV_SPI_TRANSFER_HANDLE handle, uintptr_t context)
{
    // The context handle was set to an application specific
    // object. It is now retrievable easily in the event handler.
    MY_APP_OBJ myAppObj = (MY_APP_OBJ *) context;

    switch(event)
    {
        case DRV_SPI_TRANSFER_EVENT_COMPLETE:
            // This means the data was transferred.
            break;

        case DRV_SPI_TRANSFER_EVENT_ERROR:
            // Error handling here.
            break;

        default:
            break;
    }
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine.
eventHandler	Pointer to the event handler function.
context	The value of parameter will be passed back to the client unchanged, when the eventHandler function is called. It can be used to identify any client specific data object that identifies the instance of the client module (for example, it may be a pointer to the client module's state structure).

Function

```
void DRV_SPI_TransferEventHandlerSet
(
    const DRV_HANDLE handle,
    const DRV_SPI_TRANSFER_EVENT_HANDLER eventHandler,
    const uintptr_t context
)
```

c) Transfer Functions

DRV_SPI_ReadTransfer Function

This is a blocking function that receives data over SPI.

C

```
bool DRV_SPI_ReadTransfer(const DRV_HANDLE handle, void* pReceiveData, size_t rxSize);
```

Returns

- true - receive is successful
- false - error has occurred

Description

This function does a blocking read operation. The function blocks till the data receive is complete. Function will return true if the receive is successful or false in case of an error. The failure will occur for the following reasons:

- if the handle is invalid
- if the pointer to the receive buffer is NULL
- if the receive size is 0

Remarks

- This function is thread safe in a RTOS application.
- This function should not be called from an interrupt context.

Preconditions

- `DRV_SPI_Open` must have been called to obtain a valid opened device handle.
- `DRV_SPI_TransferSetup` must have been called if GPIO pin has to be used for chip select or any of the setup parameters has to be changed dynamically.

Example

```
MY_APP_OBJ myAppObj;
uint8_t myRxBuffer[MY_RX_BUFFER_SIZE];

// mySPIHandle is the handle returned by the DRV_SPI_Open function.

if (DRV_SPI_ReadTransfer(mySPIHandle, myRxBuffer, MY_RX_BUFFER_SIZE) == false)
{
    // Handle error here
}
```

Parameters

Parameters	Description
handle	Handle of the communication channel as returned by the <code>DRV_SPI_Open</code> function.
*pReceiveData	Pointer to the buffer where the data is to be received. For 9 to 15bit mode, data should be right aligned in the 16 bit memory location.

rxSize	Number of bytes to be received. Always, size should be given in terms of bytes. For example, if 10 15-bit data are to be received, the receive size should be 20 bytes.
--------	---

Function

```
void DRV_SPI_ReadTransfer
(
const DRV_HANDLE handle,
void* pReceiveData,
size_t rxSize
);
```

DRV_SPI_WriteTransfer Function

This is a blocking function that transmits data over SPI.

C

```
bool DRV_SPI_WriteTransfer(const DRV_HANDLE handle, void* pTransmitData, size_t txSize);
```

Returns

- true - transfer is successful
- false - error has occurred

Description

This function does a blocking write operation. The function blocks till the data transmit is complete. Function will return true if the transmit is successful or false in case of an error. The failure will occur for the following reasons:

- if the handle is invalid
- if the pointer to the transmit buffer is NULL
- if the transmit size is 0

Remarks

- This function is thread safe in a RTOS application.
- This function should not be called from an interrupt context.

Preconditions

- [DRV_SPI_Open](#) must have been called to obtain a valid opened device handle.
- [DRV_SPI_TransferSetup](#) must have been called if GPIO pin has to be used for chip select or any of the setup parameters has to be changed dynamically.

Example

```
MY_APP_OBJ myAppObj;
uint8_t myTxBuffer[MY_TX_BUFFER_SIZE];

// mySPIHandle is the handle returned by the DRV_SPI_Open function.

if (DRV_SPI_WriteTransfer(mySPIHandle, myTxBuffer, MY_TX_BUFFER_SIZE) == false)
{
    // Handle error here
}
```

Parameters

Parameters	Description
handle	Handle of the communication channel as returned by the DRV_SPI_Open function.
*pTransmitData	Pointer to the data which has to be transmitted. For 9 to 15bit mode, data should be right aligned in the 16 bit memory location.

txSize	Number of bytes to be transmitted. Always, size should be given in terms of bytes. For example, if 10 15-bit data are to be transmitted, the transmit size should be 20 bytes.
--------	--

Function

```
void DRV_SPI_WriteTransfer
(
const DRV_HANDLE handle,
void* pTransmitData,
size_t txSize
);
```

DRV_SPI_WriteTransfer Function

This is a blocking function that transmits and receives data over SPI.

C

```
bool DRV_SPI_WriteReadTransfer(const DRV_HANDLE handle, void* pTransmitData, size_t txSize,
void* pReceiveData, size_t rxSize);
```

Returns

- true - write-read is successful
- false - error has occurred

Description

This function does a blocking write-read operation. The function blocks till the data receive is complete. Function will return true if the receive is successful or false in case of an error. The failure will occur for the following reasons:

- if the handle is invalid
- if the transmit size is non-zero and pointer to the transmit buffer is NULL
- if the receive size is non-zero and pointer to the receive buffer is NULL

Remarks

- This function is thread safe in a RTOS application.
- This function should not be called from an interrupt context.

Preconditions

- [DRV_SPI_Open](#) must have been called to obtain a valid opened device handle.
- [DRV_SPI_TransferSetup](#) must have been called if GPIO pin has to be used for chip select or any of the setup parameters has to be changed dynamically.

Example

```
MY_APP_OBJ myAppObj;
uint8_t myTxBuffer[MY_TX_BUFFER_SIZE];
uint8_t myRxBuffer[MY_RX_BUFFER_SIZE];

// mySPIHandle is the handle returned by the DRV_SPI_Open function.

if (DRV_SPI_WriteReadTransfer(mySPIHandle, myTxBuffer, MY_TX_BUFFER_SIZE,
myRxBuffer, MY_RX_BUFFER_SIZE) == false)
{
    // Handle error here
}
```

Parameters

Parameters	Description
handle	Handle of the communication channel as returned by the DRV_SPI_Open function.

*pTransmitData	Pointer to the data which has to be transmitted. For 9 to 15bit mode, data should be right aligned in the 16 bit memory location.
txSize	Number of bytes to be transmitted. Always, size should be given in terms of bytes. For example, if 10 15-bit data are to be transmitted, the transmit size should be 20 bytes.
*pReceiveData	Pointer to the buffer where the data is to be received. For 9 to 15bit mode, data should be right aligned in the 16 bit memory location.
rxSize	Number of bytes to be received. Always, size should be given in terms of bytes. For example, if 10 15-bit data are to be received, the receive size should be 20 bytes. If "n" number of bytes has to be received AFTER transmitting "m" number of bytes, then "txSize" should be set as "m" and "rxSize" should be set as "m+n".

Function

```
void DRV_SPI_WriteReadTransfer
(
    const DRV_HANDLE handle,
    void* pTransmitData,
    size_t txSize,
    void* pReceiveData,
    size_t rxSize
);
```

DRV_SPI_ReadTransferAdd Function

Queues a read operation.

C

```
void DRV_SPI_ReadTransferAdd(const DRV_HANDLE handle, void* pReceiveData, size_t rxSize,
DRV_SPI_TRANSFER_HANDLE * const transferHandle);
```

Returns

None.

Description

This function schedules a non-blocking read operation. The function returns with a valid transfer handle in the transferHandle argument if the request was scheduled successfully. The function adds the request to the instance specific software queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. This API will write rxSize bytes of dummy data and will read rxSize bytes of data in the memory location pointed by pReceiveData.

The function returns [DRV_SPI_TRANSFER_HANDLE_INVALID](#) in the transferHandle argument:

- if pReceiveData is NULL.
- if rxSize is zero.
- if the transfer handle is NULL.
- if the queue size is full or queue depth is insufficient.
- if the driver handle is invalid.

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_SPI_TRANSFER_EVENT_COMPLETE](#) event if the transfer was processed successfully or [DRV_SPI_TRANSFER_EVENT_ERROR](#) event if the transfer was not processed successfully.

Remarks

- This function can be called from within the SPI Driver Transfer Event Handler that is registered by the client.
- It should not be called in the event handler associated with another SPI driver instance or event handler of any other peripheral.
- It should not be called directly in any ISR.

Preconditions

- [DRV_SPI_Open](#) must have been called to obtain a valid opened device handle.

- [DRV_SPI_TransferSetup](#) must have been called if GPIO pin has to be used for chip select or any of the setup parameters has to be changed dynamically.

Example

```

MY_APP_OBJ myAppObj;
uint8_t myRxBuffer[MY_RX_BUFFER_SIZE];
DRV_SPI_TRANSFER_HANDLE transferHandle;

// mySPIHandle is the handle returned by the DRV_SPI_Open function.

DRV_SPI_ReadTransferAdd(mySPIHandle, myRxBuffer, MY_RX_BUFFER_SIZE, &transferHandle);

if(transferHandle == DRV_SPI_TRANSFER_HANDLE_INVALID)
{
    // Error handling here
}

// Event is received when the transfer is processed.

```

Parameters

Parameters	Description
handle	Handle of the communication channel as returned by the DRV_SPI_Open function.
*pReceiveData	Pointer to the location where received data has to be stored. It is user's responsibility to ensure pointed location has sufficient memory to store the read data. For 9 to 15bit mode, received data will be right aligned in the 16 bit memory location.
rxSize	Number of bytes to be received. Always, size should be given in terms of bytes. For example, if 10 15-bit data are to be received, the receive size should be 20 bytes.
transferHandle	Handle which is returned by transfer add function.

Function

```

void DRV_SPI_ReadTransferAdd
(
    const DRV_HANDLE handle,
    void* pReceiveData,
    size_t rxSize,
    DRV_SPI_TRANSFER_HANDLE * const transferHandle
);

```

DRV_SPI_WriteTransferAdd Function

Queues a write operation.

C

```

void DRV_SPI_WriteTransferAdd(const DRV_HANDLE handle, void* pTransmitData, size_t txSize,
DRV_SPI_TRANSFER_HANDLE * const transferHandle);

```

Returns

None.

Description

This function schedules a non-blocking write operation. The function returns with a valid transfer handle in the transferHandle argument if the request was scheduled successfully. The function adds the request to the instance specific software queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. This API will write txSize bytes of data and the dummy data received will be ignored.

The function returns [DRV_SPI_TRANSFER_HANDLE_INVALID](#) in the transferHandle argument:

- if pTransmitData is NULL.

- if txSize is zero.
- if the transfer handle is NULL.
- if the queue size is full or queue depth is insufficient.
- if the driver handle is invalid.

If the requesting client registered an event callback with the driver, the driver will issue a `DRV_SPI_TRANSFER_EVENT_COMPLETE` event if the transfer was processed successfully or `DRV_SPI_TRANSFER_EVENT_ERROR` event if the transfer was not processed successfully.

Remarks

- This function can be called from within the SPI Driver Transfer Event Handler that is registered by the client.
- It should NOT be called in the event handler associated with another SPI driver instance or event handler of any other peripheral.
- It should not be called directly in any ISR.

Preconditions

- `DRV_SPI_Open` must have been called to obtain a valid opened device handle.
- `DRV_SPI_TransferSetup` must have been called if GPIO pin has to be used for chip select or any of the setup parameters has to be changed dynamically.

Example

```
MY_APP_OBJ myAppObj;
uint8_t myTxBuffer[MY_TX_BUFFER_SIZE];
DRV_SPI_TRANSFER_HANDLE transferHandle;

// mySPIHandle is the handle returned by the DRV_SPI_Open function.

DRV_SPI_WriteTransferAdd(mySPIHandle, myTxBuffer, MY_TX_BUFFER_SIZE, &transferHandle);

if(transferHandle == DRV_SPI_TRANSFER_HANDLE_INVALID)
{
    // Error handling here
}

// Event is received when the transfer is processed.
```

Parameters

Parameters	Description
handle	Handle of the communication channel as returned by the <code>DRV_SPI_Open</code> function.
*pTransmitData	Pointer to the data which has to be transmitted. For 9 to 15bit mode, data should be right aligned in the 16 bit memory location.
txSize	Number of bytes to be transmitted. Always, size should be given in terms of bytes. For example, if 10 15-bit data are to be transmitted, the transmit size should be 20 bytes.
transferHandle	Handle which is returned by transfer add function.

Function

```
void DRV_SPI_WriteTransferAdd
(
    const DRV_HANDLE handle,
    void* pTransmitData,
    size_t txSize,
    DRV_SPI_TRANSFER_HANDLE * const transferHandle
);
```

DRV_SPI_WriteReadTransferAdd Function

Queues a write-read transfer operation.

C

```
void DRV_SPI_WriteReadTransferAdd(const DRV_HANDLE handle, void* pTransmitData, size_t txSize,
void* pReceiveData, size_t rxSize, DRV_SPI_TRANSFER_HANDLE * const transferHandle);
```

Returns

None.

Description

This function schedules a non-blocking write-read operation. The function returns with a valid transfer handle in the transferHandle argument if the request was scheduled successfully. The function adds the request to the instance specific software queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. This API will write txSize and at the same time counting of rxSize to be read will start. If user wants 'n' bytes to be read after txSize has been written, then he should keep rxSize value as 'txSize + n'.

The function returns [DRV_SPI_TRANSFER_HANDLE_INVALID](#) in the transferHandle argument:

- if neither of the transmit or receive arguments are valid.
- if the transfer handle is NULL.
- if the queue size is full or queue depth is insufficient.
- if the driver handle is invalid.

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_SPI_TRANSFER_EVENT_COMPLETE](#) event if the transfer was processed successfully or [DRV_SPI_TRANSFER_EVENT_ERROR](#) event if the transfer was not processed successfully.

Remarks

- This function can be called from within the SPI Driver Transfer Event Handler that is registered by the client.
- It should not be called in the event handler associated with another SPI driver instance or event handler of any other peripheral.
- It should not be called directly in any ISR.

Preconditions

- [DRV_SPI_Open](#) must have been called to obtain a valid opened device handle.
- [DRV_SPI_TransferSetup](#) must have been called if GPIO pin has to be used for chip select or any of the setup parameters has to be changed dynamically.

Example

```
MY_APP_OBJ myAppObj;
uint8_t myTxBuffer[MY_TX_BUFFER_SIZE];
uint8_t myRxBuffer[MY_RX_BUFFER_SIZE];
DRV_SPI_TRANSFER_HANDLE transferHandle;

// mySPIHandle is the handle returned by the DRV_SPI_Open function.

DRV_SPI_WriteReadTransferAdd(mySPIHandle, myTxBuffer, MY_TX_BUFFER_SIZE,
                             myRxBuffer, MY_RX_BUFFER_SIZE, &transferHandle);

if(transferHandle == DRV_SPI_TRANSFER_HANDLE_INVALID)
{
    // Error handling here
}

// Event is received when the transfer is processed.
```

Parameters

Parameters	Description
handle	Handle of the communication channel as returned by the DRV_SPI_Open function.
*pTransmitData	Pointer to the data which has to be transmitted. if it is NULL, that means only data receiving is expected. For 9 to 15bit mode, data should be right aligned in the 16 bit memory location.

txSize	Number of bytes to be transmitted. Always, size should be given in terms of bytes. For example, if 10 15-bit data are to be transmitted, the transmit size should be 20 bytes.
*pReceiveData	Pointer to the location where received data has to be stored. It is user's responsibility to ensure pointed location has sufficient memory to store the read data. If it is NULL, that means only data transmission is expected. For 9 to 15bit mode, received data will be right aligned in the 16 bit memory location.
rxSize	Number of bytes to be received. Always, size should be given in terms of bytes. For example, if 10 15-bit data are to be received, the receive size should be 20 bytes. If "n" number of bytes has to be received AFTER transmitting "m" number of bytes, then "txSize" should be set as "m" and "rxSize" should be set as "m+n".
transferHandle	Handle which is returned by transfer add function.

Function

```
void DRV_SPI_WriteReadTransferAdd
(
    const DRV_HANDLE handle,
    void* pTransmitData,
    size_t txSize,
    void* pReceiveData,
    size_t rxSize,
    DRV_SPI_TRANSFER_HANDLE * const transferHandle
);
```

d) Transfer Status Functions

DRV_SPI_TransferStatusGet Function

Returns transfer add request status.

C

```
DRV_SPI_TRANSFER_EVENT DRV_SPI_TransferStatusGet(const DRV_SPI_TRANSFER_HANDLE transferHandle);
```

Returns

One of the elements of the enum "DRV_SPI_TRANSFER_EVENT".

Description

This function can be used to poll the status of the queued transfer request if the application doesn't prefer to use the event handler (callback) function to get notified.

Remarks

None.

Preconditions

Either [DRV_SPI_ReadTransferAdd](#) or [DRV_SPI_WriteTransferAdd](#) or [DRV_SPI_WriteReadTransferAdd](#) function must have been called and a valid transfer handle must have been returned.

Example

```
// myAppObj is an application specific object.
MY_APP_OBJ myAppObj;

uint8_t mybuffer[MY_BUFFER_SIZE];
DRV_SPI_TRANSFER_HANDLE transferHandle;
DRV_SPI_TRANSFER_EVENT event;
```

```

// mySPIHandle is the handle returned by the DRV_SPI_Open function.

DRV_SPI_ReadTransferAdd( mySPIHandle, myBuffer, MY_RECEIVE_SIZE, &transferHandle);

if(transferHandle == DRV_SPI_TRANSFER_HANDLE_INVALID)
{
    // Error handling here
}

//Check the status of the transfer request
//This call can be used to wait until the transfer is completed.
event = DRV_SPI_TransferStatusGet(transferHandle);

```

Parameters

Parameters	Description
transferHandle	Handle of the transfer request of which status has to be obtained.

Function

[DRV_SPI_TRANSFER_EVENT](#) DRV_SPI_TransferStatusGet(const [DRV_SPI_TRANSFER_HANDLE](#) transferHandle)

e) Data Types and Constants

DRV_SPI_CLOCK_PHASE Enumeration

Identifies SPI Clock Phase Options

C

```

typedef enum {
    DRV_SPI_CLOCK_PHASE_VALID_TRAILING_EDGE,
    DRV_SPI_CLOCK_PHASE_VALID.LEADING_EDGE
} DRV_SPI_CLOCK_PHASE;

```

Members

Members	Description
DRV_SPI_CLOCK_PHASE_VALID_TRAILING_EDGE	Input data is valid on clock trailing edge and output data is ready on leading edge
DRV_SPI_CLOCK_PHASE_VALID.LEADING_EDGE	Input data is valid on clock leading edge and output data is ready on trailing edge

Description

SPI Driver Clock Phase

This enumeration identifies possible SPI Clock Phase Options.

Remarks

None.

DRV_SPI_CLOCK_POLARITY Enumeration

Identifies SPI Clock Polarity Options

C

```

typedef enum {
    DRV_SPI_CLOCK_POLARITY_IDLE_LOW,
    DRV_SPI_CLOCK_POLARITY_IDLE_HIGH
}

```

```
 } DRV_SPI_CLOCK_POLARITY;
```

Description

SPI Driver Clock Polarity

This enumeration identifies possible SPI Clock Polarity Options.

Remarks

None.

DRV_SPI_CS_POLARITY Enumeration

Identifies SPI Chip Select Polarity Options

C

```
typedef enum {
    DRV_SPI_CS_POLARITY_ACTIVE_LOW,
    DRV_SPI_CS_POLARITY_ACTIVE_HIGH
} DRV_SPI_CS_POLARITY;
```

Description

SPI Driver Chip Select Polarity

This enumeration identifies possible SPI Chip Select Polarity Options.

Remarks

None.

DRV_SPI_DATA_BITS Enumeration

Identifies SPI bits per transfer

C

```
typedef enum {
    DRV_SPI_DATA_BITS_8,
    DRV_SPI_DATA_BITS_9,
    DRV_SPI_DATA_BITS_10,
    DRV_SPI_DATA_BITS_11,
    DRV_SPI_DATA_BITS_12,
    DRV_SPI_DATA_BITS_13,
    DRV_SPI_DATA_BITS_14,
    DRV_SPI_DATA_BITS_15,
    DRV_SPI_DATA_BITS_16
} DRV_SPI_DATA_BITS;
```

Description

SPI Driver Data Bits

This enumeration identifies number of bits per SPI transfer.

Remarks

For 9 to 15bit modes, data should be right aligned in the 16 bit memory location.

DRV_SPI_TRANSFER_SETUP Structure

Defines the data required to setup the SPI transfer

C

```
typedef struct {
```

```

uint32_t baudRateInHz;
DRV_SPI_CLOCK_PHASE clockPhase;
DRV_SPI_CLOCK_POLARITY clockPolarity;
DRV_SPI_DATA_BITS dataBits;
SYS_PORT_PIN chipSelect;
DRV_SPI_CS_POLARITY csPolarity;
} DRV_SPI_TRANSFER_SETUP;

```

Description

SPI Driver Setup Data

This data type defines the data required to setup the SPI transfer. The data is passed to the [DRV_SPI_TransferSetup](#) API to setup the SPI peripheral settings dynamically.

Remarks

None.

DRV_SPI_TRANSFER_EVENT Enumeration

Identifies the possible events that can result from a transfer add request.

C

```

typedef enum {
    DRV_SPI_TRANSFER_EVENT_PENDING,
    DRV_SPI_TRANSFER_EVENT_COMPLETE,
    DRV_SPI_TRANSFER_EVENT_HANDLE_EXPIRED,
    DRV_SPI_TRANSFER_EVENT_ERROR,
    DRV_SPI_TRANSFER_EVENT_HANDLE_INVALID
} DRV_SPI_TRANSFER_EVENT;

```

Members

Members	Description
DRV_SPI_TRANSFER_EVENT_PENDING	Transfer request is pending
DRV_SPI_TRANSFER_EVENT_COMPLETE	All data were transferred successfully.
DRV_SPI_TRANSFER_EVENT_HANDLE_EXPIRED	Transfer Handle given is expired. It means transfer is completed but with or without error is not known. In case of Non-DMA transfer, since there is no possibility of error, it can be assumed same as DRV_SPI_TRANSFER_EVENT_COMPLETE
DRV_SPI_TRANSFER_EVENT_ERROR	There was an error while processing transfer request.
DRV_SPI_TRANSFER_EVENT_HANDLE_INVALID	Transfer Handle given is invalid

Description

SPI Driver Transfer Events

This enumeration identifies the possible events that can result from a transfer add request caused by the client calling either [DRV_SPI_ReadTransferAdd](#) or [DRV_SPI_WriteTransferAdd](#) or [DRV_SPI_WriteReadTransferAdd](#) functions.

Remarks

Either DRV_SPI_TRANSFER_EVENT_COMPLETE or DRV_SPI_TRANSFER_EVENT_ERROR is passed in the "event" parameter of the event handling callback function that the client registered with the driver by calling the [DRV_SPI_TransferEventHandlerSet](#) function when a transfer request is completed.

When status polling is used, any one of these events is returned by [DRV_SPI_TransferStatusGet](#) function.

DRV_SPI_TRANSFER_HANDLE Type

Handle identifying the transfer request queued.

C

```

typedef uintptr_t DRV_SPI_TRANSFER_HANDLE;

```

Description

SPI Driver Transfer Handle

A transfer handle value is returned by a call to the [DRV_SPI_ReadTransferAdd](#) or [DRV_SPI_WriteTransferAdd](#) or [DRV_SPI_WriteReadTransferAdd](#) functions. This handle is associated with the transfer request passed into the function and it allows the application to track the completion of the transfer request. The transfer handle value returned from the "transfer add" function is returned back to the client by the "event handler callback" function registered with the driver.

This handle can also be used to poll the transfer completion status using [DRV_SPI_TransferStatusGet](#) API.

The transfer handle assigned to a client request expires when a new transfer request is made after the completion of the current request.

Remarks

None

DRV_SPI_TRANSFER_EVENT_HANDLER Type

Pointer to a SPI Driver Transfer Event handler function

C

```
typedef void (* DRV_SPI_TRANSFER_EVENT_HANDLER)(DRV_SPI_TRANSFER_EVENT event,  
DRV_SPI_TRANSFER_HANDLE transferHandle, uintptr_t context);
```

Returns

None.

Description

SPI Driver Transfer Event Handler Function Pointer

This data type defines the required function signature for the SPI driver transfer event handling callback function. A client must register a pointer using the transfer event handling function whose function signature (parameter and return value types) match the types specified by this function pointer in order to receive transfer related event calls back from the driver.

The parameters and return values are described here and a partial example implementation is provided.

Remarks

- If the event is [DRV_SPI_TRANSFER_EVENT_COMPLETE](#), it means that the data was transferred successfully.
- If the event is [DRV_SPI_TRANSFER_EVENT_ERROR](#), it means that the data was not transferred successfully.
- The transferHandle parameter contains the transfer handle of the transfer request that is associated with the event.
- The context parameter contains the a handle to the client context, provided at the time the event handling function was registered using the [DRV_SPI_TransferEventHandlerSet](#) function. This context handle value is passed back to the client as the "context" parameter. It can be any value necessary to identify the client context or instance (such as a pointer to the client's data) of the client that made the transfer add request.
- The event handler function executes in interrupt context of the peripheral. Hence it is recommended of the application to not perform process intensive or blocking operations with in this function.
- The [DRV_SPI_ReadTransferAdd](#), [DRV_SPI_WriteTransferAdd](#) and [DRV_SPI_WriteReadTransferAdd](#) functions can be called in the event handler to add a transfer request to the driver queue. These functions can only be called to add transfers to the driver instance whose event handler is running. For example, SPI2 driver transfer requests cannot be added in SPI1 driver event handler. Similarly, SPIx transfer requests should not be added in event handler of any other peripheral.

Example

```
void APP_MyTransferEventHandler( DRV_SPI_TRANSFER_EVENT event,  
                                DRV_SPI_TRANSFER_HANDLE transferHandle,  
                                uintptr_t context )
```

```

{
    MY_APP_DATA_STRUCT pAppData = (MY_APP_DATA_STRUCT) context;

    switch(event)
    {
        case DRV_SPI_TRANSFER_EVENT_COMPLETE:
            // Handle the completed transfer.
            break;

        case DRV_SPI_TRANSFER_EVENT_ERROR:
            // Handle error.
            break;
    }
}

```

Parameters

Parameters	Description
event	Identifies the type of event
transferHandle	Handle identifying the transfer to which the event relates
context	Value identifying the context of the application that registered the event handling function.

DRV_SPI_TRANSFER_HANDLE_INVALID Macro

Definition of an invalid transfer handle.

C

```
#define DRV_SPI_TRANSFER_HANDLE_INVALID
```

Description

SPI Driver Invalid Transfer Handle

This is the definition of an invalid transfer handle. An invalid transfer handle is returned by [DRV_SPI_WriteReadTransferAdd](#) or [DRV_SPI_WriteTransferAdd](#) or [DRV_SPI_ReadTransferAdd](#) function if the buffer add request was not successful. It can happen due to invalid arguments or lack of space in the queue.

Remarks

None

SPI Flash Driver Libraries Help

This section describes the SPI flash based driver libraries.

AT25DF Driver Library Help

This section describes the AT25DF driver library.

Introduction

This driver provides an interface to access the AT25DF Flash Memory over the SPI interface.

Description

This library provides a non-blocking interface to read, write and erase AT25DF Flash Memory. The library uses the SPI peripheral library (PLIB) to interface with the AT25DF Flash.

Key Features:

- Supports Multiple variants of the AT25DF Flash devices
- Supports a single instance of the AT25DF Flash and a single client to the driver
- Supports page writes and Sector/Bulk/Chip Erase Operations
- Supports writes to random memory address and across page boundaries
- The library interface is compliant to the block media interface expected by the Memory Driver. This allows running a file system on the AT25DF Flash using the Memory Driver and the File System Service
- The library can be used in both bare-metal and RTOS environments

Using the Library

This section describes the basic architecture of the AT25DF Library and provides information on how to use the library.

Description

The AT25DF library provides non-blocking APIs to read, write and Sector/Bulk/Chip erase AT25DF Flash. It uses the SPI peripheral library to interface with the AT25DF Flash.

- The library provides APIs to perform reads, writes and erase from/to any Flash memory address, with number of bytes spanning multiple pages
- The library provides API to perform page write to Flash. Here, the memory start address must be aligned to the Flash page boundary
- Application can either register a callback to get notified once the data transfer is complete or can poll the status of the data transfer
- The library interface complies to the block driver interface expected by the Memory Driver. This allows application to run a file system on the AT25DF Flash media using the Memory Driver and the File System Service
- The library can be used in both bare-metal and RTOS environments

Abstraction Model

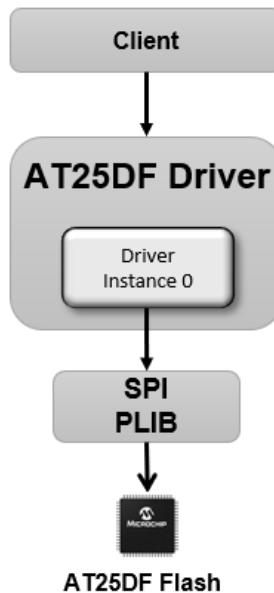
This library provides a low-level abstraction of the AT25DF Flash Driver Library with a convenient C language interface.

Description

The AT25DF library interface provides read, write and erase functions that abstract out the internal workings of the AT25DF driver and the underlying SPI protocol. The AT25DF library supports a single instance of the AT25DF Flash and a single client.

The client can be:

- Application - Directly access the AT25DF Flash using the APIs provided by the AT25DF library
- Memory Driver - Application can run a file system on the AT25DF Flash by connecting it to the Memory Driver which can further be connected to the File System Service



AT25DF Driver Block Diagram

How the Library Works

This section provides information on how the AT25DF driver library works.

Description

- The AT25DF Driver Library registers an event handler with the underlying SPI peripheral library (PLIB). This event handler is called by the PLIB from the interrupt context to notify the AT25DF driver that the requested transfer is complete
- The library's state machine is driven from the interrupt context. Once a transfer is complete a callback (if registered by the application) is given to the application from the interrupt context
- The library does not support queuing of more than one requests. The application must check and ensure that any previous request is completed before submitting a new one. This can be done either by polling the status of the data transfer or registering a callback

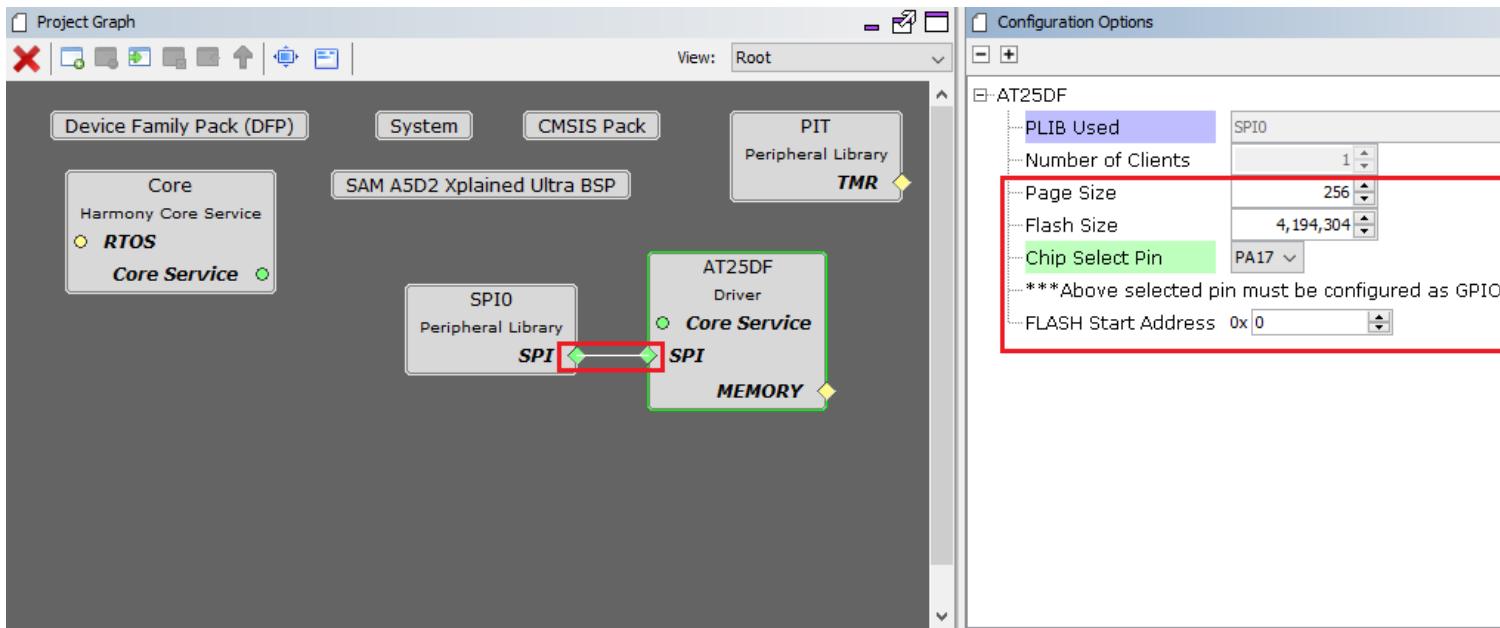
Configuring the Library

This section provides information on how to configure the AT25DF Driver library.

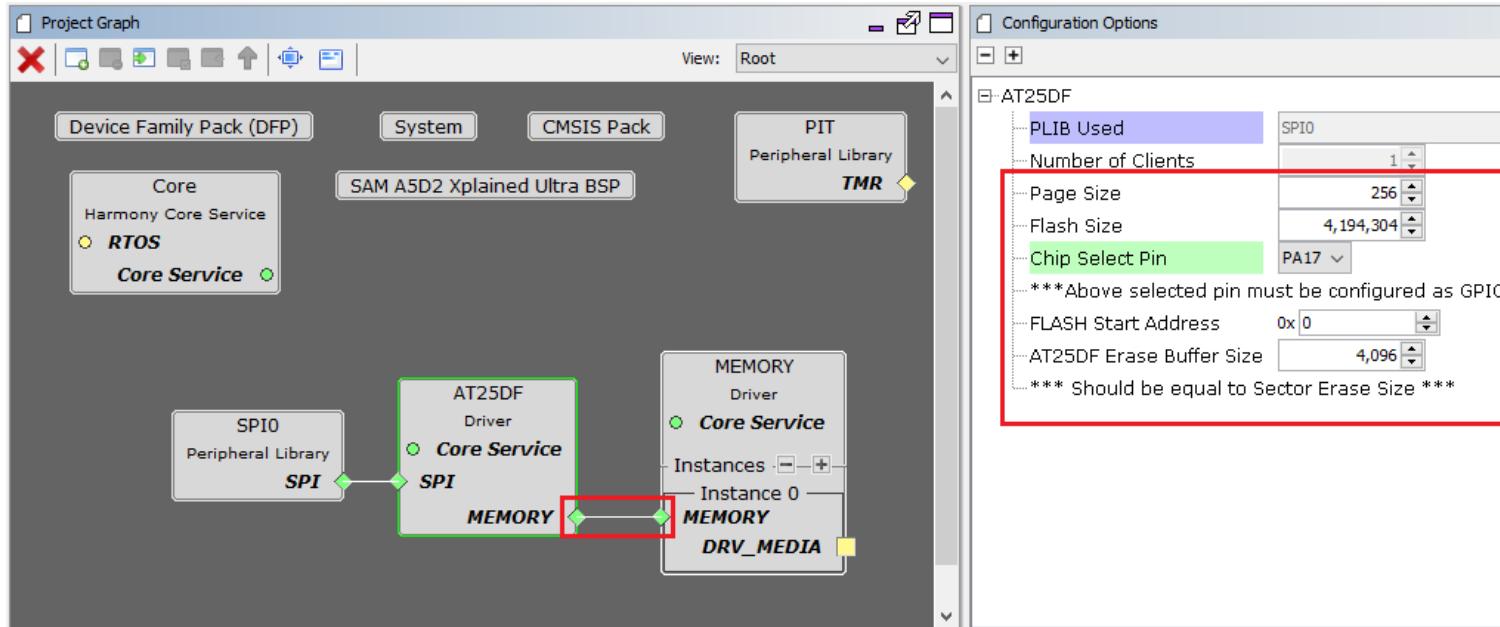
Description

AT25DF Driver library should be configured via the MHC. Below is the snapshot of the MHC configuration window for configuring the

AT25DF driver and a brief description of various configuration options.



AT25DF Driver without connecting to Memory Driver



AT25DF Driver with connection to Memory Driver

User Configurations:

- PLIB Used:**
 - Indicates the SPI peripheral instance used by the AT25DF driver
- Number of Clients:**
 - Indicates maximum number of clients
 - Always set to one as it supports only a single client
- FLASH Page Size:**
 - Size of one page of FLASH memory (in bytes)
- FLASH Flash Size:**
 - Total size of the FLASH memory (in bytes)
- Chip Select Pin:**

- FLASH chip select pin (active low)
- This pin must be configured as GPIO output in "Pin Settings" configuration
- **AT25DF FLASH Start Address:**
 - The FLASH memory start address.
 - This is mainly used when the AT25DF driver is connected to the Memory Block Driver
- **AT25DF Erase Buffer Size:**
 - Specifies the size for erase buffer used by Memory driver
 - The size of the buffer should be equal to erase sector size as the memory driver will call [DRV_AT25DF_SectorErase](#)
 - This option appears only when the AT25DF driver is connected to the Memory driver for block operations

Building the Library

This section provides information on how the AT25DF Driver Library can be built.

Description



MHC *All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.*

Library Interface

a) System Functions

	Name	Description
≡	DRV_AT25DF_Initialize	Initializes the AT25DF FLASH device

b) Core Client Functions

	Name	Description
≡	DRV_AT25DF_Open	Opens the specified AT25DF driver instance and returns a handle to it.
≡	DRV_AT25DF_Close	Closes the opened-instance of the AT25DF driver.

c) Data Transfer Functions

	Name	Description
≡	DRV_AT25DF_BlockErase	Erase a block from the specified block start address.
≡	DRV_AT25DF_ChipErase	Erase entire flash memory.
≡	DRV_AT25DF_EventHandlerSet	Allows a client to identify a transfer event handling function for the driver to call back when the requested transfer has finished.
≡	DRV_AT25DF_PageWrite	Writes one page of data starting at the specified address.
≡	DRV_AT25DF_Read	Reads 'n' bytes of data from the specified start address of FLASH.
≡	DRV_AT25DF_SectorErase	Erase the sector from the specified block start address.
≡	DRV_AT25DF_Status	Gets the current status of the AT25DF driver module.
≡	DRV_AT25DF_TransferStatusGet	Gets the current status of the transfer request.
≡	DRV_AT25DF_Write	Writes 'n' bytes of data starting at the specified address.

d) Block Interface Functions

	Name	Description
≡	DRV_AT25DF_GeometryGet	Returns the geometry of the device.

e) Data Types and Constants

	Name	Description
	DRV_AT25DF_EVENT_HANDLER	Pointer to a AT25DF Driver Event handler function

	DRV_AT25DF_GEOMETRY	Defines the data type for AT25DF FLASH Geometry details.
	DRV_AT25DF_TRANSFER_STATUS	Defines the data type for AT25DF Driver transfer status.

Description

This section describes the API functions of the AT25DF Driver library.

Refer to each section for a detailed description.

a) System Functions

DRV_AT25DF_Initialize Function

Initializes the AT25DF FLASH device

C

```
SYS_MODULE_OBJ DRV_AT25DF_Initialize(const SYS_MODULE_INDEX drvIndex, const SYS_MODULE_INIT *  
const init);
```

Returns

If successful, returns a valid handle to a driver instance object. Otherwise, returns [SYS_MODULE_OBJ_INVALID](#).

Description

This routine initializes the AT25DF FLASH device driver making it ready for clients to open and use. The initialization data is specified by the init parameter. It is a single instance driver, so this API should be called only once.

Remarks

This routine must be called before any other DRV_AT25DF routine is called. This routine should only be called once during system initialization.

Preconditions

None.

Example

```
SYS_MODULE_OBJ sysObjDrvAT25DF;

DRV_AT25DF_PLIB_INTERFACE drvAT25DFPlibAPI = {  
    .writeRead = (DRV_AT25DF_PLIB_WRITE_READ)SPI0_WriteRead,  
    .write = (DRV_AT25DF_PLIB_WRITE)SPI0_Write,  
    .read = (DRV_AT25DF_PLIB_READ)SPI0_Read,  
    .isBusy = (DRV_AT25DF_PLIB_IS_BUSY)SPI0_IsBusy,  
    .callbackRegister = (DRV_AT25DF_PLIB_CALLBACK_REGISTER)SPI0_CallbackRegister,  
};

DRV_AT25DF_INIT drvAT25DFInitData = {  
    .spiPlib = &drvAT25DFPlibAPI,  
    .numClients = DRV_AT25DF_CLIENTS_NUMBER_IDX,  
    .pageSize = DRV_AT25DF_PAGE_SIZE,  
    .flashSize = DRV_AT25DF_FLASH_SIZE,  
    .blockStartAddress = 0x0,  
    .chipSelectPin = DRV_AT25DF_CHIP_SELECT_PIN_IDX  
};

sysObjDrvAT25DF = DRV_AT25DF_Initialize(DRV_AT25DF_INDEX, (SYS_MODULE_INIT  
*)&drvAT25DFInitData);
```

Parameters

Parameters	Description
drvIndex	Identifier for the instance to be initialized.
init	Pointer to the init data structure containing any data necessary to initialize the driver.

Function

```
SYS_MODULE_OBJ DRV_AT25DF_Initialize(
const   SYS_MODULE_INDEX drvIndex,
const   SYS_MODULE_INIT * const init
)
```

b) Core Client Functions

DRV_AT25DF_Open Function

Opens the specified AT25DF driver instance and returns a handle to it.

C

```
DRV_HANDLE DRV_AT25DF_Open(const SYS_MODULE_INDEX drvIndex, const DRV_IO_INTENT ioIntent);
```

Returns

If successful, the routine returns a valid open-instance handle (a number identifying both the caller and the module instance).

If an error occurs, the return value is **DRV_HANDLE_INVALID**. Error can occur

- if the driver has been already opened once and in use.
- if the driver instance being opened is not initialized or is invalid.

Description

This routine opens the specified AT25DF driver instance and provides a handle that must be provided to all other client-level operations to identify the caller and the instance of the driver. The ioIntent parameter defines how the client interacts with this driver instance.

This driver is a single client driver, so DRV_AT25DF_Open API should be called only once until driver is closed.

Remarks

This driver ignores the ioIntent argument.

The handle returned is valid until the **DRV_AT25DF_Close** routine is called.

Preconditions

Function **DRV_AT25DF_Initialize** must have been called before calling this function.

Example

```
DRV_HANDLE handle;

handle = DRV_AT25DF_Open(DRV_AT25DF_INDEX, DRV_IO_INTENT_READWRITE);
if (handle == DRV_HANDLE_INVALID)
{
    // Unable to open the driver
    // May be the driver is not initialized
}
```

Parameters

Parameters	Description
drvIndex	Identifier for the object instance to be opened

ioIntent	Zero or more of the values from the enumeration DRV_IO_INTENT "ORed" together to indicate the intended use of the driver.
----------	---

Function

```
DRV_HANDLE DRV_AT25DF_Open
(
const  SYS_MODULE_INDEX drvIndex,
const  DRV_IO_INTENT ioIntent
)
```

DRV_AT25DF_Close Function

Closes the opened-instance of the AT25DF driver.

C

```
void DRV_AT25DF_Close(const DRV_HANDLE handle);
```

Returns

None.

Description

This routine closes opened-instance of the AT25DF driver, invalidating the handle. A new handle must be obtained by calling [DRV_AT25DF_Open](#) before the caller may use the driver again.

Remarks

None.

Preconditions

[DRV_AT25DF_Open](#) must have been called to obtain a valid opened device handle.

Example

```
// 'handle', returned from the DRV_AT25DF_Open
DRV_AT25DF_Close(handle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
void DRV_AT25DF_Close( const DRV_Handle handle )
```

c) Data Transfer Functions

DRV_AT25DF_BlockErase Function

Erase a block from the specified block start address.

C

```
bool DRV_AT25DF_BlockErase(const DRV_HANDLE handle, uint32_t address);
```

Returns

false

- if Write enable fails before sending sector erase command to flash
 - if block erase command itself fails
- true
- if the erase request is successfully sent to the flash

Description

This function schedules a non-blocking block erase operation of flash memory. The block size is 64 KByte.

The requesting client should call [DRV_AT25DF_TransferStatusGet\(\)](#) API to know the current status of the request.

Remarks

This routine will block wait until erase request is submitted successfully.

Client should wait until erase is complete to send next transfer request.

Preconditions

The [DRV_AT25DF_Open\(\)](#) routine must have been called for the specified AT25DF driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_AT25DF_Open
uint32_t blockStart = 0;

if(false == DRV_AT25DF_BlockErase(handle, blockStart))
{
    // Error handling here
}

// Wait for erase to be completed
while(DRV_AT25DF_TRANSFER_STATUS_BUSY == DRV_AT25DF_TransferStatusGet(handle));
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
address	block start address to be erased.

Function

```
bool DRV_AT25DF_BlockErase(const DRV_HANDLE handle, uint32_t address);
```

DRV_AT25DF_ChipErase Function

Erase entire flash memory.

C

```
bool DRV_AT25DF_ChipErase(const DRV_HANDLE handle);
```

Returns

false

- if Write enable fails before sending sector erase command to flash
- if chip erase command itself fails

true

- if the erase request is successfully sent to the flash

Description

This function schedules a non-blocking chip erase operation of flash memory.

The requesting client should call [DRV_AT25DF_TransferStatusGet\(\)](#) API to know the current status of the request.

Remarks

This routine will block wait until erase request is submitted successfully.

Client should wait until erase is complete to send next transfer request.

Preconditions

The `DRV_AT25DF_Open()` routine must have been called for the specified AT25DF driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_AT25DF_Open

if(false == DRV_AT25DF_ChipErase(handle))
{
    // Error handling here
}

// Wait for erase to be completed
while(DRV_AT25DF_TRANSFER_STATUS_BUSY == DRV_AT25DF_TransferStatusGet(handle));
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
bool DRV_AT25DF_ChipErase(const DRV_HANDLE handle);
```

DRV_AT25DF_EventHandlerSet Function

Allows a client to identify a transfer event handling function for the driver to call back when the requested transfer has finished.

C

```
void DRV_AT25DF_EventHandlerSet(const DRV_HANDLE handle, const DRV_AT25DF_EVENT_HANDLER
eventHandler, const uintptr_t context);
```

Returns

None.

Description

This function allows a client to register a transfer event handling function with the driver to call back when the requested transfer has finished.

The event handler should be set before the client submits any transfer requests that could generate events. The event handler once set, persists until the client closes the driver or sets another event handler (which could be a "NULL" pointer to indicate no callback).

Remarks

If the client does not want to be notified when the queued buffer transfer has completed, it does not need to register a callback.

Preconditions

`DRV_AT25DF_Open` must have been called to obtain a valid opened device handle.

Example

```
#define BUFFER_SIZE 256
#define MEM_ADDRESS 0x00

// myAppObj is an application specific state data object.
MY_APP_OBJ myAppObj;

uint8_t myBuffer[BUFFER_SIZE];

// myHandle is the handle returned from DRV_AT25DF_Open API.

// Client registers an event handler with driver. This is done once
```

```

DRV_AT25DF_EventHandlerSet( myHandle, APP_AT25DFTransferEventHandler, (uintptr_t)&myAppObj ) ;

if (DRV_AT25DF_Read(myHandle, myBuffer, BUFFER_SIZE, MEM_ADDRESS) == false)
{
    // Error handling here
}

// The registered event handler is called when the request is complete.

void APP_AT25DFTransferEventHandler(DRV_AT25DF_TRANSFER_STATUS event, uintptr_t context)
{
    // The context handle was set to an application specific
    // object. It is now retrievable easily in the event handler.
    MY_APP_OBJ* pMyAppObj = (MY_APP_OBJ *) context;

    switch(event)
    {
        case DRV_AT25DF_TRANSFER_STATUS_COMPLETED:
            // This means the data was transferred.
            break;

        case DRV_AT25DF_TRANSFER_STATUS_ERROR:
            // Error handling here.
            break;

        default:
            break;
    }
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine.
eventHandler	Pointer to the event handler function.
context	The value of parameter will be passed back to the client unchanged, when the eventHandler function is called. It can be used to identify any client specific data object that identifies the instance of the client module (for example, it may be a pointer to the client module's state structure).

Function

```

void DRV_AT25DF_EventHandlerSet(
    const DRV_HANDLE handle,
    const DRV_AT25DF_EVENT_HANDLER eventHandler,
    const uintptr_t context
)

```

DRV_AT25DF_PageWrite Function

Writes one page of data starting at the specified address.

C

```

bool DRV_AT25DF_PageWrite(const DRV_HANDLE handle, void * txData, uint32_t address);

```

Returns

false

- if handle is invalid
- if the pointer to the transmit data is NULL
- if the driver is busy handling another transfer request

true

- if the write request is accepted.

Description

This function schedules a non-blocking write operation for writing one page of data starting from the given address of the FLASH.

The requesting client should call [DRV_AT25DF_TransferStatusGet](#) API to know the current status of the request OR the requesting client can register a callback function with the driver to get notified of the status.

Remarks

None.

Preconditions

[DRV_AT25DF_Open](#) must have been called to obtain a valid opened device handle.

"address" provided must be page boundary aligned in order to avoid overwriting the data in the beginning of the page.

Example

```
#define PAGE_SIZE 256
#define MEM_ADDRESS 0x0

uint8_t writeBuffer[PAGE_SIZE];

// myHandle is the handle returned from DRV_AT25DF_Open API.
// In the below example, the transfer status is polled. However, application can
// register a callback and get notified when the transfer is complete.

if (DRV_AT25DF_PageWrite(myHandle, writeBuffer, MEM_ADDRESS) != true)
{
    // Error handling here
}
else
{
    // Wait for write to be completed
    while(DRV_AT25DF_TransferStatusGet(myHandle) == DRV_AT25DF_TRANSFER_STATUS_BUSY);
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
txData	The source buffer containing data to be written to the AT25DF FLASH
address	Write memory start address from where the data should be written. It must be page boundary aligned in order to avoid overwriting the data in the beginning of the page.

Function

bool DRV_AT25DF_PageWrite(const [DRV_HANDLE](#) handle, void *txData, uint32_t address)

DRV_AT25DF_Read Function

Reads 'n' bytes of data from the specified start address of FLASH.

C

```
bool DRV_AT25DF_Read(const DRV_HANDLE handle, void * rxData, uint32_t rxDataLength, uint32_t
address);
```

Returns

false

- if handle is invalid
- if the pointer to the receive buffer is NULL or number of bytes to read is 0
- if the driver is busy handling another transfer request

true

- if the read request is accepted.

Description

This function schedules a non-blocking read operation for the requested number of data bytes from the given address of the FLASH.

The requesting client should call [DRV_AT25DF_TransferStatusGet](#) API to know the current status of the request OR the requesting client can register a callback function with the driver to get notified of the status.

Remarks

None.

Preconditions

[DRV_AT25DF_Open](#) must have been called to obtain a valid opened device handle.

Example

```
#define BUFFER_SIZE 1024
#define MEM_ADDRESS 0x00

uint8_t readBuffer[BUFFER_SIZE];

// myHandle is the handle returned from DRV_AT25DF_Open API.
// In the below example, the transfer status is polled. However, application can
// register a callback and get notified when the transfer is complete.

if (DRV_AT25DF_Read(myHandle, readBuffer, BUFFER_SIZE, MEM_ADDRESS) != true)
{
    // Error handling here
}
else
{
    // Wait for read to be completed
    while(DRV_AT25DF_TransferStatusGet(myHandle) == DRV_AT25DF_TRANSFER_STATUS_BUSY);
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
rxData	Buffer pointer into which the data read from the DRV_AT25DF Flash memory will be placed.
rxDataLength	Total number of bytes to be read.
address	Memory start address from where the data should be read.

Function

bool DRV_AT25DF_Read(const [DRV_HANDLE](#) handle, void *rxData, uint32_t rxDataLength, uint32_t address)

[DRV_AT25DF_SectorErase Function](#)

Erase the sector from the specified block start address.

C

```
bool DRV_AT25DF_SectorErase(const DRV\_HANDLE handle, uint32_t address);
```

Returns

false

- if Write enable fails before sending sector erase command to flash
- if sector erase command itself fails

true

- if the erase request is successfully sent to the flash

Description

This function schedules a non-blocking sector erase operation of flash memory. Each Sector is of 4 KByte.

The requesting client should call [DRV_AT25DF_TransferStatusGet\(\)](#) API to know the current status of the request.

Remarks

This routine will block wait until erase request is submitted successfully.

Client should wait until erase is complete to send next transfer request.

Preconditions

The [DRV_AT25DF_Open\(\)](#) routine must have been called for the specified AT25DF driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_AT25DF_Open
uint32_t sectorStart = 0;

if(false == DRV_AT25DF_SectorErase(handle, sectorStart))
{
    // Error handling here
}

// Wait for erase to be completed
while(DRV_AT25DF_TRANSFER_STATUS_BUSY == DRV_AT25DF_TransferStatusGet(handle));
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
address	block start address from where a sector needs to be erased.

Function

```
bool DRV_AT25DF_SectorErase(const DRV_HANDLE handle, uint32_t address);
```

DRV_AT25DF_Status Function

Gets the current status of the AT25DF driver module.

C

```
SYS_STATUS DRV_AT25DF_Status(const SYS_MODULE_INDEX drvIndex);
```

Returns

SYS_STATUS_READY - Indicates that the driver is ready and accept requests for new operations.

SYS_STATUS_UNINITIALIZED - Indicates the driver is not initialized.

Description

This routine provides the current status of the AT25DF driver module.

Remarks

None.

Preconditions

Function [DRV_AT25DF_Initialize](#) should have been called before calling this function.

Example

```
SYS_STATUS status;

status = DRV_AT25DF_Status(DRV_AT25DF_INDEX);
```

Parameters

Parameters	Description
drvIndex	Identifier for the instance used to initialize driver

Function

`SYS_STATUS DRV_AT25DF_Status(const SYS_MODULE_INDEX drvIndex)`

DRV_AT25DF_TransferStatusGet Function

Gets the current status of the transfer request.

C

`DRV_AT25DF_TRANSFER_STATUS DRV_AT25DF_TransferStatusGet(const DRV_HANDLE handle);`

Returns

One of the status element from the enum `DRV_AT25DF_TRANSFER_STATUS`.

Description

This routine gets the current status of the transfer request.

Remarks

None.

Preconditions

`DRV_AT25DF_PageWrite`, `DRV_AT25DF_Write` or `DRV_AT25DF_Read` must have been called to obtain the status of transfer.

Example

```
// myHandle is the handle returned from DRV_AT25DF_Open API.

if (DRV_AT25DF_TransferStatusGet(myHandle) == DRV_AT25DF_TRANSFER_STATUS_COMPLETED)
{
    // Operation Done
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

`DRV_AT25DF_TRANSFER_STATUS DRV_AT25DF_TransferStatusGet(const DRV_HANDLE handle)`

DRV_AT25DF_Write Function

Writes 'n' bytes of data starting at the specified address.

C

`bool DRV_AT25DF_Write(const DRV_HANDLE handle, void * txData, uint32_t txDataLength, uint32_t address);`

Returns

`false`

- if handle is invalid
- if the pointer to transmit buffer is NULL or number of bytes to write is 0
- if the driver is busy handling another transfer request

true

- if the write request is accepted.

Description

This function schedules a non-blocking write operation for writing txDataLength bytes of data starting from given address of FLASH.

The requesting client should call [DRV_AT25DF_TransferStatusGet](#) API to know the current status of the request OR the requesting client can register a callback function with the driver to get notified of the status.

Remarks

None.

Preconditions

[DRV_AT25DF_Open](#) must have been called to obtain a valid opened device handle.

Example

```

#define PAGE_SIZE      256
#define BUFFER_SIZE    1024
#define MEM_ADDRESS    0x00

uint8_t writeBuffer[BUFFER_SIZE];

// myHandle is the handle returned from DRV_AT25DF_Open API.
// In the below example, the transfer status is polled. However, application can
// register a callback and get notified when the transfer is complete.

if (DRV_AT25DF_Write(myHandle, writeBuffer, BUFFER_SIZE, MEM_ADDRESS) != true)
{
    // Error handling here
}
else
{
    // Wait for write to be completed
    while(DRV_AT25DF_TransferStatusGet(myHandle) == DRV_AT25DF_TRANSFER_STATUS_BUSY);
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
txData	The source buffer containing data to be programmed into AT25DF FLASH
txDataLength	Total number of bytes to be written.
address	Memory start address from where the data should be written

Function

bool DRV_AT25DF_Write(const [DRV_HANDLE](#) handle, void *txData, uint32_t txDataLength, uint32_t address)

d) Block Interface Functions

[DRV_AT25DF_GeometryGet Function](#)

Returns the geometry of the device.

C

```
bool DRV_AT25DF_GeometryGet(const DRV\_HANDLE handle, DRV\_AT25DF\_GEOMETRY * geometry);
```

Returns

- false
- if handle is invalid
- true
- if able to get the geometry details of the flash

Description

This API gives the following geometrical details of the DRV_AT25DF Flash:

- Number of Read/Write/Erase Blocks and their size in each region of the device

Remarks

None.

Preconditions

[DRV_AT25DF_Open](#) must have been called to obtain a valid opened device handle.

Example

```
DRV_AT25DF_GEOMETRY flashGeometry;
uint32_t readBlockSize, writeBlockSize, eraseBlockSize;
uint32_t nReadBlocks, nReadRegions, totalFlashSize;

// myHandle is the handle returned from DRV_AT25DF_Open API.

DRV_AT25DF_GeometryGet(myHandle, &flashGeometry);

readBlockSize = flashGeometry.readBlockSize;
nReadBlocks = flashGeometry.readNumBlocks;
nReadRegions = flashGeometry.readNumRegions;

writeBlockSize = flashGeometry.writeBlockSize;
eraseBlockSize = flashGeometry.eraseBlockSize;

totalFlashSize = readBlockSize * nReadBlocks * nReadRegions;
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
geometry	Pointer to flash device geometry table instance

Function

bool DRV_AT25DF_GeometryGet(const [DRV_HANDLE](#) handle, [DRV_AT25DF_GEOMETRY](#) *geometry)

e) Data Types and Constants

[DRV_AT25DF_EVENT_HANDLER](#) Type

Pointer to a AT25DF Driver Event handler function

C

```
typedef void (* DRV\_AT25DF\_EVENT\_HANDLER)(DRV\_AT25DF\_TRANSFER\_STATUS event, uintptr\_t context);
```

Returns

None.

Description

AT25DF Driver Transfer Event Handler Function Pointer

This data type defines the required function signature for the AT25DF driver event handling callback function. A client must register a pointer using the event handling function whose function signature (parameter and return value types) match the types specified by this function pointer in order to receive transfer related event calls back from the driver.

The parameters and return values are described here and a partial example implementation is provided.

Remarks

If the event is DRV_AT25DF_TRANSFER_STATUS_COMPLETED, it means that the data was transferred successfully.

If the event is DRV_AT25DF_TRANSFER_STATUS_ERROR, it means that the data was not transferred successfully.

The context parameter contains the handle to the client context, provided at the time the event handling function was registered using the [DRV_AT25DF_EventHandlerSet](#) function. This context handle value is passed back to the client as the "context" parameter. It can be any value necessary to identify the client context or instance (such as a pointer to the client's data) instance of the client that made the buffer add request.

The event handler function executes in the driver's interrupt context. It is recommended of the application to not perform process intensive or blocking operations with in this function.

The [DRV_AT25DF_Read](#), [DRV_AT25DF_Write](#) and [DRV_AT25DF_PageWrite](#) functions can be called in the event handler to submit a request to the driver.

Example

```
void APP_MyTransferEventHandler( DRV_AT25DF_TRANSFER_STATUS event, uintptr_t context )
{
    MY_APP_DATA_STRUCT* pAppData = (MY_APP_DATA_STRUCT*) context;

    switch(event)
    {
        case DRV_AT25DF_TRANSFER_STATUS_COMPLETED:
            // Handle the transfer complete event.
            break;

        case DRV_AT25DF_TRANSFER_STATUS_ERROR:
        default:
            // Handle error.
            break;
    }
}
```

Parameters

Parameters	Description
event	Identifies the type of event
context	Value identifying the context of the application that registered the event handling function.

DRV_AT25DF_GEOMETRY Structure

Defines the data type for AT25DF FLASH Geometry details.

C

```
typedef struct {
    uint32_t readBlockSize;
    uint32_t readNumBlocks;
    uint32_t readNumRegions;
    uint32_t writeBlockSize;
    uint32_t writeNumBlocks;
    uint32_t writeNumRegions;
    uint32_t eraseBlockSize;
```

```

    uint32_t eraseNumBlocks;
    uint32_t eraseNumRegions;
    uint32_t blockStartAddress;
} DRV_AT25DF_GEOMETRY;

```

Description

DRV_AT25DF Geometry data

This will be used to get the geometry details of the attached AT25DF FLASH device.

Remarks

None.

DRV_AT25DF_TRANSFER_STATUS Enumeration

Defines the data type for AT25DF Driver transfer status.

C

```

typedef enum {
    DRV_AT25DF_TRANSFER_STATUS_BUSY,
    DRV_AT25DF_TRANSFER_STATUS_COMPLETED,
    DRV_AT25DF_TRANSFER_STATUS_ERROR
} DRV_AT25DF_TRANSFER_STATUS;

```

Members

Members	Description
DRV_AT25DF_TRANSFER_STATUS_BUSY	Transfer is being processed
DRV_AT25DF_TRANSFER_STATUS_COMPLETED	Transfer is successfully completed
DRV_AT25DF_TRANSFER_STATUS_ERROR	Transfer had error

Description

DRV_AT25DF Transfer Status

This will be used to indicate the current transfer status of the AT25DF FLASH driver operations.

Remarks

None.

SQI Flash Driver Libraries Help

This section describes the SQI flash based driver libraries.

MX25L Driver Library Help

This section describes the MX25L driver Library.

Introduction

This section provides an interface to access the MX25L Flash Memory over the QSPI interface.

Description

This driver provides a non-blocking interface to read, write and erase MX25L Flash memory. The driver uses the QSPI peripheral library to interface with the MX25L Flash.

Key Features:

- Supports Multiple variants of the MX25L Flash devices
- Supports a single instance of the MX25L Flash and a single client to the driver
- Supports Sector/Bulk/Chip Erase Operations
- Supports writes to random memory address within page boundaries
- The library can be used in both Bare-Metal and RTOS environments

Using the Library

This section describes the basic architecture of the MX25L driver and provides information on how it works.

Description

The MX25L driver provides non-blocking APIs to read, write and erase MX25L Flash memory.

The MX25L driver can be used in following ways:

- To perform page write to MX25L Flash. Here, the memory start address must be aligned to the page boundary
- To perform Sector/Bulk/Chip Erase operations
- To unlock flash before performing Erase/Write operations
- To read flash JEDEC-ID
- To interface with the Memory driver to perform block operations on the MX25L Flash

Note:

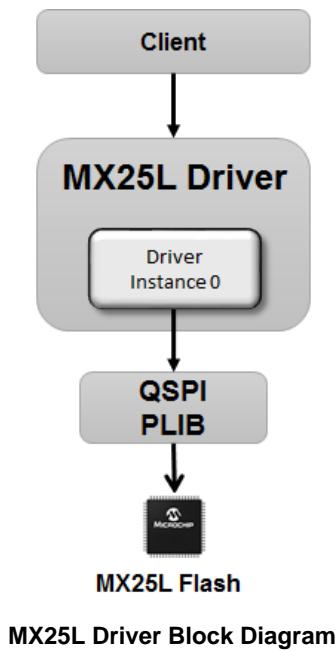
- The client should poll for the status of the data transfer

Abstraction Model

This section provides an abstraction of MX25L driver Library.

Description

The MX25L driver interface provides read, write and Erase functions that abstract out the internal workings of the MX25L driver and the underlying QSPI/SQI protocol.



How the Library Works

This section describes the basic architecture of the MX25L driver and provides information on how it works.

Description

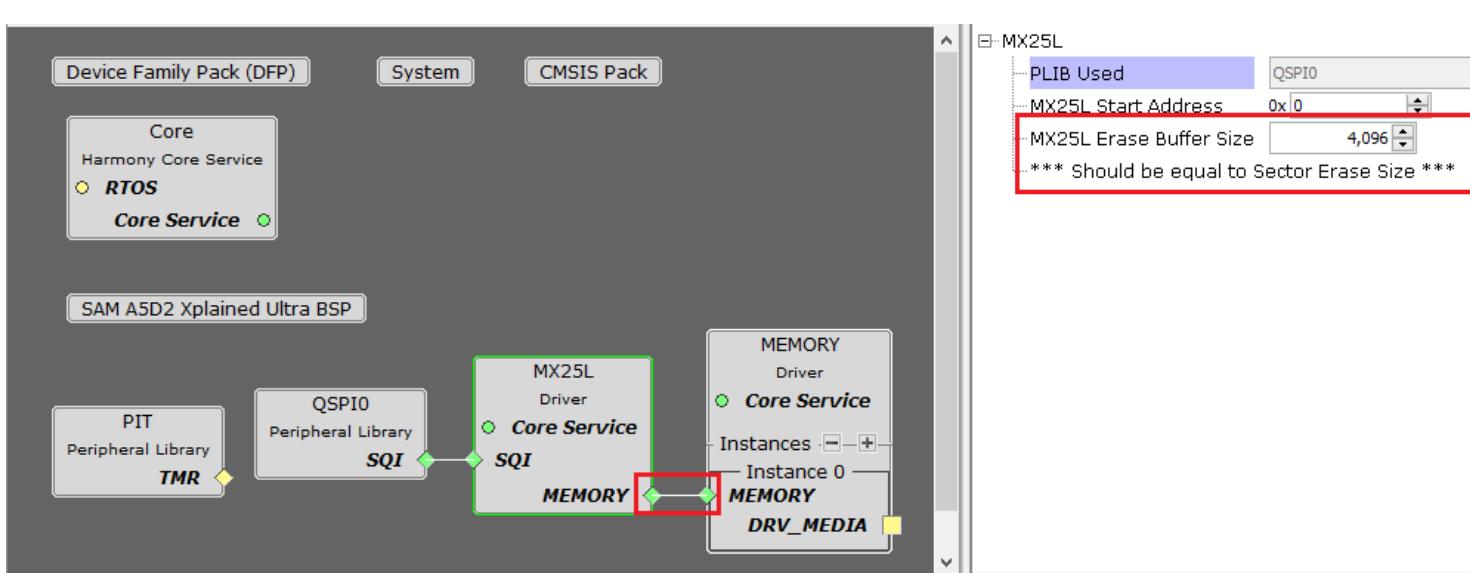
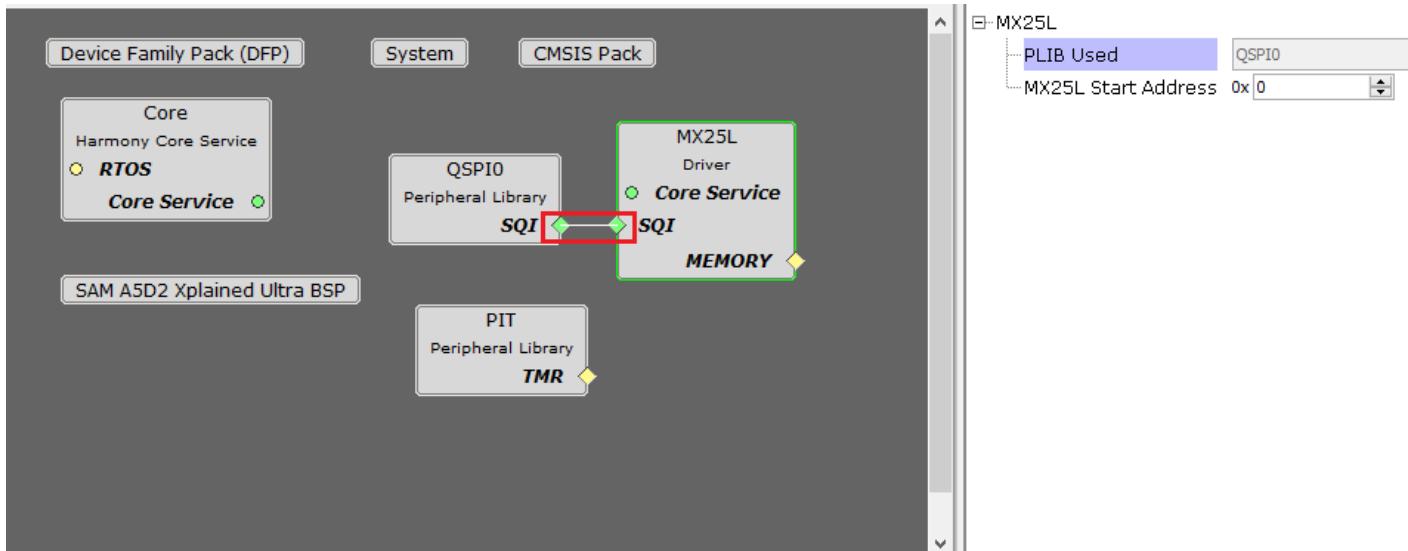
- The MX25L Driver performs initialization and puts the driver to ready state. This status of the driver can be checked using [DRV_MX25L_Status\(\)](#)
- The MX25L driver library performs set of flash operations during [DRV_MX25L_Open\(\)](#). If any of the below flash operations fails, an invalid Handle will be returned. [DRV_MX25L_Open\(\)](#) can be repeatedly called until it returns a valid handle.
 - Resets the Flash
 - Configures the flash device to QUAD IO Mode
 - Unlocks the flash
- When the client requests for device geometry, it queries for the JEDEC-Id and populates the geometry table [DRV_MX25L_GEOMETRY](#) appropriately
- The driver does not support queuing of more than one requests. The application must check and ensure that any previous request is completed before submitting a new one. This can be done by polling the status of data transfer using [DRV_MX25L_TransferStatusGet\(\)](#)

Configuring the Library

This section provides information on how to configure the MX25L driver.

Description

The MX25L driver library should be configured through the MHC. The following figures show the MHC configuration window for the MX25L driver and brief description.



Configuration Options:

- **PLIB Used:**
 - Specifies the Peripheral library connected
- **Number Of Clients:**
 - Indicates maximum number of clients
 - Always set to one as it supports only a single client
- **MX25L Start Address:**
 - Specifies the flash memory start address to be used for Transfer operations
 - The start address will be populated in the device geometry table [DRV_MX25L_GEOMETRY](#)
- **MX25L Erase Buffer Size:**
 - Specifies the size for erase buffer used by Memory driver
 - The size of the buffer should be equal to erase sector size as the memory driver will call [DRV_MX25L_SectorErase](#)
 - This option appears only when the MX25L driver is connected to the Memory driver for block operations

Building the Library

This section provides information on how the MX25L driver can be built.

Description



All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

Library Interface

a) System Functions

	Name	Description
≡	DRV_MX25L_Initialize	Initializes the MX25L Driver

b) Core Client Functions

	Name	Description
≡	DRV_MX25L_Open	Opens the specified MX25L driver instance and returns a handle to it
≡	DRV_MX25L_Close	Closes an opened-instance of the MX25L driver

c) Transfer Functions

	Name	Description
≡	DRV_MX25L_ChipErase	Erase entire flash memory.
≡	DRV_MX25L_PageWrite	Writes one page of data starting at the specified address.
≡	DRV_MX25L_Read	Reads n bytes of data from the specified start address of flash memory.
≡	DRV_MX25L_ReadJedecId	Reads JEDEC-ID of the flash device.
≡	DRV_MX25L_ResetFlash	Reset the flash device to standby mode.
≡	DRV_MX25L_SectorErase	Erase the sector from the specified block start address.
≡	DRV_MX25L_Status	Gets the current status of the MX25L driver module.
≡	DRV_MX25L_TransferStatusGet	Gets the current status of the transfer request.

d) Block Interface Functions

	Name	Description
≡	DRV_MX25L_GeometryGet	Returns the geometry of the device.

e) Data Types and Constants

	Name	Description
	DRV_MX25L_GEOMETRY	MX25L Device Geometry data.
	DRV_MX25L_TRANSFER_STATUS	MX25L Driver Transfer Status

Description

This section describes the Application Programming Interface (API) functions of the MX25L driver.

a) System Functions

DRV_MX25L_Initialize Function

Initializes the MX25L Driver

C

```
SYS_MODULE_OBJ DRV_MX25L_Initialize(const SYS_MODULE_INDEX drvIndex, const SYS_MODULE_INIT
*const init);
```

Returns

If successful, returns a valid handle to a driver instance object. Otherwise it returns [SYS_MODULE_OBJ_INVALID](#).

Description

This routine initializes the MX25L driver making it ready for client to use.

- Resets the Flash Device
- Puts it on QUAD IO Mode
- Unlocks the flash

Remarks

This routine must be called before any other MX25L driver routine is called.

This routine should only be called once during system initialization.

This routine will block for hardware access.

Preconditions

None.

Example

```
// This code snippet shows an example of initializing the MX25L Driver
// with MX25L QSPI flash device attached.

SYS_MODULE_OBJ objectHandle;

const DRV_MX25L_PLIB_INTERFACE drvMX25LPlibAPI = {
    .CommandWrite = QSPI_CommandWrite,
    .RegisterRead = QSPI_RegisterRead,
    .RegisterWrite = QSPI_RegisterWrite,
    .MemoryRead = QSPI_MemoryRead,
    .MemoryWrite = QSPI_MemoryWrite
};

const DRV_MX25L_INIT drvMX25LInitData =
{
    .mx25lPlib = &drvMX25LPlibAPI,
};

objectHandle = DRV_MX25L_Initialize((SYS_MODULE_INDEX)DRV_MX25L_INDEX, (SYS_MODULE_INIT *)
)&drvMX25LInitData);

if (SYS_MODULE_OBJ_INVALID == objectHandle)
{
    // Handle error
}
```

Parameters

Parameters	Description
drvIndex	Identifier for the instance to be initialized
init	Pointer to a data structure containing any data necessary to initialize the driver.

Function

```
SYS_MODULE_OBJ DRV_MX25L_Initialize
(
const SYS_MODULE_INDEX drvIndex,
const SYS_MODULE_INIT *const init
);
```

b) Core Client Functions

DRV_MX25L_Open Function

Opens the specified MX25L driver instance and returns a handle to it

C

```
DRV_HANDLE DRV_MX25L_Open(const SYS_MODULE_INDEX drvIndex, const DRV_IO_INTENT ioIntent);
```

Returns

If successful, the routine returns a valid open-instance handle (a number identifying both the caller and the module instance).

If an error occurs, `DRV_HANDLE_INVALID` is returned. Errors can occur under the following circumstances:

- if the driver hardware instance being opened is not initialized.

Description

This routine opens the specified MX25L driver instance and provides a handle.

This handle must be provided to all other client-level operations to identify the caller and the instance of the driver.

Remarks

The handle returned is valid until the `DRV_MX25L_Close` routine is called.

If the driver has already been opened, it should not be opened again.

Preconditions

Function `DRV_MX25L_Initialize` must have been called before calling this function.

Driver should be in ready state to accept the request. Can be checked by calling `DRV_MX25L_Status()`.

Example

```
DRV_HANDLE handle;

handle = DRV_MX25L_Open(DRV_MX25L_INDEX);
if (DRV_HANDLE_INVALID == handle)
{
    // Unable to open the driver
}
```

Parameters

Parameters	Description
drvIndex	Identifier for the instance to be opened
ioIntent	Zero or more of the values from the enumeration <code>DRV_IO_INTENT</code> "ORed" together to indicate the intended use of the driver

Function

```
DRV_HANDLE DRV_MX25L_Open( const SYS_MODULE_INDEX drvIndex, const DRV_IO_INTENT ioIntent );
```

DRV_MX25L_Close Function

Closes an opened-instance of the MX25L driver

C

```
void DRV_MX25L_Close(const DRV_HANDLE handle);
```

Returns

None

Description

This routine closes an opened-instance of the MX25L driver, invalidating the handle.

Remarks

After calling this routine, the handle passed in "handle" must not be used with any of the remaining driver routines. A new handle must be obtained by calling [DRV_MX25L_Open](#) before the caller may use the driver again.

Usually there is no need for the driver client to verify that the Close operation has completed.

Preconditions

[DRV_MX25L_Open](#) must have been called to obtain a valid opened device handle.

Example

```
DRV_HANDLE handle; // Returned from DRV_MX25L_Open

DRV_MX25L_Close(handle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
void DRV_MX25L_Close( const DRV_HANDLE handle );
```

c) Transfer Functions

[DRV_MX25L_ChipErase Function](#)

Erase entire flash memory.

C

```
bool DRV_MX25L_ChipErase( const DRV_HANDLE handle );
```

Returns

false

- if Write enable fails before sending sector erase command to flash
- if chip erase command itself fails

true

- if the erase request is successfully sent to the flash

Description

This function schedules a non-blocking chip erase operation of flash memory.

The requesting client should call [DRV_MX25L_TransferStatusGet\(\)](#) API to know the current status of the request.

The request is sent in QUAD_MODE to flash device.

Remarks

This routine will block wait until erase request is submitted successfully.

Client should wait until erase is complete to send next transfer request.

Preconditions

The [DRV_MX25L_Open\(\)](#) routine must have been called for the specified MX25L driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_MX25L_Open

if(false == DRV_MX25L_ChipErase(handle))
{
    // Error handling here
}

// Wait for erase to be completed
while(DRV_MX25L_TRANSFER_BUSY == DRV_MX25L_TransferStatusGet(handle));
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
bool DRV_MX25L_ChipErase( const DRV_HANDLE handle );
```

DRV_MX25L_PageWrite Function

Writes one page of data starting at the specified address.

C

```
bool DRV_MX25L_PageWrite( const DRV_HANDLE handle, void * tx_data, uint32_t address );
```

Returns

- false
 - if Write enable fails before sending sector erase command to flash
 - if write command itself fails
- true
 - if the write request is successfully sent to the flash

Description

This function schedules a non-blocking write operation for writing maximum one page of data into flash memory.

The requesting client should call [DRV_MX25L_TransferStatusGet\(\)](#) API to know the current status of the request.

The request is sent in QUAD_MODE to flash device.

Remarks

This routine will block wait until write request is submitted successfully.

Client should wait until write is complete to send next transfer request.

Preconditions

The [DRV_MX25L_Open\(\)](#) routine must have been called for the specified MX25L driver instance.

The flash address location which has to be written, must have been erased before using the [MX25L_xxxErase\(\)](#) routine.

The flash address has to be a Page aligned address.

Example

```
#define PAGE_SIZE    256
#define BUFFER_SIZE  1024
#define MEM_ADDRESS  0x0

DRV_HANDLE handle; // Returned from DRV_MX25L_Open
uint8_t writeBuffer[BUFFER_SIZE];
```

```

bool status = false;

if(false == DRV_MX25L_SectorErase(handle))
{
    // Error handling here
}

// Wait for erase to be completed
while(DRV_MX25L_TRANSFER_BUSY == DRV_MX25L_TransferStatusGet(handle));

for (uint32_t j = 0; j < BUFFER_SIZE; j += PAGE_SIZE)
{
    if (true != DRV_MX25L_PageWrite(handle, (void *)&writeBuffer[j], (MEM_ADDRESS + j)))
    {
        status = false;
        break;
    }

    // Wait for write to be completed
    while(DRV_MX25L_TRANSFER_BUSY == DRV_MX25L_TransferStatusGet(handle));
    status = true;
}

if(status == false)
{
    // Error handling here
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
*tx_data	The source buffer containing data to be programmed into MX25L Flash
tx_data_length	Total number of bytes to be written. should not be greater than page size
address	Write memory start address from where the data should be written

Function

```
bool DRV_MX25L_PageWrite( const DRV_HANDLE handle, void *tx_data, uint32_t tx_data_length, uint32_t address );
```

DRV_MX25L_Read Function

Reads n bytes of data from the specified start address of flash memory.

C

```
bool DRV_MX25L_Read( const DRV_HANDLE handle, void * rx_data, uint32_t rx_data_length, uint32_t address );
```

Returns

false

- if read command itself fails

true

- if number of bytes requested are read from flash memory

Description

This function schedules a blocking operation for reading requested number of data bytes from the flash memory.

The request is sent in QUAD_MODE to flash device.

Remarks

This routine will block waiting until read request is completed successfully.

Preconditions

The `DRV_MX25L_Open()` routine must have been called for the specified MX25L driver instance.

Example

```
#define BUFFER_SIZE 1024
#define MEM_ADDRESS 0x0

DRV_HANDLE handle; // Returned from DRV_MX25L_Open
uint8_t readBuffer[BUFFER_SIZE];

if (true != DRV_MX25L_Read(handle, (void *)&readBuffer, BUFFER_SIZE, MEM_ADDRESS))
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
*rx_data	Buffer pointer into which the data read from the MX25L Flash memory will be placed.
rx_data_length	Total number of bytes to be read.
address	Read memory start address from where the data should be read.

Function

```
bool DRV_MX25L_Read( const DRV_HANDLE handle, void *rx_data, uint32_t rx_data_length, uint32_t address );
```

DRV_MX25L_ReadJedecId Function

Reads JEDEC-ID of the flash device.

C

```
bool DRV_MX25L_ReadJedecId( const DRV_HANDLE handle, void * jedec_id );
```

Returns

- false
 - if read jedec-id command fails
- true
 - if the read is successfully completed

Description

This function schedules a blocking operation for reading the JEDEC-ID. This information can be used to get the flash device geometry.

The request is sent in QUAD_MODE to flash device.

Remarks

This routine will block wait for transfer to complete.

Preconditions

The `DRV_MX25L_Open()` routine must have been called for the specified MX25L driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_MX25L_Open
uint32_t jedec_id = 0;

if(true != DRV_MX25L_ReadJedecId(handle, &jedec_id))
{
    // Error handling here
```

```
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
bool DRV_MX25L_ReadJedecId( const DRV_HANDLE handle, void *jedec_id );
```

DRV_MX25L_ResetFlash Function

Reset the flash device to standby mode.

C

```
bool DRV_MX25L_ResetFlash();
```

Returns

false

- if Reset-Enable or Reset flash command itself fails

true

- if the reset is successfully completed

Description

This function schedules a blocking operation for resetting the flash device to standby mode. All the volatile bits and settings will be cleared then, which makes the device return to the default status as power on.

Remarks

This routine will block wait for request to complete.

Preconditions

The [DRV_MX25L_Open\(\)](#) routine must have been called for the specified MX25L driver instance.

Example

```
if(true != DRV_MX25L_ResetFlash())
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
bool DRV_MX25L_ResetFlash(void);
```

DRV_MX25L_SectorErase Function

Erase the sector from the specified block start address.

C

```
bool DRV_MX25L_SectorErase(const DRV_HANDLE handle, uint32_t address);
```

Returns

false

- if Write enable fails before sending sector erase command to flash

- if sector erase command itself fails
- if the erase request is successfully sent to the flash

Description

This function schedules a non-blocking sector erase operation of flash memory. Each Sector is of 4 KByte.

The requesting client should call [DRV_MX25L_TransferStatusGet\(\)](#) API to know the current status of the request.

The request is sent in QUAD_MODE to flash device.

Remarks

This routine will block wait until erase request is submitted successfully.

Client should wait until erase is complete to send next transfer request.

Preconditions

The [DRV_MX25L_Open\(\)](#) routine must have been called for the specified MX25L driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_MX25L_Open
uint32_t sectorStart = 0;

if(false == DRV_MX25L_SectorErase(handle, sectorStart))
{
    // Error handling here
}

// Wait for erase to be completed
while(DRV_MX25L_TRANSFER_BUSY == DRV_MX25L_TransferStatusGet(handle));
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
address	block start address from where a sector needs to be erased.

Function

```
bool DRV_MX25L_SectorErase( const DRV_HANDLE handle, uint32_t address );
```

DRV_MX25L_Status Function

Gets the current status of the MX25L driver module.

C

```
SYS_STATUS DRV_MX25L_Status(const SYS_MODULE_INDEX drvIndex);
```

Returns

SYS_STATUS_READY - Indicates that the driver is ready and accept requests for new operations.

SYS_STATUS_UNINITIALIZED - Indicates the driver is not initialized.

SYS_STATUS_BUSY - Indicates the driver is in busy state.

Description

This routine provides the current status of the MX25L driver module.

Remarks

This routine will NEVER block wait for hardware.

Preconditions

Function [DRV_MX25L_Initialize](#) should have been called before calling this function.

Example

```
SYS_STATUS Status;

Status = DRV_MX25L_Status(DRV_MX25L_INDEX);
```

Parameters

Parameters	Description
drvIndex	Identifier for the instance used to initialize driver

Function

```
SYS_STATUS DRV_MX25L_Status( const SYS_MODULE_INDEX drvIndex );
```

DRV_MX25L_TransferStatusGet Function

Gets the current status of the transfer request.

C

```
DRV_MX25L_TRANSFER_STATUS DRV_MX25L_TransferStatusGet( const DRV_HANDLE handle );
```

Returns

DRV_MX25L_TRANSFER_ERROR_UNKNOWN

- If the flash status register read request fails

DRV_MX25L_TRANSFER_BUSY

- If the current transfer request is still being processed

DRV_MX25L_TRANSFER_COMPLETED

- If the transfer request is completed

Description

This routine gets the current status of the transfer request. The application must use this routine where the status of a scheduled request needs to be polled on.

Remarks

This routine will block for hardware access.

Preconditions

The [DRV_MX25L_Open\(\)](#) routine must have been called for the specified MX25L driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_MX25L_Open

if (DRV_MX25L_TRANSFER_COMPLETED == DRV_MX25L_TransferStatusGet(handle))
{
    // Operation Done
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
DRV_MX25L_TRANSFER_STATUS DRV_MX25L_TransferStatusGet( const DRV_HANDLE handle );
```

d) Block Interface Functions

DRV_MX25L_GeometryGet Function

Returns the geometry of the device.

C

```
bool DRV_MX25L_GeometryGet(const DRV_HANDLE handle, DRV_MX25L_GEOMETRY * geometry);
```

Returns

false

- if read device id fails

true

- if able to get the geometry details of the flash

Description

This API gives the following geometrical details of the MX25L Flash:

- Number of Read/Write/Erase Blocks and their size in each region of the device
- Flash block start address.

Remarks

This API is more useful when used to interface with block driver like memory driver.

Preconditions

The [DRV_MX25L_Open\(\)](#) routine must have been called for the specified MX25L driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_MX25L_Open
DRV_MX25L_GEOMETRY mx251FlashGeometry;
uint32_t readBlockSize, writeBlockSize, eraseBlockSize;
uint32_t nReadBlocks, nReadRegions, totalFlashSize;

DRV_MX25L_GeometryGet(handle, &mx251FlashGeometry);

readBlockSize = mx251FlashGeometry.read_blockSize;
nReadBlocks = mx251FlashGeometry.read_numBlocks;
nReadRegions = mx251FlashGeometry.numReadRegions;

writeBlockSize = mx251FlashGeometry.write_blockSize;
eraseBlockSize = mx251FlashGeometry.erase_blockSize;

totalFlashSize = readBlockSize * nReadBlocks * nReadRegions;
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
*geometry_table	pointer to flash device geometry table instance

Function

```
bool DRV_MX25L_GeometryGet( const DRV_HANDLE handle, MX25L_GEOMETRY *geometry );
```

e) Data Types and Constants

DRV_MX25L_GEOMETRY Structure

MX25L Device Geometry data.

C

```
typedef struct {
    uint32_t read_blockSize;
    uint32_t read_numBlocks;
    uint32_t numReadRegions;
    uint32_t write_blockSize;
    uint32_t write_numBlocks;
    uint32_t numWriteRegions;
    uint32_t erase_blockSize;
    uint32_t erase_numBlocks;
    uint32_t numEraseRegions;
    uint32_t blockStartAddress;
} DRV_MX25L_GEOMETRY;
```

Description

This data type will be used to get the geometry details of the MX25L flash device.

Remarks

None.

DRV_MX25L_TRANSFER_STATUS Enumeration

MX25L Driver Transfer Status

C

```
typedef enum {
    DRV_MX25L_TRANSFER_BUSY,
    DRV_MX25L_TRANSFER_COMPLETED,
    DRV_MX25L_TRANSFER_ERROR_UNKNOWN
} DRV_MX25L_TRANSFER_STATUS;
```

Members

Members	Description
DRV_MX25L_TRANSFER_BUSY	Transfer is being processed
DRV_MX25L_TRANSFER_COMPLETED	Transfer is successfully completed
DRV_MX25L_TRANSFER_ERROR_UNKNOWN	Transfer had error

Description

This data type will be used to indicate the current transfer status for MX25L driver.

Remarks

None.

SST26 Driver Library Help

This section describes the SST26 driver Library.

Introduction

This section provides an interface to access the SST26 Flash Memory over the QSPI/SQI interface.

Description

This driver provides a non-blocking interface to read, write and erase SST26 Flash memory. The driver uses the QSPI/SQI peripheral library to interface with the SST26 Flash.

Key Features:

- Supports Multiple variants of the SST26 Flash devices
- Supports a single instance of the SST26 Flash and a single client to the driver
- Supports Sector/Bulk/Chip Erase Operations
- Supports writes to random memory address within page boundaries
- The library can be used in both Bare-Metal and RTOS environments

Using the Library

This section describes the basic architecture of the SST26 driver and provides information on how it works.

Description

The SST26 driver provides non-blocking API's to read, write and erase SST26 Flash memory.

The SST26 driver can be used in following ways:

- To perform page write to SST26 Flash. Here, the memory start address must be aligned to the page boundary
- To perform Sector/Bulk/Chip Erase operations
- To unlock flash before performing Erase/Write operations
- To read flash JEDEC-ID
- To interface with the Memory driver to perform block operations on the SST26 Flash

Note:

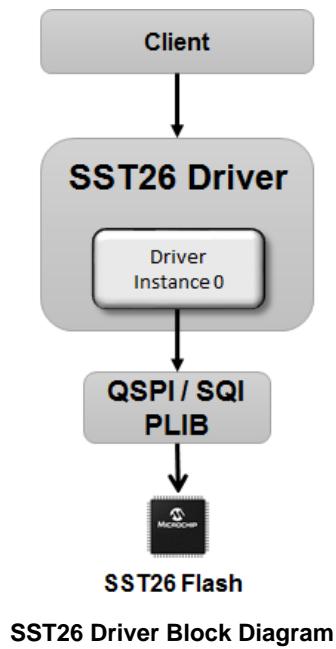
- The client should poll for the status of the data transfer

Abstraction Model

This section provides an abstraction of SST26 driver Library.

Description

The SST26 driver interface provides read, write and Erase functions that abstract out the internal workings of the SST26 driver and the underlying QSPI/SQI protocol.



How the Library Works

This section describes the basic architecture of the SST26 driver and provides information on how it works.

Description

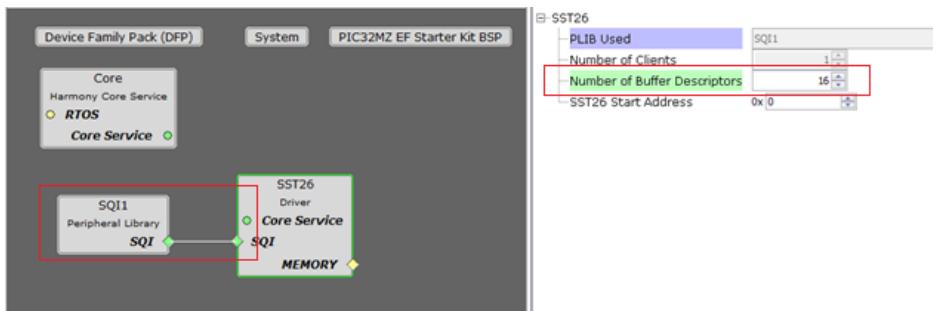
- The SST26 Driver performs initialization and puts the driver to ready state. This status of the driver can be checked using [DRV_SST26_Status\(\)](#)
- The SST26 driver library performs set of flash operations during [DRV_SST26_Open\(\)](#). If any of the below flash operations fails, an invalid Handle will be returned. [DRV_SST26_Open\(\)](#) can be repeatedly called until it returns a valid handle.
 - Resets the Flash
 - Configures the flash device to QUAD IO Mode
 - Unlocks the flash
- When the client requests for device geometry, it queries for the JEDEC-Id and populates the geometry table [DRV_SST26_Geometry](#) appropriately
- The driver does not support queuing of more than one requests. The application must check and ensure that any previous request is completed before submitting a new one. This can be done by polling the status of data transfer using [DRV_SST26_TransferStatusGet\(\)](#)

Configuring the Library

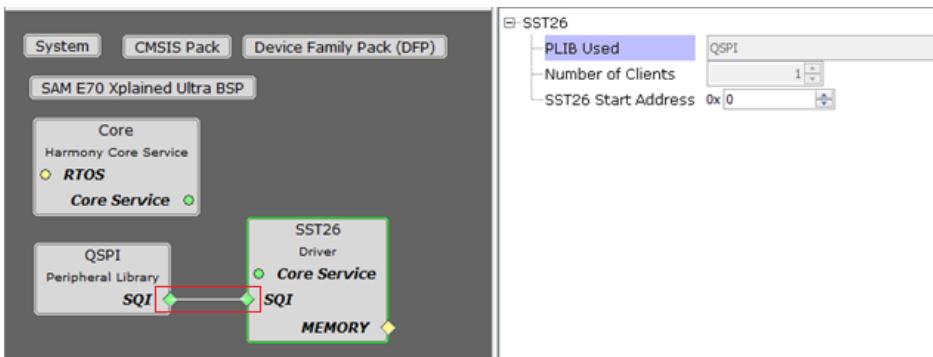
This section provides information on how to configure the SST26 driver.

Description

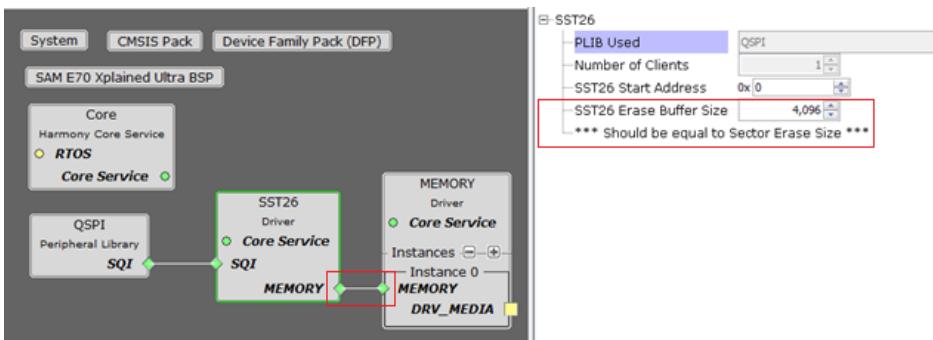
The SST26 driver library should be configured through the MHC. The following figures show the MHC configuration window for the SST26 driver and brief description.



SST26 Driver with SQI Peripheral connected



SST26 Driver without connecting to Memory Driver



SST26 Driver with connection to Memory Driver

Configuration Options:

- PLIB Used:**
 - Specifies the Peripheral library connected
- Number Of Clients:**
 - Indicates maximum number of clients
 - Always set to one as it supports only a single client
- Number Of Buffer Descriptors**
 - Indicates Maximum number of SQI DMA Buffer Descriptors to be used to create chain of requests
 - Increase in number of descriptors will allow to read **(256 * Number of Descriptors)** Bytes from flash at one shot
 - This option appears only when SQI peripheral is connected to the driver
- SST26 Start Address:**
 - Specifies the flash memory start address to be used for Transfer operations
 - The start address will be populated in the device geometry table [DRV_SST26_GEOMETRY](#)
- SST26 Erase Buffer Size:**
 - Specifies the size for erase buffer used by Memory driver
 - The size of the buffer should be equal to erase sector size as the memory driver will call [DRV_SST26_SectorErase](#)
 - This option appears only when the SST26 driver is connected to the Memory driver for block operations

Building the Library

This section provides information on how the SST26 driver can be built.

Description



All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

Library Interface

a) System Functions

	Name	Description
≡	DRV_SST26_Initialize	Initializes the SST26 Driver

b) Core Client Functions

	Name	Description
≡	DRV_SST26_Open	Opens the specified SST26 driver instance and returns a handle to it
≡	DRV_SST26_Close	Closes an opened-instance of the SST26 driver

c) Transfer Functions

	Name	Description
≡	DRV_SST26_UnlockFlash	Unlocks the flash device for Erase and Program operations.
≡	DRV_SST26_ReadJedecId	Reads JEDEC-ID of the flash device.
≡	DRV_SST26_SectorErase	Erase the sector from the specified block start address.
≡	DRV_SST26_BulkErase	Erase a block from the specified block start address.
≡	DRV_SST26_ChipErase	Erase entire flash memory.
≡	DRV_SST26_PageWrite	Writes one page of data starting at the specified address.
≡	DRV_SST26_Read	Reads n bytes of data from the specified start address of flash memory.
≡	DRV_SST26_Status	Gets the current status of the SST26 driver module.
≡	DRV_SST26_TransferStatusGet	Gets the current status of the transfer request.

d) Block Interface Functions

	Name	Description
≡	DRV_SST26_GeometryGet	Returns the geometry of the device.

e) Data Types and Constants

	Name	Description
	DRV_SST26_GEOMETRY	SST26 Device Geometry data.
	DRV_SST26_TRANSFER_STATUS	SST26 Driver Transfer Status

Description

This section describes the Application Programming Interface (API) functions of the SST26 driver.

a) System Functions

DRV_SST26_Initialize Function

Initializes the SST26 Driver

C

```
SYS_MODULE_OBJ DRV_SST26_Initialize(const SYS_MODULE_INDEX drvIndex, const SYS_MODULE_INIT  
*const init);
```

Returns

If successful, returns a valid driver instance object. Otherwise it returns **SYS_MODULE_OBJ_INVALID**.

Description

This routine initializes the SST26 driver making it ready for client to use.

Remarks

This routine must be called before any other SST26 driver routine is called.

This routine should only be called once during system initialization.

Preconditions

None.

Example

```
// This code snippet shows an example of initializing the SST26 Driver  
// with SST26 QSPI flash device attached.  
  
SYS_MODULE_OBJ objectHandle;  
  
const DRV_SST26_PLIB_INTERFACE drvSST26PlibAPI = {  
    .CommandWrite = QSPI_CommandWrite,  
    .RegisterRead = QSPI_RegisterRead,  
    .RegisterWrite = QSPI_RegisterWrite,  
    .MemoryRead = QSPI_MemoryRead,  
    .MemoryWrite = QSPI_MemoryWrite  
};  
  
const DRV_SST26_INIT drvSST26InitData =  
{  
    .sst26Plib = &drvSST26PlibAPI,  
};  
  
objectHandle = DRV_SST26_Initialize((SYS_MODULE_INDEX)DRV_SST26_INDEX, (SYS_MODULE_INIT  
*)&drvSST26InitData);  
  
if (SYS_MODULE_OBJ_INVALID == objectHandle)  
{  
    // Handle error  
}
```

Parameters

Parameters	Description
drvIndex	Identifier for the instance to be initialized
init	Pointer to a data structure containing any data necessary to initialize the driver.

Function

```
SYS_MODULE_OBJ DRV_SST26_Initialize  
(  
    const SYS_MODULE_INDEX drvIndex,  
    const SYS_MODULE_INIT *const init
```

);

b) Core Client Functions

DRV_SST26_Open Function

Opens the specified SST26 driver instance and returns a handle to it

C

```
DRV_HANDLE DRV_SST26_Open(const SYS_MODULE_INDEX drvIndex, const DRV_IO_INTENT ioIntent);
```

Returns

If successful, the routine returns a valid open-instance handle (a number identifying both the caller and the module instance).

If an error occurs, **DRV_HANDLE_INVALID** is returned. Errors can occur under the following circumstances:

- if the driver hardware instance being opened is not initialized.

Description

This routine opens the specified SST26 driver instance and provides a handle.

It performs the following blocking operations:

- Resets the Flash Device
- Puts it on QUAD IO Mode
- Unlocks the flash if **DRV_SST26_Open** was called with write intent.

This handle must be provided to all other client-level operations to identify the caller and the instance of the driver.

Remarks

The handle returned is valid until the **DRV_SST26_Close** routine is called.

If the driver has already been opened, it should not be opened again.

Preconditions

Function **DRV_SST26_Initialize** must have been called before calling this function.

Driver should be in ready state to accept the request. Can be checked by calling **DRV_SST26_Status()**.

Example

```
DRV_HANDLE handle;

handle = DRV_SST26_Open(DRV_SST26_INDEX);
if (DRV_HANDLE_INVALID == handle)
{
    // Unable to open the driver
}
```

Parameters

Parameters	Description
drvIndex	Identifier for the instance to be opened
ioIntent	Zero or more of the values from the enumeration DRV_IO_INTENT "ORed" together to indicate the intended use of the driver

Function

```
DRV_HANDLE DRV_SST26_Open( const SYS_MODULE_INDEX drvIndex, const DRV_IO_INTENT ioIntent );
```

DRV_SST26_Close Function

Closes an opened-instance of the SST26 driver

C

```
void DRV_SST26_Close(const DRV_HANDLE handle);
```

Returns

None

Description

This routine closes an opened-instance of the SST26 driver, invalidating the handle.

Remarks

After calling this routine, the handle passed in "handle" must not be used with any of the remaining driver routines. A new handle must be obtained by calling [DRV_SST26_Open](#) before the caller may use the driver again.

Usually there is no need for the driver client to verify that the Close operation has completed.

Preconditions

[DRV_SST26_Open](#) must have been called to obtain a valid opened device handle.

Example

```
DRV_HANDLE handle; // Returned from DRV_SST26_Open

DRV_SST26_Close(handle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
void DRV_SST26_Close( const DRV_HANDLE handle );
```

c) Transfer Functions**DRV_SST26_UnlockFlash Function**

Unlocks the flash device for Erase and Program operations.

C

```
bool DRV_SST26_UnlockFlash(const DRV_HANDLE handle);
```

Returns

false

- if Write enable fails before sending unlock command to flash
- if Unlock flash command itself fails

true

- if the unlock is successfully completed

Description

This function schedules a blocking operation for unlocking the flash blocks globally. This allows to perform erase and program operations on the flash.

The request is sent in QUAD_MODE to flash device.

Remarks

None.

Preconditions

The [DRV_SST26_Open\(\)](#) routine must have been called for the specified SST26 driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_SST26_Open

if(true != DRV_SST26_UnlockFlash(handle))
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
bool DRV_SST26_UnlockFlash( const DRV_HANDLE handle );
```

DRV_SST26_ReadJedecId Function

Reads JEDEC-ID of the flash device.

C

```
bool DRV_SST26_ReadJedecId( const DRV_HANDLE handle, void * jedec_id );
```

Returns

- false
 - if read jedec-id command fails
- true
 - if the read is successfully completed

Description

This function schedules a blocking operation for reading the JEDEC-ID. This information can be used to get the flash device geometry.

The request is sent in QUAD_MODE to flash device.

Remarks

None.

Preconditions

The [DRV_SST26_Open\(\)](#) routine must have been called for the specified SST26 driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_SST26_Open
uint32_t jedec_id = 0;

if(true != DRV_SST26_ReadJedecId(handle, &jedec_id))
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
bool DRV_SST26_ReadJedecId( const DRV_HANDLE handle, void *jedec_id );
```

DRV_SST26_SectorErase Function

Erase the sector from the specified block start address.

C

```
bool DRV_SST26_SectorErase( const DRV_HANDLE handle, uint32_t address );
```

Returns

false

- if Write enable fails before sending sector erase command to flash
- if sector erase command itself fails

true

- if the erase request is successfully sent to the flash

Description

This function schedules a non-blocking sector erase operation of flash memory. Each Sector is of 4 KByte.

The requesting client should call [DRV_SST26_TransferStatusGet\(\)](#) API to know the current status of the request.

The request is sent in QUAD_MODE to flash device.

Remarks

None.

Preconditions

The [DRV_SST26_Open\(\)](#) routine must have been called for the specified SST26 driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_SST26_Open
uint32_t sectorStart = 0;

if(false == DRV_SST26_SectorErase(handle, sectorStart))
{
    // Error handling here
}

// Wait for erase to be completed
while(DRV_SST26_TRANSFER_BUSY == DRV_SST26_TransferStatusGet(handle));
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
address	block start address from where a sector needs to be erased.

Function

```
bool DRV_SST26_SectorErase( const DRV_HANDLE handle, uint32_t address );
```

DRV_SST26_BulkErase Function

Erase a block from the specified block start address.

C

```
bool DRV_SST26_BulkErase( const DRV_HANDLE handle, uint32_t address );
```

Returns

- false
- if Write enable fails before sending sector erase command to flash
 - if block erase command itself fails
- true
- if the erase request is successfully sent to the flash

Description

This function schedules a non-blocking block erase operation of flash memory. The block size can be 8 KByte, 32KByte or 64 KByte.

The requesting client should call [DRV_SST26_TransferStatusGet\(\)](#) API to know the current status of the request.

The request is sent in QUAD_MODE to flash device.

Remarks

None.

Preconditions

The [DRV_SST26_Open\(\)](#) routine must have been called for the specified SST26 driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_SST26_Open
uint32_t blockStart = 0;

if(false == DRV_SST26_SectorErase(handle, blockStart))
{
    // Error handling here
}

// Wait for erase to be completed
while(DRV_SST26_TRANSFER_BUSY == DRV_SST26_TransferStatusGet(handle));
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
address	block start address to be erased.

Function

```
bool DRV_SST26_BulkErase( const DRV_HANDLE handle, uint32_t address );
```

DRV_SST26_ChipErase Function

Erase entire flash memory.

C

```
bool DRV_SST26_ChipErase( const DRV_HANDLE handle );
```

Returns

- false
- if Write enable fails before sending sector erase command to flash
 - if chip erase command itself fails
- true
- if the erase request is successfully sent to the flash

Description

This function schedules a non-blocking chip erase operation of flash memory.

The requesting client should call [DRV_SST26_TransferStatusGet\(\)](#) API to know the current status of the request.

The request is sent in QUAD_MODE to flash device.

Remarks

None.

Preconditions

The [DRV_SST26_Open\(\)](#) routine must have been called for the specified SST26 driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_SST26_Open

if(false == DRV_SST26_ChipErase(handle))
{
    // Error handling here
}

// Wait for erase to be completed
while(DRV_SST26_TRANSFER_BUSY == DRV_SST26_TransferStatusGet(handle));
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
bool DRV_SST26_ChipErase( const DRV_HANDLE handle );
```

DRV_SST26_PageWrite Function

Writes one page of data starting at the specified address.

C

```
bool DRV_SST26_PageWrite( const DRV_HANDLE handle, void * tx_data, uint32_t address );
```

Returns

false

- if Write enable fails before sending sector erase command to flash
- if write command itself fails

true

- if the write request is successfully sent to the flash

Description

This function schedules a non-blocking write operation for writing maximum one page of data into flash memory.

The requesting client should call [DRV_SST26_TransferStatusGet\(\)](#) API to know the current status of the request.

The request is sent in QUAD_MODE to flash device.

Remarks

None.

Preconditions

The [DRV_SST26_Open\(\)](#) routine must have been called for the specified SST26 driver instance.

The flash address location which has to be written, must have been erased before using the SST26_xxxErase() routine.

The flash address has to be a Page aligned address.

Example

```
#define PAGE_SIZE    256
#define BUFFER_SIZE 1024
```

```

#define MEM_ADDRESS 0x0

DRV_HANDLE handle; // Returned from DRV_SST26_Open
uint8_t writeBuffer[BUFFER_SIZE];
bool status = false;

if(false == DRV_SST26_SectorErase(handle))
{
    // Error handling here
}

// Wait for erase to be completed
while(DRV_SST26_TRANSFER_BUSY == DRV_SST26_TransferStatusGet(handle));

for (uint32_t j = 0; j < BUFFER_SIZE; j += PAGE_SIZE)
{
    if (true != DRV_SST26_PageWrite(handle, (void *)&writeBuffer[j], (MEM_ADDRESS + j)))
    {
        status = false;
        break;
    }

    // Wait for write to be completed
    while(DRV_SST26_TRANSFER_BUSY == DRV_SST26_TransferStatusGet(handle));
    status = true;
}

if(status == false)
{
    // Error handling here
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
*tx_data	The source buffer containing data to be programmed into SST26 Flash
tx_data_length	Total number of bytes to be written. should not be greater than page size
address	Write memory start address from where the data should be written

Function

```
bool DRV_SST26_PageWrite( const DRV_HANDLE handle, void *tx_data, uint32_t tx_data_length, uint32_t address );
```

DRV_SST26_Read Function

Reads n bytes of data from the specified start address of flash memory.

C

```
bool DRV_SST26_Read( const DRV_HANDLE handle, void * rx_data, uint32_t rx_data_length, uint32_t address );
```

Returns

- false
 - if read command itself fails
- true
 - if number of bytes requested are read from flash memory

Description

This function schedules a blocking operation for reading requested number of data bytes from the flash memory.

The request is sent in QUAD_MODE to flash device.

Remarks

None.

Preconditions

The [DRV_SST26_Open\(\)](#) routine must have been called for the specified SST26 driver instance.

Example

```
#define BUFFER_SIZE 1024
#define MEM_ADDRESS 0x0

DRV_HANDLE handle; // Returned from DRV_SST26_Open
uint8_t readBuffer[BUFFER_SIZE];

if (true != DRV_SST26_Read(handle, (void *)&readBuffer, BUFFER_SIZE, MEM_ADDRESS))
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
*rx_data	Buffer pointer into which the data read from the SST26 Flash memory will be placed.
rx_data_length	Total number of bytes to be read.
address	Read memory start address from where the data should be read.

Function

bool DRV_SST26_Read(const [DRV_HANDLE](#) handle, void *rx_data, uint32_t rx_data_length, uint32_t address);

DRV_SST26_Status Function

Gets the current status of the SST26 driver module.

C

```
SYS_STATUS DRV_SST26_Status(const SYS_MODULE_INDEX drvIndex);
```

Returns

SYS_STATUS_READY - Indicates that the driver is ready and accept requests for new operations.

SYS_STATUS_UNINITIALIZED - Indicates the driver is not initialized.

SYS_STATUS_BUSY - Indicates the driver is in busy state.

Description

This routine provides the current status of the SST26 driver module.

Remarks

None.

Preconditions

Function [DRV_SST26_Initialize](#) should have been called before calling this function.

Example

```
SYS_STATUS Status;

Status = DRV_SST26_Status(DRV_SST26_INDEX);
```

Parameters

Parameters	Description
drvIndex	Identifier for the instance used to initialize driver

Function

```
SYS_STATUS DRV_SST26_Status( const SYS_MODULE_INDEX drvIndex );
```

DRV_SST26_TransferStatusGet Function

Gets the current status of the transfer request.

C

```
DRV_SST26_TRANSFER_STATUS DRV_SST26_TransferStatusGet( const DRV_HANDLE handle );
```

Returns

DRV_SST26_TRANSFER_ERROR_UNKNOWN

- If the flash status register read request fails

DRV_SST26_TRANSFER_BUSY

- If the current transfer request is still being processed

DRV_SST26_TRANSFER_COMPLETED

- If the transfer request is completed

Description

This routine gets the current status of the transfer request. The application must use this routine where the status of a scheduled request needs to be polled on.

Remarks

None.

Preconditions

The [DRV_SST26_Open\(\)](#) routine must have been called for the specified SST26 driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_SST26_Open

if (DRV_SST26_TRANSFER_COMPLETED == DRV_SST26_TransferStatusGet(handle))
{
    // Operation Done
}
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
DRV_SST26_TRANSFER_STATUS DRV_SST26_TransferStatusGet( const DRV_HANDLE handle );
```

d) Block Interface Functions

DRV_SST26_GeometryGet Function

Returns the geometry of the device.

C

```
bool DRV_SST26_GeometryGet(const DRV_HANDLE handle, DRV_SST26_GEOMETRY * geometry);
```

Returns

false

- if read device id fails

true

- if able to get the geometry details of the flash

Description

This API gives the following geometrical details of the SST26 Flash:

- Number of Read/Write/Erase Blocks and their size in each region of the device
- Flash block start address.

Remarks

This API is more useful when used to interface with block driver.

Preconditions

The [DRV_SST26_Open\(\)](#) routine must have been called for the specified SST26 driver instance.

Example

```
DRV_HANDLE handle; // Returned from DRV_SST26_Open
DRV_SST26_GEOMETRY sst26FlashGeometry;
uint32_t readBlockSize, writeBlockSize, eraseBlockSize;
uint32_t nReadBlocks, nReadRegions, totalFlashSize;

DRV_SST26_GeometryGet(handle, &sst26FlashGeometry);

readBlockSize = sst26FlashGeometry.read_blockSize;
nReadBlocks = sst26FlashGeometry.read_numBlocks;
nReadRegions = sst26FlashGeometry.numReadRegions;

writeBlockSize = sst26FlashGeometry.write_blockSize;
eraseBlockSize = sst26FlashGeometry.erase_blockSize;

totalFlashSize = readBlockSize * nReadBlocks * nReadRegions;
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
*geometry_table	pointer to flash device geometry table instance

Function

```
bool DRV_SST26_GeometryGet( const DRV_HANDLE handle, SST26_GEOMETRY *geometry );
```

e) Data Types and Constants**DRV_SST26_GEOMETRY Structure**

SST26 Device Geometry data.

C

```
typedef struct {
    uint32_t read_blockSize;
    uint32_t read_numBlocks;
```

```

    uint32_t numReadRegions;
    uint32_t write_blockSize;
    uint32_t write_numBlocks;
    uint32_t numWriteRegions;
    uint32_t erase_blockSize;
    uint32_t erase_numBlocks;
    uint32_t numEraseRegions;
    uint32_t blockStartAddress;
} DRV_SST26_GEOmetry;

```

Description

This data type will be used to get the geometry details of the SST26 flash device.

Remarks

None.

DRV_SST26_TRANSFER_STATUS Enumeration

SST26 Driver Transfer Status

C

```

typedef enum {
    DRV_SST26_TRANSFER_BUSY,
    DRV_SST26_TRANSFER_COMPLETED,
    DRV_SST26_TRANSFER_ERROR_UNKNOWN
} DRV_SST26_TRANSFER_STATUS;

```

Members

Members	Description
DRV_SST26_TRANSFER_BUSY	Transfer is being processed
DRV_SST26_TRANSFER_COMPLETED	Transfer is successfully completed
DRV_SST26_TRANSFER_ERROR_UNKNOWN	Transfer had error

Description

This data type will be used to indicate the current transfer status for SST26 driver.

Remarks

None.

USART Driver Library Help

This section describes the USART driver library.

Introduction

This library provides an interface to manage the data transfer operations using the USART module.

Description

This driver provides application ready routines to read and write data from/to the USART peripheral. The USART driver support the following features:

- Supports multi-instance and multi-client mode
- Provides data transfer events
- Supports blocking and non-blocking operation
- Features thread-safe functions for use in RTOS applications
- Supports DMA transfers

Using the Library

This section describes the basic architecture of the USART driver library and provides information on how to use it.

Description

The USART driver builds on top of the USART or UART peripheral library (PLIB) and provides write, read APIs in blocking and non-blocking modes.

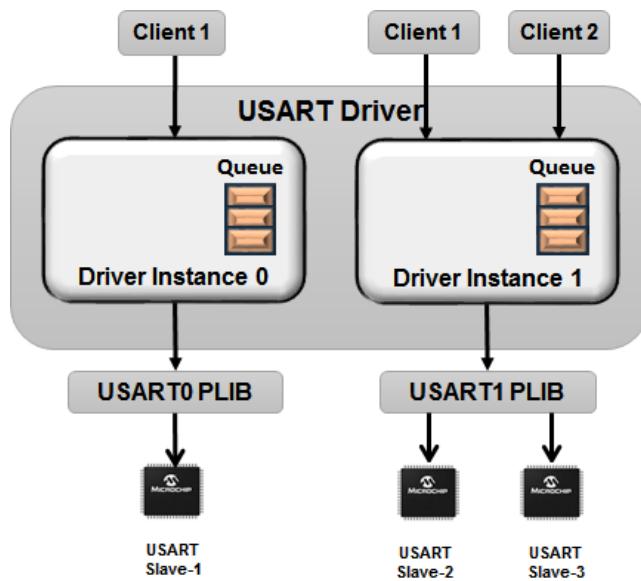
- In *asynchronous* (non-blocking) mode, application can either register a callback to get notified once the data transfer is complete or can poll the status of the data transfer using the status APIs
- In *asynchronous* mode, application can queue more than one transmit/receive requests without waiting for the previous request to be completed. The number of transmit/receive requests that can be queued depends on the depth of the transfer queue configured using the MHC
- The *asynchronous* mode is supported in both bare-metal and RTOS environment
- The *synchronous* (blocking) mode of the driver is supported only in an RTOS environment
- The *synchronous* mode of the driver does not support callback or queuing multiple requests. This is because the implementation is blocking in nature
- Supports DMA for Transfer/Receive in both *asynchronous* and *synchronous* mode

Abstraction Model

This section describes how the abstraction is modeled in software and introduces the library's interface.

Description

The following diagram illustrates the model used by the USART Driver.



How the Library Works

This section provides information on how the USART Driver Library works.

Description

- The USART driver is built on top of the USART/UART peripheral library
- The USART driver registers a callback with the underlying USART peripheral library to receive transfer related events from the peripheral library. The USART driver callback is called by the peripheral library from the interrupt context

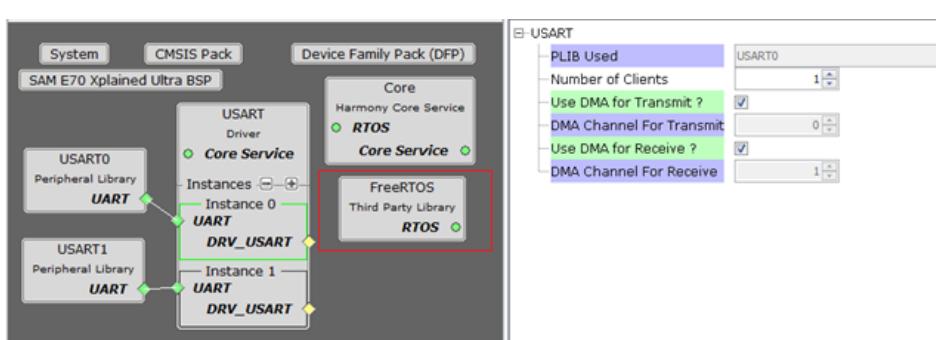
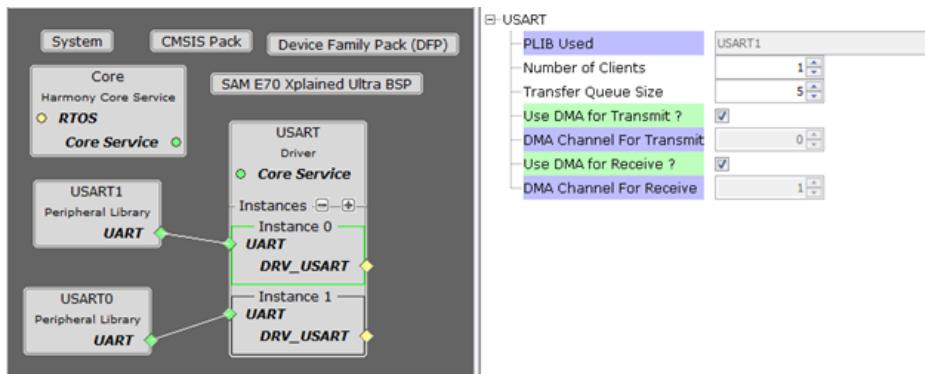
- Once the transfer is complete, the driver calls the callback registered by the application (from the interrupt context) or the application can poll the status of the transfer
- Each instance of the driver (in asynchronous/non-blocking mode) has a dedicated queue which can be configured using the MHC configuration options. The requests submitted by the clients are queued in the respective driver instance request queue
- The USART driver can be used with DMA for data Transfer/Receive
- The USART driver is capable of supporting multiple instances of the USART/UART peripheral

Configuring the Library

This Section provides information on how to configure the USART Driver library.

Description

The USART driver library should be configured through the MHC. The following figure shows the MHC configuration window for the USART driver and brief description.



Common User Configuration for all Instances

1. Driver Mode:

- Allows User to select the mode of driver(**Asynchronous or Synchronous**). This setting is common for all the instances

Instance Specific User Configurations

- PLIB Used:**
 - Indicates the underlying USART/UART PLIB used by the driver.
- Number of clients:**
 - The total number of clients that can open the given USART driver instance.
- Transfer Queue Size:**

- Indicates the size of the transmit/receive queue for the given USART/UART driver instance.
- Available only in Asynchronous mode of Operations
- **Use DMA for Transmit?**
 - Enables DMA For transmitting the data
 - **DMA Channel For Transmit:**
 - DMA Channel for transmission is automatically allocated in DMA configurations
- **Use DMA for Receive?**
 - Enables DMA For Receiving the data
 - **DMA Channel For Receive:**
 - DMA Channel for Receiving is automatically allocated in DMA configurations

Building the Library

This section provides information on how the USART driver library can be built.

Description



All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

Library Interface

a) System Functions

	Name	Description
≡	DRV_USART_Initialize	Initializes the USART instance for the specified driver index.
≡	DRV_USART_Status	Gets the current status of the USART driver module.

b) Core Client Functions

	Name	Description
≡	DRV_USART_Open	Opens the specified USART driver instance and returns a handle to it.
≡	DRV_USART_Close	Closes an opened-instance of the USART driver.

c) Data Transfer Functions

	Name	Description
≡	DRV_USART_SerialSetup	Sets the USART serial communication settings dynamically.
≡	DRV_USART_BufferEventHandlerSet	Allows a client to identify a buffer event handling function for the driver to call back when queued buffer transfers have finished.
≡	DRV_USART_ReadBuffer	This is a blocking function that reads data over USART.
≡	DRV_USART_ReadBufferAdd	Queues a read operation.
≡	DRV_USART_WriteBuffer	This is a blocking function that writes data over USART.
≡	DRV_USART_WriteBufferAdd	Queues a write operation.
≡	DRV_USART_BufferCompletedBytesGet	Returns the number of bytes that have been processed for the specified buffer request.
≡	DRV_USART_BufferStatusGet	Returns the transmit/receive request status.
≡	DRV_USART_ReadQueuePurge	Removes all buffer requests from the queue for the given client.
≡	DRV_USART_WriteQueuePurge	Removes all write requests from the queue for the given client.
≡	DRV_USART_ErrorGet	Gets the USART hardware errors associated with the client.

d) Data Types and Constants

	Name	Description
	DRV_USART_INIT	Defines the data required to initialize the USART driver
	DRV_USART_BUFFER_HANDLE	Handle identifying a read or write buffer passed to the driver.
	DRV_USART_BUFFER_EVENT	Identifies the possible events that can result from a buffer add request.
	DRV_USART_BUFFER_EVENT_HANDLER	Pointer to a USART Driver Buffer Event handler function
	DRV_USART_ERROR	Defines the different types of errors for USART driver
	DRV_USART_BUFFER_HANDLE_INVALID	Definition of an invalid buffer handle.
	DRV_USART_SERIAL_SETUP	Defines the data required to dynamically set the serial settings.

Description

This section describes the Application Programming Interface (API) functions of the USART Driver Library.

Refer to each section for a detailed description.

a) System Functions

DRV_USART_Initialize Function

Initializes the USART instance for the specified driver index.

C

```
SYS_MODULE_OBJ DRV_USART_Initialize(const SYS_MODULE_INDEX index, const SYS_MODULE_INIT* const init);
```

Returns

If successful, returns a valid handle to a driver instance object. Otherwise, returns [SYS_MODULE_OBJ_INVALID](#).

Description

This routine initializes the USART driver instance for the specified driver index, making it ready for clients to open and use it. The initialization data is specified by the init parameter. The initialization may fail if the number of driver objects allocated are insufficient or if the specified driver instance is already initialized. The driver instance index is independent of the USART module ID. For example, driver instance 0 can be assigned to USART2.

Remarks

This routine must be called before any other USART routine is called.

This routine should only be called once during system initialization. This routine will NEVER block for hardware access.

Preconditions

None.

Example

```
// The following code snippet shows an example USART driver initialization.

SYS_MODULE_OBJ objectHandle;

const DRV_USART_PLIB_INTERFACE drvUsart0PlibAPI = {
    .readCallbackRegister = (DRV_USART_PLIB_READ_CALLBACK_REG)USART1_ReadCallbackRegister,
    .read = (DRV_USART_PLIB_READ)USART1_Read,
    .readIsBusy = (DRV_USART_PLIB_READ_IS_BUSY)USART1_ReadIsBusy,
    .readCountGet = (DRV_USART_PLIB_READ_COUNT_GET)USART1_ReadCountGet,
    .writeCallbackRegister = (DRV_USART_PLIB_WRITE_CALLBACK_REG)USART1_WriteCallbackRegister,
    .write = (DRV_USART_PLIB_WRITE)USART1_Write,
    .writeIsBusy = (DRV_USART_PLIB_WRITE_IS_BUSY)USART1_WriteIsBusy,
    .writeCountGet = (DRV_USART_PLIB_WRITE_COUNT_GET)USART1_WriteCountGet,
```

```

.errorGet = (DRV_USART_PLIB_ERROR_GET)USART1_ErrorGet,
.serialSetup = (DRV_USART_PLIB_SERIAL_SETUP)USART1_SerialSetup
};

const DRV_USART_INIT drvUsart0InitData = {
.usartPlib = &drvUsart0PlibAPI,
.numClients = DRV_USART_CLIENTS_NUMBER_IDX0,
.clientObjPool = (uintptr_t)&drvUSART0ClientObjPool[0],
.dmaChannelTransmit = DRV_USART_XMIT_DMA_CH_IDX0,
.usartTransmitAddress = (void *)&(USART1_REGS->US_THR),
.dmaChannelReceive = DRV_USART_RCV_DMA_CH_IDX0,
.usartReceiveAddress = (void *)&(USART1_REGS->US_RHR),
.bufferObjPoolSize = DRV_USART_QUEUE_SIZE_IDX0,
.bufferObjPool = (uintptr_t)&drvUSART0BufferObjPool[0],
.interruptUSART = USART1_IRQn,
.interruptDMA = XDMAC_IRQn,
.remapDataWidth = drvUsart0remapDataWidth,
.remapParity = drvUsart0remapParity,
.remapStopBits = drvUsart0remapStopBits,
.remapError = drvUsart0remapError,
};

objectHandle = DRV_USART_Initialize(DRV_USART_INDEX_1, (SYS_MODULE_INIT*)&drvUsart0InitData);

if (objectHandle == SYS_MODULE_OBJ_INVALID)
{
    // Handle error
}

```

Parameters

Parameters	Description
index	Identifier for the instance to be initialized
init	Pointer to the init data structure containing any data necessary to initialize the driver.

Function

```

SYS_MODULE_OBJ DRV_USART_Initialize
(
const SYS_MODULE_INDEX index,
const SYS_MODULE_INIT * const init
)

```

DRV_USART_Status Function

Gets the current status of the USART driver module.

C

```
SYS_STATUS DRV_USART_Status(SYS_MODULE_OBJ object);
```

Returns

SYS_STATUS_READY - Initialization have succeeded and the USART is ready for additional operations
SYS_STATUS_UNINITIALIZED - Indicates that the driver has not been initialized

Description

This routine provides the current status of the USART driver module.

Remarks

A driver can be opened only when its status is SYS_STATUS_READY.

Preconditions

Function [DRV_USART_Initialize](#) should have been called before calling this function.

Example

```
SYS_MODULE_OBJ      object;      // Returned from DRV_USART_Initialize
SYS_STATUS         usartStatus;

usartStatus = DRV_USART_Status(object);
if (usartStatus == SYS_STATUS_READY)
{
    // This means the driver can be opened using the
    // DRV_USART_Open() function.
}
```

Parameters

Parameters	Description
object	Driver object handle, returned from the DRV_USART_Initialize routine

Function

[SYS_STATUS](#) [DRV_USART_Status](#)([SYS_MODULE_OBJ](#) object)

b) Core Client Functions

DRV_USART_Open Function

Opens the specified USART driver instance and returns a handle to it.

C

```
DRV_HANDLE DRV_USART_Open(const SYS\_MODULE\_INDEX index, const DRV\_IO\_INTENT ioIntent);
```

Returns

If successful, the routine returns a valid open-instance handle (a number identifying both the caller and the module instance).

If an error occurs, the return value is [DRV_HANDLE_INVALID](#). Error can occur

- if the number of client objects allocated via [DRV_USART_CLIENTS_NUMBER](#) is insufficient.
- if the client is trying to open the driver but driver has been opened exclusively by another client.
- if the driver peripheral instance being opened is not initialized or is invalid.
- if the client is trying to open the driver exclusively, but has already been opened in a non exclusive mode by another client.
- if the driver is not ready to be opened, typically when the initialize routine has not completed execution.

Description

This routine opens the specified USART driver instance and provides a handle that must be provided to all other client-level operations to identify the caller and the instance of the driver. The ioIntent parameter defines how the client interacts with this driver instance.

Specifying a [DRV_IO_INTENT_EXCLUSIVE](#) will cause the driver to provide exclusive access to this client. The driver cannot be opened by any other client.

Remarks

The handle returned is valid until the [DRV_USART_Close](#) routine is called. This routine will NEVER block waiting for hardware. If the requested intent flags are not supported, the routine will return [DRV_HANDLE_INVALID](#). This function is thread safe in a RTOS application.

Preconditions

Function [DRV_USART_Initialize](#) must have been called before calling this function.

Example

```
DRV_HANDLE handle;

handle = DRV_USART_Open(DRV_USART_INDEX_0, DRV_IO_INTENT_EXCLUSIVE);
if (handle == DRV_HANDLE_INVALID)
{
    // Unable to open the driver
    // May be the driver is not initialized or the initialization
    // is not complete.
}
```

Parameters

Parameters	Description
index	Identifier for the object instance to be opened
intent	Zero or more of the values from the enumeration DRV_IO_INTENT "ORed" together to indicate the intended use of the driver. See function description for details.

Function

```
DRV_HANDLE DRV_USART_Open
(
const SYS_MODULE_INDEX index,
const DRV_IO_INTENT ioIntent
)
```

DRV_USART_Close Function

Closes an opened-instance of the USART driver.

C

```
void DRV_USART_Close(const DRV_HANDLE handle);
```

Returns

None.

Description

This routine closes an opened-instance of the USART driver, invalidating the handle. Any buffers in the driver queue that were submitted by this client will be removed. A new handle must be obtained by calling [DRV_USART_Open](#) before the caller may use the driver again.

Remarks

None.

Preconditions

[DRV_USART_Open](#) must have been called to obtain a valid opened device handle.

Example

```
// 'handle', returned from the DRV_USART_Open

DRV_USART_Close(handle);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

```
void DRV_USART_Close( DRV_Handle handle )
```

c) Data Transfer Functions

DRV_USART_SerialSetup Function

Sets the USART serial communication settings dynamically.

C

```
bool DRV_USART_SerialSetup(const DRV_HANDLE handle, DRV_USART_SERIAL_SETUP* setup);
```

Returns

true - Serial setup was updated successfully. false - Failure while updating serial setup.

Description

This function sets the USART serial communication settings dynamically.

Remarks

This routine must not be called from the interrupt context.

Preconditions

[DRV_USART_Open](#) must have been called to obtain a valid opened device handle. The USART transmit or receive transfer status should not be busy.

Example

```
// 'handle', returned from the DRV_USART_Open

DRV_USART_SERIAL_SETUP setup = {
    115200,
    DRV_USART_PARITY_ODD,
    DRV_USART_DATA_8_BIT,
    DRV_USART_STOP_1_BIT
};

DRV_USART_SerialSetup(handle, &setup);
```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine
setup	Pointer to the structure containing the serial setup.

Function

```
bool DRV_USART_SerialSetup
(
    const DRV_HANDLE handle,
    DRV_USART_SERIAL_SETUP* setup
)
```

DRV_USART_BufferEventHandlerSet Function

Allows a client to identify a buffer event handling function for the driver to call back when queued buffer transfers have finished.

C

```
void DRV_USART_BufferEventHandlerSet(const DRV_HANDLE handle, const
DRV_USART_BUFFER_EVENT_HANDLER eventHandler, const uintptr_t context);
```

Returns

None.

Description

This function allows a client to register a buffer event handling function with the driver to call back when queued buffer transfers have finished. When a client calls either the [DRV_USART_ReadBufferAdd](#) or [DRV_USART_WriteBufferAdd](#) function, it is provided with a handle identifying the buffer that was added to the driver's buffer queue. The driver will pass this handle back to the client by calling "eventHandler" function when the buffer transfer has completed.

The event handler should be set before the client performs any "buffer add" operations that could generate events. The event handler once set, persists until the client closes the driver or sets another event handler (which could be a "NULL" pointer to indicate no callback).

Remarks

If the client does not want to be notified when the queued buffer transfer has completed, it does not need to register a callback. This function is thread safe when called in a RTOS application.

Preconditions

[DRV_USART_Open](#) must have been called to obtain a valid opened device handle.

Example

```
// myAppObj is an application specific state data object.
MY_APP_OBJ myAppObj;

uint8_t mybuffer[MY_BUFFER_SIZE];
DRV_USART_BUFFER_HANDLE bufferHandle;

// myUSARTHandle is the handle returned
// by the DRV_USART_Open function.

// Client registers an event handler with driver. This is done once

DRV_USART_BufferEventHandlerSet(
    myUSARTHandle,
    APP_USARTBufferEventHandler,
    (uintptr_t)&myAppObj
);

DRV_USART_ReadBufferAdd(
    myUSARTHandle,
    myBuffer,
    MY_BUFFER_SIZE,
    &bufferHandle
);

if(bufferHandle == DRV_USART_BUFFER_HANDLE_INVALID)
{
    // Error handling here
}

// Event is received when the buffer is processed.

void APP_USARTBufferEventHandler(
    DRV_USART_BUFFER_EVENT event,
    DRV_USART_BUFFER_HANDLE handle,
    uintptr_t context
)
{
    // The context handle was set to an application specific
```

```

// object. It is now retrievable easily in the event handler.
MY_APP_OBJ* myAppObj = (MY_APP_OBJ *) context;

switch(event)
{
    case DRV_USART_BUFFER_EVENT_COMPLETE:
        // This means the data was transferred.
        break;

    case DRV_USART_BUFFER_EVENT_ERROR:
        // Error handling here.
        break;

    default:
        break;
}
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine.
eventHandler	Pointer to the event handler function.
context	The value of parameter will be passed back to the client unchanged, when the eventHandler function is called. It can be used to identify any client specific data object that identifies the instance of the client module (for example, it may be a pointer to the client module's state structure).

Function

```

void DRV_USART_BufferEventHandlerSet
(
    const DRV_HANDLE handle,
    const DRV_USART_BUFFER_EVENT_HANDLER eventHandler,
    const uintptr_t context
)

```

DRV_USART_ReadBuffer Function

This is a blocking function that reads data over USART.

C

```
bool DRV_USART_ReadBuffer(const DRV_HANDLE handle, void* buffer, const size_t size);
```

Returns

true - read is successful false - error has occurred

Description

This function does a blocking read operation. The function blocks till the data read is complete or error has occurred during read. Function will return false to report failure. The failure will occur for the following reasons:

- if the handle is invalid
- if the input buffer pointer is NULL
- if the buffer size is 0
- Hardware errors

Remarks

This function is thread safe in a RTOS application. This function should not be called from an interrupt context.

Preconditions

[DRV_USART_Open](#) must have been called to obtain a valid opened device handle.

Example

```

MY_APP_OBJ myAppObj;
uint8_t myBuffer[MY_BUFFER_SIZE];

// myUSARTHandle is the handle returned
// by the DRV_USART_Open function.

if (DRV_USART_ReadBuffer(myUSARTHandle, myBuffer, MY_BUFFER_SIZE) == false)
{
    // Error handling here
}

```

Parameters

Parameters	Description
handle	Handle of the communication channel as return by the DRV_USART_Open function.
buffer	Pointer to the receive buffer.
size	Buffer size in bytes.

Function

```

bool DRV_USART_ReadBuffer
(
    const DRV\_HANDLE handle,
    void* buffer,
    const size_t size
);

```

DRV_USART_ReadBufferAdd Function

Queues a read operation.

C

```

void DRV_USART_ReadBufferAdd(const DRV\_HANDLE handle, void* buffer, const size_t size,
DRV\_USART\_BUFFER\_HANDLE* const bufferHandle);

```

Returns

The buffer handle is returned in the bufferHandle argument. This is [DRV_USART_BUFFER_HANDLE_INVALID](#) if the request was not successful.

Description

This function schedules a non-blocking read operation. The function returns with a valid buffer handle in the bufferHandle argument if the read request was scheduled successfully. The function adds the request to the hardware instance receive queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. The function returns [DRV_USART_BUFFER_HANDLE_INVALID](#) in the bufferHandle argument:

- if a buffer could not be allocated to the request because the queue is full
- if the input buffer handle is NULL
- if the input buffer pointer is NULL
- if the buffer size (number of bytes to read) is 0
- if the driver handle is invalid

If the requesting client registered an event callback with the driver, the driver will issue a [DRV_USART_BUFFER_EVENT_COMPLETE](#) event if the buffer was processed successfully or [DRV_USART_BUFFER_EVENT_ERROR](#) event if the buffer was not processed successfully.

Remarks

This function is thread safe in a RTOS application. It can be called from within the USART Driver Buffer Event Handler that is

registered by the client. It should not be called in the event handler associated with another USART driver instance. It should not be called directly in an ISR.

Preconditions

`DRV_USART_Open` must have been called to obtain a valid opened device handle.

Example

```
MY_APP_OBJ myAppObj;
uint8_t mybuffer[MY_BUFFER_SIZE];
DRV_USART_BUFFER_HANDLE bufferHandle;

// myUSARTHandle is the handle returned
// by the DRV_USART_Open function.

DRV_USART_ReadBufferAdd(
    myUSARTHandle,
    myBuffer,
    MY_BUFFER_SIZE,
    &bufferHandle
);

if(bufferHandle == DRV_USART_BUFFER_HANDLE_INVALID)
{
    // Error handling here
}

// Event is received when the buffer is processed.
```

Parameters

Parameters	Description
handle	Handle of the communication channel as returned by the <code>DRV_USART_Open</code> function.
buffer	Buffer where the received data will be stored.
size	Buffer size in bytes.
bufferHandle	Pointer to an argument that will contain the return buffer handle.

Function

```
void DRV_USART_ReadBufferAdd
(
    const DRV_HANDLE handle,
    void* buffer,
    const size_t size,
    DRV_USART_BUFFER_HANDLE* bufferHandle
)
```

DRV_USART_WriteBuffer Function

This is a blocking function that writes data over USART.

C

```
bool DRV_USART_WriteBuffer(const DRV_HANDLE handle, void* buffer, const size_t size);
```

Returns

true - write is successful false - error has occurred

Description

This function does a blocking write operation. The function blocks till the data write is complete. Function will return false to report failure. The failure will occur for the following reasons:

- if the handle is invalid
- if the input buffer pointer is NULL
- if the buffer size is 0

Remarks

This function is thread safe in a RTOS application. This function should not be called from an interrupt context.

Preconditions

[DRV_USART_Open](#) must have been called to obtain a valid opened device handle.

Example

```
MY_APP_OBJ myAppObj;
uint8_t myBuffer[MY_BUFFER_SIZE];

// myUSARTHandle is the handle returned
// by the DRV_USART_Open function.

if (DRV_USART_WriteBuffer(myUSARTHandle, myBuffer, MY_BUFFER_SIZE) == false)
{
    // Error handling here
}
```

Parameters

Parameters	Description
handle	Handle of the communication channel as return by the DRV_USART_Open function.
buffer	Pointer to the data to be transmitted.
size	Buffer size in bytes.

Function

```
bool DRV_USART_WriteBuffer
(
    const DRV\_HANDLE handle,
    void* buffer,
    const size_t size
);
```

DRV_USART_WriteBufferAdd Function

Queues a write operation.

C

```
void DRV_USART_WriteBufferAdd(const DRV\_HANDLE handle, void* buffer, const size_t size,
DRV\_USART\_BUFFER\_HANDLE* bufferHandle);
```

Returns

The bufferHandle parameter will contain the return buffer handle. This will be [DRV_USART_BUFFER_HANDLE_INVALID](#) if the function was not successful.

Description

This function schedules a non-blocking write operation. The function returns with a valid buffer handle in the bufferHandle argument if the write request was scheduled successfully. The function adds the request to the driver instance queue and returns immediately. While the request is in the queue, the application buffer is owned by the driver and should not be modified. On returning, the bufferHandle parameter may be [DRV_USART_BUFFER_HANDLE_INVALID](#) for the following reasons:

- if a buffer could not be allocated to the request because the queue is full
- if the input buffer handle is NULL
- if the input buffer pointer is NULL

- if the buffer size (number of bytes to write) is 0
- if the driver handle is invalid

If the requesting client registered an event callback with the driver, the driver will issue a DRV_USART_BUFFER_EVENT_COMPLETE event if the buffer was processed successfully or a DRV_USART_BUFFER_EVENT_ERROR event if the buffer was not processed successfully.

Remarks

This function is thread safe in a RTOS application. It can be called from within the USART Driver Buffer Event Handler that is registered by this client. It should not be called in the event handler associated with another USART driver instance. It should not otherwise be called directly in an ISR.

Preconditions

[DRV_USART_Open](#) must have been called to obtain a valid opened device handle.

Example

```
MY_APP_OBJ myAppObj;
uint8_t mybuffer[MY_BUFFER_SIZE];
DRV_USART_BUFFER_HANDLE bufferHandle;

// myUSARTHandle is the handle returned
// by the DRV_USART_Open function.

DRV_USART_WriteBufferAdd(
    myUSARTHandle,
    myBuffer,
    MY_BUFFER_SIZE,
    &bufferHandle
);

if(bufferHandle == DRV_USART_BUFFER_HANDLE_INVALID)
{
    // Error handling here
}

// Event is received when
// the buffer is processed.
```

Parameters

Parameters	Description
handle	Handle of the communication channel as return by the DRV_USART_Open function.
buffer	Data to be transmitted.
size	Buffer size in bytes.
bufferHandle	Pointer to an argument that will contain the return buffer handle.

Function

```
void DRV_USART_WriteBufferAdd
(
    const DRV_HANDLE handle,
    void* buffer,
    size_t size,
    DRV_USART_BUFFER_HANDLE* bufferHandle
);
```

DRV_USART_BufferCompletedBytesGet Function

Returns the number of bytes that have been processed for the specified buffer request.

C

```
size_t DRV_USART_BufferCompletedBytesGet(DRV_USART_BUFFER_HANDLE bufferHandle);
```

Returns

Returns the number of bytes that have been processed for this buffer.

Returns `DRV_USART_BUFFER_HANDLE_INVALID` for an invalid or an expired buffer handle.

Description

The client can use this function, in a case where the buffer is terminated due to an error, to obtain the number of bytes that have been processed. Or in any other use case. This function can be used for non-DMA buffer transfers only. It cannot be used when the USART driver is configured to use DMA.

Remarks

This function is expected to work in non-DMA mode only. This function is thread safe when used in a RTOS application.

Preconditions

`DRV_USART_Open` must have been called to obtain a valid opened device handle.

Either the `DRV_USART_ReadBufferAdd` or `DRV_USART_WriteBufferAdd` function must have been called and a valid buffer handle returned.

Example

```
// myAppObj is an application specific object.
MY_APP_OBJ myAppObj;

uint8_t mybuffer[MY_BUFFER_SIZE];
DRV_USART_BUFFER_HANDLE bufferHandle;

// myUSARTHandle is the handle returned
// by the DRV_USART_Open function.

// Client registers an event handler with driver. This is done once
DRV_USART_BufferEventHandlerSet(
    myUSARTHandle,
    APP_USARTBufferEventHandler,
    (uintptr_t)&myAppObj
);

DRV_USART_ReadBufferAdd(
    myUSARTHandle,
    myBuffer,
    MY_BUFFER_SIZE,
    bufferHandle
);

if(bufferHandle == DRV_USART_BUFFER_HANDLE_INVALID)
{
    // Error handling here
}

// Event Processing Technique. Event is received when
// the buffer is processed.

void APP_USARTBufferEventHandler(
    DRV_USART_BUFFER_EVENT event,
    DRV_USART_BUFFER_HANDLE bufferHandle,
    uintptr_t context
)
{
    // The context handle was set to an application specific
    // object. It is now retrievable easily in the event handler.

    MY_APP_OBJ* myAppObj = (MY_APP_OBJ *)context;
```

```

size_t processedBytes;

switch(event)
{
    case DRV_USART_BUFFER_EVENT_COMPLETE:
        // This means the data was transferred.
        break;

    case DRV_USART_BUFFER_EVENT_ERROR:
        // Error handling here.
        // We can find out how many bytes have been processed in this
        // buffer request prior to the error.
        processedBytes= DRV_USART_BufferCompletedBytesGet(bufferHandle);
        break;

    default:
        break;
}
}

```

Parameters

Parameters	Description
bufferHandle	Handle for the buffer of which the processed number of bytes to be obtained.

Function

```

size_t DRV_USART_BufferCompletedBytesGet
(
    DRV_USART_BUFFER_HANDLE bufferHandle
);

```

DRV_USART_BufferStatusGet Function

Returns the transmit/receive request status.

C

```
DRV_USART_BUFFER_EVENT DRV_USART_BufferStatusGet(const DRV_USART_BUFFER_HANDLE bufferHandle);
```

Returns

Returns either pending, success or error event for the buffer. Pending means the buffer is queued but not serviced yet.

Description

This function can be used to poll the status of the queued buffer request if the application doesn't prefer to use the event handler (callback) function to get notified.

Remarks

This function returns error event if the buffer handle is invalid.

Preconditions

DRV_USART_Open must have been called to obtain a valid opened device handle.

Either the DRV_USART_ReadBufferAdd or DRV_USART_WriteBufferAdd function must have been called and a valid buffer handle returned.

Example

```

// myAppObj is an application specific object.
MY_APP_OBJ myAppObj;

uint8_t mybuffer[MY_BUFFER_SIZE];
DRV_USART_BUFFER_HANDLE bufferHandle;
DRV_USART_BUFFER_EVENT event;

```

```

// myUSARTHandle is the handle returned
// by the DRV_USART_Open function.

// Client registers an event handler with driver. This is done once

DRV_USART_BufferEventHandlerSet(
    myUSARTHandle,
    APP_USARTBufferEventHandler,
    (uintptr_t)&myAppObj
);

DRV_USART_ReadBufferAdd(
    myUSARTHandle,
    myBuffer,
    MY_BUFFER_SIZE,
    bufferHandle
);

if(bufferHandle == DRV_USART_BUFFER_HANDLE_INVALID)
{
    // Error handling here
}

//Check the status of the buffer
//This call can be used to wait until the buffer is processed.

while ((event = DRV_USART_BufferStatusGet(bufferHandle)) == DRV_USART_BUFFER_EVENT_PENDING);

//Buffer is processed, check the event variable to determine if the buffer request
//is executed successfully or not.

```

Parameters

Parameters	Description
bufferhandle	Handle for the buffer of which the processed number of bytes to be obtained.

Function

```

DRV_USART_BUFFER_EVENT DRV_USART_BufferStatusGet
(
const DRV_USART_BUFFER_HANDLE bufferHandle
)

```

DRV_USART_ReadQueuePurge Function

Removes all buffer requests from the queue for the given client.

C

```
bool DRV_USART_ReadQueuePurge(const DRV_HANDLE handle);
```

Returns

true - Read queue purge is successful.
false - Read queue purge has failed.

Description

This function removes all the buffer requests from the queue. The client can use this function to purge the queue on timeout or to remove unwanted stalled buffer requests or in any other use case.

Remarks

This function is thread safe when used in an RTOS environment. Avoid this function call from within the callback.

Preconditions

`DRV_USART_Open` must have been called to obtain a valid opened device handle.

Example

```
// myUSARTHandle is the handle returned by the DRV_USART_Open function.
// Use DRV_USART_ReadBufferAdd to queue read requests

// Application timeout function, where remove queued buffers.
void APP_TimeOut(void)
{
    if(DRV_USART_ReadQueuePurge(myUSARTHandle) == false)
    {
        //Couldn't purge the read queue, try again.
    }
    else
    {
        //Queue purge successful.
    }
}
```

Parameters

Parameters	Description
handle	Handle of the communication channel as returned by the <code>DRV_USART_Open</code> function.

Function

`bool DRV_USART_ReadQueuePurge(const DRV_HANDLE handle)`

DRV_USART_WriteQueuePurge Function

Removes all write requests from the queue for the given client.

C

```
bool DRV_USART_WriteQueuePurge(const DRV_HANDLE handle);
```

Returns

true - Write queue purge is successful.

false - Write queue purge has failed.

Description

This function removes all the buffer requests from the queue. The client can use this function to purge the queue on timeout or to remove unwanted stalled buffer requests or in any other use case.

Remarks

This function is thread safe when used in an RTOS environment. Avoid this function call from within the callback.

Preconditions

`DRV_USART_Open` must have been called to obtain a valid opened device handle.

Example

```
// myUSARTHandle is the handle returned by the DRV_USART_Open function.
// Use DRV_USART_WriteBufferAdd to queue write requests

// Application timeout function, where remove queued buffers.
void APP_TimeOut(void)
{
    if(DRV_USART_WriteQueuePurge(myUSARTHandle) == false)
    {
        //Couldn't purge the write queue, try again.
```

```

    }
    else
    {
        //Queue purge successful.
    }
}

```

Parameters

Parameters	Description
handle	Handle of the communication channel as returned by the DRV_USART_Open function.

Function

bool DRV_USART_WriteQueuePurge(const [DRV_HANDLE](#) handle)

DRV_USART_ErrorGet Function

Gets the USART hardware errors associated with the client.

C

```
DRV_USART_ERROR DRV_USART_ErrorGet(const DRV_HANDLE handle);
```

Returns

Errors occurred as listed by [DRV_USART_ERROR](#). This function reports multiple USART errors if occurred.

Description

This function returns the errors associated with the given client. The call to this function also clears all the associated error flags. This function can be used for non-DMA buffer transfers only. It cannot be used when the USART driver is configured to use DMA.

Remarks

USART errors are normally associated with the receiver. The driver clears all the errors internally and only returns the occurred error information for the client. The errors are valid only until it is over written by the error status of the next transfer. Hence, application may want to call this routine from the callback itself, in case error is reported by the driver in the callback. This function is expected to work in non-DMA mode only.

Preconditions

[DRV_USART_Open](#) must have been called to obtain a valid opened device handle.

Example

```

// 'handle', returned from the DRV_USART_Open

if (DRV_USART_ErrorGet(handle) & DRV_USART_ERROR_OVERRUN)
{
    //Errors are cleared by the driver, take respective action
    //for the overrun error case.
}

```

Parameters

Parameters	Description
handle	A valid open-instance handle, returned from the driver's open routine

Function

[DRV_USART_ERROR](#) DRV_USART_ErrorGet(const [DRV_HANDLE](#) handle)

d) Data Types and Constants

DRV_USART_INIT Type

Defines the data required to initialize the USART driver

C

```
typedef struct _DRV_USART_INIT DRV_USART_INIT;
```

Description

USART Driver Initialization Data

This data type defines the data required to initialize the USART driver.

Remarks

This structure is implementation specific. It is fully defined in `drv_usart_definitions.h`.

DRV_USART_BUFFER_HANDLE Type

Handle identifying a read or write buffer passed to the driver.

C

```
typedef uintptr_t DRV_USART_BUFFER_HANDLE;
```

Description

USART Driver Buffer Handle

A buffer handle value is returned by a call to the `DRV_USART_ReadBufferAdd` or `DRV_USART_WriteBufferAdd` functions. This handle is associated with the buffer passed into the function and it allows the application to track the completion of the data from (or into) that buffer. The buffer handle value returned from the "buffer add" function is returned back to the client by the "event handler callback" function registered with the driver.

The buffer handle assigned to a client request expires when the client has been notified of the completion of the buffer transfer (after event handler function that notifies the client returns) or after the buffer has been retired by the driver if no event handler callback was set.

Remarks

None

DRV_USART_BUFFER_EVENT Enumeration

Identifies the possible events that can result from a buffer add request.

C

```
typedef enum {
    DRV_USART_BUFFER_EVENT_PENDING = 0,
    DRV_USART_BUFFER_EVENT_COMPLETE = 1,
    DRV_USART_BUFFER_EVENT_HANDLE_EXPIRED = 2,
    DRV_USART_BUFFER_EVENT_ERROR = -1,
    DRV_USART_BUFFER_EVENT_HANDLE_INVALID = -2
} DRV_USART_BUFFER_EVENT;
```

Members

Members	Description
DRV_USART_BUFFER_EVENT_PENDING = 0	The buffer is pending to be serviced
DRV_USART_BUFFER_EVENT_COMPLETE = 1	All data from or to the buffer was transferred successfully.

DRV_USART_BUFFER_EVENT_HANDLE_EXPIRED = 2	Transfer Handle given is expired. It means transfer is completed but with or without error is not known.
DRV_USART_BUFFER_EVENT_ERROR = -1	There was an error while processing the buffer transfer request.
DRV_USART_BUFFER_EVENT_HANDLE_INVALID = -2	Transfer Handle given is invalid

Description

USART Driver Buffer Events

This enumeration identifies the possible events that can result from a buffer add request caused by the client calling either the [DRV_USART_ReadBufferAdd](#) or [DRV_USART_WriteBufferAdd](#) functions.

Remarks

One of these values is passed in the "event" parameter of the event handling callback function that the client registered with the driver by calling the [DRV_USART_BufferEventHandlerSet](#) function when a buffer transfer request is completed.

DRV_USART_BUFFER_EVENT_HANDLER Type

Pointer to a USART Driver Buffer Event handler function

C

```
typedef void (* DRV_USART_BUFFER_EVENT_HANDLER)(DRV_USART_BUFFER_EVENT event,
DRV_USART_BUFFER_HANDLE bufferHandle, uintptr_t context);
```

Returns

None.

Description

USART Driver Buffer Event Handler Function Pointer

This data type defines the required function signature for the USART driver buffer event handling callback function. A client must register a pointer using the buffer event handling function whose function signature (parameter and return value types) match the types specified by this function pointer in order to receive buffer related event calls back from the driver.

The parameters and return values are described here and a partial example implementation is provided.

Remarks

If the event is `DRV_USART_BUFFER_EVENT_COMPLETE`, it means that the data was transferred successfully.

If the event is `DRV_USART_BUFFER_EVENT_ERROR`, it means that the data was not transferred successfully. The [DRV_USART_BufferCompletedBytesGet](#) function can be called to find out how many bytes were processed.

The `bufferHandle` parameter contains the buffer handle of the buffer that associated with the event. And `bufferHandle` will be valid while the buffer request is in the queue and during callback, unless an error occurred. After callback returns, the driver will retire the buffer handle.

The `context` parameter contains the a handle to the client context, provided at the time the event handling function was registered using the [DRV_USART_BufferEventHandlerSet](#) function. This context handle value is passed back to the client as the "context" parameter. It can be any value necessary to identify the client context or instance (such as a pointer to the client's data) instance of the client that made the buffer add request.

The event handler function executes in the peripheral's interrupt context. It is recommended of the application to not perform process intensive or blocking operations within this function.

The [DRV_USART_ReadBufferAdd](#) and [DRV_USART_WriteBufferAdd](#) functions can be called in the event handler to add a buffer to the driver queue. These functions can only be called to add buffers to the driver whose event handler is running. For example, USART2 driver buffers cannot be added in USART1 driver event handler.

Example

```
void APP_MyBufferEventHandler(
    DRV_USART_BUFFER_EVENT event,
    DRV_USART_BUFFER_HANDLE bufferHandle,
    uintptr_t context
)
{
```

```

MY_APP_DATA_STRUCT* pAppData = (MY_APP_DATA_STRUCT* ) context;

switch(event)
{
    case DRV_USART_BUFFER_EVENT_COMPLETE:
        // Handle the completed buffer.
        break;

    case DRV_USART_BUFFER_EVENT_ERROR:
    default:
        // Handle error.
        break;
}
}

```

Parameters

Parameters	Description
event	Identifies the type of event
bufferHandle	Handle identifying the buffer to which the event relates
context	Value identifying the context of the application that registered the event handling function.

DRV_USART_ERROR Type

Defines the different types of errors for USART driver

C

```
typedef enum _DRV_USART_ERROR DRV_USART_ERROR;
```

Description

USART Driver Errors

This data type defines the different types of errors for USART driver. DRV_USART_ERROR_NONE : No errors

DRV_USART_ERROR_OVERRUN : Receive Overflow error

DRV_USART_ERROR_PARITY : Parity error

DRV_USART_ERROR_FRAMING : Framing error

Remarks

This structure is implementation specific. It is fully defined in `drv_usart_definitions.h`.

DRV_USART_BUFFER_HANDLE_INVALID Macro

Definition of an invalid buffer handle.

C

```
#define DRV_USART_BUFFER_HANDLE_INVALID
```

Description

USART Driver Invalid Buffer Handle

This is the definition of an invalid buffer handle. An invalid buffer handle is returned by `DRV_USART_ReadBufferAdd` and `DRV_USART_WriteBufferAdd` functions if the buffer add request was not successful.

Remarks

None

DRV_USART_SERIAL_SETUP Type

Defines the data required to dynamically set the serial settings.

C

```
typedef struct _DRV_USART_SERIAL_SETUP DRV_USART_SERIAL_SETUP;
```

Description

USART Driver Serial Setup Data

This data type defines the data required to dynamically set the serial settings for the specific USART driver instance.

Remarks

This structure is implementation specific. It is fully defined in `drv_usart_definitions.h`.

Common Driver Library Help**a) Common Driver Services**

	Name	Description
	DRV_HANDLE	Handle to an opened device driver.
	DRV_HANDLE_INVALID	Invalid device handle.
	DRV_IO_INTENT	Identifies the intended usage of the device when it is opened.
	DRV_IO_ISBLOCKING	Returns if the I/O intent provided is blocking
	DRV_IO_ISNONBLOCKING	Returns if the I/O intent provided is non-blocking.
	DRV_IO_ISEXCLUSIVE	Returns if the I/O intent provided is non-blocking.
	DRV_IO_BUFFER_TYPES	Identifies to which buffer a device operation will apply.
	DRV_CLIENT_STATUS	Identifies the current status/state of a client's connection to a driver.

Description

This section provides information that is common to all drivers.

a) Common Driver Services**DRV_HANDLE Type**

Handle to an opened device driver.

C

```
typedef uintptr_t DRV_HANDLE;
```

Description

Device Handle

This handle identifies the open instance of a device driver. It must be passed to all other driver routines (except the initialization, deinitialization, or power routines) to identify the caller.

Remarks

Every application or module that wants to use a driver must first call the driver's open routine. This is the only routine that is absolutely required for every driver.

If a driver is unable to allow an additional module to use it, it must then return the special value [DRV_HANDLE_INVALID](#). Callers should check the handle returned for this value to ensure this value was not returned before attempting to call any other driver routines using the handle.

DRV_HANDLE_INVALID Macro

Invalid device handle.

C

```
#define DRV_HANDLE_INVALID (((DRV_HANDLE) -1))
```

Description

Invalid Device Handle

If a driver is unable to allow an additional module to use it, it must then return the special value DRV_HANDLE_INVALID. Callers should check the handle returned for this value to ensure this value was not returned before attempting to call any other driver routines using the handle.

Remarks

None.

DRV_IO_INTENT Enumeration

Identifies the intended usage of the device when it is opened.

C

```
typedef enum {
    DRV_IO_INTENT_READ,
    DRV_IO_INTENT_WRITE,
    DRV_IO_INTENT_READWRITE,
    DRV_IO_INTENT_BLOCKING,
    DRV_IO_INTENT_NONBLOCKING,
    DRV_IO_INTENT_EXCLUSIVE,
    DRV_IO_INTENT_SHARED
} DRV_IO_INTENT;
```

Members

Members	Description
DRV_IO_INTENT_READ	Read
DRV_IO_INTENT_WRITE	Write
DRV_IO_INTENT_READWRITE	Read and Write
DRV_IO_INTENT_BLOCKING	The driver will block and will return when the operation is complete
DRV_IO_INTENT_NONBLOCKING	The driver will return immediately
DRV_IO_INTENT_EXCLUSIVE	The driver will support only one client at a time
DRV_IO_INTENT_SHARED	The driver will support multiple clients at a time

Description

Device Driver I/O Intent

This enumeration identifies the intended usage of the device when the caller opens the device. It identifies the desired behavior of the device driver for the following:

- Blocking or non-blocking I/O behavior (do I/O calls such as read and write block until the operation is finished or do they return immediately and require the caller to call another routine to check the status of the operation)
- Support reading and/or writing of data from/to the device
- Identify the buffering behavior (sometimes called "double buffering" of the driver. Indicates if the driver should maintain its own read/write buffers and copy data to/from these buffers to/from the caller's buffers.

- Identify the DMA behavior of the peripheral

Remarks

The buffer allocation method is not identified by this enumeration. Buffers can be allocated statically at build time, dynamically at run-time, or even allocated by the caller and passed to the driver for its own usage if a driver-specific routine is provided for such. This choice is left to the design of the individual driver and is considered part of its interface.

These values can be considered "flags". One selection from each of the groups below can be ORed together to create the complete value passed to the driver's open routine.

DRV_IO_ISBLOCKING Macro

Returns if the I/O intent provided is blocking

C

```
#define DRV_IO_ISBLOCKING(intent) (intent & DRV_IO_INTENT_BLOCKING)
```

Description

Device Driver Blocking Status Macro

This macro returns if the I/O intent provided is blocking.

Remarks

None.

DRV_IO_ISNONBLOCKING Macro

Returns if the I/O intent provided is non-blocking.

C

```
#define DRV_IO_ISNONBLOCKING(intent) (intent & DRV_IO_INTENT_NONBLOCKING )
```

Description

Device Driver Non Blocking Status Macro

This macro returns if the I/ intent provided is non-blocking.

Remarks

None.

DRV_IO_ISEXCLUSIVE Macro

Returns if the I/O intent provided is non-blocking.

C

```
#define DRV_IO_ISEXCLUSIVE(intent) (intent & DRV_IO_INTENT_EXCLUSIVE)
```

Description

Device Driver Exclusive Status Macro

This macro returns if the I/O intent provided is non-blocking.

Remarks

None.

DRV_IO_BUFFER_TYPES Enumeration

Identifies to which buffer a device operation will apply.

C

```
typedef enum {
    DRV_IO_BUFFER_TYPE_NONE = 0x00,
    DRV_IO_BUFFER_TYPE_READ = 0x01,
    DRV_IO_BUFFER_TYPE_WRITE = 0x02,
    DRV_IO_BUFFER_TYPE_RW = DRV_IO_BUFFER_TYPE_READ|DRV_IO_BUFFER_TYPE_WRITE
} DRV_IO_BUFFER_TYPES;
```

Members

Members	Description
DRV_IO_BUFFER_TYPE_NONE = 0x00	Operation does not apply to any buffer
DRV_IO_BUFFER_TYPE_READ = 0x01	Operation applies to read buffer
DRV_IO_BUFFER_TYPE_WRITE = 0x02	Operation applies to write buffer
DRV_IO_BUFFER_TYPE_RW = DRV_IO_BUFFER_TYPE_READ DRV_IO_BUFFER_TYPE_WRITE	Operation applies to both read and write buffers

Description

Device Driver IO Buffer Identifier

This enumeration identifies to which buffer (read, write, both, or neither) a device operation will apply. This is used for "flush" (or similar) operations.

DRV_CLIENT_STATUS Enumeration

Identifies the current status/state of a client's connection to a driver.

C

```
typedef enum {
    DRV_CLIENT_STATUS_ERROR_EXTENDED = -10,
    DRV_CLIENT_STATUS_ERROR = -1,
    DRV_CLIENT_STATUS_CLOSED = 0,
    DRV_CLIENT_STATUS_BUSY = 1,
    DRV_CLIENT_STATUS_READY = 2,
    DRV_CLIENT_STATUS_READY_EXTENDED = 10
} DRV_CLIENT_STATUS;
```

Members

Members	Description
DRV_CLIENT_STATUS_ERROR_EXTENDED = -10	Indicates that a driver-specific error has occurred.
DRV_CLIENT_STATUS_ERROR = -1	An unspecified error has occurred.
DRV_CLIENT_STATUS_CLOSED = 0	The driver is closed, no operations for this client are ongoing, and/or the given handle is invalid.
DRV_CLIENT_STATUS_BUSY = 1	The driver is currently busy and cannot start additional operations.
DRV_CLIENT_STATUS_READY = 2	The module is running and ready for additional operations
DRV_CLIENT_STATUS_READY_EXTENDED = 10	Indicates that the module is in a driver-specific ready/run state.

Description

Driver Client Status

This enumeration identifies the current status/state of a client's link to a driver.

Remarks

The enumeration used as the return type for the client-level status routines defined by each device driver or system module (for example, DRV_USART_ClientStatus) must be based on the values in this enumeration.

System Service Libraries Help

This section provides help for the System Service libraries that are available in MPLAB Harmony 3 Core.

Introduction

Describes system services provided by MPLAB Harmony.

Description

MPLAB Harmony provides system service libraries to support common functionality and manage resources that are shared by multiple drivers, libraries, and other modules.

A system service encapsulates code that manages a shared resource or implements a common capability in a single location so that it does not need to be replicated by individual drivers and libraries. This feature eliminates duplicated code and creates consistency across all modules, and also helps to eliminate potential conflicts and complex configuration issues and runtime interactions, resulting in a smaller and simpler overall solution.

System services may directly manage one or more peripherals or core processor capabilities by utilizing peripheral libraries, special function registers, special CPU instructions, or coprocessor registers. Some system services may utilize drivers, other system services, or even entire middleware stacks to share or emulate a common resource.

System services may be implemented statically (possibly generated by the MPLAB Harmony Configurator (MHC)) or dynamically to support multiple channels and instances like a driver. However, system services will not normally provide common *Open* and *Close* functions like a device driver.

In general, the distinguishing feature of a system service is that it implements a common capability that would otherwise "cut horizontally" across multiple modules in a system, causing interoperability and compatibility conflicts if the capability were implemented by other libraries.

System service functions use the following naming convention:

`SYS_<module-abbreviation>_[<feature-short-name>]<operation>`

Where,

- `SYS_` indicates that this is a system service function
- `<module-abbreviation>` is the abbreviated name of the system service module to which this function belongs
- `[<feature-short-name>]` is an optional short (or shortened) name that identifies the feature of the associated system service module to which this function refers. The feature short name will appear in the name of all functions that interact with or provide access to that particular feature.
- `<operation>` is a verb that identifies the action taken by the function

For example, `SYS_TIME_TimerStart`, where:

- `<module-abbreviation>` = TMR, which indicates that this is a Timer System Service function
- `<feature-short-name>` = Alarm, which indicates that this function controls the alarm feature of the Timer System Service
- `<operation>` = Set, which indicates that this function sets the value of the alarm feature of the Timer System Service, as indicated by the function's parameters (not shown above).

Cache System Service Library Help

This section describes the Cache System Service Library.

Introduction

This library provides an abstracted interface to cache maintenance operations.

Description

The Cache System Service provides interface to Enable, Disable, Clean, Invalidate Data and Instruction Cache.

Using the Library

This section describes the basic architecture of the Cache System Service Library and provides information on how to use it.

Description

Interface Header File: sys_cache.h

The interface to the Cache System Service library is defined in the sys_cache.h header file. Any C language source (.c) file that uses the Cache System Service Library use this API's to perform Cache operations.

Abstraction Model

This model explains how the system interfaces with the Cache System Service and the application.

Description

This library provides an abstraction of the Cache subsystem that is used by device drivers, middleware libraries and applications to perform Cache maintenance operations.

Cache Service Abstraction Block Diagram

Cache System Service

The Cache system service uses either CMSIS Cache interfaces or the device specific Cache Peripheral interfaces based on the device selection to perform the Data and Instruction Cache operations.

Configuring the Library

This Section provides information on how to configure Cache System Service Library.

Description

Cache System Service Library is configured automatically based on the availability of the Cache on the device.

Building the Library

This section lists the files that are available in the Cache System Service Library.

Description

The following three tables list and describe the header (.h) and source (.c) files that implement this library. The parent folder for these files is <install-dir>/core/system/cache.

Interface File(s)

This table lists and describes the header files that must be included (i.e., using #include) by any code that uses this library.

Source File Name	Description
sys_cache.h	Cache System Service Library API header file.

Required File(s)

 **MHC** *All of the required files listed in the following table are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.*

This table lists and describes the source and header files that must always be included in the MPLAB X IDE project to build this library.

Source File Name	Description
/src/sys_cache.c	Cache System Service Library implementation.

Optional File(s)

This table lists and describes the source and header files that may optionally be included if required for the desired

implementation.

Source File Name	Description
N/A	There are no optional files for the Cache System Service Library.

Module Dependencies

The Cache System Service Library depends on the availability of the device cache.

Library Interface

Functions

	Name	Description
≡◊	SYS_CACHE_CleanDCache	Clean Data Cache.
≡◊	SYS_CACHE_CleanDCache_by_Addr	Data Cache Clean by address.
≡◊	SYS_CACHE_CleanInvalidateDCache	Clean and Invalidate Data Cache.
≡◊	SYS_CACHE_CleanInvalidateDCache_by_Addr	Data Cache Clean and Invalidate by address.
≡◊	SYS_CACHE_DisableCaches	Disables both Instruction and Data Caches.
≡◊	SYS_CACHE_DisableDCache	Disable Data Cache.
≡◊	SYS_CACHE_DisableICache	Disable Instruction Cache.
≡◊	SYS_CACHE_EnableCaches	Enables both Instruction and Data Caches.
≡◊	SYS_CACHE_EnableDCache	Enable Instruction Cache.
≡◊	SYS_CACHE_EnableICache	Enable Instruction Cache.
≡◊	SYS_CACHE_InvalidateDCache	Invalidate Data Cache.
≡◊	SYS_CACHE_InvalidateDCache_by_Addr	Data Cache Invalidate by address.
≡◊	SYS_CACHE_InvalidateICache	Invalidate Instruction Cache.

Description

This section describes the APIs of the DMA System Service Library.

Refer to each section for a detailed description.

SYS_CACHE_CleanDCache Function

Clean Data Cache.

C

```
void SYS_CACHE_CleanDCache();
```

Returns

None.

Description

Cleans Data Cache.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_CleanDCache();
```

Function

```
void SYS_CACHE_CleanDCache (void)
```

SYS_CACHE_CleanDCache_by_Addr Function

Data Cache Clean by address.

C

```
void SYS_CACHE_CleanDCache_by_Addr(uint32_t * addr, int32_t size);
```

Returns

None.

Description

Cleans Data Cache for the given address.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_CleanDCache_by_Addr(addr, size);
```

Parameters

Parameters	Description
addr	address (aligned to 32-byte boundary)
size	size of memory block (in number of bytes)

Function

```
void SYS_CACHE_CleanDCache_by_Addr (uint32_t *addr, int32_t size)
```

SYS_CACHE_CleanInvalidateDCache Function

Clean and Invalidate Data Cache.

C

```
void SYS_CACHE_CleanInvalidateDCache();
```

Returns

None.

Description

Cleans and Invalidates Data Cache.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_CleanInvalidateDCache();
```

Function

```
void SYS_CACHE_CleanInvalidateDCache (void)
```

SYS_CACHE_CleanInvalidateDCache_by_Addr Function

Data Cache Clean and Invalidate by address.

C

```
void SYS_CACHE_CleanInvalidateDCache_by_Addr(uint32_t * addr, int32_t size);
```

Returns

None.

Description

Cleans and invalidates Data Cache for the given address.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_CleanInvalidateDCache_by_Addr(addr, size);
```

Parameters

Parameters	Description
addr	address (aligned to 32-byte boundary)
size	size of memory block (in number of bytes)

Function

```
void SYS_CACHE_CleanInvalidateDCache_by_Addr (uint32_t *addr, int32_t size)
```

SYS_CACHE_DisableCaches Function

Disables both Instruction and Data Caches.

C

```
void SYS_CACHE_DisableCaches();
```

Returns

None.

Description

Turns off both Instruction and Data Caches.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_DisableCaches();
```

Function

```
void SYS_CACHE_DisableCaches (void)
```

SYS_CACHE_DisableDCache Function

Disable Data Cache.

C

```
void SYS_CACHE_DisableDCache();
```

Returns

None.

Description

Turns off Data Cache.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_DisableDCache();
```

Function

```
void SYS_CACHE_DisableDCache (void)
```

SYS_CACHE_DisableICache Function

Disable Instruction Cache.

C

```
void SYS_CACHE_DisableICache();
```

Returns

None.

Description

Turns off Instruction Cache.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_DisableICache();
```

Function

```
void SYS_CACHE_DisableICache (void)
```

SYS_CACHE_EnableCaches Function

Enables both Instruction and Data Caches.

C

```
void SYS_CACHE_EnableCaches();
```

Returns

None.

Description

Turns on both Instruction and Data Caches.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_EnableCaches();
```

Function

```
void SYS_CACHE_EnableCaches(void)
```

SYS_CACHE_EnableDCache Function

Enable Instruction Cache.

C

```
void SYS_CACHE_EnableDCache();
```

Returns

None.

Description

Turns on Data Cache.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_EnableDCache();
```

Function

```
void SYS_CACHE_EnableDCache(void)
```

SYS_CACHE_EnableICache Function

Enable Instruction Cache.

C

```
void SYS_CACHE_EnableICache();
```

Returns

None.

Description

Turns on Instruction Cache.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_EnableICache();
```

Function

```
void SYS_CACHE_EnableICache(void)
```

SYS_CACHE_InvalidateDCache Function

Invalidate Data Cache.

C

```
void SYS_CACHE_InvalidateDCache();
```

Returns

None.

Description

Invalidates Data Cache.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_InvalidateDCache();
```

Function

```
void SYS_CACHE_InvalidateDCache(void)
```

SYS_CACHE_InvalidateDCache_by_Addr Function

Data Cache Invalidate by address.

C

```
void SYS_CACHE_InvalidateDCache_by_Addr(uint32_t * addr, int32_t size);
```

Returns

None.

Description

Invalidates Data Cache for the given address.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_InvalidateDCache_by_Addr(addr, size);
```

Parameters

Parameters	Description
addr	address (aligned to 32-byte boundary)
size	size of memory block (in number of bytes)

Function

```
void SYS_CACHE_InvalidateDCache_by_Addr (uint32_t *addr, int32_t size)
```

SYS_CACHE_InvalidateICache Function

Invalidate Instruction Cache.

C

```
void SYS_CACHE_InvalidateICache();
```

Returns

None.

Description

Invalidates Instruction Cache.

Remarks

None.

Preconditions

None.

Example

```
SYS_CACHE_InvalidateICache();
```

Function

```
void SYS_CACHE_InvalidateICache (void)
```

Command Processor System Service Library Help

This section describes the Command Processor System Service Library.

Introduction

This library provides an abstraction of the Command Processor System Service Library with a convenient C language interface. It provides the framework for a command console that can support commands from multiple client sources.

Description

The Command Processor System Service provides the developer with simple APIs to implement a command console. The console may support commands from one or more client software modules.

Using the Library

This topic describes the basic architecture of the Command Processor System Service Library and provides information on its use.

Description

In conjunction with the Console System Service, the Command Processor System Service provides the user with an ASCII command prompt. It will interpret the commands entered at the prompt and process accordingly. It also supports command history, as well as command help.

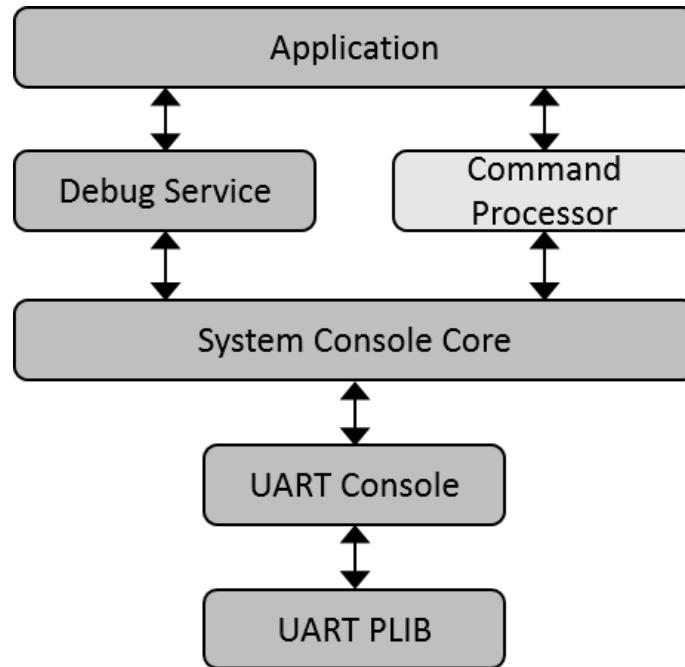
Abstraction Model

This topic provides a description of the software abstraction for the Command Processor System Service.

Description

The Command Processor System Service Library is a collection of operations specific to supporting user input commands. The commands can be uniquely native to each client service and can be dynamically added. The library can support multiple client services at once.

The Command Processor System Service is a module that works closely with the Console System Service to present a user interface command prompt.



How the Library Works

This topic describes the basic architecture of the Command System Service Library and provides information on its implementation.

Description

Initialization and Reinitialization

Initialization of the Command Processor System Service initializes the status of the module and sets the state of the internal state machine.

The Command Processor Status and Tasks routines are required for the normal operation of the service.

Adding Commands

The Command Processor System Service will accept commands dynamically during run-time through the follow interface:

```
SYS_COMMAND_ADDGRP(const _SYS_CMD_DCPT* pCmdTbl, int nCmds, const char*
groupName, const char* menuStr)
```

Command Prompt

In conjunction with the Console System Service, the Command Processor System Service provides the user with an ASCII command prompt. It will interpret the commands entered at the prompt and process accordingly. It also supports command history, as well as command help.

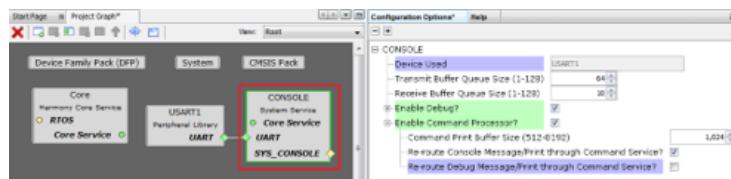
Configuring the Library

This section provides information on how to configure the Command System Service library.

Description

The Command Processor System Service library should be configured via MHC. Below is the snapshot of the MHC configuration window and a brief description of various configuration options.

In MHC, the Command Processor System Service configuration options are available under the Console System Service component.



Configuration Options:

- **Device Used:**
 - Indicates the hardware UART Peripheral Library instance used by the Console System Service
- **Transmit Buffer Queue Size (1-128):**
 - Indicates the maximum number of data transmit requests that can be queued
- **Receive Buffer Queue Size (1-128):**
 - Indicates the maximum number of data reception requests that can be queued
- **Enable Debug?:**
 - Enable Debug System Service. Refer the Debug System Service for the Debug service configuration options
- **Enable Command Processor?:**
 - Enable Command Processor System Service
 - **Command Print Buffer Size (512-8192):**
 - Size of the command print buffer in bytes
 - **Re-route Console Message/Print through Command Service?:**
 - Re-routes the [SYS_MESSAGE](#), [SYS_CONSOLE_MESSAGE](#), [SYS_PRINT](#) and [SYS_CONSOLE_PRINT](#) macros through the Command Service
 - **Re-route Debug Message/Print through Command Service?:**
 - Re-routes the [SYS_DEBUG_MESSAGE](#), [SYS_DEBUG_PRINT](#), [SYS_ERROR_PRINT](#), [SYS_DEBUG](#) and [SYS_ERROR](#) macros through the Command Service
 - For re-routing debug messages through command service, the debug system service must be enabled in MHC configuration

Building the Library

This section provides information on how the Command Processor System Service Library can be built.

Description



MHC *All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.*

Library Interface

This section describes the APIs of the Command Processor System Service Library.

Refer to each section for a detailed description.

a) System Interaction Functions

b) Command I/O Functions

c) Data Types and Constants

Console System Service Library Help

This section describes the Console System Service Library.

Introduction

The Console System Service routes data or message traffic between a console device and a middleware layer or application. The most common use of the Console Service is to route debug or error messages to a terminal program on a host development system.

Description

The Console System Service consists of a core layer and a console device layer. The core layer handles module initialization and system functions. It provides a common API for use by applications and middleware libraries to send and receive data to and from one or more console devices. The Console System core layer maintains the status and device descriptor information for each console instance that has been initialized. Currently, a single instance of console is supported.

The console device layer contains the functional implementation of the core layer APIs. Each console device may have a different implementation, but the behavior of the API should be uniform across different devices. The console device layer interacts with the peripheral libraries (PLIBs) to send and receive data to and from the hardware peripheral. The details of the data transaction are abstracted by the console device layer.

The implementation is non-blocking in nature. The request from the middleware or application return immediately and the data transfer is controlled by a state machine implemented in the console device layer. The calling program is notified of the data transfer completion by a callback mechanism, or can optionally poll the status of the console device layer to see if it is busy (one or more requests are pending) or ready for more data (no request is pending).

The console device layer provides the ability to queue data buffers written to the console. The size of the queue is defined by a configuration option.

Using the Library

This topic describes the basic architecture of the Console System Service Library and provides information and examples on its use.

Description

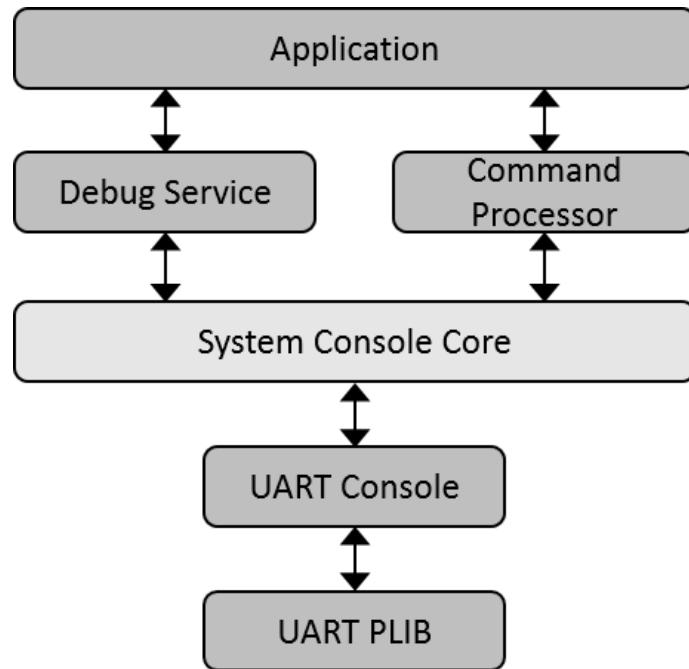
The Console System Service allows the application/middleware to route messages/debug information to a console running on a host computer.

- Depending on the application need, the size of the read and write queues can be configured to allow queuing of multiple requests
- The read/write API called by the calling program returns immediately. The request is queued internally by the console device layer and the data is transferred by the state machine implemented by the console device layer
- The application can register callback with the Console System Service to receive read/write completion/error related notifications

Abstraction Model

This library provides a set of functions that send and receive data to and from a console I/O device.

Description



Console Service Software Abstraction Block Diagram

The Console System Service is a middleware library that is part of a layered software architecture. The purpose of this software layering is to allow each module to provide a consistent interface to its client, thus making it easy for the developer to add and remove modules as needed. The console core layer provides a POSIX-like read/write API to applications and middleware libraries to send and receive data to and from the console device. Data and message buffering, along with the details of the data transfer are contained within the console device and peripheral library (PLIB) layers.

Additional APIs are provided to handle system functions, register a callback function for non-blocking implementations, and flush (reset) the internal queues in the event of an error condition.

How the Library Works

This topic describes the basic architecture of the Console System Service Library and provides information on its implementation.

Description

Each supported console device has its own implementation of the Console System service APIs. Function pointers to the console device implementations are provided in the console device descriptor registered to each console instance. This allows the user to utilize the same API for all console devices, making application code more portable across different devices.

Note: Currently only the UART Console Device is implemented.

UART Console Device

The UART Console Device provides a convenient user I/O interface to applications running on a SAM/PIC32 with UART support.

Description

Read

While the user may request multiple bytes of data per read, a typical terminal emulator program sends only one byte per transaction. When multiple bytes are requested, the UART Console Device layer will queue individual byte reads until all bytes are read. The bytes are sent to the user-supplied read buffer as they are read, and the read callback is triggered when all bytes have been read. Only one read operation can be active at a time. The size of the read queue is a configuration option. The size of the read queue determines the number of read requests (not the number of bytes) that can be queued. Each read request in turn can request for multiple bytes to be read. A call to the console read API with the read queue full returns 0.

The read function accepts a pointer to a read buffer as one of the arguments. It is the responsibility of the application programmer to properly allocate the read buffer.

Write

The UART console device is capable of writing multiple data bytes per transaction, and queuing multiple write transactions. The size of the write queue is a configuration option. If the user tries to queue more write transactions than the write queue can accommodate, the write function will return 0.

The write function accepts a pointer to a write buffer as one of the arguments. It is the responsibility of the application programmer to properly allocate the write buffer.

State Machine

The read and write state machines are run from the interrupt context (from the callback called by the underlying UART PLIB). The underlying PLIB calls the UART console device event handler when the requested number of bytes are transmitted or received (or in case of an error condition). The read/write state machine dispatches application/middleware callback functions and initiates a data transfer if the read/write queue has any request to service.

Register Callback

The callback registration mechanism associates a user function with a read or write completion event. The callback function includes an argument containing a pointer to the read or write buffer associated with the transfer that initiated the callback.

Separate callback functions must be registered for read and write events. If there is no callback function registered, the event will complete as normal, with no callback executed.

Flush

The flush routine in the UART implementation resets the read and write queues. A flush operation is typically triggered in response to an error condition.

Configuring the Library

This section provides information on how to configure the Console System Service library.

Description

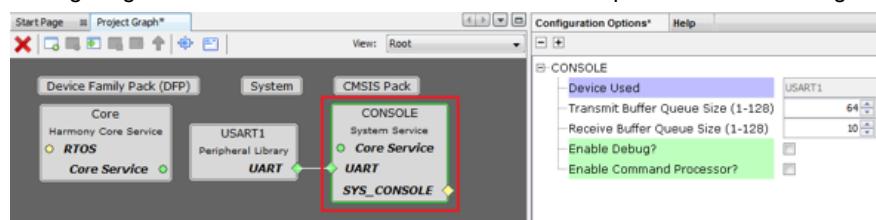
Refer the console device specific configuration options.

UART Console Device Configuration Options

This topic provided configuration option examples for the UART Console Device.

Description

The UART Console System Service library should be configured through the MHC. The following figure shows the MHC configuration window for configuring the UART Console Device and a brief description of various configuration options.



Configuration Options:

- Device Used:**
 - Indicates the hardware UART Peripheral Library instance used by the Console System Service
- Transmit Buffer Queue Size (1-128) :**
 - Indicates the maximum number of data transmit requests that can be queued
- Receive Buffer Queue Size (1-128):**
 - Indicates the maximum number of data reception requests that can be queued
- Enable Debug?:**
 - Enable Debug System Service. Refer the Debug System Service for more details on configuring the Debug service
- Enable Command Processor?:**
 - Enable Command Processor System Service. Refer to the Command Processor System Service for more details on configuring the Command Processor System service

Building the Library

This section provides information on how the Console System Service Library can be built.

Description



All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

Library Interface

a) System Functions

	Name	Description
≡	SYS_CONSOLE_Initialize	Initializes the console instance module and opens or initializes the specific module instance to which it is associated.
≡	SYS_CONSOLE_Status	Returns status of the specific instance of the Console module.
≡	SYS_CONSOLE_Tasks	Maintains the console's state machine.

b) Core Functions

	Name	Description
≡	SYS_CONSOLE_Read	Reads data from the console device.
≡	SYS_CONSOLE_Write	Writes data to the console device.
≡	SYS_CONSOLE_RegisterCallback	Registers a callback function with the console service that will be executed when the read or write request is complete (or in case of an error condition during read/write).
≡	SYS_CONSOLE_Flush	Flushes the read and write queues for the given console instance.

c) Data Types and Constants

	Name	Description
	STDERR_FILENO	This is macro STDERR_FILENO.
	STDIN_FILENO	These are in unistd.h
	STDOUT_FILENO	This is macro STDOUT_FILENO.
	SYS_CONSOLE_INDEX_0	Console System Service index definitions.
	SYS_CONSOLE_INDEX_1	This is macro SYS_CONSOLE_INDEX_1.
	SYS_CONSOLE_INDEX_2	This is macro SYS_CONSOLE_INDEX_2.
	SYS_CONSOLE_INDEX_3	This is macro SYS_CONSOLE_INDEX_3.
	SYS_CONSOLE_MESSAGE	This is macro SYS_CONSOLE_MESSAGE.
	SYS_CONSOLE_PRINT	This is macro SYS_CONSOLE_PRINT.
	SYS_CONSOLE_CALLBACK	Pointer to a console system service callback function.
	SYS_CONSOLE_EVENT	Identifies the system console event for which the callback is being registered.

Description

This section describes the APIs of the Console System Service Library.

Refer to each section for a detailed description.

a) System Functions

SYS_CONSOLE_Initialize Function

Initializes the console instance module and opens or initializes the specific module instance to which it is associated.

C

```
SYS_MODULE_OBJ SYS_CONSOLE_Initialize(const SYS_MODULE_INDEX index, const SYS_MODULE_INIT* const init);
```

Returns

If successful, returns a valid handle to the console instance. Otherwise, it returns [SYS_MODULE_OBJ_INVALID](#). The returned object must be passed as argument to [SYS_CONSOLE_Tasks](#) and [SYS_CONSOLE_Status](#) routines.

Description

This function initializes the internal data structures used by the console module. It also initializes the associated I/O driver/PLIB.

Remarks

This routine should only be called once during system initialization.

Preconditions

None.

Example

```
SYS_MODULE_OBJ objectHandle;

// Populate the console initialization structure
const SYS_CONSOLE_INIT sysConsole0Init =
{
    .deviceInitData = (void*)&sysConsole0UARTInitData,
    .consDevDesc = &sysConsoleUARTDevDesc,
    .deviceIndex = 0,
};

objectHandle = SYS_CONSOLE_Initialize(SYS_CONSOLE_INDEX_0, (SYS_MODULE_INIT *)&sysConsole0Init);
```

```

if (objectHandle == SYS_MODULE_OBJ_INVALID)
{
    // Handle error
}

```

Parameters

Parameters	Description
index	Index for the instance to be initialized
init	Pointer to a data structure containing any data necessary to initialize the Console System service. This pointer may be null if no data is required because static overrides have been provided.

Function

```

SYS_MODULE_OBJ SYS_CONSOLE_Initialize(
const SYS_MODULE_INDEX index,
const SYS_MODULE_INIT* const init
)

```

SYS_CONSOLE_Status Function

Returns status of the specific instance of the Console module.

C

```
SYS_STATUS SYS_CONSOLE_Status(SYS_MODULE_OBJ object);
```

Returns

- SYS_STATUS_READY - Indicates that the driver is initialized and is ready to accept new requests from the clients.
- SYS_STATUS_BUSY - Indicates that the driver is busy with a previous requests from the clients. However, depending on the configured queue size for transmit and receive, it may be able to queue a new request.
- SYS_STATUS_ERROR - Indicates that the driver is in an error state. Any value less than SYS_STATUS_ERROR is also an error state.
- SYS_STATUS_UNINITIALIZED - Indicates that the driver is not initialized.

Description

This function returns the status of the specific module instance.

Remarks

None.

Preconditions

The [SYS_CONSOLE_Initialize](#) function should have been called before calling this function.

Example

```

// Given "object" returned from SYS_CONSOLE_Initialize

SYS_STATUS consStatus;

consStatus = SYS_CONSOLE_Status (object);
if (consStatus == SYS_STATUS_READY)
{
    // Console is initialized and is ready to accept client requests.
}

```

Parameters

Parameters	Description
object	SYS CONSOLE object handle, returned from SYS_CONSOLE_Initialize

Function

`SYS_STATUS SYS_CONSOLE_Status (SYS_MODULE_OBJ object)`

SYS_CONSOLE_Tasks Function

Maintains the console's state machine.

C

```
void SYS_CONSOLE_Tasks(SYS\_MODULE\_OBJ object);
```

Returns

None

Description

This function runs the console system service's internal state machine.

Remarks

This function is normally not called directly by an application. It is called by the system's Tasks routine (SYS_Tasks) or by the appropriate raw ISR.

Preconditions

The [SYS_CONSOLE_Initialize](#) function must have been called for the specified CONSOLE driver instance.

Example

```
SYS_MODULE_OBJ object; // Returned from SYS\_CONSOLE\_Initialize

while (true)
{
    SYS_CONSOLE_Tasks (object);

    // Do other tasks
}
```

Parameters

Parameters	Description
object	SYS CONSOLE object handle, returned from SYS_CONSOLE_Initialize

Function

`void SYS_CONSOLE_Tasks (SYS_MODULE_OBJ object)`

b) Core Functions

SYS_CONSOLE_Read Function

Reads data from the console device.

C

```
ssize_t SYS_CONSOLE_Read(const SYS\_MODULE\_INDEX index, int fd, void\* buf, size\_t count);
```

Returns

The requested number of bytes to read is returned back if the request is accepted successfully. In case of error, the returned value is less than the requested number of bytes to read.

Description

This function reads the data from the console device.

Remarks

None.

Preconditions

The [SYS_CONSOLE_Initialize](#) function should have been called before calling this function.

Example

```
ssize_t nr;
char myBuffer[MY_BUFFER_SIZE];
nr = SYS_CONSOLE_Read( SYS_CONSOLE_INDEX_0, 0, myBuffer, MY_BUFFER_SIZE );
if (nr != MY_BUFFER_SIZE)
{
    // handle error
}
```

Parameters

Parameters	Description
index	Console instance index
fd	I/O stream handle. Maintained for backward compatibility. NULL value can be passed as a parameter.
buf	Buffer to hold the read data.
count	Number of bytes to read.

Function

```
ssize_t SYS_CONSOLE_Read(
const    SYS_MODULE_INDEX index,
int fd,
void* buf,
size_t count
)
```

SYS_CONSOLE_Write Function

Writes data to the console device.

C

```
ssize_t SYS_CONSOLE_Write(const SYS_MODULE_INDEX index, int fd, const void* buf, size_t count);
```

Returns

The requested number of bytes to write is returned back if the request is accepted successfully. In case of error, the returned value is less than the requested number of bytes to write.

Description

This function writes data to the console device.

Remarks

None.

Preconditions

The [SYS_CONSOLE_Initialize](#) function should have been called before calling this function.

Example

```
ssize_t nr;
char myBuffer[] = "message";
nr = SYS_CONSOLE_Write( SYS_CONSOLE_INDEX_0, 0, myBuffer, strlen(myBuffer) );
if (nr != strlen(myBuffer))
{
    // Handle error
}
```

Parameters

Parameters	Description
index	Console instance index
fd	I/O stream handle. Maintained for backward compatibility. NULL value can be passed as a parameter.
buf	Buffer holding the data to be written.
count	Number of bytes to write.

Function

```
ssize_t SYS_CONSOLE_Write(
    const SYS_MODULE_INDEX index,
    int fd,
    const void* buf,
    size_t count
)
```

SYS_CONSOLE_RegisterCallback Function

Registers a callback function with the console service that will be executed when the read or write request is complete (or in case of an error condition during read/write).

C

```
void SYS_CONSOLE_RegisterCallback(const SYS_MODULE_INDEX index, SYS_CONSOLE_CALLBACK cbFunc,
    SYS_CONSOLE_EVENT event);
```

Returns

None.

Description

This function is used by an application to register a callback function with the console service. The callback function is called in response to a read/write completion (or error) event. Separate callback functions are required for each event. To receive events, the callback must be registered before submitting a read/write request.

Remarks

None.

Preconditions

The [SYS_CONSOLE_Initialize](#) function should have been called before calling this function.

Example

```
//Registering a "APP_ReadComplete" read callback function
SYS_CONSOLE_RegisterCallback(SYS_CONSOLE_INDEX_0, APP_ReadComplete,
    SYS_CONSOLE_EVENT_READ_COMPLETE);
```

```
//Registering a "APP_WriteComplete" write callback function
SYS_CONSOLE_RegisterCallback(SYS_CONSOLE_INDEX_0, APP_WriteComplete,
                             SYS_CONSOLE_EVENT_WRITE_COMPLETE);
```

Parameters

Parameters	Description
index	Console instance index
cbFunc	The name of the callback function
event	Enumerated list of events that can trigger a callback

Function

```
void SYS_CONSOLE_RegisterCallback(
    const SYS_MODULE_INDEX index,
    SYS_CONSOLE_CALLBACK cbFunc,
    SYS_CONSOLE_EVENT event
)
```

SYS_CONSOLE_Flush Function

Flushes the read and write queues for the given console instance.

C

```
void SYS_CONSOLE_Flush(const SYS_MODULE_INDEX index);
```

Returns

None.

Description

This function flushes queued read and write requests. The request that is already in progress cannot be flushed. Only the queued pending requests will be flushed.

Remarks

None.

Preconditions

The [SYS_CONSOLE_Initialize](#) function should have been called before calling this function.

Example

```
SYS_CONSOLE_Flush(SYS_CONSOLE_INDEX_0);
```

Parameters

Parameters	Description
index	Console instance index

Function

```
void SYS_CONSOLE_Flush(const SYS_MODULE_INDEX index)
```

c) Data Types and Constants

STDERR_FILENO Macro

C

```
#define STDERR_FILENO 2
```

Description

This is macro STDERR_FILENO.

STDIN_FILENO Macro

C

```
#define STDIN_FILENO 0
```

Description

These are in unistd.h

STDOUT_FILENO Macro

C

```
#define STDOUT_FILENO 1
```

Description

This is macro STDOUT_FILENO.

SYS_CONSOLE_INDEX_0 Macro

Console System Service index definitions.

C

```
#define SYS_CONSOLE_INDEX_0 0
```

Description

SYS Console Module Index Numbers

These constants provide Console System Service index definitions.

Remarks

These constants should be used in place of hard-coded numeric literals.

SYS_CONSOLE_INDEX_1 Macro

C

```
#define SYS_CONSOLE_INDEX_1 1
```

Description

This is macro SYS_CONSOLE_INDEX_1.

SYS_CONSOLE_INDEX_2 Macro

C

```
#define SYS_CONSOLE_INDEX_2 2
```

Description

This is macro SYS_CONSOLE_INDEX_2.

SYS_CONSOLE_INDEX_3 Macro

C

```
#define SYS_CONSOLE_INDEX_3 3
```

Description

This is macro SYS_CONSOLE_INDEX_3.

SYS_CONSOLE_MESSAGE Macro

C

```
#define SYS_CONSOLE_MESSAGE(message)
```

Description

This is macro SYS_CONSOLE_MESSAGE.

SYS_CONSOLE_PRINT Macro

C

```
#define SYS_CONSOLE_PRINT(fmt, ...)
```

Description

This is macro SYS_CONSOLE_PRINT.

SYS_CONSOLE_CALLBACK Type

Pointer to a console system service callback function.

C

```
typedef void (* SYS_CONSOLE_CALLBACK)(void* pBuffer);
```

Returns

None.

Description

This data type defines a pointer to a console service callback function, thus defining the function signature.

Remarks

None.

Preconditions

The console service must have been initialized using the [SYS_CONSOLE_Initialize](#) function before attempting to register a SYS Console callback function.

Example

```
void MyCallback ( void* pBuffer )
{
    if (pBuffer != NULL)
    {
        //Free the memory pointed by pBuffer if it was allocated dynamically.
    }
}
```

Parameters

Parameters	Description
pBuffer	Pointer to the processed read/write buffer. It can be used identify the buffer that is processed by the console system service and free the buffer memory if it was allocated dynamically.

Function

```
void ( * SYS_CONSOLE_CALLBACK ) ( void* pBuffer )
```

SYS_CONSOLE_EVENT Enumeration

Identifies the system console event for which the callback is being registered.

C

```
typedef enum {
    SYS_CONSOLE_EVENT_WRITE_COMPLETE,
    SYS_CONSOLE_EVENT_READ_COMPLETE
} SYS_CONSOLE_EVENT;
```

Members

Members	Description
SYS_CONSOLE_EVENT_WRITE_COMPLETE	System console write complete event
SYS_CONSOLE_EVENT_READ_COMPLETE	System console read complete event

Description

System Console Event

This enum is used to identify if the callback being registered is to be called on a read or on a write complete event.

Debug System Service Library Help

This section describes the Debug System Service Library.

Introduction

This library implements the Debug System Service. The Debug System Service provides a convenient mechanism for the application developer to send formatted or unformatted messages to a system console.

Description

The Debug System Service provides a set of functions that allow the developer to output debug and/or error messages based on a global error level. The messages are sent to the System Console Service, where they are routed to a console device.

The Debug System Service maintains a global error level, which may be set during initialization and changed dynamically at run-time. Both formatted and unformatted messages can be output or not, depending on the current global error level.

Using the Library

This topic describes the basic architecture of the Debug System Service Library and provides information on its use.

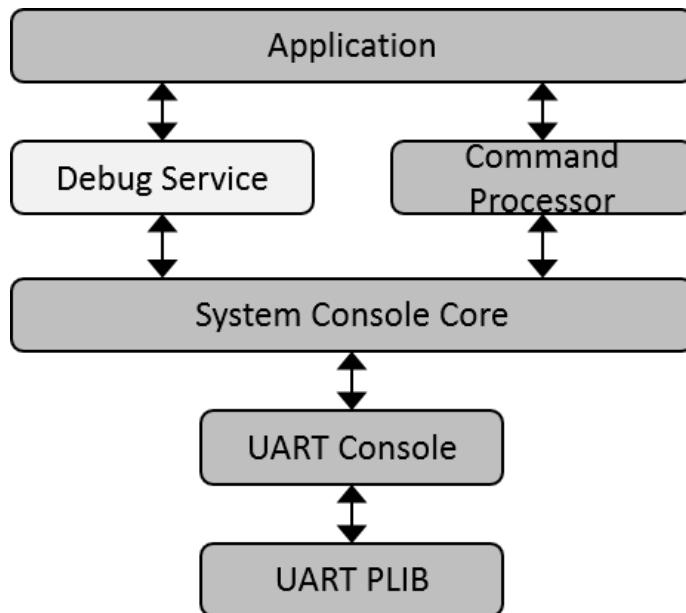
Description

When the Debug System Service is initialized, it sets the global system error level to the specified level. This level determines the threshold at which debug and error messages are sent to the console. This allows different debug and error reporting verbosity depending on the needs of the developer. The Debug System Service also provides APIs to dynamically set the error level during program execution. This allows the developer to increase or decrease debug verbosity to specific areas of interest within the program.

Abstraction Model

This library provides a set of functions that allow the developer to quickly and easily provide debug and error messaging during and after program development.

Description



Debug Service Software Abstraction Block Diagram

The Debug System Service provides APIs for the application developer to send formatted or unformatted messages to a system console. The console core layer provides a POSIX-like read/write API to applications and middleware libraries to send and receive data to and from the console device. Data and message buffering, along with the details of the data transfer are contained within the console device and peripheral library (PLIB) layers.

How the Library Works

The Debug System Service library can be used by a device driver, middleware layer, or application to report error conditions and output debug messages to a console device during program operation.

Description

Debug Messages and Error Reporting

The following macros are available to output debug and error messages. The default implementation of these macros resolves to

nothing by the preprocessor. This is to allow the developer to leave debug messaging in the released code without impacting code size or performance. Typically, the developer would define SYS_DEBUG_USE_CONSOLE macro through MHC configuration for debug builds, to map these macros to appropriate debug service implementation.

- **SYS_MESSAGE**(message) prints a simple message string to the output device irrespective of the value of the global error level
- **SYS_DEBUG_MESSAGE**(level, message) prints a debug message to the console device if the global error level is equal to or lower than that specified by the "level" argument
- **SYS_PRINT**(fmt, ...) prints formatted messages to the console. The message formatting is the same as printf
- **SYS_DEBUG_PRINT**(level, fmt, ...) prints formatted messages to the console if the global error level is equal to or lower than that specified by the "level" argument. The message formatting is the same as printf

Changing the System Error Level

Two functions are provided to manipulate the global system error level at runtime. This may be useful when you want to increase the debug verbosity for a particular section of code, but not for the entire program

- **SYS_DEBUG_ErrorLevelGet()** returns the current global system error level
- **SYS_DEBUG_ErrorLevelSet(level)** sets the current global system error level

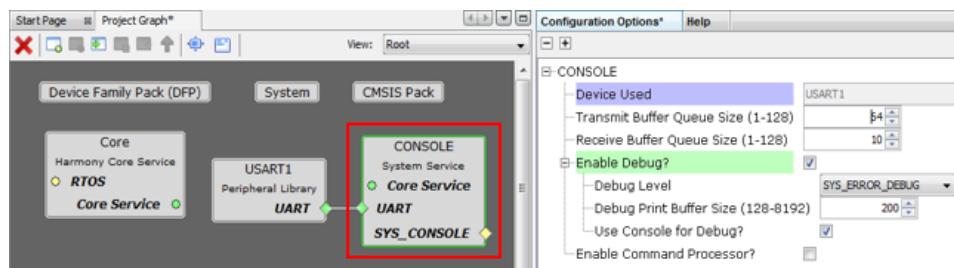
Configuring the Library

This section provides information on how to configure the Debug System Service library.

Description

The Debug System Service library should be configured through the MHC. The following figure shows the MHC configuration window and a brief description of various configuration options.

In MHC, the Debug System Service configuration options are available under the Console System Service component.



Configuration Options:

- **Device Used:**
 - Indicates the hardware UART Peripheral Library instance used by the Console System Service
- **Transmit Buffer Queue Size (1-128):**
 - Indicates the maximum number of data transmit requests that can be queued
- **Receive Buffer Queue Size (1-128):**
 - Indicates the maximum number of data reception requests that can be queued
- **Enable Debug?:**
 - Enable Debug System Service
 - **Debug Level:**
 - Indicates the global error level set during initialization. Application can change the global error level during runtime using an API
 - **Debug Print Buffer Size (128-8192):**
 - Indicates the size of the print buffer in bytes
 - **Use Console for Debug:**
 - Check this option to map the debug macros to debug implementation. Un-checking this option maps the debug macros to nothing
- **Enable Command Processor:**
 - Enable Command Processor System Service. Refer the Command Processor System Service for more information on configuring the Command Processor System Service

Building the Library

This section provides information on how the Debug System Service Library can be built.

Description



MHC *All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.*

Library Interface

a) System Functions

	Name	Description
≡	SYS_DEBUG_Initialize	Initializes the global error level and specific module instance.
≡	SYS_DEBUG_Status	Returns status of the specific instance of the debug service module.
≡	SYS_DEBUG_Tasks	Maintains the debug module's state machine.
≡	SYS_DEBUG_Message	Prints a message to the console regardless of the system error level.
≡	SYS_DEBUG_Print	Formats and prints a message with a variable number of arguments to the console regardless of the system error level.
	SYS_DEBUG_BreakPoint	Inserts a software breakpoint instruction when building in Debug mode.

b) Changing System Error Level Functions

	Name	Description
≡	SYS_DEBUG_ErrorLevelGet	Returns the global system Error reporting level.
≡	SYS_DEBUG_ErrorLevelSet	Sets the global system error reporting level.

c) Data Types and Constants

	Name	Description
	SYS_ERROR_LEVEL	System error message priority levels.
	SYS_DEBUG_INDEX_0	This is macro SYS_DEBUG_INDEX_0.
	SYS_MESSAGE	Prints a message to the console regardless of the system error level.
	SYS_DEBUG_MESSAGE	Prints a debug message if the system error level is defined at or lower than the level specified.
	SYS_PRINT	Formats and prints an error message with a variable number of arguments regardless of the system error level.
	SYS_DEBUG_PRINT	Formats and prints an error message if the system error level is defined at or lower than the level specified.
	_SYS_DEBUG_MESSAGE	Prints a debug message if the specified level is at or below the global system error level.
	_SYS_DEBUG_PRINT	Formats and prints a debug message if the specified level is at or below the global system error level.

Description

This section describes the APIs of the Debug System Service Library.

Refer to each section for a detailed description.

a) System Functions

SYS_DEBUG_Initialize Function

Initializes the global error level and specific module instance.

C

```
SYS_MODULE_OBJ SYS_DEBUG_Initialize(const SYS_MODULE_INDEX index, const SYS_MODULE_INIT* const init);
```

Returns

If successful, returns SYS_MODULE_OBJ_STATIC. Otherwise, it returns [SYS_MODULE_OBJ_INVALID](#).

Description

This function initializes the global error level. It also initializes any internal system debug module data structures.

Remarks

This routine should only be called once during system initialization.

Preconditions

None.

Example

```
SYS_MODULE_OBJ objectHandle;
SYS_DEBUG_INIT debugInit =
{
    .moduleInit = {0},
    .errorLevel = SYS_DEBUG_GLOBAL_ERROR_LEVEL,
    .consoleIndex = 0,
};

objectHandle = SYS_DEBUG_Initialize(SYS_DEBUG_INDEX_0, (SYS_MODULE_INIT*)&debugInit);
if (objectHandle == SYS_MODULE_OBJ_INVALID)
{
    // Handle error
}
```

Parameters

Parameters	Description
index	Index for the instance to be initialized.
init	Pointer to a data structure containing any data necessary to initialize the debug service. This pointer may be null if no data is required because static overrides have been provided.

Function

```
SYS_MODULE_OBJ SYS_DEBUG_Initialize(
const SYS_MODULE_INDEX index,
const SYS_MODULE_INIT* const init
)
```

SYS_DEBUG_Status Function

Returns status of the specific instance of the debug service module.

C

```
SYS_STATUS SYS_DEBUG_Status(SYS_MODULE_OBJ object);
```

Returns

- **SYS_STATUS_READY** - Indicates that the module is running and ready to service requests. Any value greater than **SYS_STATUS_READY** is also a normal running state in which the module is ready to accept new operations.
- **SYS_STATUS_BUSY** - Indicates that the module is busy with a previous system level operation.
- **SYS_STATUS_ERROR** - Indicates that the module is in an error state. Any value less than **SYS_STATUS_ERROR** is also an error state.
- **SYS_STATUS_UNINITIALIZED** - Indicates that the module has not been initialized.

Description

This function returns the status of the specific debug service module instance.

Remarks

None.

Preconditions

The [SYS_DEBUG_Initialize](#) function should have been called before calling this function.

Example

```
SYS_MODULE_OBJ      object;      // Returned from SYS_CONSOLE_Initialize
SYS_STATUS         debugStatus;

debugStatus = SYS_DEBUG_Status (object);
if (debugStatus == SYS_STATUS_READY)
{
    // Debug service is initialized and ready to accept requests.
}
```

Parameters

Parameters	Description
object	Debug module object handle, returned from SYS_DEBUG_Initialize

Function

[SYS_STATUS](#) [SYS_DEBUG_Status](#) ([SYS_MODULE_OBJ](#) object)

SYS_DEBUG_Tasks Function

Maintains the debug module's state machine.

C

```
void SYS_DEBUG_Tasks(SYS\_MODULE\_OBJ object);
```

Returns

None.

Description

This function is used to maintain the debug module's internal state machine.

Remarks

This function is normally not called directly by an application. The task routine may not be called if the debug service does not require maintaining an internal state machine.

Preconditions

The [SYS_DEBUG_Initialize](#) function must have been called.

Example

```
SYS_MODULE_OBJ      object;      // Returned from SYS_DEBUG_Initialize
```

```

while (true)
{
    SYS_DEBUG_Tasks (object);

    // Do other tasks
}

```

Parameters

Parameters	Description
object	SYS DEBUG object handle, returned from SYS_DEBUG_Initialize

Function

```
void SYS_DEBUG_Tasks( SYS\_MODULE\_OBJ object )
```

SYS_DEBUG_Message Function

Prints a message to the console regardless of the system error level.

C

```
void SYS_DEBUG_Message(const char * message);
```

Returns

None.

Description

This function prints a message to the console regardless of the system error level. It can be used as an implementation of the [SYS_MESSAGE](#) and [SYS_DEBUG_MESSAGE](#) macros.

Remarks

Do not call this function directly. Call the [SYS_MESSAGE](#) or [SYS_DEBUG_MESSAGE](#) macros instead.

The default [SYS_MESSAGE](#) and [SYS_DEBUG_MESSAGE](#) macro definitions remove the messages and message function calls from the source code. To access and utilize the messages, define the [SYS_DEBUG_USE_CONSOLE](#) macro or override the definitions of the individual macros.

Preconditions

[SYS_DEBUG_Initialize](#) must have returned a valid object handle.

Example

```

// In configuration.h file: #define SYS_DEBUG_USE_CONSOLE
// In sys_debug.h file: #define SYS_MESSAGE(message) SYS_DEBUG_Message(message)

SYS_MESSAGE("My Message\n");

```

Parameters

Parameters	Description
message	Pointer to a message string to be displayed.

Function

```
void SYS_DEBUG_Message(const char *message)
```

SYS_DEBUG_Print Function

Formats and prints a message with a variable number of arguments to the console regardless of the system error level.

C

```
void SYS_DEBUG_Print(const char * format, ...);
```

Returns

None.

Description

This function formats and prints a message with a variable number of arguments to the console regardless of the system error level. It can be used to implement the [SYS_PRINT](#) and [SYS_DEBUG_PRINT](#) macros.

Remarks

The format string and arguments follow the printf convention.

Do not call this function directly. Call the [SYS_PRINT](#) or [SYS_DEBUG_PRINT](#) macros instead.

The default [SYS_PRINT](#) and [SYS_DEBUG_PRINT](#) macro definitions remove the messages and message function calls. To access and utilize the messages, define the [SYS_DEBUG_USE_CONSOLE](#) macro or override the definitions of the individual macros.

Preconditions

[SYS_DEBUG_Initialize](#) must have returned a valid object handle.

Example

```
// In configuration.h file: #define SYS_DEBUG_USE_CONSOLE
// In sys_debug.h file: #define SYS_PRINT(fmt, ...) SYS_DEBUG_Print(fmt, ##__VA_ARGS__)

// In source code
int result;

result = SomeOperation();
if (result > MAX_VALUE)
{
    SYS_PRINT("Result of %d exceeds max value", result);
}
```

Parameters

Parameters	Description
format	Pointer to a buffer containing the format string for the message to be displayed.
...	Zero or more optional parameters to be formatted as defined by the format string.

Function

void SYS_DEBUG_Print(const char *format, ...)

SYS_DEBUG_BreakPoint Macro

Inserts a software breakpoint instruction when building in Debug mode.

C

```
#define SYS_DEBUG_BreakPoint
```

Description

Macro: `SYS_DEBUG_BreakPoint(void)`

This macro inserts a software breakpoint instruction when building in Debug mode. The Macro will be mapped to proper instruction based on the architecture used.

Remarks

Compiles out if not built for debugging.

Example

```
if (myDebugTestFailed)
{
    SYS_DEBUG_BreakPoint();
```

```
}
```

b) Changing System Error Level Functions

SYS_DEBUG_ErrorLevelGet Function

Returns the global system Error reporting level.

C

```
SYS_ERROR_LEVEL SYS_DEBUG_ErrorLevelGet();
```

Returns

The global System Error Level.

Description

This function returns the global System Error reporting level.

Remarks

None.

Preconditions

[SYS_DEBUG_Initialize](#) must have returned a valid object handle.

Example

```
SYS_ERROR_LEVEL level;  
  
level = SYS_DEBUG_ErrorLevelGet();
```

Function

```
SYS_ERROR_LEVEL SYS_DEBUG_ErrorLevelGet(void)
```

SYS_DEBUG_ErrorLevelSet Function

Sets the global system error reporting level.

C

```
void SYS_DEBUG_ErrorLevelSet(SYS_ERROR_LEVEL level);
```

Returns

None.

Description

This function sets the global system error reporting level.

Remarks

None.

Preconditions

[SYS_DEBUG_Initialize](#) must have returned a valid object handle.

Example

```
SYS_DEBUG_ErrorLevelSet(SYS_ERROR_WARNING);
```

Parameters

Parameters	Description
level	The desired system error level.

Function

```
void SYS_DEBUG_ErrorLevelSet( SYS\_ERROR\_LEVEL level)
```

c) Data Types and Constants

SYS_ERROR_LEVEL Enumeration

System error message priority levels.

C

```
typedef enum {
    SYS_ERROR_FATAL = 0,
    SYS_ERROR_ERROR = 1,
    SYS_ERROR_WARNING = 2,
    SYS_ERROR_INFO = 3,
    SYS_ERROR_DEBUG = 4
} SYS_ERROR_LEVEL;
```

Members

Members	Description
SYS_ERROR_FATAL = 0	Errors that have the potential to cause a system crash.
SYS_ERROR_ERROR = 1	Errors that have the potential to cause incorrect behavior.
SYS_ERROR_WARNING = 2	Warnings about potentially unexpected behavior or side effects.
SYS_ERROR_INFO = 3	Information helpful to understanding potential errors and warnings.
SYS_ERROR_DEBUG = 4	Verbose information helpful during debugging and testing.

Description

SYS_ERROR_LEVEL enumeration

This enumeration defines the supported system error message priority values.

Remarks

Used by debug message macros to compare individual message priority against a global system-wide error message priority level to determine if an individual message should be displayed.

SYS_DEBUG_INDEX_0 Macro

C

```
#define SYS_DEBUG_INDEX_0 0
```

Description

This is macro SYS_DEBUG_INDEX_0.

SYS_MESSAGE Macro

Prints a message to the console regardless of the system error level.

C

```
#define SYS_MESSAGE(message)
```

Returns

None.

Description

Macro: SYS_MESSAGE(const char* message)

This macro is used to print a message to the console regardless of the system error level. It can be mapped to any desired implementation.

Remarks

By default, this macro is defined as nothing, effectively removing all code generated by calls to it. To process SYS_MESSAGE calls, this macro must be defined in a way that maps calls to it to the desired implementation (see example, above).

This macro can be mapped to the system console service (along with other system debug macros) by defining SYS_DEBUG_USE_CONSOLE in the system configuration (configuration.h) instead of defining it individually.

Preconditions

If mapped to the [SYS_DEBUG_Message](#) function, then the system debug service must be initialized and running.

Example

```
// In configuration.h file: #define SYS_DEBUG_USE_CONSOLE
// In sys_debug.h file: #define SYS_MESSAGE(message) SYS_DEBUG_Message(message)

// In source code
SYS_MESSAGE( "My Message" );
```

Parameters

Parameters	Description
message	Pointer to a buffer containing the message string to be displayed.

SYS_DEBUG_MESSAGE Macro

Prints a debug message if the system error level is defined at or lower than the level specified.

C

```
#define SYS_DEBUG_MESSAGE(level,message)
```

Returns

None.

Description

This function prints a debug message if the system error level is defined at or lower than the level specified. If mapped to the [SYS_DEBUG_Message](#) function, then the system debug service must be initialized and running.

Remarks

By default, this macro is defined as nothing, effectively removing all code generated by calls to it. To process SYS_DEBUG_MESSAGE calls, this macro must be defined in a way that maps calls to it to the desired implementation (see example, above).

This macro can be mapped to the system console service (along with other system debug macros) by defining SYS_DEBUG_USE_CONSOLE in the system configuration (configuration.h) instead of defining it individually.

Preconditions

If mapped to the [SYS_DEBUG_Message](#) function, then the system debug service must be initialized and running.

Example

```
// In configuration.h file: #define SYS_DEBUG_USE_CONSOLE
// In sys_debug.h file: #define SYS_DEBUG_MESSAGE( level, message ) _SYS_DEBUG_MESSAGE( level,
message )

SYS_DEBUG_ErrorLevelSet(SYS_ERROR_DEBUG);
SYS_DEBUG_MESSAGE(SYS_ERROR_WARNING, "System Debug Message rn");
```

Parameters

Parameters	Description
level	The current error level threshold for displaying the message.
message	Pointer to a buffer containing the message to be displayed.

Function

SYS_DEBUG_MESSAGE([SYS_ERROR_LEVEL](#) level, const char* message)

SYS_PRINT Macro

Formats and prints an error message with a variable number of arguments regardless of the system error level.

C

```
#define SYS_PRINT(fmt, ...)
```

Returns

None.

Description

This function formats and prints an error message with a variable number of arguments regardless of the system error level.

Remarks

The format string and arguments follow the printf convention.

By default, this macro is defined as nothing, effectively removing all code generated by calls to it. To process SYS_PRINT calls, this macro must be defined in a way that maps calls to it to the desired implementation (see example, above).

This macro can be mapped to the system console service (along with other system debug macros) by defining SYS_DEBUG_USE_CONSOLE in the system configuration (configuration.h) instead of defining it individually.

Preconditions

If mapped to the [SYS_DEBUG_Print](#) function, then the system debug service must be initialized and running.

Example

```
// In configuration.h file: #define SYS_DEBUG_USE_CONSOLE
// In sys_debug.h file: #define SYS_PRINT(fmt, ...) SYS_DEBUG_Print(fmt, ##__VA_ARGS__)

// In source code
int result;

result = SomeOperation();
if (result > MAX_VALUE)
{
    SYS_PRINT("Result of %d exceeds max value", result);
    // Take appropriate action
}
```

Parameters

Parameters	Description
format	Pointer to a buffer containing the format string for the message to be displayed.
...	Zero or more optional parameters to be formatted as defined by the format string.

Function

SYS_PRINT(const char* format, ...)

SYS_DEBUG_PRINT Macro

Formats and prints an error message if the system error level is defined at or lower than the level specified.

C

```
#define SYS_DEBUG_PRINT(level, fmt, ...)
```

Returns

None.

Description

Macro: SYS_DEBUG_PRINT([SYS_ERROR_LEVEL](#) level, const char* format, ...)

This macro formats and prints an error message if the system error level is defined at or lower than the level specified.

Remarks

The format string and arguments follow the printf convention.

By default, this macro is defined as nothing, effectively removing all code generated by calls to it. To process SYS_DEBUG_PRINT calls, this macro must be defined in a way that maps calls to it to the desired implementation (see example, above).

This macro can be mapped to the system console service (along with other system debug macros) by defining SYS_DEBUG_USE_CONSOLE in the system configuration (configuration.h) instead of defining it individually.

Preconditions

If mapped to the [SYS_DEBUG_Print](#) function, then the system debug service must be initialized and running.

Example

```
// In configuration.h file: #define SYS_DEBUG_USE_CONSOLE
// In sys_debug.h: #define SYS_DEBUG_PRINT(level, fmt, ...) _SYS_DEBUG_PRINT(level, fmt,
##__VA_ARGS__)

// In source code
int result;

result = SomeOperation();
if (result > MAX_VALUE)
{
    SYS_DEBUG_PRINT(SYS_ERROR_WARNING, "Result of %d exceeds max value", result);
    // Take appropriate action
}
```

Parameters

Parameters	Description
level	The current error level threshold for displaying the message.
format	Pointer to a buffer containing the format string for the message to be displayed.
...	Zero or more optional parameters to be formatted as defined by the format string.

SYS_DEBUG_MESSAGE Macro

Prints a debug message if the specified level is at or below the global system error level.

C

```
#define _SYS_DEBUG_MESSAGE(level, message) do { if((level) <= SYS_DEBUG_ErrorLevelGet())
```

```
SYS_DEBUG_Message(message); }while(0)
```

Returns

None.

Description

Macro: `_SYS_DEBUG_MESSAGE(SYS_ERROR_LEVEL level, const char* message)`

This macro prints a debug message if the specified level is at or below the global error level. It can be used to implement the `SYS_DEBUG_MESSAGE` macro.

Remarks

Do not call this macro directly. Call the `SYS_DEBUG_MESSAGE` macro instead.

The default `SYS_DEBUG_MESSAGE` macro definition removes the message and function call from the source code. To access and utilize the message, define the `SYS_DEBUG_USE_CONSOLE` macro or override the definition of the `SYS_DEBUG_MESSAGE` macro.

Preconditions

`SYS_DEBUG_Initialize` must have returned a valid object handle.

Example

```
// In configuration.h file: #define SYS_DEBUG_USE_CONSOLE
// In sys_debug.h file: #define SYS_DEBUG_MESSAGE( level,message )
SYS_DEBUG_MESSAGE( level,message )

// In source code
SYS_DEBUG_MESSAGE(SYS_ERROR_WARNING, "My debug warning messagern");
```

Parameters

Parameters	Description
level	The current error level threshold for displaying the message.
message	Pointer to a buffer containing the message to be displayed.

`_SYS_DEBUG_PRINT` Macro

Formats and prints a debug message if the specified level is at or below the global system error level.

C

```
#define _SYS_DEBUG_PRINT(level, format, ...) do { if((level) <= SYS_DEBUG_ErrorLevelGet())  
SYS_DEBUG_Print(format, ##__VA_ARGS__); } while (0)
```

Returns

None.

Description

Macro: `_SYS_DEBUG_PRINT(SYS_ERROR_LEVEL level, const char* format, ...)`

This function formats and prints a debug message if the specified level is at or below the global system error level. It can be used to implement the `SYS_DEBUG_PRINT` macro.

Remarks

Do not call this macro directly. Call the `SYS_DEBUG_PRINT` macro instead.

The default `SYS_DEBUG_PRINT` macro definition removes the message and function call from the source code. To access and utilize the message, define the `SYS_DEBUG_USE_CONSOLE` macro or override the definition of the `SYS_DEBUG_PRINT` macro.

Preconditions

`SYS_DEBUG_Initialize` must have returned a valid object handle.

Example

```

// In configuration.h file: #define SYS_DEBUG_USE_CONSOLE
// In sys_debug.h file: #define SYS_DEBUG_PRINT(level, fmt, ...) _SYS_DEBUG_PRINT(level, fmt,
##__VA_ARGS__)

// In source code
int result;

result = SomeOperation();
if (result > MAX_VALUE)
{
    SYS_DEBUG_PRINT(SYS_ERROR_WARNING, "Result of %d exceeds max value", result);
    // Take appropriate action
}

```

Parameters

Parameters	Description
level	The current error level threshold for displaying the message.
format	Pointer to a buffer containing the format string for the message to be displayed.
...	Zero or more optional parameters to be formatted as defined by the format string.

Direct Memory Access (DMA) System Service Library Help

This section describes the Direct memory Access System Service Library.

Introduction

This library provides an abstracted interface to interact with the DMA subsystem to control and manage the data transfer between different peripherals and/or memory without intervention from the CPU.

Description

The Direct Memory Access (DMA) controller is a bus master module that is useful for data transfers between different peripherals without intervention from the CPU. The source and destination of a DMA transfer can be any of the memory-mapped modules. For example, memory, or one of the Peripheral Bus (PBUS) devices such as the SPI, UART, and so on.

This library provides a low-level abstraction of the DMA System Service Library that is available on the Microchip family micro-controllers with a convenient C language interface. It can be used to simplify low-level access to the module without the necessity of interacting directly with the module's registers/PLIB, thereby hiding differences from one micro-controller variant to another.

Library Interface

a) Setup Function

	Name	Description
≡	SYS_DMA_ChannelCallbackRegister	This function allows a DMA client to set an event handler.
≡	SYS_DMA_DataWidthSetup	Setup data width of selected DMA channel.
≡	SYS_DMA_AddressModeSetup	Setup addressing mode of selected DMA channel.

b) Transfer Functions

	Name	Description
≡	SYS_DMA_ChannelTransfer	Adds a data transfer to a DMA channel and enables the channel to start data transfer.
≡	SYS_DMA_ChannelDisable	Disables the specified channel.

	SYS_DMA_ChannelsBusy	Returns the busy status of a specific DMA Channel.
---	--------------------------------------	--

c) Data Types and Constants

	Name	Description
	SYS_DMA_TRANSFER_EVENT	Enumeration of possible DMA transfer events.
	SYS_DMA_CHANNEL	This lists the set of channels available for data transfer using DMA.
	SYS_DMA_CHANNEL_CALLBACK	Pointer to a DMA Transfer Event handler function.
	SYS_DMA_DESTINATION_ADDRESSING_MODE	Enumeration of possible DMA destination addressing modes.
	SYS_DMA_SOURCE_ADDRESSING_MODE	Enumeration of possible DMA source addressing modes.
	SYS_DMA_WIDTH	Enumeration of possible DMA data width

Description

This section describes the APIs of the DMA System Service Library.

Refer to each section for a detailed description.

a) Setup Function

SYS_DMA_ChannelCallbackRegister Function

This function allows a DMA client to set an event handler.

C

```
void SYS_DMA_ChannelCallbackRegister(SYS_DMA_CHANNEL channel, const SYS_DMA_CHANNEL_CALLBACK
eventHandler, const uintptr_t contextHandle);
```

Returns

None.

Description

This function allows a client to set an event handler. The client may want to receive transfer related events in cases when it submits a DMA transfer request. The event handler should be set before the client intends to perform operations that could generate events.

This function accepts a contextHandle parameter. This parameter could be set by the client to contain (or point to) any client specific data object that should be associated with this DMA channel.

Remarks

None.

Preconditions

DMA Controller should have been initialized.

Example

```
MY_APP_OBJ myAppObj;

void APP_DMA_TransferEventHandler(SYS_DMA_TRANSFER_EVENT event, uintptr_t contextHandle)
{
    switch(event)
    {
        case SYS_DMA_TRANSFER_COMPLETE:
            // This means the data was transferred.
            break;

        case SYS_DMA_TRANSFER_ERROR:
            // Error handling here.
    }
}
```

```

        break;

    default:
        break;
    }

// User registers an event handler with DMA channel. This is done once.
SYS_DMA_ChannelCallbackRegister(channel, APP_DMA_TransferEventHandler, (uintptr_t)&myAppObj);

```

Parameters

Parameters	Description
channel	A specific DMA channel from which the events are expected.
eventHandler	Pointer to the event handler function.
contextHandle	Value identifying the context of the application/driver/middleware that registered the event handling function.

Function

```

void SYS_DMA_ChannelCallbackRegister
(
    SYS_DMA_CHANNEL channel,
    const SYS_DMA_CHANNEL_CALLBACK eventHandler,
    const uintptr_t contextHandle
)

```

SYS_DMA_DataWidthSetup Function

Setup data width of selected DMA channel.

C

```
void SYS_DMA_DataWidthSetup(SYS_DMA_CHANNEL channel, SYS_DMA_WIDTH dataWidth);
```

Returns

None.

Description

This function sets data width of selected DMA channel.

Any ongoing transaction of the specified DMA channel will be aborted when this function is called.

Remarks

None.

Preconditions

DMA Controller should have been initialized.

Example

```
SYS_DMA_DataWidthSetup(SYS_DMA_CHANNEL_1, SYS_DMA_WIDTH_16_BIT);
```

Parameters

Parameters	Description
channel	A specific DMA channel
dataWidth	Data width of DMA transfer of type SYS_DMA_WIDTH

Function

```
void SYS_DMA_DataWidthSetup( SYS_DMA_CHANNEL channel, SYS_DMA_WIDTH dataWidth);
```

SYS_DMA_AddressModeSetup Function

Setup addressing mode of selected DMA channel.

C

```
void SYS_DMA_AddressModeSetup(SYS_DMA_CHANNEL channel, SYS_DMA_SOURCE_ADDRESSING_MODE
sourceAddrMode, SYS_DMA_DESTINATION_ADDRESSING_MODE destAddrMode);
```

Returns

None.

Description

This function sets the addressing mode of selected DMA channel.

Any ongoing transaction of the specified DMA channel will be aborted when this function is called.

Remarks

None.

Preconditions

DMA Controller should have been initialized.

Example

```
SYS_DMA_AddressModeSetup(SYS_DMA_CHANNEL_1, SYS_DMA_SOURCE_ADDRESSING_MODE_FIXED,
SYS_DMA_DESTINATION_ADDRESSING_MODE_FIXED);
```

Parameters

Parameters	Description
channel	A specific DMA channel
sourceAddrMode	Source addressing mode of type SYS_DMA_SOURCE_ADDRESSING_MODE
destAddrMode	Destination addressing mode of type SYS_DMA_DESTINATION_ADDRESSING_MODE

Function

```
void SYS_DMA_AddressModeSetup( SYS_DMA_CHANNEL channel, SYS_DMA_SOURCE_ADDRESSING_MODE
sourceAddrMode, SYS_DMA_DESTINATION_ADDRESSING_MODE destAddrMode);
```

b) Transfer Functions

SYS_DMA_ChannelTransfer Function

Adds a data transfer to a DMA channel and enables the channel to start data transfer.

C

```
bool SYS_DMA_ChannelTransfer(SYS_DMA_CHANNEL channel, const void * srcAddr, const void *
destAddr, size_t blockSize);
```

Returns

- True - If transfer request is accepted.
- False - If previous transfer is in progress and the request is rejected.

Description

This function adds a single block data transfer characteristics for a specific DMA channel id it is not busy already. It also enables

the channel to start data transfer.

If the requesting client registered an event callback with the PLIB, the PLIB will issue a SYS_DMA_TRANSFER_COMPLETE event if the transfer was processed successfully and SYS_DMA_TRANSFER_ERROR event if the transfer was not processed successfully.

Remarks

When DMA transfer buffers are placed in cacheable memory, cache maintenance operation must be performed by cleaning and invalidating cache for DMA buffers located in cacheable SRAM region using CMSIS APIs. The buffer start address must be aligned to cache line and buffer size must be multiple of cache line. Refer to device documentation to find the cache line size.

Invalidate cache lines having received buffer before using it to load the latest data in the actual memory to the cache
`SCB_InvalidateDCache_by_Addr((uint32_t *)&readBuffer, sizeof(readBuffer));`

Clean cache lines having source buffer before submitting a transfer request to DMA to load the latest data in the cache to the actual memory `SCB_CleanDCache_by_Addr((uint32_t *)&writeBuffer, sizeof(writeBuffer));`

Preconditions

DMA Controller should have been initialized.

Example

```
// Transfer 10 bytes of data to UART TX using DMA channel 1
// DMA Channel has been configured and initialized by appropriate PLIB call.

MY_APP_OBJ myAppObj;
uint8_t buf[10] = {0,1,2,3,4,5,6,7,8,9};
void *srcAddr = (uint8_t *) buf;
void *destAddr = (uint8_t *) &U1TXREG;
size_t size = 10;

// User registers an event handler with PLIB. This is done once.
SYS_DMA_ChannelCallbackRegister(APP_DMA_TransferEventHandler,(uintptr_t)&myAppObj);

if (SYS_DMA_ChannelTransfer(SYS_DMA_CHANNEL_1, srcAddr, destAddr, size) == true)
{
    // do something else
}
else
{
    // try again?
}
```

Parameters

Parameters	Description
channel	A specific DMA channel
srcAddr	Source of the DMA transfer
destAddr	Destination of the DMA transfer
blockSize	Size of the transfer block

Function

```
bool SYS_DMA_ChannelTransfer
(
    SYS_DMA_CHANNEL channel,
    const void *srcAddr,
    const void *destAddr,
    size_t blockSize
)
```

SYS_DMA_ChannelDisable Function

Disables the specified channel.

C

```
void SYS_DMA_ChannelDisable(SYS_DMA_CHANNEL channel);
```

Returns

None.

Description

This function disables the specified channel and resets it. Ongoing transfer will be aborted.

Remarks

None.

Preconditions

DMA Controller should have been initialized by appropriate PLIB initialize function.

Example

```
SYS_DMA_ChannelDisable(SYS_DMA_CHANNEL_1);
```

Parameters

Parameters	Description
channel	A specific DMA channel

Function

```
void SYS_DMA_ChannelDisable ( SYS_DMA_CHANNEL channel)
```

SYS_DMA_ChannelsBusy Function

Returns the busy status of a specific DMA Channel.

C

```
bool SYS_DMA_ChannelIsBusy(SYS_DMA_CHANNEL channel);
```

Returns

Busy status of the specific channel.

- True - Channel is busy
- False - Channel is free

Description

This function returns the busy status of the DMA channel. DMA channel will be busy if any transfer is in progress.

This function can be used to check the status of the channel prior to submitting a transfer request. And this can also be used to check the status of the submitted request if callback mechanism is not preferred.

Remarks

None.

Preconditions

DMA Controller should have been initialized.

Example

```
// Transfer 10 bytes of data to UART TX using DMA channel 1
```

```
// DMA Channel has been configured and initialized by appropriate PLIB call.

uint8_t buf[10] = {0,1,2,3,4,5,6,7,8,9};
void *srcAddr = (uint8_t *) buf;
void *destAddr = (uint8_t *) &U1TXREG;
size_t size = 10;

if(false == SYS_DMA_ChannelIsBusy(SYS_DMA_CHANNEL_1))
{
    SYS_DMA_ChannelTransfer(SYS_DMA_CHANNEL_1, srcAddr, destAddr, size);
}
```

Parameters

Parameters	Description
channel	A specific DMA channel

Function

bool SYS_DMA_ChannelsBusy ([SYS_DMA_CHANNEL](#) channel)

c) Data Types and Constants

SYS_DMA_TRANSFER_EVENT Enumeration

Enumeration of possible DMA transfer events.

C

```
typedef enum {
    SYS_DMA_TRANSFER_COMPLETE,
    SYS_DMA_TRANSFER_ERROR
} SYS_DMA_TRANSFER_EVENT;
```

Members

Members	Description
SYS_DMA_TRANSFER_COMPLETE	Data was transferred successfully.
SYS_DMA_TRANSFER_ERROR	Error while processing the request

Description

DMA Transfer Events

This data type provides an enumeration of all possible DMA transfer events.

Remarks

None.

SYS_DMA_CHANNEL Enumeration

This lists the set of channels available for data transfer using DMA.

C

```
typedef enum {
    SYS_DMA_CHANNEL_0,
    SYS_DMA_CHANNEL_n,
    SYS_DMA_CHANNEL_NONE = -1
} SYS_DMA_CHANNEL;
```

Description

DMA Channels

Lists the channels available for data transfer using DMA. The number of channels may vary based on the device.

Remarks

None.

SYS_DMA_CHANNEL_CALLBACK Type

Pointer to a DMA Transfer Event handler function.

C

```
typedef void (* SYS_DMA_CHANNEL_CALLBACK)(SYS_DMA_TRANSFER_EVENT event, uintptr_t
contextHandle);
```

Description

DMA Transfer Event Handler Function

This data type defines a DMA Transfer Event Handler Function.

A DMA client must register a transfer event handler function of this type to receive transfer related events from the DMA System Service.

If the event is SYS_DMA_TRANSFER_COMPLETE, this means that the data was transferred successfully.

If the event is SYS_DMA_TRANSFER_ERROR, this means that the data was not transferred successfully.

The contextHandle parameter contains the context handle that was provided by the client at the time of registering the event handler. This context handle can be anything that the client consider helpful or necessary to identify the client context object associated with the channel of the DMA that generated the event.

The event handler function executes in an interrupt context of DMA. It is recommended to the application not to perform process intensive operations with in this function.

Remarks

None.

SYS_DMA_DESTINATION_ADDRESSING_MODE Enumeration

Enumeration of possible DMA destination addressing modes.

C

```
typedef enum {
    SYS_DMA_DESTINATION_ADDRESSING_MODE_FIXED,
    SYS_DMA_DESTINATION_ADDRESSING_MODE_INCREMENTED,
    SYS_DMA_DESTINATION_ADDRESSING_MODE_NONE = -1
} SYS_DMA_DESTINATION_ADDRESSING_MODE;
```

Members

Members	Description
SYS_DMA_DESTINATION_ADDRESSING_MODE_FIXED	Destination address is always fixed
SYS_DMA_DESTINATION_ADDRESSING_MODE_INCREMENTED	Destination address is incremented after every transfer
SYS_DMA_DESTINATION_ADDRESSING_MODE_NONE = -1	Used when Addressing mode is not supported

Description

DMA destination addressing modes

This data type provides an enumeration of all possible DMA destination addressing modes.

Remarks

None.

SYS_DMA_SOURCE_ADDRESSING_MODE Enumeration

Enumeration of possible DMA source addressing modes.

C

```
typedef enum {
    SYS_DMA_SOURCE_ADDRESSING_MODE_FIXED,
    SYS_DMA_SOURCE_ADDRESSING_MODE_INCREMENTED,
    SYS_DMA_SOURCE_ADDRESSING_MODE_NONE = -1
} SYS_DMA_SOURCE_ADDRESSING_MODE;
```

Members

Members	Description
SYS_DMA_SOURCE_ADDRESSING_MODE_FIXED	Source address is always fixed
SYS_DMA_SOURCE_ADDRESSING_MODE_INCREMENTED	Source address is incremented after every transfer
SYS_DMA_SOURCE_ADDRESSING_MODE_NONE = -1	Used when Addressing mode is not supported

Description

DMA Source addressing modes

This data type provides an enumeration of all possible DMA source addressing modes.

Remarks

None.

SYS_DMA_WIDTH Enumeration

Enumeration of possible DMA data width

C

```
typedef enum {
    SYS_DMA_WIDTH_8_BIT,
    SYS_DMA_WIDTH_16_BIT,
    SYS_DMA_WIDTH_32_BIT,
    SYS_DMA_WIDTH_NONE = -1
} SYS_DMA_WIDTH;
```

Members

Members	Description
SYS_DMA_WIDTH_8_BIT	DMA data width 8 bit
SYS_DMA_WIDTH_16_BIT	DMA data width 16 bit
SYS_DMA_WIDTH_32_BIT	DMA data width 32 bit
SYS_DMA_WIDTH_NONE = -1	Used when DMA Width is not supported

Description

DMA data width

This data type provides an enumeration of all possible DMA data width.

Remarks

None.

File System Service Library Help

This section describes the File System Service Library.

Introduction

Introduction to the MPLAB Harmony File System (FS).

Description

The MPLAB Harmony File System (FS) provides file system services to MPLAB Harmony based applications. The architecture of the File System Service is shown in the following figure.

The File System Service provides an application programming interface (API) through which a utility or user program requests services of a file system. Some file system APIs may also include interfaces for maintenance operations, such as creating or initializing a file system and verifying the file system for integrity.

The File System service is really a framework designed to support multiple file systems (native file system) and multiple media in the same application. Examples of native file systems are FAT12, FAT16, FAT32, and the Microchip File System (MPFS) among others.

MPFS is a read-only file system, which is used to store the files that do not change for example Web pages, images, etc. Each of these native file systems have a common set of APIs that can be used to access the files of that particular native file system.

The File System Service abstracts the native file system calls and provides a common interface to the user/application layer. For example, while the application layer requests for a file read or write from a disk, due to the presence of the this abstraction, the application need not be bothered about the native file system implemented on that disk. Instead, the application can call the read/write API of the File System, which in turn translates to the read/write command of the native file system used on the required disk.

This simplifies the implementation of the higher application layer and also provides a mechanism to add more native file system to the File System framework in the future.



Note: "File System Service" and "sys_fs" are synonymous.

Using the Library

This section describes the basic architecture of the File System Service Library and provides information on how to use it.

Description

Interface Header File: `sys_fs.h`

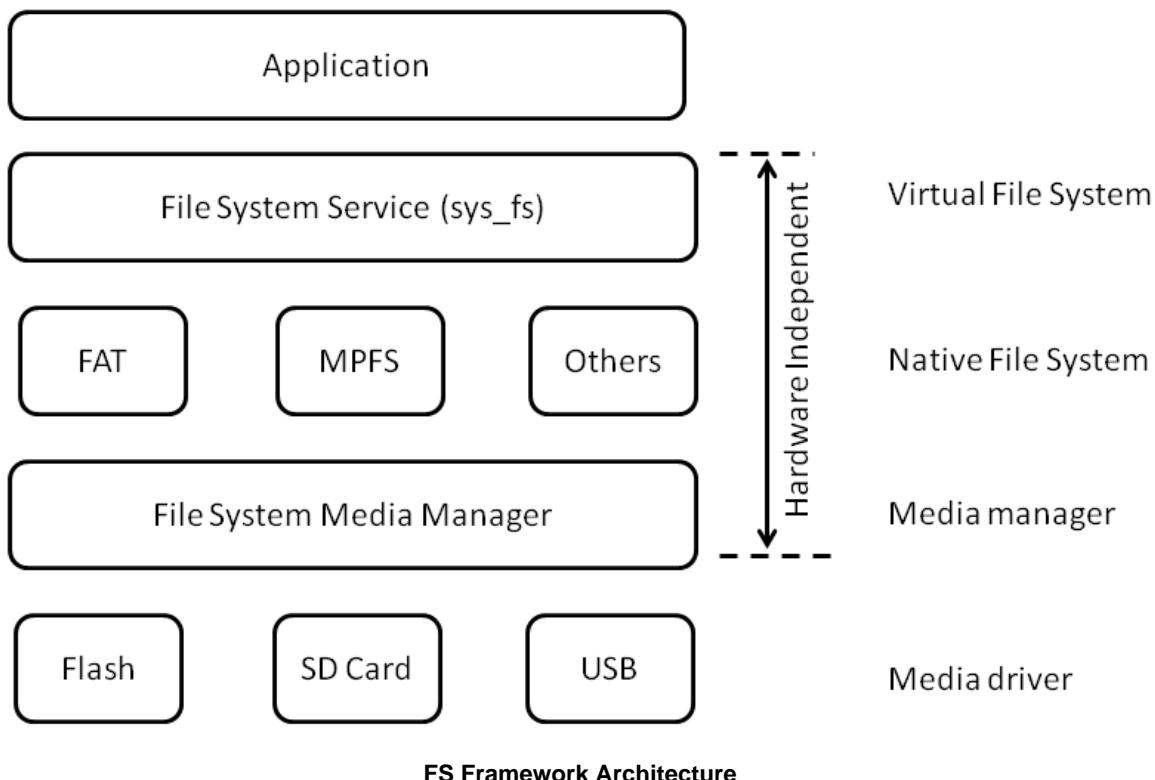
The interface to the File System Service library is defined in the `sys_fs.h` header file. Any C language source (`.c`) file that uses the File System Service Library use this API's to perform file operation on various connected media's.

Abstraction Model

This section describes the abstraction model of the MPLAB Harmony File System.

Description

The FS framework features a modular and layered architecture, as shown in the following figure.



FS Framework Architecture

As seen in the figure, the FS Framework consists of the following major blocks:

- The **Driver** for the physical media has to be included as a part of the FS Framework. This layer provides a low-level interface to access the physical media. This layer also enables multiple instances of media. Examples of drivers are:
 - Memory driver – To access files using Various Flash Memories (QSPI Flash, NVM Flash, EEPROM Flash)
 - SDCARD driver – To access files from SD card
- The **Media driver** provides a mechanism to access the media as "sectors". Sectors are the smallest storage element accessed by a file system and are contiguous memory locations. Typically, each sector has 512 bytes. Depending on the requirement, in some cases, the driver and media driver could be combined as one layer.
- The **Media manager** implements a disk and sector based media access mechanism. It also performs disk allocated/deallocated on media attach/detach. Due to the implementation of this layer, the FS Framework can support multiple disks. The media manager detects and analyzes a media based on its Master Boot Record (MBR). Therefore, it is mandatory for the media to have a MBR for it to work with the FS.
- The **Native file system** implements support for the media file system format. Examples of native file systems are: FAT12, FAT32, and MPFS, among other. At present, only the FAT and MPFS file systems are supported by the FS framework; however, more native file systems can be included.
- The **Virtual file system (or SYS_FS)** layer provides a file system independent file system operation interface. This layer translates virtual file system calls to native file system calls. Due to this layer, applications can now support multiple file systems. Interfaces provided by this layer, but not limited to, include:
 - SYS_FS_mount
 - SYS_FS_open
 - SYS_FS_read
 - SYS_FS_write
 - SYS_FS_close

How the Library Works

This topic provides information on how the MPLAB Harmony File System works.

Description

The MPLAB Harmony File System (FS) provides embedded application developers with a file system framework for retrieving and storing data from various media.

The MPLAB Harmony file system is designed to support multiple file systems (native file systems) and multiple media at the same time. Examples of native file systems are FAT12, FAT32, MPFS, and JFS, among others. Each of these native file systems has a common set of APIs that can be used to access the files of that particular native file system. The FS is a part of the MPLAB Harmony installation and is accompanied by demonstration applications that highlight usage. These demonstrations can also be modified or updated to build custom applications.

FS features include the following:

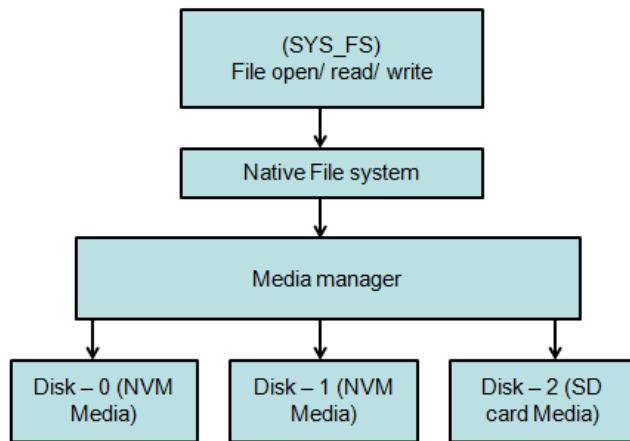
- Support for multiple file system (FAT, MPFS)
- Supports multiple physical media (NVM, SPI_FLASH, SD card)
- More physical media can be interfaced with the FS, once the driver is available for the media
- Modular and Layered architecture

Application Interaction

This topic describes how an application must interact with the File System.

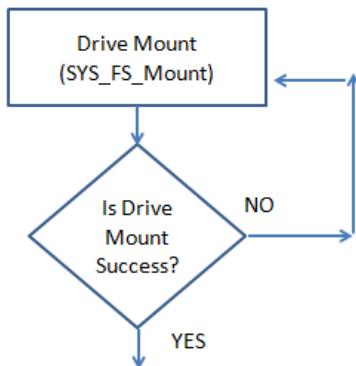
Description

The interaction of various layers is shown in the following figure.



Application Interaction with FS Framework

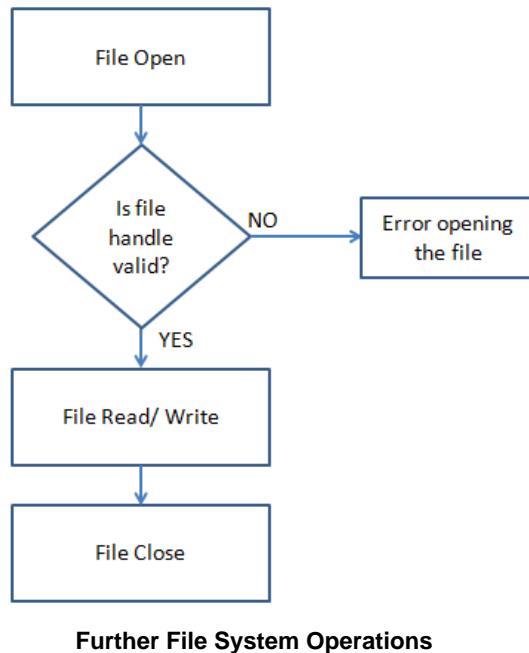
In the process of using the FS Framework, the application must first **mount** the media drive for the FS Framework to access the media. Unless the mounting process returns successfully, the application should continue trying to mount the drive. If the drive is not attached, the mounting process will fail. In such a situation, the application should not proceed further unless the mounting is success.



Application Mounts a Drive

Once the drive is mounted, the application code can then **open the file** from the drive with different attributes (such as read-only or write). If the file open returns a valid handle, the application can proceed further. Otherwise, the application will enter an error state. The reason for an invalid handle could be that the application was trying to read a file from the drive that does not exist. Another reason for an invalid handle is when the application tries to write to a drive that is write-protected.

Once the file is opened, the valid file handle is further used to **read/write** data to the file. Once the required operation is performed on the file, the file can then be **closed** by the application by passing the file handle. The following figure illustrates the process.



Using the File System

This topic describes how to use the File System.

Description

Use the Available Library Demonstration Applications

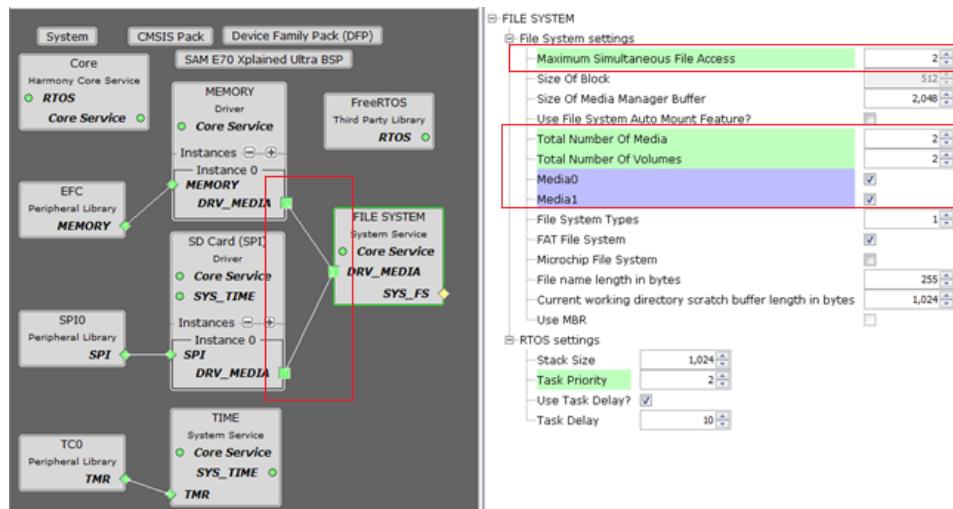
The FS framework release package contains a set of demonstration applications that are representative of common scenario (single/multi-media and single/multi-native file systems). These demonstrations can be easily modified to include application-specific initialization and application logic. The application logic must be non-blocking and could be implemented as a state machine.

Configuring the Library

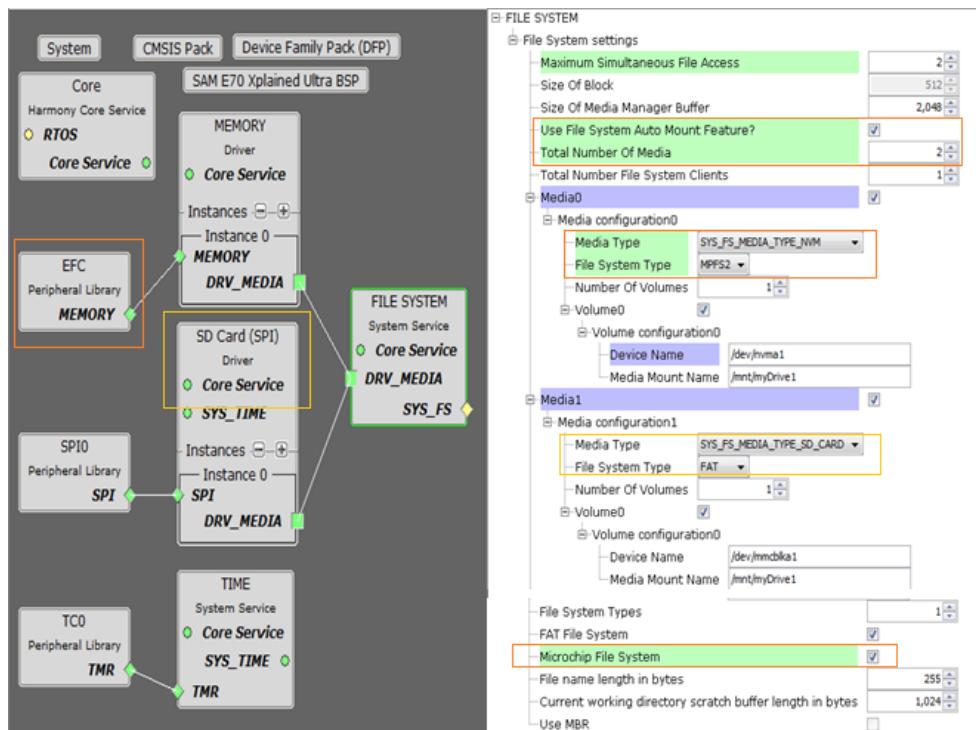
This Section provides information on how to configure File System Service Library.

Description

File System Service Library should be configured via MHC. The following figures show the MHC configuration window for File System Service and brief description.



File System Configuration with Auto Mount Disabled



File System Configuration with Auto Mount Enabled

Configuration Options:

- **Maximum Simultaneous File Access:**
 - Maximum Number of files which can be accessed by application
- **Size Of Block:**
 - Block Size used by File System layer to chunk the application data and to send to attached media
- **Size Of Media Manager Buffer:**
 - Media Manager Buffer size to store Block Data
- **Use File System Auto Mount Feature:**
 - Enables auto mount feature for all the media's
- **Total Number Of Media:**
 - Number of media to be attached to file system
- **Total Number Of Volumes:**

- Number of volumes to be created for each media
- **Media:**
 - Media details to be configured when Auto mount feature is enabled.
- **File System Types:**
 - Number of file systems used
- **FAT File System:**
 - When Selected Specifies FAT File system will be used
- **Microchip File System:**
 - When Selected Specifies MPFS File system will be used
- **File Name Length:**
 - Max file name length to be supported
- **Current Working Directory Scratch buffer length in Bytes:**
 - Buffer size to store the current directory path
- **Use MBR:**
 - Use Master Boot Record.

Building the Library

This section lists the files that are available in the File System Service Library.

Description

The following three tables list and describe the header (.h) and source (.c) files that implement this library.

Interface File(s)



All of the required files listed in the following table are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

This table lists and describes the header files that must be included (i.e., using #include) by any code that uses this library.

Source File Name	Description
/sys_fs.h	This file contains function and type declarations required to Interact with the MPLAB Harmony File System Framework.
/fat_fs/src/file_system/ff.h	FAT File System module include file. This file should be included when using the FAT File System.
/mpfs/mpfs.h	This file contains the interface definition for handling the Microchip File System (MPFS). This file should be included when using MPFS.

Required File(s)

This table lists and describes the source and header files that must always be included in the MPLAB X IDE project to build this library.

Source File Name	Description
/src/dynamic/sys_fs.c	This file contains implementation of File System interfaces.
/src/dynamic/sys_fs_media_manager.c	This file contains implementation File System Media Manager functions.
/fat_fs/src/file_system/ff.c	This file implements the FAT File system functions. This file should be included when using FAT File System.
/fat_fs/src/hardware_access/diskio.c	Low-level disk I/O module for FAT File System. This file should be included when using FAT File System.
/mpfs/src/mpfs.c	This file implements the MPFS functions. This file should be included when using MPFS.

Optional File(s)

This table lists and describes the source and header files that may optionally be included if required for the desired implementation.

Source File Name	Description
N/A	There are no optional files for this library.

Module Dependencies

The File System Service Library depends on the following modules:

- [Memory](#) Driver Library (if media is NVM, SPI flash, EEPROM Flash)
- Secure Digital (SD) Card Driver Library (if media is a SD Card)

Library Interface

a) File and Directory Operation Functions

	Name	Description
≡◊	SYS_FS_FileOpen	Opens a file.
≡◊	SYS_FS_FileClose	Closes a file.
≡◊	SYS_FS_FileCharacterPut	Writes a character to a file.
≡◊	SYS_FS_FileEOF	Checks for end of file.
≡◊	SYS_FS_FileError	Returns the file specific error.
≡◊	SYS_FS_FileNameGet	Reads the file name.
≡◊	SYS_FS_FilePrintf	Writes a formatted string into a file.
≡◊	SYS_FS_FileRead	Read data from the file.
≡◊	SYS_FS_FileSeek	Moves the file pointer by the requested offset.
≡◊	SYS_FS_FileSize	Returns the size of the file in bytes.
≡◊	SYS_FS_FileStat	Gets file status.
≡◊	SYS_FS_FileStringGet	Reads a string from the file into a buffer.
≡◊	SYS_FS_FileStringPut	Writes a string to a file.
≡◊	SYS_FSFileSync	Flushes the cached information when writing to a file.
≡◊	SYS_FS_FileTell	Obtains the file pointer position.
≡◊	SYS_FS_FileTestError	Checks for errors in the file.
≡◊	SYS_FS_FileTruncate	Truncates a file
≡◊	SYS_FS_FileWrite	Writes data to the file.
≡◊	SYS_FS_DirectoryMake	Makes a directory.
≡◊	SYS_FS_DirOpen	Open a directory
≡◊	SYS_FS_DirClose	Closes an opened directory.
≡◊	SYS_FS_DirRead	Reads the files and directories of the specified directory.
≡◊	SYS_FS_DirRewind	Rewinds to the beginning of the directory.
≡◊	SYS_FS_DirSearch	Searches for a file or directory.
≡◊	SYS_FS_DirectoryChange	Changes to a the directory specified.
≡◊	SYS_FS_CurrentWorkingDirectoryGet	Gets the current working directory
≡◊	SYS_FS_FileDirectoryModeSet	Sets the mode for the file or directory.
≡◊	SYS_FS_FileDirectoryRemove	Removes a file or directory.
≡◊	SYS_FS_FileDirectoryRenameMove	Renames or moves a file or directory.
≡◊	SYS_FS_FileDirectoryTimeSet	Sets or changes the time for a file or directory.
≡◊	SYS_FS_Error	Returns the last error.

b) General Operation Functions

	Name	Description
≡◊	SYS_FS_Initialize	Initializes the file system abstraction layer (sys_fs layer).
≡◊	SYS_FS_Tasks	Maintains the File System tasks and functionalities.
≡◊	SYS_FS_Mount	Mounts the file system.
≡◊	SYS_FS_Unmount	Unmounts the file system.
≡◊	SYS_FS_CurrentDriveGet	Gets the current drive
≡◊	SYS_FS_CurrentDriveSet	Sets the drive.
≡◊	SYS_FS_DriveLabelGet	Gets the drive label.
≡◊	SYS_FS_DriveLabelSet	Sets the drive label
≡◊	SYS_FS_DriveFormat	Formats a drive.
≡◊	SYS_FS_DrivePartition	Partitions a physical drive (media).
≡◊	SYS_FS_DriveSectorGet	Obtains total number of sectors and number of free sectors for the specified drive.
≡◊	SYS_FS_EventHandlerSet	Allows a client to identify an event handling function for the file system to call back when mount/unmount operation has completed.

c) Media Manager Functions

	Name	Description
≡◊	SYS_FS_MEDIA_MANAGER_Tasks	Media manager task function.
≡◊	SYS_FS_MEDIA_MANAGER_TransferTask	Media manager transfer task function.
≡◊	SYS_FS_MEDIA_MANAGER_Read	Gets data from a specific media address.
≡◊	SYS_FS_MEDIA_MANAGER_SectorRead	Reads a specified media sector.
≡◊	SYS_FS_MEDIA_MANAGER_SectorWrite	Writes a sector to the specified media.
≡◊	SYS_FS_MEDIA_MANAGER_Register	Function to register media drivers with the media manager.
≡◊	SYS_FS_MEDIA_MANAGER_RegisterTransferHandler	Register the event handler for data transfer events.
≡◊	SYS_FS_MEDIA_MANAGER_DeRegister	Function called by a media to deregister itself to the media manager. For static media, (like NVM or SD card), this "deregister function" is never called, since static media never gets deregistered once they are initialized. For dynamic media (like MSD), this register function is called dynamically, once the MSD media is connected.
≡◊	SYS_FS_MEDIA_MANAGER_AddressGet	Gets the starting media address based on a disk number.
≡◊	SYS_FS_MEDIA_MANAGER_MediaStatusGet	Gets the media status.
≡◊	SYS_FS_MEDIA_MANAGER_VolumePropertyGet	Gets the volume property.
≡◊	SYS_FS_MEDIA_MANAGER_CommandStatusGet	Gets the command status.
≡◊	SYS_FS_MEDIA_MANAGER_GetMediaGeometry	Gets the media geometry information.
≡◊	SYS_FS_MEDIA_MANAGER_EventHandlerSet	Register the event handler for Mount/Un-Mount events.

d) File System Data Types and Constants

	Name	Description
	SYS_FS_ERROR	Lists the various error cases.
	SYS_FS_FILE_SEEK_CONTROL	Lists the various modes of file seek.
	SYS_FS_FSTAT	File System status
	SYS_FS_FUNCTIONS	SYS FS Function signature structure for native file systems.
	SYS_FS_REGISTRATION_TABLE	The sys_fs layer has to be initialized by passing this structure with suitably initialized members.
	SYS_FS_RESULT	Lists the various results of a file operation.
	SYS_FS_FILE_OPEN_ATTRIBUTES	Lists the various attributes (modes) in which a file can be opened.
	FAT_FS_MAX_LFN	Maximum length of the Long File Name.
	FAT_FS_MAX_SS	Lists the definitions for FAT file system sector size.

	FAT_FS_USE_LFN	Lists the definitions for FAT file system LFN selection.
	SYS_FS_FILE_SYSTEM_TYPE	Enumerated data type identifying native file systems supported.
	SYS_FS_HANDLE	This type defines the file handle.
	SYS_FS_HANDLE_INVALID	Invalid file handle
	SYS_FS_FILE_DIR_ATTR	Enumerated data type identifying the various attributes for file/directory.
	SYS_FS_TIME	The structure to specify the time for a file or directory.
	SYS_FS_FORMAT	Specifies the partitioning rule.
	SYS_FS_EVENT	Identifies the possible file system events.
	SYS_FS_EVENT_HANDLER	Pointer to the File system Handler function.
	SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE_INVALID	Defines the invalid media block command handle.
	SYS_FS_MEDIA_HANDLE_INVALID	Defines the invalid media handle.
	_SYS_FS_VOLUME_PROPERTY	Structure to obtain the property of volume
	SYS_FS_MEDIA_BLOCK_EVENT	Identifies the possible events that can result from a request.
	SYS_FS_MEDIA_COMMAND_STATUS	The enumeration for status of buffer
	SYS_FS_MEDIA_FUNCTIONS	Structure of function pointers for media driver
	SYS_FS_MEDIA_MOUNT_DATA	Structure to obtain the device and mount name of media
	SYS_FS_MEDIA_PROPERTY	Contains information of property of a media.
	SYS_FS_MEDIA_STATE	The enumeration for state of media.
	SYS_FS_MEDIA_STATUS	The state of media.
	SYS_FS_MEDIA_TYPE	The enumeration for type of media.
	SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE	Handle identifying block commands of the media.
	SYS_FS_MEDIA_EVENT_HANDLER	Pointer to the Media Event Handler function.
	SYS_FS_MEDIA_GEOMETRY	Contains all the geometrical information of a media device.
	SYS_FS_MEDIA_HANDLE	Handle identifying the media registered with the media manager.
	SYS_FS_MEDIA_REGION_GEOMETRY	Contains information of a sys media region.
	SYS_FS_VOLUME_PROPERTY	Structure to obtain the property of volume

Description

This section describes the APIs of the File System Service Library.

Refer to each section for a detailed description.

a) File and Directory Operation Functions

SYS_FS_FileOpen Function

Opens a file.

C

```
SYS_FS_HANDLE SYS_FS_FileOpen(const char* fname, SYS_FS_FILE_OPEN_ATTRIBUTES attributes);
```

Returns

On success - A valid file handle will be returned On failure - [SYS_FS_HANDLE_INVALID](#). The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function opens a file with the requested attributes.

Remarks

None.

Preconditions

Prior to opening a file, the name of the volume on which the file resides should be known and the volume should be mounted.

Example

```

SYS_FS_HANDLE fileHandle;

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG" ,
    (SYS_FS_FILE_OPEN_READ)) ;

if(fileHandle != SYS_FS_HANDLE_INVALID)
{
    // File open succeeded.
}
else
{
    // File open failed.
}

// Using SYS_FS_CurrentDriveSet () function.

SYS_FS_HANDLE fileHandle;

SYS_FS_CurrentDriveSet( "/mnt/myDrive" ) ;

fileHandle = SYS_FS_FileOpen( "FILE.JPG" , (SYS_FS_FILE_OPEN_READ)) ;
if(fileHandle != SYS_FS_HANDLE_INVALID)
{
    // File open succeeded.
}
else
{
    // File open failed.
}

```

Parameters

Parameters	Description
fname	The name of the file to be opened along with the path. The fname format is as follows
format is as follows	"/mnt/volumeName/dirName/fileName". volumeName is the name of the volume/drive. dirName is the name of the directory under which the file is located. fileName is the name of the file to be opened. The "/mnt/volumeName" portion from the fName can be omitted if the SYS_FS_CurrentDriveSet () has been invoked to set the current drive/volume.
attributes	Access mode of the file, of type SYS_FS_FILE_OPEN_ATTRIBUTES

Function

```

SYS_FS_HANDLE SYS_FS_FileOpen
(
    const char* fname,
    SYS_FS_FILE_OPEN_ATTRIBUTES attributes
);

```

SYS_FS_FileClose Function

Closes a file.

C

```
SYS_FS_RESULT SYS_FS_FileClose(SYS_FS_HANDLE handle);
```

Returns

SYS_FS_RES_SUCCESS - File close operation was successful. SYS_FS_RES_FAILURE - File close operation failed. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function closes an opened file.

Remarks

None.

Preconditions

A valid file handle must be obtained before closing a file.

Example

```
SYS_FS_HANDLE fileHandle;
fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG",
    (SYS_FS_FILE_OPEN_READ));

if( fileHandle != SYS_FS_HANDLE_INVALID)
{
    // File open is successful
}

SYS_FS_FileClose(fileHandle);
```

Parameters

Parameters	Description
handle	A valid handle, which was obtained while opening the file.

Function

```
SYS_FS_RESULT SYS_FS_FileClose
(
    SYS_FS_HANDLE handle
);
```

SYS_FS_FileCharacterPut Function

Writes a character to a file.

C

```
SYS_FS_RESULT SYS_FS_FileCharacterPut(SYS_FS_HANDLE handle, char data);
```

Returns

SYS_FS_RES_SUCCESS - Write operation was successful. SYS_FS_RES_FAILURE - Write operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function writes a character to a file.

Remarks

None.

Preconditions

The file into which a character has to be written, has to be present and should have been opened.

Example

```

SYS_FS_RESULT res;
SYS_FS_HANDLE fileHandle;

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG" , (SYS_FS_FILE_OPEN_WRITE_PLUS) );
if(fileHandle != SYS_FS_HANDLE_INVALID)
{
    // File open is successful
}

// Write a character to the file.
res = SYS_FS_FileCharacterPut(fileHandle, 'c' );
if(res != SYS_FS_RES_SUCCESS)
{
    // Character write operation failed.
}

```

Parameters

Parameters	Description
handle	file handle to which the character is to be written.
data	character to be written to the file.

Function

```

SYS_FS_RESULT SYS_FS_FileCharacterPut
(
    SYS_FS_HANDLE handle,
    char data
);

```

SYS_FS_FileEOF Function

Checks for end of file.

C

```
bool SYS_FS_FileEOF(SYS_FS_HANDLE handle);
```

Returns

On success returns true indicating that the file pointer has reached the end of the file. On failure returns false. This could be due to file pointer having not reached the end of the file. Or due to an invalid file handle. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

Checks whether or not the file position indicator is at the end of the file.

Remarks

None.

Preconditions

A valid file handle must be obtained before knowing a EOF.

Example

```

SYS_FS_HANDLE fileHandle;
bool eof;

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG" ,
    (SYS_FS_FILE_OPEN_READ) );

if(fileHandle != SYS_FS_HANDLE_INVALID)

```

```

{
    // File open is successful
}
...
...
eof = SYS_FS_FileEOF(fileHandle);

if(eof == false)
{
    // Check the error state using SYS_FS_FileError
}

```

Parameters

Parameters	Description
handle	file handle obtained during file Open.

Function

```

bool SYS_FS_FileEOF
(
    SYS_FS_HANDLE handle
);

```

SYS_FS_FileError Function

Returns the file specific error.

C

```
SYS_FS_ERROR sys_FS_FileError(SYS_FS_HANDLE handle);
```

Returns

Error code of type [SYS_FS_ERROR](#).

Description

For file system functions which accepts valid handle, any error happening in those functions could be retrieved with [SYS_FS_FileError](#). This function returns errors which are file specific.

Please note that if an invalid handle is passed to a file system function, in such a case, [SYS_FS_FileError](#) will not return the correct type of error, as the handle was invalid. Therefore, it would be prudent to check the errors using the [SYS_FS_Error](#) function.

Remarks

None.

Preconditions

This function has to be called immediately after a failure is observed while doing a file operation. Any subsequent failure will overwrite the cause of previous failure.

Example

```

...
const char *buf = "Hello World";
size_t nbytes;
size_t bytes_written;
SYS_FS_HANDLE fd;
SYS_FS_ERROR err;
...

bytes_written = SYS_FS_FileWrite((const void *)buf, nbytes, fd);

if(bytes_written == -1)

```

```

{
    // error while writing file
    // find the type (reason) of error
    err = SYS_FS_FileError(fd);
}

```

Parameters

Parameters	Description
handle	A valid file handle

Function

```

SYS_FS_ERROR SYS_FS_FileError
(
    SYS_FS_HANDLE handle
);

```

SYS_FS_FileNameGet Function

Reads the file name.

C

```
bool SYS_FS_FileNameGet(SYS_FS_HANDLE handle, uint8_t* cName, uint16_t wLen);
```

Returns

Returns true if the file name was read successfully. Returns false if the file name was not read successfully. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function reads the file name of a file that is already open.

Remarks

None.

Preconditions

The file handle referenced by handle is already open.

Example

```

SYS_FS_HANDLE fileHandle;
bool stat;
uint8_t fileName[255];

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG",
    (SYS_FS_FILE_OPEN_READ));

if(fileHandle != SYS_FS_HANDLE_INVALID)
{
    // File open is successful
}
...
...

stat = SYS_FS_FileNameGet(fileHandle, fileName, 8 );

if(stat == false)
{
    // file not located based on handle passed
    // Check the error state using SYS_FS_FileError
}

```

Parameters

Parameters	Description
handle	File handle obtained during file Open.
cName	Where to store the name of the file.
wLen	The maximum length of data to store in cName.

Function

```
bool SYS_FS_FileNameGet
(
    SYS_FS_HANDLE handle,
    uint8_t* cName,
    uint16_t wLen
);
```

SYS_FS_FilePrintf Function

Writes a formatted string into a file.

C

```
SYS_FS_RESULT SYS_FS_FilePrintf(SYS_FS_HANDLE handle, const char * string, ...);
```

Returns

SYS_FS_RES_SUCCESS - Formatted string write operation was successful. SYS_FS_RES_FAILURE - Formatted string write operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function writes a formatted string into a file.

Remarks

None.

Preconditions

The file into which a string has to be written, must exist and should be open.

Example

```
SYS_FS_RESULT res;
SYS_FS_HANDLE fileHandle;

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.txt", (SYS_FS_FILE_OPEN_WRITE_PLUS) );

if(fileHandle != SYS_FS_HANDLE_INVALID)
{
    // File open is successful
}

// Write a string
res = SYS_FS_FilePrintf(fileHandle, "%d", 1234);
if( res != SYS_FS_RES_SUCCESS)
{
    // write operation failed.
}
```

Parameters

Parameters	Description
handle	File handle to which formatted string is to be written.
string	Pointer to formatted string which has to be written into file.

Function

```
SYS_FS_RESULT SYS_FS_FilePrintf
(
    SYS_FS_HANDLE handle,
    const char *string,
    ...
);
```

SYS_FS_FileRead Function

Read data from the file.

C

```
size_t SYS_FS_FileRead(SYS_FS_HANDLE handle, void * buf, size_t nbyte);
```

Returns

On success returns the number of bytes read successfully(0 or positive number). On failure returns -1. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function attempts to read nbyte bytes of data from the file associated with the file handle into the buffer pointed to by buf.

Remarks

None.

Preconditions

A valid file handle must be obtained before reading a file.

Example

```
...
char buf[20];
size_t nbytes;
size_t bytes_read;
SYS_FS_HANDLE fd;
...
nbytes = sizeof(buf);
bytes_read = SYS_FS_FileRead(fd, buf, nbytes);
...
```

Parameters

Parameters	Description
handle	File handle obtained during file open.
buf	Pointer to buffer into which data is read.
nbyte	Number of bytes to be read

Function

```
size_t SYS_FS_FileRead
(
    SYS_FS_HANDLE handle,
    void *buf,
    size_t nbyte
);
```

SYS_FS_FileSeek Function

Moves the file pointer by the requested offset.

C

```
int32_t SYS_FS_FileSeek(SYS_FS_HANDLE fildes, int32_t offset, SYS_FS_FILE_SEEK_CONTROL whence);
```

Returns

On success - The number of bytes by which file pointer is moved (0 or positive number) On Failure - (-1) If the chosen offset value was (-1), the success or failure can be determined with [SYS_FS_Error](#).

Description

This function sets the file pointer for a open file associated with the file handle, as follows: whence = SYS_FS_SEEK_SET - File offset is set to offset bytes from the beginning. whence = SYS_FS_SEEK_CUR - File offset is set to its current location plus offset. whence = SYS_FS_SEEK_END - File offset is set to the size of the file plus offset. The offset specified for this option should be negative for the file pointer to be valid.

Trying to move the file pointer using SYS_FS_FileSeek, beyond the range of file will only cause the pointer to be moved to the last location of the file.

Remarks

None.

Preconditions

A valid file handle must be obtained before seeking a file.

Example

```
SYS_FS_HANDLE fileHandle;
int status;

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG",
    (SYS_FS_FILE_OPEN_READ));

if(fileHandle != SYS_FS_HANDLE_INVALID)
{
    // File open is successful
}
...
...

status = SYS_FS_FileSeek(fileHandle, 5, SYS_FS_SEEK_CUR);

if((status != -1) && (status == 5))
{
    // Success
}
```

Parameters

Parameters	Description
handle	A valid file handle obtained during file open.
offset	The number of bytes which act as file offset. This value could be a positive or negative value.
whence	Type of File Seek operation as specified in SYS_FS_FILE_SEEK_CONTROL .

Function

```
int32_t SYS_FS_FileSeek
(
    SYS_FS_HANDLE handle,
```

```
int32_t offset,
    SYS_FS_FILE_SEEK_CONTROL whence
);
```

SYS_FS_FileSize Function

Returns the size of the file in bytes.

C

```
int32_t SYS_FS_FileSize(SYS_FS_HANDLE handle);
```

Returns

On success returns the size of the file in bytes. On failure returns -1. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function returns the size of the file as pointed by the handle.

Remarks

None.

Preconditions

A valid file handle must be obtained before knowing a file size.

Example

```
SYS_FS_HANDLE fileHandle;
long fileSize;

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG" ,
    (SYS_FS_FILE_OPEN_READ));

if(fileHandle != SYS_FS_HANDLE_INVALID)
{
    // File open is successful
}
...
...

fileSize = SYS_FS_FileSize(fileHandle);

if(fileSize != -1)
{
    // Success
}
```

Parameters

Parameters	Description
handle	File handle obtained during file Open.

Function

```
int32_t SYS_FS_FileSize
(
    SYS_FS_HANDLE handle
);
```

SYS_FS_FileStat Function

Gets file status.

C

```
SYS_FS_RESULT SYS_FS_FileStat(const char * fname, SYS_FS_FSTAT * buf);
```

Returns

SYS_FS_RES_SUCCESS - File stat operation was successful. SYS_FS_RES_FAILURE - File stat operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function obtains information about a file associated with the file name, and populates the information in the structure pointed to by buf. This function can read the status of file regardless of whether a file is opened or not.

Remarks

None.

Preconditions

Prior to opening a file, the name of the volume on which the file resides should be known and the volume should be mounted.

Example

```
SYS_FS_fStat fileStat;

if(SYS_FS_FileStat("/mnt/myDrive/FILE.TXT", &fileStat) == SYS_FS_RES_SUCCESS)
{
    // Successfully read the status of file "FILE.TXT"
}
```

Parameters

Parameters	Description
fname	Name of the file with the path and the volume name. The string of volume and file name has to be preceded by "/mnt/". Also, the volume name and file name has to be separated by a slash "/".
buf	pointer to SYS_FS_FSTAT structure.

Function

```
SYS_FS_RESULT SYS_FS_FileStat
(
    const char *fname,
    SYS_FS_FSTAT *buf
)
```

SYS_FS_FileStringGet Function

Reads a string from the file into a buffer.

C

```
SYS_FS_RESULT SYS_FS_FileStringGet(SYS_FS_HANDLE handle, char* buff, uint32_t len);
```

Returns

SYS_FS_RES_SUCCESS - String read operation was successful. SYS_FS_RES_FAILURE - String read operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function reads a string of specified length from the file into a buffer. The read operation continues until 1. 'n' is stored 2. reached end of the file or 3. the buffer is filled with len - 1 characters. The read string is terminated with a '0'.

Remarks

None.

Preconditions

The file from which a string has to be read, has to be present and should have been opened.

Example

```
SYS_FS_RESULT res;
SYS_FS_HANDLE fileHandle;
char buffer[100];

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG", (SYS_FS_FILE_OPEN_WRITE_PLUS));
if( fileHandle != SYS_FS_HANDLE_INVALID)
{
    // File open is successful
}

// Read a string from the file.
res = SYS_FS_FileStringGet(fileHandle, buffer, 50);
if( res != SYS_FS_RES_SUCCESS)
{
    //String read operation failed.
}
```

Parameters

Parameters	Description
handle	Handle of the file from which string is to be read.
buff	Buffer in which the string is to be stored.
len	length of string to be read.

Function

```
SYS_FS_RESULT SYS_FS_FileStringGet
(
    SYS_FS_HANDLE handle,
    char* buff,
    uint32_t len
);
```

SYS_FS_FileStringPut Function

Writes a string to a file.

C

```
SYS_FS_RESULT SYS_FS_FileStringPut(SYS_FS_HANDLE handle, const char * string);
```

Returns

SYS_FS_RES_SUCCESS - String write operation was successful. SYS_FS_RES_FAILURE - String write operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function writes a string into a file. The string to be written should be NULL terminated. The terminator character will not be written.

Remarks

None.

Preconditions

The file into which a string has to be written, has to be present and should have been opened.

Example

```
SYS_FS_RESULT res;
SYS_FS_HANDLE fileHandle;

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG", SYS_FS_FILE_OPEN_WRITE_PLUS );
if( fileHandle != SYS_FS_HANDLE_INVALID )
{
    // File open is successful
}

// Write a string
res = SYS_FS_FileStringPut( fileHandle, "Hello World" );
if( res != SYS_FS_RES_SUCCESS )
{
    // String write operation failed.
}
```

Parameters

Parameters	Description
handle	File handle to which string is to be written.
string	Pointer to the null terminated string which has to be written into file.

Function

```
SYS_FS_RESULT SYS_FS_FileStringPut
(
    SYS_FS_HANDLE handle,
    const char *string
);
```

SYS_FS_FileSync Function

Flushes the cached information when writing to a file.

C

```
SYS_FS_RESULT SYS_FS_FileSync( SYS_FS_HANDLE handle );
```

Returns

SYS_FS_RES_SUCCESS - File sync operation was successful. SYS_FS_RES_FAILURE - File sync operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function flushes the cached information when writing to a file. The SYS_FS_FileSync function performs the same process as [SYS_FS_FileClose](#) function; however, the file is left open and can continue read/write/seek operations to the file.

Remarks

None.

Preconditions

A valid file handle has to be passed as input to the function. The file which has to be flushed, has to be present and should have been opened in write mode.

Example

```

SYS_FS_RESULT res;
SYS_FS_HANDLE fileHandle;
const char *buf = "Hello World";
size_t nbytes;
size_t bytes_written;

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG", (SYS_FS_FILE_OPEN_WRITE_PLUS) );

if( fileHandle != SYS_FS_HANDLE_INVALID)
{
    // File open is successful
}

// Write data to the file
bytes_written = SYS_FS_FileWrite( (const void *)buf, nbytes, fileHandle);

// Flush the file
res = SYS_FSFileSync(fileHandle);
if( res != SYS_FS_RES_SUCCESS)
{
    // renaming has gone wrong
}

```

Parameters

Parameters	Description
handle	valid file handle

Function

```

SYS_FS_RESULT SYS_FSFileSync
(
    SYS_FS_HANDLE handle
);

```

SYS_FS_FileTell Function

Obtains the file pointer position.

C

```
int32_t SYS_FS_FileTell(SYS_FS_HANDLE handle);
```

Returns

On success returns the current file position. On failure returns -1. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

Obtains the current value of the file position indicator for the file pointed to by handle.

Remarks

None.

Preconditions

A valid file handle must be obtained before performing a file tell.

Example

```

SYS_FS_HANDLE fileHandle;
int32_t tell;

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG",
                             (SYS_FS_FILE_OPEN_READ));

if(fileHandle != SYS_FS_HANDLE_INVALID)
{
    // File open is successful
}
...
...

tell = SYS_FS_FileTell(fileHandle);

if(tell != -1)
{
    // Success
}

```

Parameters

Parameters	Description
handle	File handle obtained during file Open.

Function

```

int32_t SYS_FS_FileTell
(
    SYS_FS_HANDLE handle
);

```

SYS_FS_FileTestError Function

Checks for errors in the file.

C

```
bool SYS_FS_FileTestError(SYS_FS_HANDLE handle);
```

Returns

On success returns false indicating that the file has no errors. On failure returns true. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function checks whether or not file has any errors.

Remarks

None.

Preconditions

A valid file handle must be obtained before passing to the function

Example

```

SYS_FS_HANDLE fileHandle;
bool err;

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG", (SYS_FS_FILE_OPEN_READ));

if(fileHandle != SYS_FS_HANDLE_INVALID)

```

```

{
    // File open is successful
}
...
...

err = SYS_FS_FileTestError(fileHandle);
if(err == true)
{
    // either file has error, or there
    // was an error in working with the "SYS_FS_FileTestError" function
}

```

Parameters

Parameters	Description
handle	file handle obtained during file Open.

Function

```

bool SYS_FS_FileTestError
(
    SYS_FS_HANDLE handle
);

```

SYS_FS_FileTruncate Function

Truncates a file

C

```
SYS_FS_RESULT SYS_FS_FileTruncate(SYS_FS_HANDLE handle);
```

Returns

SYS_FS_RES_SUCCESS - File truncate operation was successful. SYS_FS_RES_FAILURE - File truncate operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function truncates the file size to the current file read/write pointer. This function has no effect if the file read/write pointer is already pointing to end of the file.

Remarks

None.

Preconditions

A valid file handle has to be passed as input to the function. The file has to be opened in a mode where writes to file is possible (such as read plus or write mode).

Example

```

SYS_FS_HANDLE fileHandle;
size_t nbytes;
size_t bytes_read;
SYS_FS_RESULT res;

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG" ,
    (SYS_FS_FILE_OPEN_READ));

if(fileHandle != SYS_FS_HANDLE_INVALID)
{
    // File open is successful
}

// Read the file content

```

```

nbytes = sizeof(buf);
bytes_read = SYS_FS_FileRead(buf, nbytes, fileHandle);
// Truncate the file
res = SYS_FS_FileTruncate(fileHandle);
if(res != SYS_FS_RES_SUCCESS)
{
    // Truncation failed.
}

SYS_FS_FileClose(fileHandle);

```

Parameters

Parameters	Description
handle	A valid handle which was obtained while opening the file.

Function

```

SYS_FS_RESULT SYS_FS_FileTruncate
(
    SYS_FS_HANDLE handle
);

```

SYS_FS_FileWrite Function

Writes data to the file.

C

```
size_t SYS_FS_FileWrite(SYS_FS_HANDLE handle, const void * buf, size_t nbyte);
```

Returns

On success returns the number of bytes written successfully(0 or positive number). On failure returns -1. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function attempts to write nbyte bytes from the buffer pointed to by buf to the file associated with the file handle.

Remarks

None.

Preconditions

A valid file handle must be obtained before writing a file.

Example

```

...
const char *buf = "Hello World";
size_t nbytes;
size_t bytes_written;
SYS_FS_HANDLE fd;
...

bytes_written = SYS_FS_FileWrite(fd, (const void *)buf, nbytes);
...

```

Parameters

Parameters	Description
handle	File handle obtained during file open.
buf	Pointer to buffer from which data is to be written
nbyte	Number of bytes to be written

Function

```
size_t SYS_FS_FileWrite
(
    SYS_FS_HANDLE handle,
    const void *buf,
    size_t nbyte
);
```

SYS_FS_DirectoryMake Function

Makes a directory.

C

```
SYS_FS_RESULT SYS_FS_DirectoryMake(const char* path);
```

Returns

SYS_FS_RES_SUCCESS - Indicates that the creation of the directory was successful. SYS_FS_RES_FAILURE - Indicates that the creation of the directory was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function makes a new directory as per the specified path.

Remarks

None.

Preconditions

The disk has to be mounted before a directory could be made.

Example

```
SYS_FS_RESULT res;

res = SYS_FS_DirectoryMake("Dir1");

if(res == SYS_FS_RES_FAILURE)
{
    // Directory make failed
}
```

Parameters

Parameters	Description
path	Path of the new directory

Function

```
SYS_FS_RESULT SYS_FS_DirectoryMake
(
    const char* path
);
```

SYS_FS_DirOpen Function

Open a directory

C

```
SYS_FS_HANDLE SYS_FS_DirOpen(const char* path);
```

Returns

On success a valid handle to the directory will be returned. On failure [SYS_FS_HANDLE_INVALID](#) will be returned. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function opens the requested directory.

Remarks

None

Preconditions

The volume on which the directory is present should be mounted.

Example

```
SYS_FS_HANDLE dirHandle;

dirHandle = SYS_FS_DirOpen("/mnt/myDrive/Dir1");
// For root directory, end with a "/"
// dirHandle = SYS_FS_DirOpen("/mnt/myDrive/");

if(dirHandle != SYS_FS_HANDLE_INVALID)
{
    // Directory open is successful
}
```

Parameters

Parameters	Description
path	Path to the directory along with the volume name. The string of volume and directory name has to be preceded by "/mnt/". Also, the volume name and directory name has to be separated by a slash "/". If the directory specified is only the root directory, the path has to be ended with "/".

Function

```
SYS_FS_HANDLE SYS_FS_DirOpen
(
const char* path
);
```

SYS_FS_DirClose Function

Closes an opened directory.

C

```
SYS_FS_RESULT SYS_FS_DirClose(SYS_FS_HANDLE handle);
```

Returns

SYS_FS_RES_SUCCESS - Directory close operation was successful. SYS_FS_RES_FAILURE - Directory close operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function closes a directory that was opened earlier opened with the [SYS_FS_DirOpen](#) function.

Remarks

None.

Preconditions

A valid directory handle must be obtained before closing the directory.

Example

```

SYS_FS_HANDLE dirHandle;

dirHandle = SYS_FS_DirOpen("/mnt/myDrive/Dir1");

if(dirHandle != SYS_FS_HANDLE_INVALID)
{
    // Directory open is successful
}

// Perform required operation on the directory

// Close the directory
if(SYS_FS_DirClose(dirHandle) == SYS_FS_RES_FAILURE)
{
    // Close operation failed.
}

```

Parameters

Parameters	Description
handle	directory handle obtained during directory open.

Function

```

SYS_FS_RESULT SYS_FS_DirClose
(
    SYS_FS_HANDLE handle
);

```

SYS_FS_DirRead Function

Reads the files and directories of the specified directory.

C

```
SYS_FS_RESULT SYS_FS_DirRead(SYS_FS_HANDLE handle, SYS_FS_FSTAT * stat);
```

Returns

SYS_FS_RES_SUCCESS - Indicates that the directory read operation was successful. End of the directory condition is indicated by setting the fname and Ifname(if Ifname is used) fields of the [SYS_FS_FSTAT](#) structure to '0'

SYS_FS_RES_FAILURE - Indicates that the directory read operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function reads the files and directories specified in the open directory.

Remarks

None.

Preconditions

A valid directory handle must be obtained before reading a directory.

Example

```

SYS_FS_HANDLE dirHandle;
SYS_FS_FSTAT stat;
char longFileName[300];
uintptr_t longFileSize;

dirHandle = SYS_FS_DirOpen("/mnt/myDrive/Dir1");

```

```

if(dirHandle != SYS_FS_HANDLE_INVALID)
{
    // Directory open is successful
}

// If long file name is used, the following elements of the "stat"
// structure needs to be initialized with address of proper buffer.
stat.lfname = longFileName;
stat.lfsize = 300;

if(SYS_FS_DirRead(dirHandle, &stat) == SYS_FS_RES_FAILURE)
{
    // Directory read failed.
}
else
{
    // Directory read succeeded.
    if ((stat.lfname[0] == '0') && (stat.fname[0] == '0'))
    {
        // reached the end of the directory.
    }
    else
    {
        // continue reading the directory.
    }
}
}

```

Parameters

Parameters	Description
handle	Directory handle obtained during directory open.
stat	Pointer to SYS_FS_FSTAT , where the properties of the open directory will be populated after the SYS_FS_DirRead function returns successfully. If LFN is used, then the "lfname" member of the SYS_FS_FSTAT structure should be initialized with the address of a suitable buffer and the "lfsize" should be initialized with the size of the buffer. Once the function returns, the buffer whose address is held in "lfname" will have the file name(long file name) The file system supports 8.3 file name(Short File Name) and also long file name. 8.3 filenames are limited to at most eight characters, followed optionally by a filename extension consisting of a period . and at most three further characters. If the file name fits within the 8.3 limits then generally there will be no valid LFN for it. The stat structure's fname field will contain the SFN and if there is a valid LFN entry for the file then the long file name will be copied into lfname member of the structure.

Function

```

SYS_FS_RESULT SYS_FS_DirRead
(
    SYS_FS_HANDLE handle,
    SYS_FS_FSTAT *stat
);

```

SYS_FS_DirRewind Function

Rewinds to the beginning of the directory.

C

```
SYS_FS_RESULT SYS_FS_DirRewind(SYS_FS_HANDLE handle);
```

Returns

SYS_FS_RES_SUCCESS - Directory rewind operation was successful. SYS_FS_RES_FAILURE - Directory rewind operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function rewinds the directory to the start. Once a search of directory or directory read is completed, the rewind function is used to begin searching the directory from the start.

Remarks

None.

Preconditions

A valid directory handle must be obtained before reading a directory.

Example

```

SYS_FS_HANDLE dirHandle;
SYS_FS_FSTAT stat;
char longFileName[300];
uintptr_t longFileSize;

dirHandle = SYS_FS_DirOpen("/mnt/myDrive/Dir1");

if(dirHandle != SYS_FS_HANDLE_INVALID)
{
    // Directory open is successful
}

// If long file name is used, the following elements of the "stat"
// structure needs to be initialized with address of proper buffer.
stat.lfname = longFileName;
stat.lfsize = 300;

if(SYS_FS_DirRead(dirHandle, &stat) == SYS_FS_RES_FAILURE)
{
    // Directory read operation failed.
}

// Do more search
// Do some more search

// Now, rewind the directory to begin search from start

if(SYS_FS_DirRewind(dirHandle) == SYS_FS_RES_FAILURE)
{
    // Directory rewind failed.
}

```

Parameters

Parameters	Description
handle	directory handle obtained during directory open.

Function

```

SYS_FS_RESULT SYS_FS_DirRewind
(
    SYS_FS_HANDLE handle
);

```

SYS_FS_DirSearch Function

Searches for a file or directory.

C

```
SYS_FS_RESULT SYS_FS_DirSearch(SYS_FS_HANDLE handle, const char * name, SYS_FS_FILE_DIR_ATTR attr, SYS_FS_FSTAT * stat);
```

Returns

SYS_FS_RES_SUCCESS - Indicates that the file or directory was found. The stat parameter will contain information about the file or directory. SYS_FS_RES_FAILURE - Indicates that the file or directory was not found. The reason for the failure can be retrieved with [SYS_FS_Error](#) or [SYS_FS_FileError](#).

Description

This function searches for the requested file or directory. The file or directory is specified in the attr parameter, which is of type [SYS_FS_FILE_DIR_ATTR](#).

Remarks

None.

Preconditions

A valid directory handle must be obtained before searching the directory.

Example

```
SYS_FS_HANDLE dirHandle;
SYS_FS_FSTAT stat;
char longFileName[300];
uintptr_t longFileSize;

dirHandle = SYS_FS_DirOpen("/mnt/myDrive/Dir1");

if(dirHandle != SYS_FS_HANDLE_INVALID)
{
    // Directory open is successful
}

// If long file name is used, the following elements of the "stat"
// structure needs to be initialized with address of proper buffer.
stat.lfname = longFileName;
stat.lfsize = 300;

if(SYS_FS_DirSearch(dirHandle, "FIL*.*", SYS_FS_ATTR_ARC, &stat) == SYS_FS_RES_FAILURE)
{
    // Specified file not found
}
else
{
    // File found. Read the complete file name from "stat.lfname" and
    // other file parameters from the "stat" structure
}
```

Parameters

Parameters	Description
handle	directory handle obtained during directory open.
name	name of file or directory needed to be searched. The file name can have wild card entries as follows
?	• - Indicates that one character in a filename can vary (e.g. F?LE.T?T)
attr	Attribute of the name of type SYS_FS_FILE_DIR_ATTR . This attribute specifies whether to search a file or a directory. Other attribute types could also be specified.

stat	Empty structure of type SYS_FS_FSTAT , where the properties of the file/directory will be populated. If LFN is used, then the "Ifname" member of the SYS_FS_FSTAT structure should be initialized with address of suitable buffer. Also, the "Ifsize" should be initialized with the size of buffer. Once the function returns, the buffer whose address is held in "Ifname" will have the file name (long file name).
------	--

Function

```
SYS_FS_RESULT SYS_FS_DirSearch
(
    SYS_FS_HANDLE handle,
    const char * name,
    SYS_FS_FILE_DIR_ATTR attr,
    SYS_FS_FSTAT *stat
);
```

SYS_FS_DirectoryChange Function

Changes to a the directory specified.

C

```
SYS_FS_RESULT SYS_FS_DirectoryChange(const char* path);
```

Returns

SYS_FS_RES_SUCCESS - Indicates that the directory change operation was successful. SYS_FS_RES_FAILURE - Indicates that the directory change operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function changes the present directory to a new directory.

Remarks

None.

Preconditions

The disk has to be mounted and the directory to be changed must exist.

Example

```
SYS_FS_RESULT res;

res = SYS_FS_DirectoryChange("Dir1");

if(res == SYS_FS_RES_FAILURE)
{
    // Directory change failed
}
```

Parameters

Parameters	Description
path	Path of the directory to be changed to.

Function

```
SYS_FS_RESULT SYS_FS_DirectoryChange
(
    const char* path
);
```

SYS_FS_CurrentWorkingDirectoryGet Function

Gets the current working directory

C

```
SYS_FS_RESULT SYS_FS_CurrentWorkingDirectoryGet(char * buff, uint32_t len);
```

Returns

SYS_FS_RES_SUCCESS - Get current working directory operation was successful. SYS_FS_RES_FAILURE - Get current working directory operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function gets the current working directory path along with the working drive.

Remarks

None.

Preconditions

At least one disk must be mounted.

Example

```
SYS_FS_RESULT res;
char buffer[16];

switch(appState)
{
    case TRY_MOUNT:
        if(SYS_FS_Mount("/dev/mmcblk0", "/mnt/myDrive", FAT, 0, NULL) != SYS_FS_RES_SUCCESS)
        {
            // Failure, try mounting again
        }
        else
        {
            // Mount was successful. Create a directory.
            AppState = CREATE_DIR;
        }
        break;

    case CREATE_DIR:
        res = SYS_FS_DirectoryMake("Dir1");
        if(res == SYS_FS_RES_FAILURE)
        {
            // Directory creation failed
            AppState = ERROR;
        }
        else
        {
            // Directory creation was successful. Change to the new
            // directory.
            AppState = CHANGE_DIR;
        }
        break;

    case CHANGE_DIR:
        res = SYS_FS_DirectoryChange("Dir1");
        if(res == SYS_FS_RES_FAILURE)
        {
            // Directory change failed
            AppState = ERROR;
        }
        else
```

```

    {
        // Directory change was successful. Get current working
        // directory
        appState = GET_CWD;
    }
    break;

    case GET_CWD:
        res = SYS_FS_CurrentWorkingDirectoryGet(buffer, 15);
        if(res == SYS_FS_RES_FAILURE)
        {
            // Get current directory operation failed
            appState = ERROR;
        }
    break;
}

```

Parameters

Parameters	Description
buff	Pointer to a buffer which will contain the name of the current working directory and drive, once the function completes.
len	Size of the buffer.

Function

```

SYS_FS_RESULT SYS_FS_CurrentWorkingDirectoryGet
(
    char *buff,
    uint32_t len
);

```

SYS_FS_FileDirectoryModeSet Function

Sets the mode for the file or directory.

C

```

SYS_FS_RESULT SYS_FS_FileDirectoryModeSet(const char* path, SYS_FS_FILE_DIR_ATTR attr,
SYS_FS_FILE_DIR_ATTR mask);

```

Returns

SYS_FS_RES_SUCCESS - Mode set operation was successful. SYS_FS_RES_FAILURE - Mode set operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function sets the mode for a file or directory from the specified list of attributes.

Remarks

None.

Preconditions

The file or directory for which the mode is to be set must exist.

Example

```

// Set read-only flag, clear archive flag and others are retained.
SYS_FS_FileDirectoryModeSet("file.txt", SYS_FS_ATTR_RDO, SYS_FS_ATTR_RDO | SYS_FS_ATTR_ARC);

```

Parameters

Parameters	Description
path	Path for the file/directory, for which the mode is to be set.

attr	Attribute flags to be set in one or more combination of the type SYS_FS_FILE_DIR_ATTR . The specified flags are set and others are cleared.
mask	Attribute mask of type SYS_FS_FILE_DIR_ATTR that specifies which attribute is changed. The specified attributes are set or cleared.

Function

```
SYS\_FS\_RESULT SYS_FS_FileDirectoryModeSet
(
    const char* path,
    SYS\_FS\_FILE\_DIR\_ATTR attr,
    SYS\_FS\_FILE\_DIR\_ATTR mask
);
```

SYS_FS_FileDirectoryRemove Function

Removes a file or directory.

C

```
SYS\_FS\_RESULT SYS\_FS\_FileDirectoryRemove(const char* path);
```

Returns

[SYS_FS_RES_SUCCESS](#) - Indicates that the file or directory remove operation was successful. [SYS_FS_RES_FAILURE](#) - Indicates that the file or directory remove operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function removes a file or directory as specified by the path.

Remarks

None.

Preconditions

- The disk has to be mounted before a directory could be removed.
- The file or directory to be removed has to present.
- The file/sub-directory must not have read-only attribute (AM_RDO), or the function will be rejected with FR_DENIED.
- The sub-directory must be empty and must not be current directory, or the function will be rejected with FR_DENIED.
- The file/sub-directory must not be opened.

Example

```
SYS_FS_RESULT res;

res = SYS\_FS\_FileDirectoryRemove( "Dir1" );

if(res == SYS\_FS\_RES\_FAILURE)
{
    // Directory remove operation failed
}
//...
//...
```

Parameters

Parameters	Description
path	Path of the File or directory to be removed.

Function

```
SYS\_FS\_RESULT SYS_FS_FileDirectoryRemove
```

```

(
const char* path
);

```

SYS_FS_FileDirectoryRenameMove Function

Renames or moves a file or directory.

C

```
SYS_FS_RESULT SYS_FS_FileDirectoryRenameMove(const char * oldPath, const char * newPath);
```

Returns

SYS_FS_RES_SUCCESS - Rename/move operation was successful. SYS_FS_RES_FAILURE - Rename/move operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function renames or moves a file or directory.

Remarks

This function cannot move files/ directory from one drive to another. Do not rename/ move files which are open.

Preconditions

The file or directory to be renamed or moved must exist. This function cannot move files or directories from one drive to another. Do not rename or move files that are open.

Example

```

SYS_FS_RESULT res;

// rename "file.txt" to "renamed_file.txt"
res = SYS_FS_FileDirectoryRenameMove("file.txt", "renamed_file.txt");
if( res != SYS_FS_RES_SUCCESS)
{
    // Rename operation failed.
}

// Now, move "renamed_file.txt" inside directory "Dir1"
res = SYS_FS_FileDirectoryRenameMove("renamed_file.txt", "Dir1/renamed_file.txt");
if( res != SYS_FS_RES_SUCCESS)
{
    // File move operation failed.
}

```

Parameters

Parameters	Description
oldPath	Path for the file/directory, which has to be renamed/moved.
newPath	New Path for the file/directory.

Function

```

SYS_FS_RESULT SYS_FS_FileDirectoryRenameMove
(
const char *oldPath,
const char *newPath
);

```

SYS_FS_FileDirectoryTimeSet Function

Sets or changes the time for a file or directory.

C

```
SYS_FS_RESULT SYS_FS_FileDirectoryTimeSet(const char* path, SYS_FS_TIME * time);
```

Returns

SYS_FS_RES_SUCCESS - Set time operation was successful. SYS_FS_RES_FAILURE - Set time operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function sets or change the time for a file or directory.

Remarks

None.

Preconditions

The file/directory for which time is to be set must exist.

Example

```
void setTime(void)
{
    SYS_FS_RESULT res;
    SYS_FS_TIME time;

    time.packedTime = 0;

    // All FAT FS times are calculated based on 0 = 1980
    time.discreteTime.year = (2013 - 1980); // Year is 2013
    time.discreteTime.month = 8;           // Month (August)
    time.discreteTime.day = 9;            // Day (9)
    time.discreteTime.hour = 15;          // 3 PM
    time.discreteTime.minute = 06;        // 06 minutes
    time.discreteTime.second = 00;        // 00 seconds

    res = SYS_FS_FileDirectoryTimeSet("file.txt", &time);
    if( res != SYS_FS_RES_SUCCESS)
    {
        // time change has gone wrong
    }
}
```

Parameters

Parameters	Description
path	A path for the file/directory, for which the time is to be set.
ptr	Pointer to the structure of type SYS_FS_TIME , which contains the time data to be set.

Function

```
SYS_FS_RESULT SYS_FS_FileDirectoryTimeSet
(
    const char* path,
    SYS_FS_TIME *time
);
```

SYS_FS_Error Function

Returns the last error.

C

```
SYS_FS_ERROR SYS_FS_Error();
```

Returns

Error code of type [SYS_FS_ERROR](#).

Description

When a file system operation fails, the application can know the reason of failure by calling the `SYS_FS_Error`. This function only reports the errors which are not file (or file handle) specific. For example, for functions such as [SYS_FS_Mount](#) and [SYS_FS_FileOpen](#), which do not take handle, any errors happening inside such function calls could be reported using `SYS_FS_Error` function. Even for functions, which take handle as its input parameters, the `SYS_FS_Error` function can be used to report the type of error for cases where the passed handle itself is invalid.

Remarks

None.

Preconditions

This function has to be called immediately after a failure is observed while doing a file operation. Any subsequent failure will overwrite the cause of previous failure.

Example

```
SYS_FS_HANDLE fileHandle;
SYS_FS_ERROR err;

fileHandle = SYS_FS_FileOpen( "/mnt/myDrive/FILE.JPG" ,
    (SYS_FS_FILE_OPEN_READ));

if( fileHandle == SYS_FS_HANDLE_INVALID)
{
    // If failure, now know the specific reason for failure
    err = SYS_FS_Error();
}
```

Function

```
SYS_FS_ERROR SYS_FS_Error
(
void
)
```

b) General Operation Functions

SYS_FS_Initialize Function

Initializes the file system abstraction layer (sys_fs layer).

C

```
SYS_FS_RESULT SYS_FS_Initialize( const void* initData);
```

Returns

`SYS_FS_RES_SUCCESS` - SYS FS Layer was initialized successfully. `SYS_FS_RES_FAILURE` - SYS FS Layer initialization

failed. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function initializes the abstraction layer (sys_fs layer) and sets up the necessary parameters.

Preconditions

This is the first function to be called during usage of sys_fs. Calling other functions of sys_fs without initializing the sys_fs will cause unpredictable behavior.

Example

```
// This code shows an example of how the SYS FS is initialized
// Only one file system is used

#define SYS_FS_MAX_FILE_SYSTEM_TYPE 1

// Function pointer table for FAT FS
const SYS_FS_FUNCTIONS FatFsFunctions =
{
    .mount      = f_mount,
    .unmount    = f_unmount,
    .open       = f_open,
    .read       = f_read,
    .write      = f_write,
    .close      = f_close,
    .seek       = f_lseek,
    .tell       = f_tell,
    .eof        = f_eof,
    .size       = f_size,
    .fstat      = f_stat,
};

const SYS_FS_REGISTRATION_TABLE sysFSInit [ SYS_FS_MAX_FILE_SYSTEM_TYPE ] =
{
    {
        .nativeFileSystemType = FAT,
        .nativeFileSystemFunctions = &FatFsFunctions
    }
};

SYS_FS_Initialize((const void *)sysFSInit);
```

Parameters

Parameters	Description
initData	Pointer to an array of type SYS_FS_REGISTRATION_TABLE . The number of elements of array is decided by the definition SYS_FS_MAX_FILE_SYSTEM_TYPE . If the application uses one file system (say only FAT FS), SYS_FS_MAX_FILE_SYSTEM_TYPE is defined to be 1. Otherwise, if the application uses 2 file systems (say FAT FS and MPFS2), SYS_FS_MAX_FILE_SYSTEM_TYPE is defined to be 2.

Function

```
SYS_FS_RESULT SYS_FS_Initialize
(
    const void* initData
);
```

SYS_FS_Tasks Function

Maintains the File System tasks and functionalities.

C

```
void SYS_FS_Tasks();
```

Returns

None.

Description

This function is used to run the various tasks and functionalities of sys_fs layer.

Remarks

This function is not called directly by an application. It is called by the system's Tasks routine (SYS_Tasks).

Preconditions

The [SYS_FS_Initialize](#) routine must have been called before running the tasks.

Example

```
void SYS_Tasks ( void )
{
    SYS_FS_Tasks ();
    // Do other tasks
}
```

Function

```
void SYS_FS_Tasks
(
void
);
```

SYS_FS_Mount Function

Mounts the file system.

C

```
SYS_FS_RESULT SYS_FS_Mount(const char * devName, const char * mountName,
SYS_FS_FILE_SYSTEM_TYPE filesystemtype, unsigned long mountflags, const void * data);
```

Returns

SYS_FS_RES_SUCCESS - Mount was successful. SYS_FS_RES_FAILURE - Mount was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

The mount command attaches the file system specified to a volume. The call to the mount should be non blocking in nature. The application code has to allow the [SYS_FS_Tasks](#) to run periodically while calling the SYS_FS_Mount function. If the SYS_FS_Mount is called in a blocking mode, then the SYS_Tasks() never gets a chance to run and therefore, the media will not be analyzed and finally, the SYS_FS_Mount will never succeed. This will result in a deadlock.

There is no mechanism available for the application to know if the specified volume (devName) is really attached or not. The only available possibility is to keep trying to mount the volume (with the devname), until success is achieved.

It is prudent that the application code implements a time-out mechanism while trying to mount a volume (by calling [SYS_FS_Mount](#)). The trial for mount should continue at least 10 times before assuming that the mount will never succeed. This has to be done for every new volume to be mounted.

The standard names for volumes (devName) used in the MPLAB Harmony file system is as follows: NVM - "nvm" "media number" "volume number" SD card - "mmcblk" "media number" "volume number" MSD - "sd" "media number" "volume number"

Where, "media number" a, b, c... depends on the number of the type of connected media, and where, "volume number" 1, 2, 3... depends on the number of partitions in that media.

The convention for assigning names to volumes is further described below with examples:

If a SD card (with four partitions) is attached to the system, and assuming all four partitions are recognized, there will be four

devNames:

1. mmcblk1a1
2. mmcblk1a2
3. mmcblk1a3 and
4. mmcblk1a4

Subsequently, if NVM media is attached that has only one partition, the devname will be: nvma1.

Later, if another SD card is attached to the system that has one partition, the devname will be mmcblk1b.

Finally, there will be six volume names (or devNames), which are available for the application to be mounted and used for the file system.

Remarks

None

Preconditions

The "devName" name for the volume has to be known. The file system type with which each of the volumes are formatted has to be known. Trying to mount a volume with a file system which is different from what the volume is actually formatted, will cause mount failure.

Example

```
switch(appState)
{
    case TRY_MOUNT:
        if(SYS_FS_Mount("/dev/mmcblk1a1", "/mnt/myDrive", FAT, 0, NULL) != SYS_FS_RES_SUCCESS)
        {
            // Failure, try mounting again
        }
        else
        {
            // Mount was successful. Do further file operations
            AppState = DO_FURTHER_STUFFS;
        }
    break;
}
```

Parameters

Parameters	Description
devName	The device name (name of volume) which needs to be mounted. The devName has to be preceded by the string "/dev".
mountName	Mount name for the device to be mounted. This is a name provided by the user. In future, while accessing the mounted volume (say, during SYS_FS_FileOpen operation), the mountName is used to refer the path for file. The mount name has to be preceded by the string "/mnt/".
filesystemtype	Native file system of SYS_FS_FILE_SYSTEM_TYPE type.
mountflags	Mounting control flags. This parameter is reserved for future enhancements. Therefore, always pass zero.
data	The data argument is interpreted by the different file systems. This parameter is reserved for future enhancements. Therefore, always pass NULL.

Function

```
SYS_FS_RESULT SYS_FS_Mount
(
    const char *devName,
    const char *mountName,
    SYS_FS_FILE_SYSTEM_TYPE filesystemtype,
    unsigned long mountflags,
    const void *data
);
```

SYS_FS_Unmount Function

Unmounts the file system.

C

```
SYS_FS_RESULT SYS_FS_Unmount(const char * mountName);
```

Returns

SYS_FS_RES_SUCCESS - Unmount was successful. SYS_FS_RES_FAILURE - Unmount was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function removes (unmounts) the attachment of the volume from the file system.

Preconditions

The volume name has to be known in order to pass as input to Unmount. The specified volume name to be unmounted should have been already mounted.

Example

```
if(SYS_FS_Unmount( "/mnt/myDrive" ) != SYS_FS_RES_SUCCESS)
{
    // Failure, try unmounting again
}
else
{
    // Unmount was successful.
}
```

Parameters

Parameters	Description
mountName	Mount name for the volume to be unmounted. The mount name has to be preceded by the string "/mnt/".

Function

```
SYS_FS_RESULT SYS_FS_Unmount
(
const char *mountName
);
```

SYS_FS_CurrentDriveGet Function

Gets the current drive

C

```
SYS_FS_RESULT SYS_FS_CurrentDriveGet(char* buffer);
```

Returns

SYS_FS_RES_SUCCESS - Current drive get operation was successful. SYS_FS_RES_FAILURE - Current drive get operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function gets the present drive being used. The drive information is populated in the buffer.

Remarks

None.

Preconditions

The disk has to be mounted.

Example

```
SYS_FS_RESULT res;
char buffer[255];

res = SYS_FS_CurrentDriveGet(buffer);
if(res == SYS_FS_RES_FAILURE)
{
    // Operation failed.
}
```

Parameters

Parameters	Description
buffer	Pointer to buffer which will hold the name of present drive being used.

Function

```
SYS_FS_RESULT SYS_FS_CurrentDriveGet
(
    char* buffer
);
```

SYS_FS_CurrentDriveSet Function

Sets the drive.

C

```
SYS_FS_RESULT SYS_FS_CurrentDriveSet(const char* path);
```

Returns

SYS_FS_RES_SUCCESS - Current drive set operation was successful. SYS_FS_RES_FAILURE - Current drive set operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function sets the present drive to the one as specified by the path. By default, the drive mounted last becomes the current drive for the system. This is useful for applications where only one drive (volume) is used. In such an application, there is no need to call the SYS_FS_CurrentDriveSet function. However, in the case of an application where there are multiple volumes, the user can select the current drive for the application by calling this function.

Remarks

None.

Preconditions

The disk has to be mounted.

Example

```
SYS_FS_RESULT res;

res = SYS_FS_CurrentDriveSet( "/mnt/myDrive" );
if(res == SYS_FS_RES_FAILURE)
{
    // Drive change failed
}
```

Parameters

Parameters	Description
path	Path for the drive to be set.

Function

```
SYS_FS_RESULT SYS_FS_CurrentDriveSet
(
const char* path
);
```

SYS_FS_DriveLabelGet Function

Gets the drive label.

C

```
SYS_FS_RESULT SYS_FS_DriveLabelGet(const char* drive, char * buff, uint32_t * sn);
```

Returns

SYS_FS_RES_SUCCESS - Drive label information retrieval was successful. SYS_FS_RES_FAILURE - Drive label information retrieval was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function gets the label for the drive specified. If no drive is specified, the label for the current drive is obtained.

Remarks

None.

Preconditions

At least one disk must be mounted.

Example

```
SYS_FS_RESULT res;
char buffer[255];
uint32_t serialNo;

switch(appState)
{
    case TRY_MOUNT:
        if(SYS_FS_Mount("/dev/mmcblk0", "/mnt/myDrive", FAT, 0, NULL) != SYS_FS_RES_SUCCESS)
        {
            // Failure, try mounting again
        }
        else
        {
            // Mount was successful. Get label now
            AppState = GET_LABEL;
        }
        break;

    case GET_LABEL:
        res = SYS_FS_DriveLabelGet("/mnt/myDrive", buffer, &serialNo);

        if(res == SYS_FS_RES_FAILURE)
        {
            // Fetching drive label information failed
        }
        //...
        //...
        break;
}
```

}

Parameters

Parameters	Description
drive	Pointer to buffer which will hold the name of drive being for which the label is requested. If this string is NULL, then the label of the current drive is obtained by using this function.
buff	Buffer which will hold the string of label.
sn	Serial number of the drive. If this information is not needed, it can be set as NULL.

Function

```
SYS_FS_RESULT SYS_FS_DriveLabelGet
(
const char* drive,
char *buff,
uint32_t *sn
);
```

SYS_FS_DriveLabelSet Function

Sets the drive label

C

```
SYS_FS_RESULT SYS_FS_DriveLabelSet(const char * drive, const char * label);
```

Returns

SYS_FS_RES_SUCCESS - Drive label set operation was successful. SYS_FS_RES_FAILURE - Drive label set operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function sets the label for the drive specified. If no drive is specified, the label for the current drive is set.

Remarks

None.

Preconditions

At least one disk must be mounted.

Example

```
SYS_FS_RESULT res;

switch(appState)
{
    case TRY_MOUNT:
        if(SYS_FS_Mount("/dev/mmcblk0", "/mnt/myDrive", FAT, 0, NULL) != SYS_FS_RES_SUCCESS)
        {
            // Failure, try mounting again
        }
        else
        {
            // Mount was successful. Get label now
            AppState = GET_LABEL;
        }
        break;

    case GET_LABEL:
        res = SYS_FS_DriveLabelSet("/mnt/myDrive", "MY_LABEL");
        if(res == SYS_FS_RES_FAILURE)
```

```

    {
        // Drive label get failed
    }
//...
//...
break;
}

```

Parameters

Parameters	Description
drive	Pointer to string that holds the name of drive being for which the label is to be set. If this string is NULL, the label of the current drive is set by using this function.
label	Pointer to string which contains the label to be set.

Function

```

SYS_FS_RESULT SYS_FS_DriveLabelSet
(
const char* drive,
const char *label
);

```

SYS_FS_DriveFormat Function

Formats a drive.

C

```
SYS_FS_RESULT SYS_FS_DriveFormat(const char* drive, SYS_FS_FORMAT fmt, uint32_t clusterSize);
```

Returns

SYS_FS_RES_SUCCESS - Drive format was successful. SYS_FS_RES_FAILURE - Drive format was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function formats a logic drive (create a FAT file system on the logical drive), as per the format specified.

If the logical drive that has to be formatted has been bound to any partition (1-4) by multiple partition feature, the FAT volume is created into the specified partition. In this case, the second argument fmt is ignored. The physical drive must have been partitioned prior to using this function.

Remarks

None.

Preconditions

At least one disk must be mounted. The physical drive must have already been partitioned.

Example

```

SYS_FS_RESULT res;

switch(appState)
{
    case TRY_MOUNT:
        if(SYS_FS_Mount("/dev/mmcblk0", "/mnt/myDrive", FAT, 0, NULL) != SYS_FS_RES_SUCCESS)
        {
            // Failure, try mounting again
        }
        else
        {
            // Mount was successful. Format now.
            AppState = FORMAT_DRIVE;
        }
}

```

```

    }

break;

case FORMAT_DRIVE:
    res = SYS_FS_DriveFormat( "/mnt/myDrive", SYS_FS_FORMAT_SFD, 0 );
    if(res == SYS_FS_RES_FAILURE)
    {
        // Format of the drive failed.
    }
    //...
    break;
}

```

Parameters

Parameters	Description
drive	Pointer to buffer which will hold the name of drive being for which the format is to be done. If this string is NULL, then then current drive will be formatted. It is important to end the drive name with a "/".
fmt	Format type.
clusterSize	Cluster size. The value must be sector (size * n), where n is 1 to 128 and power of 2. When a zero is given, the cluster size depends on the volume size.

Function

```

SYS_FS_RESULT SYS_FS_DriveFormat
(
    const char* drive,
    SYS_FS_FORMAT fmt,
    uint32_t clusterSize
);

```

SYS_FS_DrivePartition Function

Partitions a physical drive (media).

C

```
SYS_FS_RESULT SYS_FS_DrivePartition(const char * path, const uint32_t partition[], void * work);
```

Returns

SYS_FS_RES_SUCCESS - Partition was successful. SYS_FS_RES_FAILURE - Partition was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

This function partitions a physical drive (media) into requested partition sizes. This function will alter the MBR of the physical drive and make it into multi partitions. Windows operating systems do not support multi partitioned removable media. Maximum 4 partitions can be created on a media.

Remarks

None

Preconditions

Prior to partitioning the media, the media should have a valid MBR and it should be mounted as a volume with the file system.

Example

```

//=====
// Initially, consider the case of a SD card that has only one partition.
//=====
SYS_FS_RESULT res;

```

```
// Following 4 element array specifies the size of 2 partitions as
// 256MB (=524288 sectors). The 3rd and 4th partition are not created
// since, the sizes of those are zero.
uint32_t plist[] = {524288, 524288, 0, 0};

// Work area for function SYS_FS_DrivePartition
char work[FAT_FS_MAX_SS];

switch(appState)
{
    case TRY_MOUNT:
        if(SYS_FS_Mount("/dev/mmcblk0", "/mnt/myDrive", FAT, 0, NULL) != SYS_FS_RES_SUCCESS)
        {
            // Failure, try mounting again
        }
        else
        {
            // Mount was successful. Partition now.
            AppState = PARTITION_DRIVE;
        }
        break;

    case PARTITION_DRIVE:
        res = SYS_FS_DrivePartition("/mnt/myDrive", plist, work);
        if(res == SYS_FS_RES_FAILURE)
        {
            // Drive partition went wrong
        }
        else
        {
            // Partition was successful. Power cycle the board so that
            // all partitions are recognized. Then try mounting both
            // partitions.
        }
        break;

    default:
        break;
}

//=====
//The following code is after the SD card is partitioned and then
//powered ON.
//=====
SYS_FS_RESULT res;

switch(appState)
{
    case TRY_MOUNT_1ST_PARTITION:
        if(SYS_FS_Mount("/dev/mmcblk0", "/mnt/myDrive1", FAT, 0, NULL) != SYS_FS_RES_SUCCESS)
        {
            // Failure, try mounting again
            AppState = TRY_MOUNT_1ST_PARTITION;
        }
        else
        {
            // Mount was successful. Mount second partition.
            AppState = TRY_MOUNT_2ND_PARTITION;
        }
        break;

    case TRY_MOUNT_2ND_PARTITION:
        if(SYS_FS_Mount("/dev/mmcblk0", "/mnt/myDrive2", FAT, 0, NULL) != SYS_FS_RES_SUCCESS)
        {
            // Failure, try mounting again
            AppState = TRY_MOUNT_2ND_PARTITION;
        }
}
```

```

    else
    {
        // Mount was successful. Try formating first partition.
        appState = TRY_FORMATING_1ST_PARTITION;
    }
    break;
```



```

case TRY_FORMATING_1ST_PARTITION:
    if(SYS_FS_DriveFormat("/mnt/myDrive1/", SYS_FS_FORMAT_FDISK, 0) == SYS_FS_RES_FAILURE)
    {
        // Failure
    }
    else
    {
        // Try formating second partitions.
        appState = TRY_FORMATING_2ND_PARTITION;
    }
```



```

case TRY_FORMATING_2ND_PARTITION:
    if(SYS_FS_DriveFormat("/mnt/myDrive2/", SYS_FS_FORMAT_FDISK, 0) == SYS_FS_RES_FAILURE)
    {
        // Failure
    }
    else
    {
        // Use both partitions as 2 separate volumes.
    }
```



```

default:
    break;
```

}

Parameters

Parameters	Description
path	Path to the volume with the volume name. The string of volume name has to be preceded by "/mnt/". Also, the volume name and directory name has to be separated by a slash "/".
partition	Array with 4 items, where each items mentions the sizes of each partition in terms of number of sector. 0th element of array specifies the number of sectors for first partition and 3rd element of array specifies the number of sectors for fourth partition.
work	Pointer to the buffer for function work area. The size must be at least FAT_FS_MAX_SS bytes.

Function

```

SYS_FS_RESULT SYS_FS_DrivePartition
(
    const char *path,
    const uint32_t partition[],
    void * work
);
```

SYS_FS_DriveSectorGet Function

Obtains total number of sectors and number of free sectors for the specified drive.

C

```

SYS_FS_RESULT SYS_FS_DriveSectorGet(const char * path, uint32_t * totalSectors, uint32_t * freeSectors);
```

Returns

SYS_FS_RES_SUCCESS - Sector information get operation was successful. SYS_FS_RES_FAILURE - Sector information get operation was unsuccessful. The reason for the failure can be retrieved with [SYS_FS_Error](#).

Description

Function to obtain the total number of sectors and number of free sectors in a drive (media).

Remarks

None.

Preconditions

The drive for which the information is to be retrieved should be mounted.

Example

```
uint32_t totalSectors, freeSectors;
SYS_FS_RESULT res;

if(SYS_FS_Mount("/dev/mmcblk0", "/mnt/myDrive", FAT, 0, NULL) != SYS_FS_RES_SUCCESS)
{
    // Failure, try mounting again
}
else
{
    // Mount was successful.
    // Do other FS stuffs.
}
// Perform usual FS tasks.
//.....
//.....

// Now, determine the total sectors and free sectors
res = SYS_FS_DriveSectorGet("/mnt/myDrive", &totalSectors, &freeSectors);
if(res == SYS_FS_RES_FAILURE)
{
    //Sector information get operation failed.
}
```

Parameters

Parameters	Description
path	Path to the volume with the volume name. The string of volume name must be preceded by "/mnt/". Also, the volume name and directory name must be separated by a slash "/".
totalSectors	Pointer to a variable passed to the function, which will contain the total number of sectors available in the drive (media).
freeSectors	Pointer to a variable passed to the function, which will contain the free number of sectors available in the drive (media).

Function

```
SYS_FS_RESULT SYS_FS_DriveSectorGet
(
const char* path,
uint32_t *totalSectors,
uint32_t *freeSectors
);
```

SYS_FS_EventHandlerSet Function

Allows a client to identify an event handling function for the file system to call back when mount/unmount operation has completed.

C

```
void SYS_FS_EventHandlerSet(const void * eventHandler, const uintptr_t context);
```

Returns

None.

Description

This function allows a client to identify an event handling function for the File System to call back when mount/unmount operation has completed. The file system will pass mount name back to the client by calling "eventHandler" when AutoMount feature is enabled for File system.

Remarks

On Mount/Un-Mount of a volume all the registered clients will be notified. The client should check if the mount name passed when event handler is called is the one it is expecting and then proceed as demonstrated in above example.

If the client does not want to be notified when the mount/unmount operation has completed, it does not need to register a callback.

This API is Available only when SYS_FS_AUTOMOUNT_ENABLE is set to true.

Preconditions

The [SYS_FS_Initialize\(\)](#) routine must have been called.

Example

```
// Client registers an event handler with file system. This is done once.
SYS_FS_EventHandlerSet(APP_SysFSEventHandler, (uintptr_t)NULL);

// Event Processing Technique. Event is received when operation is done.
void APP_SysFSEventHandler
(
    SYS_FS_EVENT event,
    void* eventData,
    uintptr_t context
)
{
    switch(event)
    {
        case SYS_FS_EVENT_MOUNT:
            if(strcmp((const char *)eventData, "/mnt/myDrive1") == 0)
            {
                gSDCardMountFlag = true;
            }
            else if(strcmp((const char *)eventData, "/mnt/myDrive2") == 0)
            {
                gNVMMountFlag = true;
            }
            break;

        case SYS_FS_EVENT_UNMOUNT:
            if(strcmp((const char *)eventData, "/mnt/myDrive1") == 0)
            {
                gSDCardMountFlag = false;
            }
            else if(strcmp((const char *)eventData, "/mnt/myDrive2") == 0)
            {
                gNVMMountFlag = false;
            }
            break;

        case SYS_FS_EVENT_ERROR:
            break;
    }
}
```

Parameters

Parameters	Description
eventHandler	Pointer to the event handler function implemented by the user
context	The value of parameter will be passed back to the client unchanged, when the eventHandler function is called. It can be used to identify any client specific data object that identifies the instance of the client module (for example, it may be a pointer to the client module's state structure).

Function

```
void SYS_FS_EventHandlerSet
(
    const void * eventHandler,
    const uintptr_t context
);
```

c) Media Manager Functions

SYS_FS_MEDIA_MANAGER_Tasks Function

Media manager task function.

C

```
void SYS_FS_MEDIA_MANAGER_Tasks();
```

Returns

None.

Description

This is the media manager task function. This task must be called repeatedly from the main loop.

Preconditions

None

Function

```
void SYS_FS_MEDIA_MANAGER_Tasks
(
    void
);
```

SYS_FS_MEDIA_MANAGER_TransferTask Function

Media manager transfer task function.

C

```
void SYS_FS_MEDIA_MANAGER_TransferTask(uint8_t mediaIndex);
```

Returns

None.

Description

This is the media manager transfer task function. This task is repeatedly called by the disk io layer of the native file system for driving the current disk read/write operation to completion.

Preconditions

None

Parameters

Parameters	Description
mediaIndex	disk number of the media

Function

```
void SYS_FS_MEDIA_MANAGER_TransferTask
(
    uint8_t mediaIndex
);
```

SYS_FS_MEDIA_MANAGER_Read Function

Gets data from a specific media address.

C

```
SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE SYS_FS_MEDIA_MANAGER_Read(uint16_t diskNum, uint8_t * destination, uint8_t * source, const uint32_t nBytes);
```

Returns

Buffer handle of type [SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE](#)

Description

This function gets data from a specific address of media. This function is intended to work with NVM media only, which can have byte level addressing. For other media, such as a SD card, byte addressing is not possible and this function will not work. Also, this function is intended to work with the MPFS2 file system only, which uses byte addressing.

Preconditions

None.

Parameters

Parameters	Description
diskNo	media number
destination	pointer to buffer where data to be placed after read
source	pointer from where data to be read
nBytes	Number of bytes to be read

Function

```
SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE SYS_FS_MEDIA_MANAGER_Read
(
    uint16_t diskNo,
    uint8_t* destination,
    uint8_t * source,
    const unsigned int nBytes
);
```

SYS_FS_MEDIA_MANAGER_SectorRead Function

Reads a specified media sector.

C

```
SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE SYS_FS_MEDIA_MANAGER_SectorRead(uint16_t diskNum, uint8_t * dataBuffer, uint32_t sector, uint32_t numSectors);
```

Returns

Buffer handle of type [SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE](#).

Description

This function reads a specified media (disk) sector. This is the function in the media manager layer. This function in turn calls the specific sector read function from the list of function pointers of the media driver.

Preconditions

None.

Parameters

Parameters	Description
diskNo	Media number
dataBuffer	Pointer to buffer where data to be placed after read
sector	Sector numer to be read
noSectors	Number of sectors to read

Function

```
SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE SYS_FS_MEDIA_MANAGER_SectorRead
(
    uint16_t diskNo,
    uint8_t * dataBuffer,
    uint32_t sector,
    uint32_t noSectors
);
```

SYS_FS_MEDIA_MANAGER_SectorWrite Function

Writes a sector to the specified media.

C

```
SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE SYS_FS_MEDIA_MANAGER_SectorWrite(uint16_t diskNum, uint32_t sector, uint8_t * dataBuffer, uint32_t numSectors);
```

Returns

Buffer handle of type [SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE](#).

Description

This function writes to a sector of the specified media (disk). This is the function in the media manager layer. This function in turn calls the specific sector write function from the list of function pointers of the media driver.

Preconditions

None.

Parameters

Parameters	Description
diskNo	media number
sector	Sector # to which data to be written
dataBuffer	pointer to buffer which holds the data to be written
noSectors	Number of sectors to be written

Function

```
SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE SYS_FS_MEDIA_MANAGER_SectorWrite
(
    uint16_t diskNo,
    uint32_t sector,
    uint8_t * dataBuffer,
    uint32_t noSectors
);
```

SYS_FS_MEDIA_MANAGER_Register Function

Function to register media drivers with the media manager.

C

```
SYS_FS_MEDIA_HANDLE SYS_FS_MEDIA_MANAGER_Register(SYS_MODULE_OBJ obj, SYS_MODULE_INDEX index,
const SYS_FS_MEDIA_FUNCTIONS * mediaFunctions, SYS_FS_MEDIA_TYPE mediaType);
```

Returns

Valid handle of type [SYS_FS_MEDIA_HANDLE](#) on successful registration of the media driver. Invalid handle of type [SYS_FS_MEDIA_HANDLE_INVALID](#) on unsuccessful registration of the media driver.

Description

This function is called by the media driver to register the functionalities with the media manager. For static media, such as NVM or a SD card, the media drivers register with this function at the time of initialization. For dynamic media, such as MSD, this register function is called dynamically, once the MSD media is connected.

Remarks

None

Preconditions

None.

Parameters

Parameters	Description
obj	driver object (of type SYS_MODULE_OBJ , value returned when driver is initialized)
index	driver index (of type SYS_MODULE_INDEX , value passed during driver initialization and opening)
mediaFunctions	List of media driver functions
mediaType	Type of media

Function

```
SYS_FS_MEDIA_HANDLE SYS_FS_MEDIA_MANAGER_Register
(
    SYS_MODULE_OBJ obj,
    SYS_MODULE_INDEX index,
```

```
const SYS_FS_MEDIA_FUNCTIONS *mediaFunctions,
SYS_FS_MEDIA_TYPE mediaType
)
```

SYS_FS_MEDIA_MANAGER_RegisterTransferHandler Function

Register the event handler for data transfer events.

C

```
void SYS_FS_MEDIA_MANAGER_RegisterTransferHandler(const void * eventHandler);
```

Returns

Pointer to the media geometry on Success else NULL.

Description

This function is used to send the command status for the disk operation.

Preconditions

None.

Parameters

Parameters	Description
eventHandler	Event handler pointer.

Function

```
void SYS_FS_MEDIA_MANAGER_RegisterTransferHandler
(
const void *eventHandler
);
```

SYS_FS_MEDIA_MANAGER_DeRegister Function

C

```
void SYS_FS_MEDIA_MANAGER_DeRegister(SYS_FS_MEDIA_HANDLE handle);
```

Returns

None.

Description

Function called by a media to deregister itself to the media manager. For static media, (like NVM or SD card), this "deregister function" is never called, since static media never gets deregistered once they are initialized. For dynamic media (like MSD), this register function is called dynamically, once the MSD media is connected.

Preconditions

None.

Parameters

Parameters	Description
handle	Handle of type SYS_FS_MEDIA_HANDLE received when the media was registered

Function

```
void SYS_FS_MEDIA_MANAGER_DeRegister
```

```

(
  SYS_FS_MEDIA_HANDLE handle
)

```

SYS_FS_MEDIA_MANAGER_AddressGet Function

Gets the starting media address based on a disk number.

C

```
uintptr_t SYS_FS_MEDIA_MANAGER_AddressGet(uint16_t diskNo);
```

Returns

Memory address of type uintptr_t.

Description

This function gets the starting address of a media. This function is intended to work only with MPFS2, which does byte addressing and needs a memory address (not disk number).

Preconditions

None.

Parameters

Parameters	Description
diskNo	media number

Function

```

uintptr_t SYS_FS_MEDIA_MANAGER_AddressGet
(
  uint16_t diskNo
);

```

SYS_FS_MEDIA_MANAGER_MediaStatusGet Function

Gets the media status.

C

```
bool SYS_FS_MEDIA_MANAGER_MediaStatusGet(const char * devName);
```

Returns

Media attach/detach status of type bool.

Description

This function gets the media status. This function is used by higher layers (sys_fs layer) to know the status of the media whether the media is attached or detached.

Preconditions

None.

Parameters

Parameters	Description
*devName	string name of the media

Function

```
bool SYS_FS_MEDIA_MANAGER_MediaStatusGet
(
    const char *devName
);
```

SYS_FS_MEDIA_MANAGER_VolumePropertyGet Function

Gets the volume property.

C

```
bool SYS_FS_MEDIA_MANAGER_VolumePropertyGet(const char * devName, SYS_FS_VOLUME_PROPERTY * str);
```

Returns

True or false.

Description

This function gets the property of the volume. This function is used by higher layers (sys_fs layer) to know the property of the volume as specified in the [SYS_FS_VOLUME_PROPERTY](#) structure.

Preconditions

None.

Parameters

Parameters	Description
*devName	String name of the media
*str	Pointer to structure of type SYS_FS_VOLUME_PROPERTY

Function

```
bool SYS_FS_MEDIA_MANAGER_VolumePropertyGet
(
    const char *devName
    SYS_FS_VOLUME_PROPERTY *str
);
```

SYS_FS_MEDIA_MANAGER_CommandStatusGet Function

Gets the command status.

C

```
SYS_FS_MEDIA_COMMAND_STATUS SYS_FS_MEDIA_MANAGER_CommandStatusGet(uint16_t diskNo,
SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE commandHandle);
```

Returns

Command status of type [SYS_FS_MEDIA_COMMAND_STATUS](#).

Description

This function gets the command status. The sector read and sector write are non-blocking functions. Therefore, this interface is provided where the code should periodically poll for the buffer status. If status is completed, the read/write operation is considered to be complete.

Preconditions

None.

Parameters

Parameters	Description
diskNo	media number
bufferHandle	the command handle which was obtained during sector read/ write

Function

```
SYS_FS_MEDIA_COMMAND_STATUS SYS_FS_MEDIA_MANAGER_CommandStatusGet
(
    uint16_t diskNo,
    SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE bufferHandle
)
```

SYS_FS_MEDIA_MANAGER_GetMediaGeometry Function

Gets the media geometry information.

C

```
SYS_FS_MEDIA_GEOMETRY * SYS_FS_MEDIA_MANAGER_GetMediaGeometry(uint16_t diskNum);
```

Returns

Pointer to the media geometry on Success else NULL.

Description

This function gets the media geometry information.

Preconditions

None.

Parameters

Parameters	Description
diskNum	Media disk number.

Function

```
SYS_FS_MEDIA_GEOMETRY * SYS_FS_MEDIA_MANAGER_GetMediaGeometry
(
    uint16_t diskNum
);
```

SYS_FS_MEDIA_MANAGER_EventHandlerSet Function

Register the event handler for Mount/Un-Mount events.

C

```
void SYS_FS_MEDIA_MANAGER_EventHandlerSet(const void * eventHandler, const uintptr_t context);
```

Description

This function is used to register a FS client event handler for notifying the Mount/Un-Mount events when AutoMount feature is enabled for File system.

On Mount/Un-Mount of a volume all the registered clients will be notified. The client should check if the mount name passed when event handler is called is the one it is expecting and then proceed.

Remarks

This API should not be called directly from Application. Application should use [SYS_FS_EventHandlerSet\(\)](#) instead.

This API is Available only when [SYS_FS_AUTOMOUNT_ENABLE](#) is set to true.

See [sys_fs.h](#) for usage information.

Parameters

Parameters	Description
eventHandler	FS Client event handler pointer
context	FS Client context

Function

```
void SYS_FS_MEDIA_MANAGER_EventHandlerSet
(
    const void * eventHandler,
    const uintptr_t context
);
```

d) File System Data Types and Constants

SYS_FS_ERROR Enumeration

Lists the various error cases.

C

```
typedef enum {
    SYS_FS_ERROR_OK = 0,
    SYS_FS_ERROR_DISK_ERR,
    SYS_FS_ERROR_INT_ERR,
    SYS_FS_ERROR_NOT_READY,
    SYS_FS_ERROR_NO_FILE,
    SYS_FS_ERROR_NO_PATH,
    SYS_FS_ERROR_INVALID_NAME,
    SYS_FS_ERROR_DENIED,
    SYS_FS_ERROR_EXIST,
    SYS_FS_ERROR_INVALID_OBJECT,
    SYS_FS_ERROR_WRITE_PROTECTED,
    SYS_FS_ERROR_INVALID_DRIVE,
    SYS_FS_ERROR_NOT_ENABLED,
    SYS_FS_ERROR_NO_FILESYSTEM,
    SYS_FS_ERROR_FORMAT_ABORTED,
    SYS_FS_ERROR_TIMEOUT,
    SYS_FS_ERROR_LOCKED,
    SYS_FS_ERROR_NOT_ENOUGH_CORE,
    SYS_FS_ERROR_TOO_MANY_OPEN_FILES,
    SYS_FS_ERROR_INVALID_PARAMETER,
    SYS_FS_ERROR_NOT_ENOUGH_FREE_VOLUME,
    SYS_FS_ERROR_FS_NOT_SUPPORTED,
    SYS_FS_ERROR_FS_NOT_MATCH_WITH_VOLUME,
    SYS_FS_ERROR_NOT_SUPPORTED_IN_NATIVE_FS
} SYS_FS_ERROR;
```

Members

Members	Description
SYS_FS_ERROR_OK = 0	Success
SYS_FS_ERROR_DISK_ERR	(1) A hard error occurred in the low level disk I/O layer
SYS_FS_ERROR_INT_ERR	(2) Assertion failed
SYS_FS_ERROR_NOT_READY	(3) The physical drive cannot work
SYS_FS_ERROR_NO_FILE	(4) Could not find the file
SYS_FS_ERROR_NO_PATH	(5) Could not find the path
SYS_FS_ERROR_INVALID_NAME	(6) The path name format is invalid
SYS_FS_ERROR_DENIED	(7) Access denied due to prohibited access or directory full
SYS_FS_ERROR_EXIST	(8) Access denied due to prohibited access
SYS_FS_ERROR_INVALID_OBJECT	(9) The file/directory object is invalid
SYS_FS_ERROR_WRITE_PROTECTED	(10) The physical drive is write protected
SYS_FS_ERROR_INVALID_DRIVE	(11) The logical drive number is invalid
SYS_FS_ERROR_NOT_ENABLED	(12) The volume has no work area
SYS_FS_ERROR_NO_FILESYSTEM	(13) There is no valid volume
SYS_FS_ERROR_FORMAT_ABORTED	(14) The Format() aborted due to any parameter error
SYS_FS_ERROR_TIMEOUT	(15) Could not get a grant to access the volume within defined period
SYS_FS_ERROR_LOCKED	(16) The operation is rejected according to the file sharing policy
SYS_FS_ERROR_NOT_ENOUGH_CORE	(17) LFN working buffer could not be allocated
SYS_FS_ERROR_TOO_MANY_OPEN_FILES	(18) Number of open files
SYS_FS_ERROR_INVALID_PARAMETER	(19) Given parameter is invalid
SYS_FS_ERROR_NOT_ENOUGH_FREE_VOLUME	(20) Too many mounts requested. Not enough free volume available
SYS_FS_ERROR_FS_NOT_SUPPORTED	(21) Requested native file system is not supported
SYS_FS_ERROR_FS_NOT_MATCH_WITH_VOLUME	(22) Requested native file system does not match the format of volume
SYS_FS_ERROR_NOT_SUPPORTED_IN_NATIVE_FS	(23) Function not supported in native file system layer

Description

File Error enumeration

This enumeration lists the various error cases. When the application calls for a file system function which has a return type of [SYS_FS_RESULT](#) and if the return value is [SYS_FS_RES_FAILURE](#), the application can know the specific reason for failure by calling the [SYS_FS_FileError](#) function. The return value of [SYS_FS_FileError](#) function will be one of the enumeration of type [SYS_FS_ERROR](#).

Remarks

None.

SYS_FS_FILE_SEEK_CONTROL Enumeration

Lists the various modes of file seek.

C

```
typedef enum {
    SYS_FS_SEEK_SET,
    SYS_FS_SEEK_CUR,
    SYS_FS_SEEK_END
} SYS_FS_FILE_SEEK_CONTROL;
```

Members

Members	Description
SYS_FS_SEEK_SET	Set file offset to input number of bytes from the start of file
SYS_FS_SEEK_CUR	Set file offset to its current location plus input number of bytes

SYS_FS_SEEK_END

Set file offset to size of the file plus input number of bytes

Description

File Seek control

This enumeration lists the various modes of file seek. When the application calls the [SYS_FS_FileSeek](#) function, it specifies the kind of seek that needs to be performed.

Remarks

None.

SYS_FS_FSTAT Structure

File System status

C

```
typedef struct {
    uint32_t fsize;
    uint16_t fdate;
    uint16_t ftime;
    uint8_t fattrib;
    char fname[13];
    char * lfname;
    uint32_t lfsize;
} SYS_FS_FSTAT;
```

Members

Members	Description
uint32_t fsize;	File size
uint16_t fdate;	Last modified date
uint16_t ftime;	Last modified time
uint8_t fattrib;	Attribute
char fname[13];	Short file name (8.3 format)
char * lfname;	Pointer to the LFN buffer
uint32_t lfsize;	Size of LFN buffer in TCHAR

Description

SYS FS File status structure

This structure holds the various status of a file. The [SYS_FS_FileStat](#) () populates the contents of this structure.

Remarks

None.

SYS_FS_FUNCTIONS Structure

SYS FS Function signature structure for native file systems.

C

```
typedef struct {
    int (* mount)(uint8_t vol);
    int (* unmount)(uint8_t vol);
    int (* open)(uintptr_t handle, const char* path, uint8_t mode);
    int (* read)(uintptr_t fp, void* buff, uint32_t btr, uint32_t *br);
    int (* write)(uintptr_t fp, const void* buff, uint32_t btw, uint32_t* bw);
    int (* close)(uintptr_t fp);
    int (* seek)(uintptr_t handle, uint32_t offset);
    uint32_t (* tell)(uintptr_t handle);
```

```

bool (* eof)(uintptr_t handle);
uint32_t (* size)(uintptr_t handle);
int (* fstat)(const char* path, uintptr_t fno);
int (* mkdir)(const char *path);
int (* chdir)(const char *path);
int (* remove)(const char *path);
int (* getlabel)(const char *path, char *buff, uint32_t *sn);
int (* setlabel)(const char *label);
int (* truncate)(uintptr_t handle);
int (* currWD)(char* buff, uint32_t len);
int (* chdrive)(uint8_t drive);
int (* chmode)(const char* path, uint8_t attr, uint8_t mask);
int (* chtime)(const char* path, uintptr_t ptr);
int (* rename)(const char *oldPath, const char *newPath);
int (* sync)(uintptr_t fp);
char * (* getstrn)(char* buff, int len, uintptr_t handle);
int (* putchr)(char c, uintptr_t handle);
int (* putstrn)(const char* str, uintptr_t handle);
int (* formattedprint)(uintptr_t handle, const char *str, ...);
bool (* testerror)(uintptr_t handle);
int (* formatDisk)(uint8_t vol, uint8_t sfd, uint32_t au);
int (* openDir)(uintptr_t handle, const char *path);
int (* readDir)(uintptr_t handle, uintptr_t stat);
int (* closeDir)(uintptr_t handle);
int (* partitionDisk)(uint8_t pdrv, const uint32_t szt[], void* work);
int (* getCluster)(const char *path, uint32_t *tot_sec, uint32_t *free_sec);
} SYS_FS_FUNCTIONS;

```

Members

Members	Description
int (* mount)(uint8_t vol);	Function pointer of native file system for mounting a volume
int (* umount)(uint8_t vol);	Function pointer of native file system for unmounting a volume
int (* open)(uintptr_t handle, const char* path, uint8_t mode);	Function pointer of native file system for opening a file
int (* read)(uintptr_t fp, void* buff, uint32_t btr, uint32_t *br);	Function pointer of native file system for reading a file
int (* write)(uintptr_t fp, const void* buff, uint32_t btw, uint32_t* bw);	Function pointer of native file system for writing to a file
int (* close)(uintptr_t fp);	Function pointer of native file system for closing a file
int (* seek)(uintptr_t handle, uint32_t offset);	Function pointer of native file system for moving the file pointer by a <ul style="list-style-type: none"> desired offset
uint32_t (* tell)(uintptr_t handle);	Function pointer of native file system for finding the position of the <ul style="list-style-type: none"> file pointer
bool (* eof)(uintptr_t handle);	Function pointer of native file system to check if the end of file is <ul style="list-style-type: none"> reached
uint32_t (* size)(uintptr_t handle);	Function pointer of native file system to know the size of file
int (* fstat)(const char* path, uintptr_t fno);	Function pointer of native file system to know the status of file
int (* mkdir)(const char *path);	Function pointer of native file system to create a directory
int (* chdir)(const char *path);	Function pointer of native file system to change a directory
int (* remove)(const char *path);	Function pointer of native file system to remove a file or directory
int (* getlabel)(const char *path, char *buff, uint32_t *sn);	Function pointer of native file system to get the volume label
int (* setlabel)(const char *label);	Function pointer of native file system to set the volume label
int (* truncate)(uintptr_t handle);	Function pointer of native file system to truncate the file
int (* currWD)(char* buff, uint32_t len);	Function pointer of native file system to obtain the current working <ul style="list-style-type: none"> directory
int (* chdrive)(uint8_t drive);	Function pointer of native file system to set the current drive
int (* chmode)(const char* path, uint8_t attr, uint8_t mask);	Function pointer of native file system to change the attribute for file <ul style="list-style-type: none"> or directory

int (* chtime)(const char* path, uintptr_t ptr);	Function pointer of native file system to change the time for a file or • directory
int (* rename)(const char *oldPath, const char *newPath);	Function pointer of native file system to rename a file or directory
int (* sync)(uintptr_t fp);	Function pointer of native file system to flush file
char * (* getstrn)(char* buff, int len, uintptr_t handle);	Function pointer of native file system to read a string from a file
int (* putchr)(char c, uintptr_t handle);	Function pointer of native file system to write a character into a file
int (* putstrn)(const char* str, uintptr_t handle);	Function pointer of native file system to write a string into a file
int (* formattedprint)(uintptr_t handle, const char *str, ...);	Function pointer of native file system to print a formatted string to • file
bool (* testerror)(uintptr_t handle);	Function pointer of native file system to test an error in a file
int (* formatDisk)(uint8_t vol, uint8_t sdf, uint32_t au);	Function pointer of native file system to format a disk
int (* openDir)(uintptr_t handle, const char *path);	Function pointer of native file system to open a directory
int (* readDir)(uintptr_t handle, uintptr_t stat);	Function pointer of native file system to read a directory
int (* closeDir)(uintptr_t handle);	Function pointer of native file system to close an opened directory
int (* partitionDisk)(uint8_t pdrv, const uint32_t szt[], void* work);	Function pointer of native file system to partition a physical drive
int (* getCluster)(const char *path, uint32_t *tot_sec, uint32_t *free_sec);	Function pointer of native file system to get total sectors and free • sectors

Description

SYS FS Function signature structure for native file systems

The SYS FS layer supports functions from each native file system layer. This structure specifies the signature for each function from native file system (parameter that needs to be passed to each function and return type for each function). If a new native file system is to be integrated with the SYS FS layer, the functions should follow the signature.

The structure of function pointer for the two native file systems: FAT FS and MPFS2 is already provided in the respective source files for the native file system. Hence the following structure is not immediately useful for the user. But the explanation for the structure is still provided for advanced users who would wish to integrate a new native file system to the MPLAB Harmony File System framework.

Remarks

None.

SYS_FS_REGISTRATION_TABLE Structure

The sys_fs layer has to be initialized by passing this structure with suitably initialized members.

C

```
typedef struct {
    SYS_FS_FILE_SYSTEM_TYPE nativeFileSystemType;
    const SYS_FS_FUNCTIONS * nativeFileSystemFunctions;
} SYS_FS_REGISTRATION_TABLE;
```

Members

Members	Description
SYS_FS_FILE_SYSTEM_TYPE nativeFileSystemType;	Native file system of type SYS_FS_FILE_SYSTEM_TYPE
const SYS_FS_FUNCTIONS * nativeFileSystemFunctions;	Pointer to the structure of type SYS_FS_FUNCTIONS which has the list of

Description

SYS_FS_REGISTRATION_TABLE structure

When the SYS FS layer is initialized, it has to know the type of native file system it has to support and the list of functions for native file system. The members of this structure can be initialized with suitable values and then passed on to [SYS_FS_Initialize](#) initialization function. Please refer to the example code provided for [SYS_FS_Initialize](#).

Remarks

None.

SYS_FS_RESULT Enumeration

Lists the various results of a file operation.

C

```
typedef enum {
    SYS_FS_RES_SUCCESS = 0,
    SYS_FS_RES_FAILURE = -1
} SYS_FS_RESULT;
```

Members

Members	Description
SYS_FS_RES_SUCCESS = 0	Operation succeeded
SYS_FS_RES_FAILURE = -1	Operation failed

Description

File operation result enum

This enumeration lists the various results of a file operation. When a file operation function is called from the application, and if the return type of the function is SYS_FS_RESULT, then the enumeration below specifies the possible values returned by the function.

Remarks

None.

SYS_FS_FILE_OPEN_ATTRIBUTES Enumeration

Lists the various attributes (modes) in which a file can be opened.

C

```
typedef enum {
    SYS_FS_FILE_OPEN_READ = 0,
    SYS_FS_FILE_OPEN_WRITE,
    SYS_FS_FILE_OPEN_APPEND,
    SYS_FS_FILE_OPEN_READ_PLUS,
    SYS_FS_FILE_OPEN_WRITE_PLUS,
    SYS_FS_FILE_OPEN_APPEND_PLUS
} SYS_FS_FILE_OPEN_ATTRIBUTES;
```

Members

Members	Description
SYS_FS_FILE_OPEN_READ = 0	reading the file = possible, if file exists. reading the file = file open returns error, if file does not exist. writing to the file = not possible. Write operation returns error
SYS_FS_FILE_OPEN_WRITE	reading the file = not possible. Read operation returns error. writing to the file = possible. If file exists, write happens from the beginning of the file, overwriting the existing content of the file. writing to the file = If file does not exist, a new file will be created and data will be written into the newly created file.
SYS_FS_FILE_OPEN_APPEND	reading the file = not possible. Read operation returns error writing to the file = possible. If file exists, write happens from the end of the file, preserving the existing content of the file. writing to the file = If file does not exist, a new file will be created and data will be written into the newly created file.

SYS_FS_FILE_OPEN_READ_PLUS	reading the file = possible, if file exists. reading the file = file open returns error, if file does not exist. writing to the file = possible, if file exists, starting from the beginning of the file (overwriting). writing to the file = file open returns error, if file does not exist.
SYS_FS_FILE_OPEN_WRITE_PLUS	reading the file = possible, if file exists. reading the file = If file does not exist, a new file will be created. writing to the file = possible. If file exists, write happens from the beginning of the file, overwriting the existing content of the file. writing to the file = If file does not exist, a new file will be created and data will be written into the newly created file.
SYS_FS_FILE_OPEN_APPEND_PLUS	reading the file = possible, if file exists. File read pointer will be moved to end of the file in this mode. reading the file = If file does not exist, a new file will be created. writing to the file = possible. If file exists, write happens from the end of the file, preserving the existing content of the file. writing to the file = If file does not exist, a new file will be created and data will be written into the newly created file.

Description

File open attributes

This enumeration lists the various attributes (modes) in which a file can be opened.

Remarks

None.

FAT_FS_MAX_LFN Macro

Maximum length of the Long File Name.

C

```
#define FAT_FS_MAX_LFN 255
```

Description

FAT File System LFN (Long File Name) max length

Defines the maximum length of file name during LFN selection. Set the value to 255.

Remarks

None.

FAT_FS_MAX_SS Macro

Lists the definitions for FAT file system sector size.

C

```
#define FAT_FS_MAX_SS 512
```

Description

FAT File System Sector size

Maximum sector size to be handled. Always set the value of sector size to 512

Remarks

None.

FAT_FS_USE_LFN Macro

Lists the definitions for FAT file system LFN selection.

C

```
#define FAT_FS_USE_LFN 1
```

Description

FAT File System LFN (long file name) selection

The FAT_FS_USE_LFN option switches the LFN support. Set the value to 1.

Remarks

None.

SYS_FS_FILE_SYSTEM_TYPE Enumeration

Enumerated data type identifying native file systems supported.

C

```
typedef enum {
    UNSUPPORTED_FS = 0,
    FAT,
    MPFS2
} SYS_FS_FILE_SYSTEM_TYPE;
```

Members

Members	Description
UNSUPPORTED_FS = 0	Unsupported File System
FAT	FAT FS native File system
MPFS2	MPFS2 native File system

Description

File System type

These enumerated values identify the native file system supported by the SYS FS.

Remarks

None.

SYS_FS_HANDLE Type

This type defines the file handle.

C

```
typedef uintptr_t SYS_FS_HANDLE;
```

Description

SYS FS File Handle

This type defines the file handle. File handle is returned by the File Open function on successful operation.

Remarks

None.

SYS_FS_HANDLE_INVALID Macro

Invalid file handle

C

```
#define SYS_FS_HANDLE_INVALID ((SYS_FS_HANDLE)(-1))
```

Description

SYS FS File Invalid Handle

This value defines the invalid file handle. Invalid file handle is returned on an unsuccessful File Open operation.

Remarks

None.

SYS_FS_FILE_DIR_ATTR Enumeration

Enumerated data type identifying the various attributes for file/directory.

C

```
typedef enum {
    SYS_FS_ATTR_RDO = 0x01,
    SYS_FS_ATTR_HID = 0x02,
    SYS_FS_ATTR_SYS = 0x04,
    SYS_FS_ATTR_VOL = 0x08,
    SYS_FS_ATTR_LFN = 0x0F,
    SYS_FS_ATTR_DIR = 0x10,
    SYS_FS_ATTR_ARC = 0x20,
    SYS_FS_ATTR_MASK = 0x3F
} SYS_FS_FILE_DIR_ATTR;
```

Members

Members	Description
SYS_FS_ATTR_RDO = 0x01	Read only
SYS_FS_ATTR_HID = 0x02	Hidden
SYS_FS_ATTR_SYS = 0x04	System
SYS_FS_ATTR_VOL = 0x08	Volume label
SYS_FS_ATTR_LFN = 0x0F	LFN entry
SYS_FS_ATTR_DIR = 0x10	Directory
SYS_FS_ATTR_ARC = 0x20	Archive
SYS_FS_ATTR_MASK = 0x3F	Mask of defined bits

Description

File or directory attribute

These enumerated values are the possible attributes for a file or directory.

Remarks

None.

SYS_FS_TIME Union

The structure to specify the time for a file or directory.

C

```
typedef union {
    struct discreteTime {
        unsigned second : 5;
        unsigned minute : 6;
        unsigned hour : 5;
        unsigned day : 5;
    }
```

```

    unsigned month : 4;
    unsigned year : 7;
}
struct timeDate {
    uint16_t time;
    uint16_t date;
}
uint32_t packedTime;
} SYS_FS_TIME;

```

Members

Members	Description
unsigned second : 5;	Second / 2 (0..29)
unsigned minute : 6;	Minute (0..59)
unsigned hour : 5;	Hour (0..23)
unsigned day : 5;	Day in month(1..31)
unsigned month : 4;	Month (1..12)
unsigned year : 7;	Year from 1980 (0..127)
uint16_t time;	Time (hour, min, seconds)
uint16_t date;	Date (year, month, day)
uint32_t packedTime;	Combined time information in a 32-bit value

Description

SYS FS File time structure

This structure holds the date and time to be used to set for a file or directory.

bits 31-25: Year from 1980 (0..127) bits 24-21: Month (1..12) bits 20-16: Day in month(1..31) bits 15-11: Hour (0..23) bits 10-5 : Minute (0..59) bits 4-0 : Seconds / 2 (0..29)

Remarks

None.

SYS_FS_FORMAT Enumeration

Specifies the partitioning rule.

C

```

typedef enum {
    SYS_FS_FORMAT_FDISK = 0,
    SYS_FS_FORMAT_SFD = 1
} SYS_FS_FORMAT;

```

Members

Members	Description
SYS_FS_FORMAT_FDISK = 0	Format disk with multiple partition
SYS_FS_FORMAT_SFD = 1	Format disk with single partition

Description

File formating partition rule

This type specifies the partitioning rule. When SYS_FS_FORMAT_FDISK format is specified, a primary partition occupying the entire disk space is created and then an FAT volume is created on the partition. When SYS_FS_FORMAT_SFD format is specified, the FAT volume starts from the first sector of the physical drive.

The SYS_FS_FORMAT_FDISK partitioning is usually used for hard disk, MMC, SDC, CFC and U Disk. It can divide a physical drive into one or more partitions with a partition table on the MBR. However Windows does not support multiple partition on the removable media. The SYS_FS_FORMAT_SFD is non-partitioned method. The FAT volume starts from the first sector on the physical drive without partition table. It is usually used for floppy disk, micro drive, optical disk, and super-floppy media.

SYS_FS_EVENT Enumeration

Identifies the possible file system events.

C

```
typedef enum {
    SYS_FS_EVENT_MOUNT,
    SYS_FS_EVENT_UNMOUNT,
    SYS_FS_EVENT_ERROR
} SYS_FS_EVENT;
```

Members

Members	Description
SYS_FS_EVENT_MOUNT	Media has been mounted successfully.
SYS_FS_EVENT_UNMOUNT	Media has been unmounted successfully.
SYS_FS_EVENT_ERROR	There was an error during the operation

Description

SYS FS Media Events

This enumeration identifies the possible events that can result from a file system.

Remarks

One of these values is passed in the "event" parameter of the event handling callback function that client registered with the file system by setting the event handler when media mount or unmount is completed.

SYS_FS_EVENT_HANDLER Type

Pointer to the File system Handler function.

C

```
typedef void (* SYS_FS_EVENT_HANDLER)(SYS_FS_EVENT event, void* eventData, uintptr_t context);
```

Returns

None.

Description

File System Event Handler function pointer

This data type defines the required function signature for the file system event handling callback function. A client must register a pointer to an event handling function whose function signature (parameter and return value types) match the types specified by this function pointer in order to receive event call backs from the file system.

Remarks

None.

Parameters

Parameters	Description
event	Identifies the type of event
eventData	Handle returned from the media operation requests
context	Value identifying the context of the application that registered the event handling function

SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE_INVALID Macro

Defines the invalid media block command handle.

C

```
#define SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE_INVALID SYS_MEDIA_BLOCK_COMMAND_HANDLE_INVALID
```

Description

Invalid media block command handle

This value defines invalid handle for the media block command. It is returned by read/write/erase routines when the request could not be taken.

Remarks

None.

SYS_FS_MEDIA_HANDLE_INVALID Macro

Defines the invalid media handle.

C

```
#define SYS_FS_MEDIA_HANDLE_INVALID DRV_HANDLE_INVALID
```

Description

Invalid media handle

This value defines invalid media handle. It is returned when the media registration is not successful.

Remarks

None.

SYS_FS_MEDIA_BLOCK_EVENT Enumeration

Identifies the possible events that can result from a request.

C

```
typedef enum {
    SYS_FS_MEDIA_EVENT_BLOCK_COMMAND_COMPLETE = SYS_MEDIA_EVENT_BLOCK_COMMAND_COMPLETE,
    SYS_FS_MEDIA_EVENT_BLOCK_COMMAND_ERROR = SYS_MEDIA_EVENT_BLOCK_COMMAND_ERROR
} SYS_FS_MEDIA_BLOCK_EVENT;
```

Members

Members	Description
SYS_FS_MEDIA_EVENT_BLOCK_COMMAND_COMPLETE = SYS_MEDIA_EVENT_BLOCK_COMMAND_COMPLETE	Block operation has been completed successfully.
SYS_FS_MEDIA_EVENT_BLOCK_COMMAND_ERROR = SYS_MEDIA_EVENT_BLOCK_COMMAND_ERROR	There was an error during the block operation

Description

SYS FS Media Events

This enumeration identifies the possible events that can result from a media.

Remarks

One of these values is passed in the "event" parameter of the event handling callback function that client registered with the driver by setting the event handler when a block request is completed.

SYS_FS_MEDIA_COMMAND_STATUS Enumeration

The enumeration for status of buffer

C

```
typedef enum {
    SYS_FS_MEDIA_COMMAND_COMPLETED = SYS_MEDIA_COMMAND_COMPLETED,
    SYS_FS_MEDIA_COMMAND_QUEUED = SYS_MEDIA_COMMAND_QUEUED,
    SYS_FS_MEDIA_COMMAND_IN_PROGRESS = SYS_MEDIA_COMMAND_IN_PROGRESS,
    SYS_FS_MEDIA_COMMAND_UNKNOWN = SYS_MEDIA_COMMAND_UNKNOWN
} SYS_FS_MEDIA_COMMAND_STATUS;
```

Members

Members	Description
SYS_FS_MEDIA_COMMAND_COMPLETED = SYS_MEDIA_COMMAND_COMPLETED	Done OK and ready
SYS_FS_MEDIA_COMMAND_QUEUED = SYS_MEDIA_COMMAND_QUEUED	Scheduled but not started
SYS_FS_MEDIA_COMMAND_IN_PROGRESS = SYS_MEDIA_COMMAND_IN_PROGRESS	Currently being in transfer
SYS_FS_MEDIA_COMMAND_UNKNOWN = SYS_MEDIA_COMMAND_UNKNOWN	Unknown buffer

Description

Status of buffer

This enumeration contains the various status of buffer.

Remarks

None.

SYS_FS_MEDIA_FUNCTIONS Structure

Structure of function pointers for media driver

C

```
typedef struct {
    bool (* mediaStatusGet)(DRV_HANDLE handle);
    SYS_FS_MEDIA_GEOMETRY * (* mediaGeometryGet)(const DRV_HANDLE handle);
    void (* sectorRead)(DRV_HANDLE clientHandle, SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE * commandHandle, void * buffer, uint32_t blockStart, uint32_t nBlock);
    void (* sectorWrite)(const DRV_HANDLE handle, SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE * commandHandle, void * sourceBuffer, uint32_t blockStart, uint32_t nBlock);
    void (* eventHandlerset)(DRV_HANDLE handle, const void * eventHandler, const uintptr_t context);
    SYS_FS_MEDIA_COMMAND_STATUS (* commandStatusGet)(DRV_HANDLE handle,
    SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE commandHandle);
    void (* Read)(DRV_HANDLE clientHandle, SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE * commandHandle, void * buffer, uint32_t blockStart, uint32_t nBlock);
    uintptr_t (* addressGet)(const DRV_HANDLE hClient);
    void (* erase)(const DRV_HANDLE handle, SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE * commandHandle, uint32_t blockStart, uint32_t nBlock);
    DRV_HANDLE (* open)(SYS_MODULE_INDEX index, DRV_IO_INTENT intent);
    void (* close)(DRV_HANDLE client);
    void (* tasks)(SYS_MODULE_OBJ obj);
} SYS_FS_MEDIA_FUNCTIONS;
```

Members

Members	Description
bool (* mediaStatusGet)(DRV_HANDLE handle);	To obtains status of media
SYS_FS_MEDIA_GEOMETRY * (* mediaGeometryGet)(const DRV_HANDLE handle);	Function to get media geometry
void (* sectorRead)(DRV_HANDLE clientHandle, SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE * commandHandle, void * buffer, uint32_t blockStart, uint32_t nBlock);	Function for sector read
void (* sectorWrite)(const DRV_HANDLE handle, SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE * commandHandle, void * sourceBuffer, uint32_t blockStart, uint32_t nBlock);	Function for sector write
void (* eventHandlerset)(DRV_HANDLE handle, const void * eventHandler, const uintptr_t context);	Function register the event handler with media
SYS_FS_MEDIA_COMMAND_STATUS (* commandStatusGet)(DRV_HANDLE handle, SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE commandHandle);	Function to obtain the command status
void (* Read)(DRV_HANDLE clientHandle, SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE * commandHandle, void * buffer, uint32_t blockStart, uint32_t nBlock);	Function to read certain bytes from the media
uintptr_t (* addressGet)(const DRV_HANDLE hClient);	Function to obtain the address of the media (to be used for NVM only)
DRV_HANDLE (* open)(SYS_MODULE_INDEX index, DRV_IO_INTENT intent);	Function to open the media driver
void (* close)(DRV_HANDLE client);	Function to close the media
void (* tasks)(SYS_MODULE_OBJ obj);	Task function of the media

Description

Media function pointers

This structure contains the definition for functions of media driver, which is registered with the media manager. In future, if any new driver needs to be registered with the media manager (say, to act as a media for file system), the new driver should have implemented all these functions.

Remarks

None.

SYS_FS_MEDIA_MOUNT_DATA Structure

Structure to obtain the device and mount name of media

C

```
typedef struct {
    const char* mountName;
    const char* devName;
    SYS_FS_MEDIA_TYPE mediaType;
    SYS_FS_FILE_SYSTEM_TYPE fsType;
} SYS_FS_MEDIA_MOUNT_DATA;
```

Members

Members	Description
const char* mountName;	Media Mount Name

const char* devName;	Media Device Name
SYS_FS_MEDIA_TYPE mediaType;	Media Type
SYS_FS_FILE_SYSTEM_TYPE fsType;	File system type on Media

Description

Media Mount Data

This structure is an input for the media manager to auto mount the media when the auto mount feature is enabled.

Remarks

None.

SYS_FS_MEDIA_PROPERTY Enumeration

Contains information of property of a media.

C

```
typedef enum {
    SYS_FS_MEDIA_SUPPORTS_BYTE_WRITES = SYS_MEDIA_SUPPORTS_BYTE_WRITES,
    SYS_FS_MEDIA_SUPPORTS_READ_ONLY = SYS_MEDIA_SUPPORTS_READ_ONLY,
    SYS_FS_MEDIA_SUPPORTS_ONE_TIME_PROGRAMMING = SYS_MEDIA_SUPPORTS_ONE_TIME_PROGRAMMING,
    SYS_FS_MEDIA_READ_IS_BLOCKING = SYS_MEDIA_READ_IS_BLOCKING,
    SYS_FS_MEDIA_WRITE_IS_BLOCKING = SYS_MEDIA_WRITE_IS_BLOCKING
} SYS_FS_MEDIA_PROPERTY;
```

Members

Members	Description
SYS_FS_MEDIA_SUPPORTS_BYTE_WRITES = SYS_MEDIA_SUPPORTS_BYTE_WRITES	Media supports Byte Write
SYS_FS_MEDIA_SUPPORTS_READ_ONLY = SYS_MEDIA_SUPPORTS_READ_ONLY	Media supports only Read operation
SYS_FS_MEDIA_SUPPORTS_ONE_TIME_PROGRAMMING = SYS_MEDIA_SUPPORTS_ONE_TIME_PROGRAMMING	Media supports OTP (One Time Programming)
SYS_FS_MEDIA_READ_IS_BLOCKING = SYS_MEDIA_READ_IS_BLOCKING	Read in blocking
SYS_FS_MEDIA_WRITE_IS_BLOCKING = SYS_MEDIA_WRITE_IS_BLOCKING	Write is blocking

Description

SYS FS Media Property Structure

This structure contains the information of property of a media device.

Remarks

For a device, if multiple properties are applicable, they can be ORed together and used.

SYS_FS_MEDIA_STATE Enumeration

The enumeration for state of media.

C

```
typedef enum {
    SYS_FS_MEDIA_STATE_DEREGISTERED = 0,
    SYS_FS_MEDIA_STATE_REGISTERED,
    SYS_FS_MEDIA_CHECK_ATTACH_STATUS,
    SYS_FS_MEDIA_READ_FIRST_SECTOR,
    SYS_FS_MEDIA_ANALYZE_FS
} SYS_FS_MEDIA_STATE;
```

Members

Members	Description
SYS_FS_MEDIA_STATE_DEREGISTERED = 0	Media is de registered with the media manager
SYS_FS_MEDIA_STATE_REGISTERED	Media is registered with the media manager
SYS_FS_MEDIA_CHECK_ATTACH_STATUS	Check the attach/detach status of the Media
SYS_FS_MEDIA_READ_FIRST_SECTOR	Read the first sector of the media
SYS_FS_MEDIA_ANALYZE_FS	Analyze the FS

Description

State of media

The media manager task picks a disk for analysis and takes it through a number of states. This enumeration mentions the state of the media.

Remarks

None.

SYS_FS_MEDIA_STATUS Enumeration

The state of media.

C

```
typedef enum {
    SYS_FS_MEDIA_DETACHED = SYS_MEDIA_DETACHED,
    SYS_FS_MEDIA_ATTACHED = SYS_MEDIA_ATTACHED
} SYS_FS_MEDIA_STATUS;
```

Members

Members	Description
SYS_FS_MEDIA_DETACHED = SYS_MEDIA_DETACHED	Media is detached
SYS_FS_MEDIA_ATTACHED = SYS_MEDIA_ATTACHED	Media is attached

Description

Status of media

This enumeration states if the media is attached or not

Remarks

None.

SYS_FS_MEDIA_TYPE Enumeration

The enumeration for type of media.

C

```
typedef enum {
    SYS_FS_MEDIA_TYPE_NVM,
    SYS_FS_MEDIA_TYPE_MSD,
    SYS_FS_MEDIA_TYPE_SD_CARD,
    SYS_FS_MEDIA_TYPE_RAM,
    SYS_FS_MEDIA_TYPE_SPIFLASH
} SYS_FS_MEDIA_TYPE;
```

Members

Members	Description
SYS_FS_MEDIA_TYPE_NVM	Media is of type NVM (internal flash (non volatile) memory)
SYS_FS_MEDIA_TYPE_MSD	Media is of type mass storage device
SYS_FS_MEDIA_TYPE_SD_CARD	Media is of type SD card
SYS_FS_MEDIA_TYPE_RAM	Media is of type RAM
SYS_FS_MEDIA_TYPE_SPIFLASH	Media is of type SPI Flash

Description

Type of media

This enumeration is for the type of media registered with the media manager.

Remarks

None.

SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE Type

Handle identifying block commands of the media.

C

```
typedef SYS_MEDIA_BLOCK_COMMAND_HANDLE SYS_FS_MEDIA_BLOCK_COMMAND_HANDLE;
```

Description

SYS FS Media Block Command Handle

A block command handle is returned by a call to the Read, Write, or Erase functions. This handle allows the application to track the completion of the operation. The handle is returned back to the client by the "event handler callback" function registered with the driver.

The handle assigned to a client request expires when the client has been notified of the completion of the operation (after event handler function that notifies the client returns) or after the buffer has been retired by the driver if no event handler callback was set.

Remarks

None.

SYS_FS_MEDIA_EVENT_HANDLER Type

Pointer to the Media Event Handler function.

C

```
typedef SYS_MEDIA_EVENT_HANDLER SYS_FS_MEDIA_EVENT_HANDLER;
```

Returns

None.

Description

Media Event Handler function pointer

This data type defines the required function signature for the media event handling callback function. A client must register a pointer to an event handling function whose function signature (parameter and return value types) match the types specified by this function pointer in order to receive event calls back from the driver.

Remarks

None.

Parameters

Parameters	Description
event	Identifies the type of event
commandHandle	Handle returned from the media operation requests
context	Value identifying the context of the application that registered the event handling function

SYS_FS_MEDIA_GEOMETRY Type

Contains all the geometrical information of a media device.

C

```
typedef SYS_MEDIA_GEOMETRY SYS_FS_MEDIA_GEOMETRY;
```

Description

SYS FS Media Device Geometry

This structure contains all the geometrical information of a media device. the structure also has property of the media like media is one time programmable (OTP) or Read Only etc.

Remarks

A memory device can have multiple erase block regions. Sum of all the regions is the total memory size of the device.

SYS_FS_MEDIA_HANDLE Type

Handle identifying the media registered with the media manager.

C

```
typedef uintptr_t SYS_FS_MEDIA_HANDLE;
```

Description

SYS FS Media Handle

The media drivers register the media services with the media manager by calling the [SYS_FS_MEDIA_MANAGER_Register](#) function. On successful registration a media handle is returned which can be used by the media driver to deregister the services from the media manager layer.

Remarks

None.

SYS_FS_MEDIA_REGION_GEOMETRY Type

Contains information of a sys media region.

C

```
typedef SYS_MEDIA_REGION_GEOMETRY SYS_FS_MEDIA_REGION_GEOMETRY;
```

Description

SYS FS Media Region Geometry Structure

This structure contains the information of a sys media region.

Remarks

A media can have multiple regions. Sum of size of all the regions is the total memory size of the media. Each region is further divided into blocks of identical size.

SYS_FS_VOLUME_PROPERTY Structure

Structure to obtain the property of volume

C

```
typedef struct _SYS_FS_VOLUME_PROPERTY {
    unsigned int volNumber;
    SYS_FS_FILE_SYSTEM_TYPE fsType;
} SYS_FS_VOLUME_PROPERTY;
```

Members

Members	Description
unsigned int volNumber;	Volume
SYS_FS_FILE_SYSTEM_TYPE fsType;	File system type

Description

Volume property

This structure is passed by sys_fs layer to know the property of a volume. The function "["SYS_FS_MEDIA_MANAGER_VolumePropertyGet"](#)" is used for the call.

Remarks

None.

Interrupt System Service Library Help

This section describes the Interrupt System Service Library.

Introduction

This library provides an interface to manage and control interrupt controllers.

Description

This library provides a low-level abstraction of the Interrupt System Service Library that is available on the Microchip family micro-controllers with a convenient C language interface. It can be used to simplify low-level access to the module without the necessity of interacting directly with the module's registers/PLIB, thereby hiding differences from one micro-controller variant to another.

Library Interface

a) Global Interrupt Management Functions

	Name	Description
≡	SYS_INT_Disable	Disable Global Interrupt
≡	SYS_INT_Enable	Enable Global Interrupt
≡	SYS_INT_IsEnabled	Returns the interrupt controller's global enable/disable status.
≡	SYS_INT_Restore	Restores the interrupt controller to the state specified in the parameter.
≡	SYS_INT_SourceRestore	Restores an interrupt vector to the state specified in the parameter.

b) Interrupt Source Management Functions

	Name	Description
≡	SYS_INT_SourceDisable	Disables the specified interrupt source.
≡	SYS_INT_SourceEnable	Enables the specified interrupt source.

≡	SYS_INT_SourceIsEnabled	Gets the enable/disable status of the specified interrupt source.
≡	SYS_INT_SourceStatusGet	Gets the pending status of the specified interrupt source.
≡	SYS_INT_SourceStatusSet	Sets the pending status of the specified interrupt source manually.
≡	SYS_INT_SourceStatusClear	Clears the pending status of the specified interrupt source.

c) Data Types and Constants

	Name	Description
	INT_SOURCE	Defines the data type for all the interrupt sources associated with the interrupt controller of the device.

Description

This section describes the APIs of the Interrupt System Service Library.

Refer to each section for a detailed description.

a) Global Interrupt Management Functions

SYS_INT_Disable Function

Disable Global Interrupt

C

```
bool SYS_INT_Disable();
```

Returns

This function disables the global interrupt and return the state of global interrupt prior to disabling it. The state information will be used to restore the global interrupt to the original state after the critical section.

- true - Global Interrupt is enabled
- false - Global Interrupt is disabled

Description

This function disables global interrupt and returns the state of the global interrupt prior to disabling it. When global interrupt is disabled, only NMI and HardFault exceptions are allowed. This may be used to disable global interrupt during critical section and restore the global interrupt state after the critical section.

Remarks

Returned status can be passed to [SYS_INT_Restore](#) to restore the previous global interrupt status (whether it was enabled or disabled).

Preconditions

None.

Example

```
bool interruptState;

// Save global interrupt state and disable interrupt
interruptState = SYS_INT_Disable();

// Critical Section

// Restore interrupt state
SYS_INT_Restore(interruptState)
```

Function

```
bool SYS_INT_Disable( void )
```

SYS_INT_Enable Function

Enable Global Interrupt

C

```
void SYS_INT_Enable();
```

Returns

None.

Description

This function enables global interrupt.

Remarks

None.

Preconditions

None

Example

```
SYS_INT_Enable();
```

Function

```
void SYS_INT_Enable( void )
```

SYS_INT_IsEnabled Function

Returns the interrupt controller's global enable/disable status.

C

```
bool SYS_INT_IsEnabled();
```

Returns

- true - Global Interrupt is enabled.
- false - Global Interrupt is disabled.

Description

This function returns global interrupt enable status.

Remarks

None.

Preconditions

None.

Example

```
if(true == SYS_INT_IsEnabled())
{
    // Global Interrupt is enabled
}
```

Function

```
bool SYS_INT_IsEnabled( void )
```

SYS_INT_Restore Function

Restores the interrupt controller to the state specified in the parameter.

C

```
void SYS_INT_Restore(bool state);
```

Returns

None.

Description

This function restores the interrupt controller to the state specified in the parameters.

Remarks

None.

Preconditions

SYS_INT_Disable must have been called to get previous state of the global interrupt.

Example

```
bool interruptState;  
  
// Save global interrupt state and disable interrupt  
interruptState = SYS_INT_Disable();  
  
// Critical Section  
  
// Restore interrupt state  
SYS_INT_Restore(interruptState)
```

Function

```
void SYS_INT_Restore( bool state )
```

SYS_INT_SourceRestore Function

Restores an interrupt vector to the state specified in the parameter.

C

```
void SYS_INT_SourceRestore( INT_SOURCE source, bool aState );
```

Returns

None.

Description

This function restores the interrupt vector to the state specified in the parameters.

Remarks

None.

Preconditions

SYS_INT_SourceDisable must have been called previously to get the state value.

Example

```
bool aState;  
  
// Save interrupt vector state and disable interrupt
```

```

aState = SYS_INT_SourceDisable( aSrcId ) ;

// Critical Section

// Restore interrupt vector state
SYS_INT_SourceRestore( aSrcId, aState )

```

Function

void SYS_INT_SourceRestore(**INT_SOURCE** source, bool state)

b) Interrupt Source Management Functions

SYS_INT_SourceDisable Function

Disables the specified interrupt source.

C

```
bool SYS_INT_SourceDisable( INT_SOURCE source );
```

Returns

- true - Interrupt line was enabled.
- false - Interrupt line was disabled.

Description

This function returns the current interrupt enable/disable status and disables the specified interrupt source/line at the interrupt controller level.

Remarks

If the corresponding module level interrupts are enabled and triggered, the triggers will be ignored at interrupt controller. For example, USART0 doesn't cause interrupt unless both the interrupt controller source/line and USART0 module level interrupt for TX or RX or Error are enabled.

Preconditions

None.

Example

```

bool usart0Int = false;
usart0Int = SYS_INT_SourceDisable(USART0_IRQn);

```

Parameters

Parameters	Description
source	Interrupt source/line available at interrupt controller.

Function

bool SYS_INT_SourceDisable(**INT_SOURCE** source)

SYS_INT_SourceEnable Function

Enables the specified interrupt source.

C

```
void SYS_INT_SourceEnable( INT_SOURCE source );
```

Returns

None.

Description

This function enables the specified interrupt source/line at the interrupt controller level.

Remarks

The corresponding module level interrupts must be enabled to trigger the specified interrupt source/line. For example, USART0 interrupt enable at interrupt controller level is not triggered unless USART0 module level interrupt for TXRDY or RXRDY or Error interrupts are not enabled.

Preconditions

None.

Example

```
SYS_INT_SourceEnable(USART0_IRQn);
```

Parameters

Parameters	Description
source	Interrupt source/line available at interrupt controller.

Function

```
void SYS_INT_SourceEnable( INT_SOURCE source )
```

SYS_INT_SourceIsEnabled Function

Gets the enable/disable status of the specified interrupt source.

C

```
bool SYS_INT_SourceIsEnabled(INT_SOURCE source);
```

Returns

- true - Interrupt line is enabled.
- false - Interrupt line is disabled.

Description

This function returns the enable/disable status of the specified interrupt source/line at the interrupt controller level.

Remarks

Unlike [SYS_INT_Disable](#), this function just returns the status and doesn't disable the interrupt line.

Preconditions

None.

Example

```
bool usart0Int = false;
usart0Int = SYS_INT_SourceIsEnabled(USART0_IRQn);
```

Parameters

Parameters	Description
source	Interrupt source/line available at interrupt controller.

Function

```
bool SYS_INT_SourceIsEnabled( INT_SOURCE source )
```

SYS_INT_SourceStatusGet Function

Gets the pending status of the specified interrupt source.

C

```
bool SYS_INT_SourceStatusGet(INT_SOURCE source);
```

Returns

- true - Interrupt status is pending.
- false - Interrupt status is not pending.

Description

This function returns the pending status of the specified interrupt source at the interrupt controller level.

Remarks

Interrupt pending status may get cleared automatically once the corresponding interrupt vector executes on some devices.

Preconditions

None.

Example

```
bool usart0IntStatus = SYS_INT_SourceStatusGet(USART0_IRQn);
```

Parameters

Parameters	Description
source	Interrupt source/line available at interrupt controller.

Function

```
bool SYS_INT_SourceStatusGet( INT_SOURCE source )
```

SYS_INT_SourceStatusSet Function

Sets the pending status of the specified interrupt source manually.

C

```
void SYS_INT_SourceStatusSet(INT_SOURCE source);
```

Returns

None.

Description

This function manually sets the pending status of the specified interrupt source at the interrupt controller level. This triggers interrupt controller for a specified source even though the interrupt condition has not met at hardware.

Remarks

This feature may not be supported by some devices.

Preconditions

None.

Example

```
//Trigger USART0 ISR handler manually
SYS_INT_SourceStatusSet(USART0_IRQn);
```

Parameters

Parameters	Description
source	Interrupt source/line available at interrupt controller.

Function

```
void SYS_INT_SourceStatusSet( INT_SOURCE source )
```

SYS_INT_SourceStatusClear Function

Clears the pending status of the specified interrupt source.

C

```
void SYS_INT_SourceStatusClear( INT_SOURCE source );
```

Returns

None.

Description

This function clears the pending status of the specified interrupt source at the interrupt controller level. It is ignored if the interrupt condition has already been cleared in hardware.

Remarks

None.

Preconditions

None.

Example

```
//Clear a pending interrupt.
SYS_INT_SourceStatusClear(USART0_IRQn);
```

Parameters

Parameters	Description
source	Interrupt source/line available at interrupt controller.

Function

```
void SYS_INT_SourceStatusClear( INT_SOURCE source )
```

c) Data Types and Constants

INT_SOURCE Type

Defines the data type for all the interrupt sources associated with the interrupt controller of the device.

C

```
typedef IRQn_Type INT_SOURCE;
```

Description

Interrupt Sources

This data type can be used with interface functions to enable, disable, set, clear and to get status of any particular interrupt source.

Remarks

This data type is defined using the CMSIS data type that defines the interrupt sources set available.

Ports System Service Library Help

This section describes the Ports System Service Library.

Introduction

This library provides an interface to manage and control general purpose input or output ports on the Microchip families of microcontrollers.

Description

Ports System service abstract different general purpose input output (GPIO) modules present on Microchip family of devices. it provides a common interface to use GPIO across all the 32 bit Microchip devices.

Library Interface

a) Port Management Functions

	Name	Description
≡	SYS_PORT_PinClear	Clears the selected pin.
≡	SYS_PORT_PinSet	Sets the selected pin.
≡	SYS_PORT_PinToggle	Toggles the selected pin.
≡	SYS_PORT_PinRead	Read the selected pin value.
≡	SYS_PORT_PinLatchRead	Read the value driven on the selected pin.
≡	SYS_PORT_PinWrite	Writes to the selected pin.
≡	SYS_PORT_PinInputEnable	Enables selected IO pin as input.
≡	SYS_PORT_PinOutputEnable	Enables selected IO pin as output.

b) Data Types and Constants

	Name	Description
	SYS_PORT	Identifies the available Port Channels.
	SYS_PORT_PIN	Identifies the available port pins.

Description

This section describes the APIs of the Ports System Service Library.

Refer to each section for a detailed description.

a) Port Management Functions

SYS_PORT_PinClear Function

Clears the selected pin.

C

```
static inline void SYS_PORT_PinClear(SYS_PORT_PIN pin);
```

Returns

None.

Description

This function drives '0' on the selected I/O line/pin.

Remarks

None.

Preconditions

None.

Example

```
SYS_PORT_PinClear(SYS_PORT_PIN_PB3);
```

Parameters

Parameters	Description
pin	One of the IO pins from the enum SYS_PORT_PIN

Function

```
void SYS_PORT_PinClear( SYS_PORT_PIN pin)
```

SYS_PORT_PinSet Function

Sets the selected pin.

C

```
static inline void SYS_PORT_PinSet(SYS_PORT_PIN pin);
```

Returns

None.

Description

This function drives '1' on the selected I/O line/pin.

Remarks

None.

Preconditions

None.

Example

```
SYS_PORT_PinSet(SYS_PORT_PIN_PB3);
```

Parameters

Parameters	Description
pin	One of the IO pins from the enum SYS_PORT_PIN

Function

```
void SYS_PORT_PinSet( SYS_PORT_PIN pin)
```

SYS_PORT_PinToggle Function

Toggles the selected pin.

C

```
static inline void SYS_PORT_PinToggle(SYS_PORT_PIN pin);
```

Returns

None.

Description

This function toggles/inverts the value on the selected I/O line/pin.

Remarks

None.

Preconditions

Port Initialization must have been done using appropriate Initialize API call.

Example

```
SYS_PORT_PinToggle(SYS_PORT_PIN_PB3);
```

Parameters

Parameters	Description
pin	One of the IO pins from the enum SYS_PORT_PIN

Function

```
void SYS_PORT_PinToggle( SYS_PORT_PIN pin)
```

SYS_PORT_PinRead Function

Read the selected pin value.

C

```
static inline bool SYS_PORT_PinRead(SYS_PORT_PIN pin);
```

Returns

Returns the read value of the selected I/O pin.

Description

This function reads the selected pin value. it reads the value regardless of pin configuration, whether uniquely as an input, or driven by the PIO Controller, or driven by peripheral.

Remarks

To read the latched value on this pin, [SYS_PORT_PinLatchRead](#) API should be used.

Preconditions

Reading the I/O line levels requires the clock of the PIO Controller to be enabled, otherwise this API reads the levels present on the I/O line at the time the clock was disabled.

Example

```
bool value;
value = SYS_PORT_PinRead(SYS_PORT_PIN_PB3);
```

Parameters

Parameters	Description
pin	One of the IO pins from the enum SYS_PORT_PIN

Function

```
bool SYS_PORT_PinRead( SYS_PORT_PIN pin)
```

SYS_PORT_PinLatchRead Function

Read the value driven on the selected pin.

C

```
static inline bool SYS_PORT_PinLatchRead(SYS_PORT_PIN pin);
```

Returns

Returns the value driven on the selected I/O pin.

Description

This function reads the data driven on the selected I/O line/pin. Whatever data is written/driven on I/O line by using any of the PORTS APIs, will be read by this API.

Remarks

To read actual pin value, [SYS_PORT_PinRead](#) API should be used.

Preconditions

None.

Example

```
bool value;  
value = SYS_PORT_PinLatchRead(SYS_PORT_PIN_PB3);
```

Parameters

Parameters	Description
pin	One of the IO pins from the enum SYS_PORT_PIN

Function

```
bool SYS_PORT_PinLatchRead ( SYS_PORT_PIN pin )
```

SYS_PORT_PinWrite Function

Writes to the selected pin.

C

```
static inline void SYS_PORT_PinWrite(SYS_PORT_PIN pin, bool value);
```

Returns

None.

Description

This function writes/drives the "value" on the selected I/O line/pin.

Remarks

None.

Preconditions

Port Initialization must have been done using appropriate Initialize API call.

Example

```
SYS_PORT_PinWrite(SYS_PORT_PIN_PB3, true);
```

Parameters

Parameters	Description
pin	One of the IO pins from the enum SYS_PORT_PIN
value	value to be written on the selected pin: <ul style="list-style-type: none"> • true: set pin to high (1). • false: clear pin to low (0).

Function

```
void SYS_PORT_PinWrite( SYS\_PORT\_PIN pin, bool value)
```

SYS_PORT_PinInputEnable Function

Enables selected IO pin as input.

C

```
static inline void SYS_PORT_PinInputEnable(SYS\_PORT\_PIN pin);
```

Returns

None.

Description

This function enables selected IO pin as input.

Remarks

None.

Preconditions

None.

Example

```
SYS_PORT_PinInputEnable(SYS\_PORT\_PIN\_PB3);
```

Parameters

Parameters	Description
pin	One of the IO pins from the enum SYS_PORT_PIN

Function

```
void SYS_PORT_PinInputEnable( SYS\_PORT\_PIN pin)
```

SYS_PORT_PinOutputEnable Function

Enables selected IO pin as output.

C

```
static inline void SYS_PORT_PinOutputEnable(SYS\_PORT\_PIN pin);
```

Returns

None.

Description

This function enables selected IO pin as output.

Remarks

None.

Preconditions

None.

Example

```
SYS_PORT_PinOutputEnable(SYS_PORT_PIN_PB3);
```

Parameters

Parameters	Description
pin	One of the IO pins from the enum SYS_PORT_PIN

Function

```
void SYS_PORT_PinOutputEnable( SYS\_PORT\_PIN pin)
```

b) Data Types and Constants

SYS_PORT Enumeration

Identifies the available Port Channels.

C

```
typedef enum {
    SYS_PORT_A,
    SYS_PORT_B,
    SYS_PORT_C,
    SYS_PORT_D,
    SYS_PORT_E
} SYS_PORT;
```

Members

Members	Description
SYS_PORT_A	Port A Pins
SYS_PORT_B	Port B Pins
SYS_PORT_C	Port C Pins
SYS_PORT_D	Port D Pins
SYS_PORT_E	Port E Pins

Description

Sys Port

This enumeration identifies the available Port Channels.

Remarks

The caller should not rely on the specific numbers assigned to any of these values as they may change from one processor to the next.

Not all ports are available on all devices. Refer to the specific device data sheet to determine which ports are supported.

SYS_PORT_PIN Enumeration

Identifies the available port pins.

C

```
typedef enum {
    SYS_PORT_PIN_PA0
```

```
 } SYS_PORT_PIN;
```

Description

Sys Port Pins

This enumeration identifies the available port pins.

Remarks

The caller should not rely on the specific numbers assigned to any of these values as they may change from one processor to the next.

Not all pins are available on all devices. Refer to the specific device data sheet to determine which pins are supported.

Time System Service Library Help

This section describes the Time System Service Library.

Introduction

This library provides interfaces to manage alarms and/or delays.

Description

The Timer System Service Library is capable of providing periodic or one-shot alarm and delays to the user. It uses a hardware timer peripheral library for providing its timing services. The hardware timer must support compare mode operation.

Key Features:

- Periodic notifications
- One-shot/single notification
- Delays
- Tickless implementation - Instead of getting interrupted from the hardware timer on every configured tick, it manages the hardware timer to generate an interrupt only when required and at appropriate times.

Using the Library

This topic describes the basic architecture of the Time System Service Library and provides information on how it works.

Description

The Time System Service provides alarm and delay functionalities to multiple clients. In addition, it also provides APIs to read the counter value which can be used to measure the time period between two events.

Alarm

- For single/one-shot alarms, the application must register a callback. Once the requested time period elapses, the application is notified by calling the registered callback. After the callback is given, the internal timer object is destroyed by Time System Service, making it available for application to request new alarms/delays.
- For periodic alarms, the application can either register a callback or can choose to poll the status of the alarm. Once the requested time period elapses, the application is notified by calling the callback if registered by the application. In case the application wants to poll the status of the alarm it can do so by calling the status API provided by the library.
- Application can use the delay functionality by using the delay related APIs and then polling the status of the requested delay. Calling the status API after the delay has expired will destroy the internal timer object making it available for new alarms/delays.
- The library also provides counter functionality, that can be used by the application to measure the time elapsed between the two events. The counter functionality does not require a dedicated timer object and is always available.

Abstraction Model

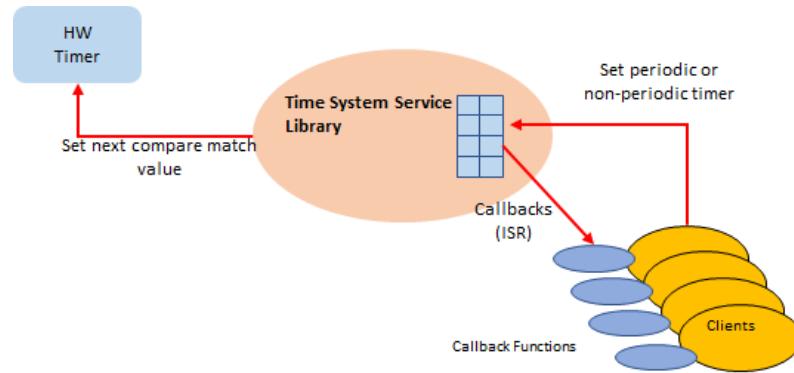
This section describes the abstraction model of the Time System Service.

Description

The Time System Service library provides an abstraction to the hardware timer to provide following functionalities.

- Periodic Callback
- One Shot/Single Callback
- Delays

The following diagram depicts the Time System Service abstraction model.



How the Library Works

This section describes the basic architecture of the Time System Service Library and provides information on its implementation.

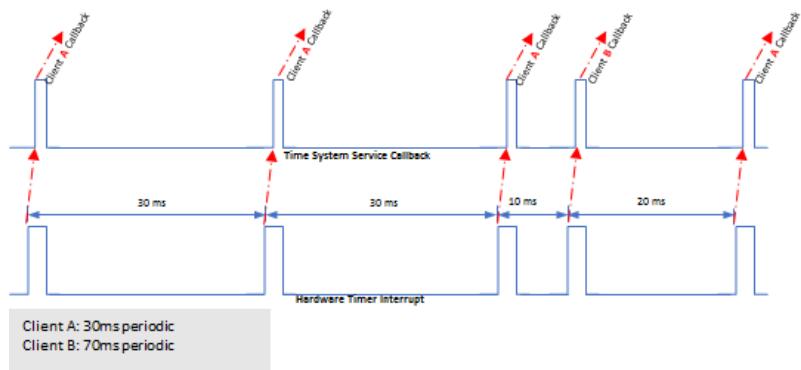
Description

The tick-less implementation reduces the overheads of servicing the unneeded hardware timer interrupt on every tick. The tick-less implementation can also provide higher resolution compared to a tick based implementation, as there is no fixed tick rate.

Execution Flow

- The Time System Service registers a callback with the underlying hardware timer peripheral library
- Depending on the alarm/delay time periods requested by various clients, the implementation manages the hardware timer such that a compare interrupt is generated only when needed and at appropriate times
 - This is achieved by maintaining a sorted list of timing requested by different clients such that the head of the list always indicates the time after which the hardware timer must interrupt and notify the Timer System Service
- Inside the Time System Service callback, the list is updated and a callback is given to the client for which the alarm/delay has expired

The following diagram shows how the tick-less implementation reduces the number of hardware interrupts. In this example, two clients - Client A and Client B requests a periodic alarm every 30 ms and 70 ms respectively.

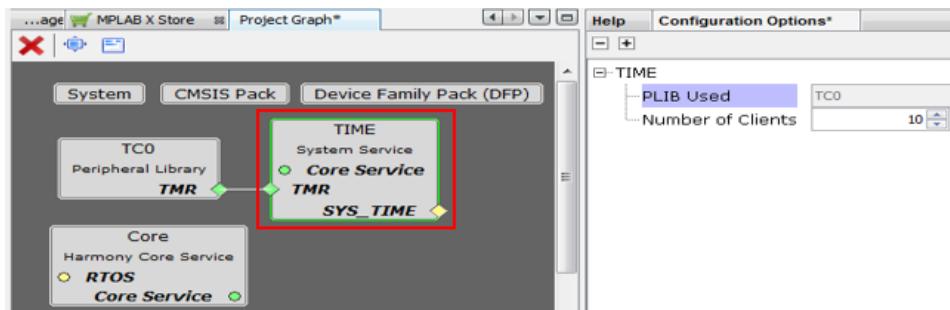


Configuring the Library

This section provides information on how to configure the Time System Service library.

Description

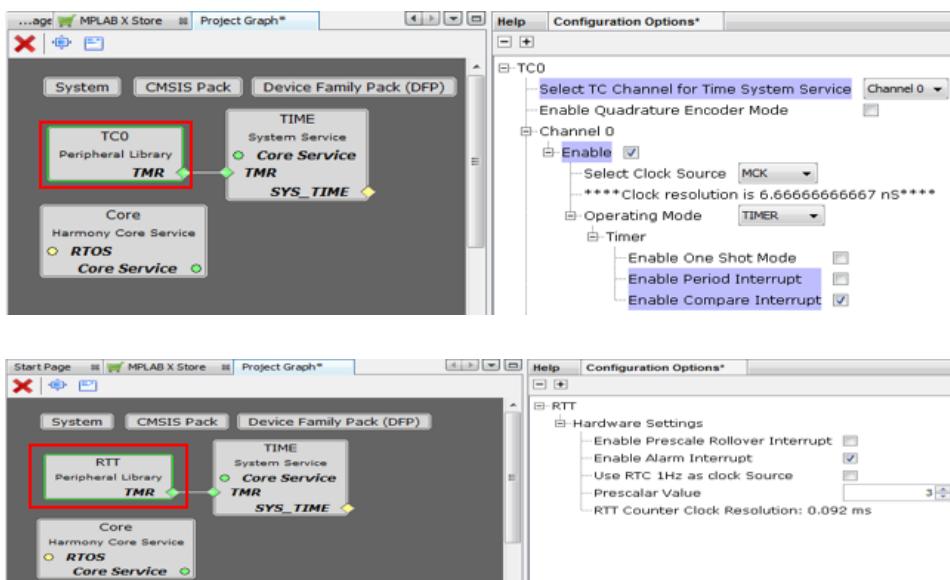
The Time System Service library should be configured through the MHC. The following figure shows the MHC configuration window for configuring the Time System Service and a brief description of various configuration options.



Configuration Options:

- **PLIB Used**
 - Indicates the hardware Timer Peripheral Library instance used by the Time System Service
- **Number of Clients**
 - Indicates the maximum number of alarm/delay requests that can be active at any given time.

The hardware Timer Peripheral library is automatically configured for the correct mode of operation when it is connected to the Time System Service as shown in the below snapshots for TC instance 0 and RTT.



Building the Library

This section provides information on how the Time System Service Library can be built.

Description



All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.

Library Interface

a) System Functions

	Name	Description
≡	SYS_TIME_Initialize	Initializes the System Time module.
≡	SYS_TIME_Status	Returns System Time status.
≡	SYS_TIME_Deinitialize	Deinitializes the specific module instance of the SYS TIMER module

b) Timer Functions

	Name	Description
≡	SYS_TIME_TimerCreate	Creates and initializes a new 32-bit software timer instance.
≡	SYS_TIME_TimerDestroy	Destroys/deallocates a software timer instance.
≡	SYS_TIME_TimerStart	Starts a software timer running.
≡	SYS_TIME_TimerStop	Stops a running software timer.
≡	SYS_TIME_TimerCounterGet	Gets the elapsed counter value of a software timer.
≡	SYS_TIME_TimerPeriodHasExpired	Reports whether or not the current period of a software timer has expired.
≡	SYS_TIME_TimerReload	Reloads (or reinitializes) the software timer instance.

c) Callback and Delay Functions

	Name	Description
≡	SYS_TIME_CallbackRegisterMS	Registers a function with the time system service to be called back when the requested number of milliseconds has expired (either once or repeatedly).
≡	SYS_TIME_CallbackRegisterUS	Registers a function with the time system service to be called back when the requested number of microseconds have expired (either once or repeatedly).
≡	SYS_TIME_DelayMS	This function is used to generate a delay of a given number of milliseconds.
≡	SYS_TIME_DelayUS	This function is used to generate a delay of a given number of microseconds.
≡	SYS_TIME_DelayIsComplete	Determines if the given delay timer has completed.

d) Counter and Conversion Functions

	Name	Description
≡	SYS_TIME_Counter64Get	Get the common 64-bit system counter value.
≡	SYS_TIME_CounterGet	Get the common 32-bit system counter value.
≡	SYS_TIME_CounterSet	Sets the common 32-bit system counter value.
≡	SYS_TIME_CountToMS	Converts a counter value to time interval in milliseconds.
≡	SYS_TIME_CountToUS	Converts a counter value to time interval in microseconds.
≡	SYS_TIME_MSToCount	Convert the given time interval in milliseconds to an equivalent counter value.
≡	SYS_TIME_USToCount	Convert the given time interval in microseconds to an equivalent counter value.
≡	SYS_TIME_FrequencyGet	Gets the frequency at which the hardware timer counts.

e) Data Types and Constants

	Name	Description
◇	_SYS_TIME_INIT	TIME system service Initialization Data Declaration
	SYS_TIME_INIT	Defines the data required to initialize the TIME system service
	SYS_TIME_CALLBACK	Pointer to a time system service callback function.

	SYS_TIME_CALLBACK_TYPE	Identifies the type of callback requested (single or periodic).
	SYS_TIME_RESULT	Result of a time service client interface operation.
	SYS_TIME_HANDLE_INVALID	Invalid handle value to a software timer instance.
	SYS_TIME_HANDLE	Handle to a software timer instance.
	SYS_TIME_PLIB_CALLBACK	TIME PLIB API Set needed by the system service
	SYS_TIME_PLIB_CALLBACK_REGISTER	This is type SYS_TIME_PLIB_CALLBACK_REGISTER .
	SYS_TIME_PLIB_COMPARE_SET	This is type SYS_TIME_PLIB_COMPARE_SET .
	SYS_TIME_PLIB_COUNTER_GET	This is type SYS_TIME_PLIB_COUNTER_GET .
	SYS_TIME_PLIB_FREQUENCY_GET	This is type SYS_TIME_PLIB_FREQUENCY_GET .
	SYS_TIME_PLIB_INTERFACE	This is type SYS_TIME_PLIB_INTERFACE .
	SYS_TIME_PLIB_PERIOD_SET	This is type SYS_TIME_PLIB_PERIOD_SET .
	SYS_TIME_PLIB_START	This is type SYS_TIME_PLIB_START .
	SYS_TIME_PLIB_STOP	This is type SYS_TIME_PLIB_STOP .

Description

This section describes the API functions of the Time System Service library.

Refer to each section for a detailed description.

a) System Functions

SYS_TIME_Initialize Function

Initializes the System Time module.

C

```
SYS_MODULE_OBJ SYS_TIME_Initialize(const SYS_MODULE_INDEX index, const SYS_MODULE_INIT * const init);
```

Returns

If successful, returns a valid handle to an object. Otherwise, it returns [SYS_MODULE_OBJ_INVALID](#).

Description

This function initializes the instance of the System Time module.

Remarks

This routine should normally only be called once during system initialization.

Example

```
const SYS_TIME_PLIB_INTERFACE sysTimePlibAPI = {
    .timerCallbackSet = (SYS\_TIME\_PLIB\_CALLBACK\_REGISTER)TC0_CH0_TimerCallbackRegister,
    .timerCounterGet = (SYS\_TIME\_PLIB\_COUNTER\_GET)TC0_CH0_TimerCounterGet,
    .timerPeriodSet = (SYS\_TIME\_PLIB\_PERIOD\_SET)TC0_CH0_TimerPeriodSet,
    .timerFrequencyGet = (SYS\_TIME\_PLIB\_FREQUENCY\_GET)TC0_CH0_TimerFrequencyGet,
    .timerCompareSet = (SYS\_TIME\_PLIB\_COMPARE\_SET)TC0_CH0_TimerCompareSet,
    .timerStart = (SYS\_TIME\_PLIB\_START)TC0_CH0_TimerStart,
    .timerStop = (SYS\_TIME\_PLIB\_STOP)TC0_CH0_TimerStop
};

const SYS_TIME_INIT sysTimeInitData =
{
    .timePlib = &sysTimePlibAPI,
    .hwTimerIntNum = TC0_CH0 IRQn,
};

SYS_MODULE_OBJ objSysTime;
```

```

objSysTime = SYS_TIME_Initialize(SYS_TIME_INDEX_0, (SYS_MODULE_INIT *)&sysTimeInitData);
if (objSysTime == SYS_MODULE_OBJ_INVALID)
{
    // Handle error
}

```

Parameters

Parameters	Description
index	Index for the instance to be initialized
init	Pointer to a data structure containing data necessary to initialize the module.

Function

```

SYS_MODULE_OBJ SYS_TIME_Initialize ( const SYS_MODULE_INDEX index,
const SYS_MODULE_INIT * const init )

```

SYS_TIME_Status Function

Returns System Time status.

C

```
SYS_STATUS SYS_TIME_Status(SYS_MODULE_OBJ object);
```

Returns

SYS_STATUS_UNINITIALIZED - Indicates that the driver is not initialized.

SYS_STATUS_READY - Indicates that the module initialization is complete and it ready to be used.

Description

This function returns the current status of the System Time module.

Remarks

None.

Preconditions

None.

Example

```

// Handle "objSysTime" value must have been returned from SYS_TIME_Initialize.
if (SYS_TIME_Status (objSysTime) == SYS_STATUS_READY)
{
    // Time system service is initialized and ready to accept new requests.
}

```

Parameters

Parameters	Description
object	SYS TIME object handle, returned from SYS_TIME_Initialize

Function

```
SYS_STATUS SYS_TIME_Status ( SYS_MODULE_OBJ object )
```

SYS_TIME_Deinitialize Function

Deinitializes the specific module instance of the SYS TIMER module

C

```
void SYS_TIME_Deinitialize(SYS_MODULE_OBJ object);
```

Returns

None.

Description

This function deinitializes the specific module instance disabling its operation (and any hardware for driver modules). Resets all of the internal data structures and fields for the specified instance to the default settings.

Remarks

Once the Initialize operation has been called, the De-initialize operation must be called before the Initialize operation can be called again.

Preconditions

The [SYS_TIME_Initialize](#) function should have been called before calling this function.

Example

```
// Handle "objSysTime" value must have been returned from SYS_TIME_Initialize.

SYS_TIME_Deinitialize (objSysTime);

if (SYS_TIME_Status (objSysTime) != SYS_STATUS_UNINITIALIZED)
{
    // Check again later if you need to know
    // when the SYS TIME is De-initialized.
}
```

Parameters

Parameters	Description
object	SYS TIMER object handle, returned from SYS_TIME_Initialize

Function

void SYS_TIME_Deinitialize ([SYS_MODULE_OBJ](#) object)

b) Timer Functions

SYS_TIME_TimerCreate Function

Creates and initializes a new 32-bit software timer instance.

C

```
SYS_TIME_HANDLE SYS\_TIME\_TimerCreate(uint32_t count, uint32_t period, SYS_TIME_CALLBACK
callback, uintptr_t context, SYS_TIME_CALLBACK_TYPE type);
```

Returns

An opaque value used to identify software timer instance if the call succeeds in allocating/creating the software timer. If the call fails [SYS_TIME_HANDLE_INVALID](#) is returned.

Description

This function creates/allocates a new instance of a 32-bit software timer.

A software timer provides a counter that is separate from other timer counters and is under control of the caller. The counter can be started and stopped under caller control and its counter value and period value can be changed while the counter is either running or stopped.

Remarks

None.

Preconditions

The `SYS_TIME_Initialize` function should have been called before calling this function.

Example

Given an implementation of the following function prototype:

```
void MyCallback ( uintptr_t context );
```

The following example creates a software timer instance.

```
SYS_TIME_HANDLE handle;
//myData is the user-defined data that will be passed back in the registered callback function.
handle = SYS_TIME_TimerCreate(0, SYS_TIME_MSToCount(200), &MyCallback, (uintptr_t)&myData,
SYS_TIME_SINGLE);
if (handle != SYS_TIME_HANDLE_INVALID)
{
    //timer is created successfully.
}
```

Parameters

Parameters	Description
count	The initial value of the counter, after the timer has been created and before it has been started.
period	The counter interval at which the timer indicates time has elapsed.
callback	Pointer to function that will be called every time the period counts have elapsed. (Actual timing will depend on system performance and the base frequency at which the time service is configured). For single shot timers, the callback cannot be NULL. For periodic timers, if the callback pointer is given as NULL, no callback will occur, but <code>SYS_TIME_TimerPeriodHasExpired</code> can still be polled to determine if the period has expired for a periodic shot timer.
context	A caller-defined value that's passed (unmodified) back to the client as a parameter of callback function. It can be used to identify the client's context or passed with any value.
type	Type of callback requested. If type is <code>SYS_TIME_SINGLE</code> , the Callback function will be called once when the time period expires. If type is <code>SYS_TIME_PERIODIC</code> Callback function will be called repeatedly, every time the time period expires until the timer object is stopped or deleted.

Function

```
SYS_TIME_HANDLE SYS_TIME_TimerCreate (
    uint32_t count,
    uint32_t period,
    SYS_TIME_CALLBACK callback,
    uintptr_t context,
    SYS_TIME_CALLBACK_TYPE type )
```

SYS_TIME_TimerDestroy Function

Destroys/deallocates a software timer instance.

C

```
SYS_TIME_RESULT SYS_TIME_TimerDestroy(SYS_TIME_HANDLE handle);
```

Returns

`SYS_TIME_SUCCESS` - If the given software was successfully destroyed.

`SYS_TIME_ERROR` - If an error occurred or the given handle was invalid.

Description

This function deletes and deallocates a software timer instance, stopping its counter and releasing the associated resources.

Remarks

Released timer resources can be reused by other clients. Single shot timers are auto destroyed on expiry. Calling `SYS_TIME_DelayIsComplete` auto destroys the delay timer if it has expired.

Preconditions

The `SYS_TIME_Initialize` and a valid handle to the software timer to be destroyed must be available.

Example

```
// "timer" is the handle to the software timer to be destroyed.
if (SYS_TIME_TimerDestroy(timer) != SYS_TIME_SUCCESS)
{
    // Handle Error
}
```

Parameters

Parameters	Description
handle	Handle to a software timer instance.

Function

`SYS_TIME_RESULT SYS_TIME_TimerDestroy (SYS_TIME_HANDLE handle)`

SYS_TIME_TimerStart Function

Starts a software timer running.

C

```
SYS_TIME_RESULT SYS_TIME_TimerStart (SYS_TIME_HANDLE handle);
```

Returns

`SYS_TIME_SUCCESS` if the operation succeeds.

`SYS_TIME_ERROR` if the operation fails (due, for example, to an invalid handle).

Description

This function starts a previously created software timer.

Remarks

Calling `SYS_TIME_TimerStart` on an already running timer will have no affect and will return `SYS_TIME_SUCCESS`. Calling `SYS_TIME_TimerStart` on a timer that is stopped, will always restart the timer from its initial configured timer/counter value and will not resume the timer from the counter value at which it was stopped.

Preconditions

The `SYS_TIME_Initialize` must have been called and a valid handle to the software timer to be started must be available.

Example

Given a "timer" handle, the following example will start the timer's counter running.

```
SYS_TIME_TimerStart(timer);
```

Parameters

Parameters	Description
handle	Handle to a software timer instance.

Function

`SYS_TIME_RESULT SYS_TIME_TimerStart (SYS_TIME_HANDLE handle)`

SYS_TIME_TimerStop Function

Stops a running software timer.

C

```
SYS_TIME_RESULT SYS_TIME_TimerStop(SYS_TIME_HANDLE handle);
```

Returns

SYS_TIME_SUCCESS if the operation succeeds.

SYS_TIME_ERROR if the operation fails (due, for example, to an invalid handle).

Description

This function stops a previously created and running software timer (i.e. the given timer's counter will stop incrementing).

Remarks

Calling SYS_TIME_TimerStop on a timer that is not running will have no affect and will return SYS_TIME_SUCCESS.

Preconditions

The [SYS_TIME_Initialize](#) must have been called and a valid handle to the software timer to be stopped must be available.

Example

Given a "timer" handle, the following example will stops the timer's counter running.

```
SYS_TIME_TimerStop(timer);
```

Parameters

Parameters	Description
handle	Handle to a software timer instance.

Function

```
SYS_TIME_RESULT SYS_TIME_TimerStop ( SYS_TIME_HANDLE handle )
```

SYS_TIME_TimerCounterGet Function

Gets the elapsed counter value of a software timer.

C

```
SYS_TIME_RESULT SYS_TIME_TimerCounterGet(SYS_TIME_HANDLE handle, uint32_t * count);
```

Returns

SYS_TIME_SUCCESS if the operation succeeds.

SYS_TIME_ERROR if the operation fails (due, for example, to an invalid handle).

Description

This function gets the elapsed counter value of the software timer identified by the handle given.

Remarks

The counter value may be stale immediately upon function return, depending upon timer frequency and system performance.

Preconditions

The [SYS_TIME_Initialize](#) must have been called and a valid handle to the software timer must be available.

Example

Given a "timer" handle, the following example will get the given software timer's elapsed counter value.

```
uint32_t count;  
if (SYS_TIME_TimerCounterGet(timer, &count) != SYS_TIME_SUCCESS)
```

```
{
    // Handle error
}
```

Parameters

Parameters	Description
handle	Handle to a software timer instance.
count	Address of the variable to receive the value of the given software timer's elapsed counter. This parameter is ignored when the return value is not SYS_TIME_SUCCESS.

Function

```
SYS_TIME_RESULT SYS_TIME_TimerCounterGet (
    SYS_TIME_HANDLE handle,
    uint32_t *count
)
```

SYS_TIME_TimerPeriodHasExpired Function

Reports whether or not the current period of a software timer has expired.

C

```
bool SYS_TIME_TimerPeriodHasExpired(SYS_TIME_HANDLE handle);
```

Returns

true - If the period has expired.

false - If the period is not expired.

Description

This function reports whether or not the current period of the given software timer has expired and clears the internal flag tracking period expiration so that each period expiration will only be reported once.

Remarks

1. For a periodic timer, a call to SYS_TIME_TimerPeriodHasExpired returns true after the first time period has expired. After calling this function, the expiry flag is internally cleared and is set again once the ongoing period of the periodic timer expires.
2. Unlike the [SYS_TIME_DelayIsComplete](#) routine the SYS_TIME_TimerPeriodHasExpired does not delete the timer, it just returns the status of the timer.
3. To poll the status of the delay timers, [SYS_TIME_DelayIsComplete](#) must be used instead of the SYS_TIME_TimerPeriodHasExpired routine, as [SYS_TIME_DelayIsComplete](#) additionally deletes the delay timer object once the delay has expired.
4. Since single shot timers does not support polling (registration of a callback is mandatory for single shot timers), the [SYS_TIME_CallbackRegisterMS](#) routine must not be used to poll the status of the single shot timers.

Preconditions

The [SYS_TIME_Initialize](#) and [SYS_TIME_TimerCreate](#) or [SYS_TIME_CallbackRegisterMS](#)/[SYS_TIME_CallbackRegisterUS](#) functions (with callback type set to SYS_TIME_PERIODIC) must have been called before calling this function.

Example

```
if (SYS_TIME_TimerPeriodHasExpired(timer) == true)
{
    // Timer has expired. Take desired action.
}
```

Parameters

Parameters	Description
handle	Handle to a software timer instance

Function

bool SYS_TIME_TimerPeriodHasExpired ([SYS_TIME_HANDLE](#) handle)

SYS_TIME_TimerReload Function

Reloads (or reinitializes) the software timer instance.

C

```
SYS_TIME_RESULT SYS\_TIME\_TimerReload(SYS_TIME_HANDLE handle, uint32_t count, uint32_t period,
SYS_TIME_CALLBACK callback, uintptr_t context, SYS_TIME_CALLBACK_TYPE type);
```

Returns

SYS_TIME_SUCCESS - If the call succeeded.

SYS_TIME_ERROR - If the call failed (and the timer was not modified).

Description

This function reloads the initial values for an already created/allocated instance of a software timer, even if it is currently running.

Remarks

This function facilitates changing multiple timer parameters quickly and atomically.

Preconditions

The [SYS_TIME_Initialize](#) must have been called and a valid handle to the software timer to be reloaded must be available.

Example

Given an implementation of the following function prototype:

```
void MyNewCallback ( uintptr_t context);
```

The following example updates a software timer instance.

```
//myNewData is the user-defined data that will be passed back in the registered callback
function.
if (SYS_TIME_TimerReload(timer, 0, SYS_TIME_MSToCount(500), &MyNewCallback,
(uintptr_t)&myNewData, SYS_TIME_PERIODIC) != SYS_TIME_SUCCESS )
{
    // Handle error
}
```

Parameters

Parameters	Description
handle	Handle to a software timer instance.
count	The new value of the counter.
period	The new period value.
callback	The new callback function pointer. For single shot timers, the callback must be specified. For periodic timers, if the callback pointer is given as NULL, no callback will occur, but SYS_TIME_TimerPeriodHasExpired can still be polled to determine if the period has expired for a periodic timer.
context	The new caller-defined value that's passed (unmodified) back to the client as a parameter of callback function.
type	Type of callback requested. If type is SYS_TIME_SINGLE, the Callback function will be called once when the time period expires. If type is SYS_TIME_PERIODIC Callback function will be called repeatedly, every time the time period expires until the timer object is stopped or deleted.

Function

```
SYS_TIME_RESULT SYS_TIME_TimerReload (
    SYS_TIME_HANDLE handle,
    uint32_t count,
    uint32_t period,
    SYS_TIME_CALLBACK callback,
    uintptr_t context,
    SYS_TIME_CALLBACK_TYPE type
)
```

c) Callback and Delay Functions

SYS_TIME_CallbackRegisterMS Function

Registers a function with the time system service to be called back when the requested number of milliseconds has expired (either once or repeatedly).

C

```
SYS_TIME_HANDLE SYS_TIME_CallbackRegisterMS(SYS_TIME_CALLBACK callback, uintptr_t context,
    uint32_t ms, SYS_TIME_CALLBACK_TYPE type);
```

Returns

SYS_TIME_HANDLE - A valid timer object handle if the call succeeds. **SYS_TIME_HANDLE_INVALID** if it fails.

Description

Creates a timer object and registers a function with it to be called back when the requested delay (specified in milliseconds) has completed. The caller must identify if the timer should call the function once or repeatedly every time the given delay period expires.

Preconditions

The **SYS_TIME_Initialize** function should have been called before calling this function.

Example

Given a callback function implementation matching the following prototype:

```
void MyCallback ( uintptr_t context );
```

The following example call will register it, requesting a 50 millisecond periodic callback.

```
//Give a SYS_TIME_CALLBACK function "MyCallback",
SYS_TIME_HANDLE handle = SYS_TIME_CallbackRegisterMS(MyCallback, (uintptr_t)0, 50,
SYS_TIME_PERIODIC);
if (handle != SYS_TIME_HANDLE_INVALID)
{
    //timer is created successfully.
}
```

Parameters

Parameters	Description
callback	Pointer to the function to be called. For single shot timers, the callback cannot be NULL. For periodic timers, if the callback pointer is given as NULL, no callback will occur, but SYS_TIME_TimerPeriodHasExpired can still be polled to determine if the period has expired for a periodic timer.
context	A client-defined value that is passed to the callback function.
ms	Time period in milliseconds.

type	Type of callback requested. If type is SYS_TIME_SINGLE, the Callback function will be called once when the time period expires. After the time period expires, the timer object will be freed. If type is SYS_TIME_PERIODIC Callback function will be called repeatedly, every time the time period expires until the timer object is stopped or deleted.
------	---

Function

```
SYS_TIME_HANDLE SYS_TIME_CallbackRegisterMS ( SYS_TIME_CALLBACK callback,
    uintptr_t context, uint32_t ms, SYS_TIME_CALLBACK_TYPE type )
```

SYS_TIME_CallbackRegisterUS Function

Registers a function with the time system service to be called back when the requested number of microseconds have expired (either once or repeatedly).

C

```
SYS_TIME_HANDLE SYS_TIME_CallbackRegisterUS(SYS_TIME_CALLBACK callback, uintptr_t context,
    uint32_t us, SYS_TIME_CALLBACK_TYPE type);
```

Returns

SYS_TIME_HANDLE - A valid timer object handle if the call succeeds. **SYS_TIME_HANDLE_INVALID** if it fails.

Description

Creates a timer object and registers a function with it to be called back when the requested delay (specified in microseconds) has completed. The caller must identify if the timer should call the function once or repeatedly every time the given delay period expires.

Preconditions

The **SYS_TIME_Initialize** function should have been called before calling this function.

Example

Given a callback function implementation matching the following prototype:

```
void MyCallback ( uintptr_t context );
```

The following example call will register it, requesting a 500 microsecond periodic callback.

```
//Give a SYS_TIME_CALLBACK function "MyCallback",
SYS_TIME_HANDLE handle = SYS_TIME_CallbackRegisterUS(MyCallback, (uintptr_t)0, 500,
SYS_TIME_PERIODIC);
if (handle != SYS_TIME_HANDLE_INVALID)
{
    //timer is created successfully.
}
```

Parameters

Parameters	Description
callback	Pointer to the function to be called. For single shot timers, the callback cannot be NULL. For periodic timers, if the callback pointer is given as NULL, no callback will occur, but SYS_TIME_TimerPeriodHasExpired can still be polled to determine if the period has expired for a periodic timer.
context	A client-defined value that is passed to the callback function.
us	Time period in microseconds.
type	Type of callback requested. If type is SYS_TIME_SINGLE, the Callback function will be called once when the time period expires. After the time period expires, the timer object will be freed. If type is SYS_TIME_PERIODIC Callback function will be called repeatedly, every time the time period expires until the timer object is stopped or deleted.

Function

```
SYS_TIME_HANDLE SYS_TIME_CallbackRegisterUS ( SYS_TIME_CALLBACK callback,
```

```
uintptr_t context, uint32_t us,           SYS_TIME_CALLBACK_TYPE type )
```

SYS_TIME_DelayMS Function

This function is used to generate a delay of a given number of milliseconds.

C

```
SYS_TIME_RESULT SYS_TIME_DelayMS(uint32_t ms, SYS_TIME_HANDLE* handle);
```

Returns

SYS_TIME_SUCCESS - If the call succeeded.

SYS_TIME_ERROR - If the call failed.

Description

The function will internally create a single shot timer which will be auto deleted when the application calls [SYS_TIME_DelayIsComplete](#) routine and the delay has expired. The function will return immediately, requiring the caller to use [SYS_TIME_DelayIsComplete](#) routine to check the delay timer's status.

Remarks

Will delay the requested number of milliseconds or longer depending on system performance.

Delay values of 0 will return SYS_TIME_ERROR.

Will return SYS_TIME_ERROR if the timer handle pointer is NULL.

Preconditions

The [SYS_TIME_Initialize](#) function must have been called before calling this function.

Example

```
SYS_TIME_HANDLE timer = SYS_TIME_HANDLE_INVALID;

if (SYS_TIME_DelayMS(100, &timer) != SYS_TIME_SUCCESS)
{
    // Handle error
}
else if (SYS_TIME_DelayIsComplete(timer) != true)
{
    // Wait till the delay has not expired
    while (SYS_TIME_DelayIsComplete(timer) == false);
}
```

Parameters

Parameters	Description
ms	The desired number of milliseconds to delay.
handle	Address of the variable to receive the timer handle value.

Function

```
SYS_TIME_RESULT SYS_TIME_DelayMS ( uint32_t ms, SYS_TIME_HANDLE* handle )
```

SYS_TIME_DelayUS Function

This function is used to generate a delay of a given number of microseconds.

C

```
SYS_TIME_RESULT SYS_TIME_DelayUS(uint32_t us, SYS_TIME_HANDLE* handle);
```

Returns

SYS_TIME_SUCCESS - If the call succeeded.

SYS_TIME_ERROR - If the call failed.

Description

The function will internally create a single shot timer which will be auto deleted when the application calls [SYS_TIME_DelayIsComplete](#) routine and the delay has expired. The function will return immediately, requiring the caller to use [SYS_TIME_DelayIsComplete](#) routine to check the delay timer's status.

Remarks

Will delay the requested number of microseconds or longer depending on system performance.

Delay values of 0 will return SYS_TIME_ERROR.

Will return SYS_TIME_ERROR if timer handle pointer is NULL.

Preconditions

The [SYS_TIME_Initialize](#) function must have been called before calling this function.

Example

```
SYS_TIME_HANDLE timer = SYS_TIME_HANDLE_INVALID;

if (SYS_TIME_DelayUS(50, &timer) != SYS_TIME_SUCCESS)
{
    // Handle error
}
else if (SYS_TIME_DelayIsComplete(timer) != true)
{
    // Wait till the delay has not expired
    while (SYS_TIME_DelayIsComplete(timer) == false);
}
```

Parameters

Parameters	Description
us	The desired number of microseconds to delay.
handle	Address of the variable to receive the timer handle value.

Function

[SYS_TIME_RESULT](#) [SYS_TIME_DelayUS](#) ([uint32_t](#) us, [SYS_TIME_HANDLE*](#) handle)

SYS_TIME_DelayIsComplete Function

Determines if the given delay timer has completed.

C

```
bool SYS\_TIME\_DelayIsComplete(SYS\_TIME\_HANDLE handle);
```

Returns

true - If the delay has completed.

false - If the delay has not completed.

Description

This function determines if the requested delay is completed or is still in progress.

Remarks

[SYS_TIME_DelayIsComplete](#) must be called to poll the status of the delay requested through [SYS_TIME_DelayMS](#) or [SYS_TIME_DelayUS](#).

[SYS_TIME_DelayIsComplete](#) must not be used to poll the status of a periodic timer. Status of a periodic timer may be polled using the [SYS_TIME_TimerPeriodHasExpired](#) routine.

Preconditions

A delay request must have been created using either the [SYS_TIME_DelayMS](#) or [SYS_TIME_DelayUS](#) functions.

Example

```
// Check if the delay has expired.
if (SYS_TIME_DelayIsComplete(timer) != true)
{
    // Delay has not expired
}
```

Parameters

Parameters	Description
handle	A SYS_TIME_HANDLE value provided by either SYS_TIME_DelayMS or SYS_TIME_DelayUS functions.

Function

bool SYS_TIME_DelayIsComplete ([SYS_TIME_HANDLE](#) handle)

d) Counter and Conversion Functions

SYS_TIME_Counter64Get Function

Get the common 64-bit system counter value.

C

```
uint64_t SYS_TIME_Counter64Get();
```

Returns

The current "live" value of the common 64-bit system counter.

Description

Returns the current "live" value of the common 64-bit system counter.

Remarks

The value returned may be stale as soon as it is provided, as the timer is live and running at full frequency resolution (as configured and as reported by the [SYS_TIME_FrequencyGet](#) function). If additional accuracy is required, use a hardware timer instance.

Preconditions

The [SYS_TIME_Initialize](#) function should have been called before calling this function.

Example

```
uint64_t timeStamp1;
uint64_t timeStamp2;
uint64_t timeDiffMs;

// Take first time stamp
timeStamp1 = SYS_TIME_Counter64Get();

// Perform some tasks.....

// Take second time stamp
timeStamp2 = SYS_TIME_Counter64Get();

// Calculate the time difference.
timeDiffMs = timeStamp2 - timeStamp1;
```

```
timeDiffMs = (uint64_t)((double)timeDiffMs/SYS_TIME_FrequencyGet())*1000.0);
```

Function

```
uint64_t SYS_TIME_Counter64Get ( void )
```

SYS_TIME_CounterGet Function

Get the common 32-bit system counter value.

C

```
uint32_t SYS_TIME_CounterGet();
```

Returns

The current "live" value of the common 32-bit system counter.

Description

Returns the current "live" value of the common 32-bit system counter.

Remarks

The value returned may be stale as soon as it is provided, as the timer is live and running at full frequency resolution (as configured and as reported by the [SYS_TIME_FrequencyGet](#) function). If additional accuracy is required, use a hardware timer instance.

Preconditions

The [SYS_TIME_Initialize](#) function should have been called before calling this function.

Example

```
uint32_t timeStamp1;
uint32_t timeStamp2;
uint32_t timeDiffMs;

// Take first time stamp
timeStamp1 = SYS_TIME_CounterGet();

//Perform some tasks....

// Take second time stamp
timeStamp2 = SYS_TIME_CounterGet();

//Calculate the time difference. Use the appropriate function -
//SYS_TIME_CountToMS or SYS_TIME_CountToUS to calculate the time difference.

timeDiffMs = SYS_TIME_CountToMS((timeStamp2 - timeStamp1));
```

Function

```
uint32_t SYS_TIME_CounterGet ( void )
```

SYS_TIME_CounterSet Function

Sets the common 32-bit system counter value.

C

```
void SYS_TIME_CounterSet(uint32_t count);
```

Returns

None

Description

Sets the current "live" value of the common 32-bit system counter.

Remarks

None.

Preconditions

The [SYS_TIME_Initialize](#) function should have been called before calling this function.

Example

```
SYS_TIME_CounterSet(1000);
```

Parameters

Parameters	Description
count	The 32-bit counter value to write to the common system counter.

Function

```
void SYS_TIME_CounterSet ( uint32_t count )
```

SYS_TIME_CountToMS Function

Converts a counter value to time interval in milliseconds.

C

```
uint32_t SYS_TIME_CountToMS(uint32_t count);
```

Returns

Number of milliseconds represented by the given counter value.

Description

This function converts a counter value to time interval in milliseconds, based on the hardware timer frequency as configured and as reported by [SYS_TIME_FrequencyGet](#).

Remarks

None.

Preconditions

The [SYS_TIME_Initialize](#) function should have been called before calling this function.

Example

Given a previously captured uint32_t counter value called "timestamp" captured using the [SYS_TIME_CounterGet](#) function, the following example will calculate number of milliseconds elapsed since timestamp was captured.

```
uint32_t count = SYS_TIME_CounterGet() - timestamp;
uint32_t ms    = SYS_TIME_CountToMS(count);
```

Parameters

Parameters	Description
count	Counter value to be converted to an equivalent value in milliseconds.

Function

```
uint32_t SYS_TIME_CountToMS ( uint32_t count )
```

SYS_TIME_CountToUS Function

Converts a counter value to time interval in microseconds.

C

```
uint32_t SYS_TIME_CountToUS(uint32_t count);
```

Returns

Number of microseconds represented by the given counter value.

Description

This function converts a counter value to time interval in microseconds, based on the hardware timer frequency as configured and as reported by [SYS_TIME_FrequencyGet](#).

Remarks

None.

Preconditions

The [SYS_TIME_Initialize](#) function should have been called before calling this function.

Example

Given a previously captured 32-bit counter value called "timestamp" captured using the [SYS_TIME_CounterGet](#) function, the following example will calculate the number of microseconds elapsed since timestamp was captured.

```
uint32_t count = SYS_TIME_CounterGet() - timestamp;
uint32_t us     = SYS_TIME_CountToUS(count);
```

Parameters

Parameters	Description
count	Counter value to be converted to an equivalent value in microseconds.

Function

```
uint32_t SYS_TIME_CountToUS ( uint32_t count )
```

SYS_TIME_MSToCount Function

Convert the given time interval in milliseconds to an equivalent counter value.

C

```
uint32_t SYS_TIME_MSToCount(uint32_t ms);
```

Returns

Number of hardware timer counts that will expire in the given time interval.

Description

This function converts a given time interval (measured in milliseconds) to an equivalent 32-bit counter value, based on the configured hardware timer frequency as reported by [SYS_TIME_FrequencyGet](#).

Remarks

None.

Preconditions

The [SYS_TIME_Initialize](#) function should have been called before calling this function.

Example

```
uint32_t futureCounter = SYS_TIME_CounterGet() + SYS_TIME_MSToCount(10);
```

Parameters

Parameters	Description
ms	Time interval in milliseconds.

Function

```
uint32_t SYS_TIME_MSToCount ( uint32_t ms )
```

SYS_TIME_USToCount Function

Convert the given time interval in microseconds to an equivalent counter value.

C

```
uint32_t SYS_TIME_USToCount(uint32_t us);
```

Returns

Number of hardware timer counts that will expire in the given time interval.

Description

This function converts a given time interval (measured in microseconds) to an equivalent 32-bit counter value, based on the configured hardware timer frequency as reported by [SYS_TIME_FrequencyGet](#).

Remarks

None.

Preconditions

The [SYS_TIME_Initialize](#) function should have been called before calling this function.

Example

```
uint32_t futureCounter = SYS_TIME_CounterGet() + SYS_TIME_USToCount(200);
```

Parameters

Parameters	Description
us	Time interval in microseconds.

Function

```
uint32_t SYS_TIME_USToCount ( uint32_t us )
```

SYS_TIME_FrequencyGet Function

Gets the frequency at which the hardware timer counts.

C

```
uint32_t SYS_TIME_FrequencyGet ( );
```

Returns

The frequency at which the hardware timer runs, if the timer has been initialized and is ready. Otherwise, it returns 0.

Description

Returns the frequency at which the hardware timer runs. This frequency determines the maximum resolution of all services provided by SYS_TIME.

Remarks

This frequency is determined by hardware capabilities and how they are configured and initialized.

Preconditions

The `SYS_TIME_Initialize` function should have been called before calling this function.

Example

```
uint32_t frequency = SYS_TIME_FrequencyGet();
```

Function

```
uint32_t SYS_TIME_FrequencyGet ( void )
```

e) Data Types and Constants

`_SYS_TIME_INIT` Structure

C

```
struct _SYS_TIME_INIT {
    const SYS_TIME_PLIB_INTERFACE* timePlib;
    INT_SOURCE hwTimerIntNum;
};
```

Members

Members	Description
const SYS_TIME_PLIB_INTERFACE* timePlib;	Identifies the PLIB API set to be used by the system service to access <ul style="list-style-type: none"> the peripheral.
INT_SOURCE hwTimerIntNum;	Interrupt source ID for the TIMER interrupt.

Description

TIME system service Initialization Data Declaration

`SYS_TIME_INIT` Type

Defines the data required to initialize the TIME system service

C

```
typedef struct _SYS_TIME_INIT SYS_TIME_INIT;
```

Description

TIME System Service Initialization Data

This data type defines the data required to initialize the TIME system service.

Remarks

This structure is implementation specific. It is fully defined in `sys_time_definitions.h`.

`SYS_TIME_CALLBACK` Type

Pointer to a time system service callback function.

C

```
typedef void (* SYS_TIME_CALLBACK)(uintptr_t context);
```

Returns

None.

Description

This data type defines a pointer to a time service callback function, thus defining the function signature. Callback functions may be registered by clients of the time service either when creating a software timer or using the SYS_TIME_Callback shortcut functions.

Remarks

None.

Preconditions

The time service must have been initialized using the [SYS_TIME_Initialize](#) function before attempting to register a SYS Time callback function.

Example

```
/*"MY_APP_DATA_STRUCT" is a user defined data structure with "isTimerExpired" as
//one of the structure members.
void MyCallback ( uintptr_t context )
{
    MY_APP_DATA_STRUCT* pAppData = (MY_APP_DATA_STRUCT *) context;
    if (pAppData != NULL)
    {
        pAppData->isTimerExpired = true;
    }
}
```

Parameters

Parameters	Description
context	A context value, returned untouched to the client when the callback occurs. It can be used to identify the instance of the client who registered the callback.

Function

```
void ( * SYS_TIME_CALLBACK ) ( uintptr_t context )
```

SYS_TIME_CALLBACK_TYPE Enumeration

Identifies the type of callback requested (single or periodic).

C

```
typedef enum {
    SYS_TIME_SINGLE,
    SYS_TIME_PERIODIC
} SYS_TIME_CALLBACK_TYPE;
```

Members

Members	Description
SYS_TIME_SINGLE	Requesting a single (one time) callback.
SYS_TIME_PERIODIC	Requesting a periodically repeating callback.

Description

System Time Callback Type

Remarks

None.

SYS_TIME_RESULT Enumeration

Result of a time service client interface operation.

C

```
typedef enum {
    SYS_TIME_SUCCESS,
    SYS_TIME_ERROR
} SYS_TIME_RESULT;
```

Members

Members	Description
SYS_TIME_SUCCESS	Operation completed with success.
SYS_TIME_ERROR	Invalid handle or operation failed.

Description

System Time Result

Identifies the result of certain time service operations.

SYS_TIME_HANDLE_INVALID Macro

Invalid handle value to a software timer instance.

C

```
#define SYS_TIME_HANDLE_INVALID ((SYS_TIME_HANDLE) (-1))
```

Description

Invalid System Time handle value to a software timer

Defines the invalid handle value to a timer instance.

Remarks

Do not rely on the actual value as it may change in different versions or implementations of the SYS Time service.

SYS_TIME_HANDLE Type

Handle to a software timer instance.

C

```
typedef uintptr_t SYS_TIME_HANDLE;
```

Description

System Time Handle

This data type is a handle to a software timer instance. It can be used to access and control a software timer.

Remarks

Do not rely on the underlying type as it may change in different versions or implementations of the SYS Time service.

SYS_TIME_PLIB_CALLBACK Type**C**

```
typedef void (* SYS_TIME_PLIB_CALLBACK)(uint32_t , uintptr_t);
```

Description

TIME PLIB API Set needed by the system service

SYS_TIME_PLIB_CALLBACK_REGISTER Type

C

```
typedef void (* SYS_TIME_PLIB_CALLBACK_REGISTER)(SYS_TIME_PLIB_CALLBACK callback, uintptr_t context);
```

Description

This is type SYS_TIME_PLIB_CALLBACK_REGISTER.

SYS_TIME_PLIB_COMPARE_SET Type

C

```
typedef void (* SYS_TIME_PLIB_COMPARE_SET)(uint32_t compare);
```

Description

This is type SYS_TIME_PLIB_COMPARE_SET.

SYS_TIME_PLIB_COUNTER_GET Type

C

```
typedef uint32_t (* SYS_TIME_PLIB_COUNTER_GET)(void);
```

Description

This is type SYS_TIME_PLIB_COUNTER_GET.

SYS_TIME_PLIB_FREQUENCY_GET Type

C

```
typedef uint32_t (* SYS_TIME_PLIB_FREQUENCY_GET)(void);
```

Description

This is type SYS_TIME_PLIB_FREQUENCY_GET.

SYS_TIME_PLIB_INTERFACE Structure

C

```
typedef struct {
    SYS_TIME_PLIB_CALLBACK_REGISTER timerCallbackSet;
    SYS_TIME_PLIB_PERIOD_SET timerPeriodSet;
    SYS_TIME_PLIB_FREQUENCY_GET timerFrequencyGet;
    SYS_TIME_PLIB_COMPARE_SET timerCompareSet;
    SYS_TIME_PLIB_START timerStart;
    SYS_TIME_PLIB_STOP timerStop;
    SYS_TIME_PLIB_COUNTER_GET timerCounterGet;
} SYS_TIME_PLIB_INTERFACE;
```

Description

This is type SYS_TIME_PLIB_INTERFACE.

SYS_TIME_PLIB_PERIOD_SET Type**C**

```
typedef void (* SYS_TIME_PLIB_PERIOD_SET)(uint32_t period);
```

Description

This is type SYS_TIME_PLIB_PERIOD_SET.

SYS_TIME_PLIB_START Type**C**

```
typedef void (* SYS_TIME_PLIB_START)(void);
```

Description

This is type SYS_TIME_PLIB_START.

SYS_TIME_PLIB_STOP Type**C**

```
typedef void (* SYS_TIME_PLIB_STOP)(void);
```

Description

This is type SYS_TIME_PLIB_STOP.

Common System Services Help

This section provides information that is common to all services.

a) Media System Services

Name	Description
SYS_MEDIA_EVENT_HANDLER	Pointer to the Media Event Handler function.
SYS_MEDIA_BLOCK_EVENT	Identifies the possible events that can result from a request.
SYS_MEDIA_COMMAND_STATUS	The enumeration for status of buffer
SYS_MEDIA_GEOMETRY	Contains all the geometrical information of a media device.
SYS_MEDIA_GEOMETRY_TABLE_ERASE_ENTRY	Erase Region Geometry Table Index Numbers
SYS_MEDIA_GEOMETRY_TABLE_READ_ENTRY	Read Region Geometry Table Index Numbers
SYS_MEDIA_GEOMETRY_TABLE_WRITE_ENTRY	Write Region Geometry Table Index Numbers
SYS_MEDIA_REGION_GEOMETRY	Contains information of a sys media region.
SYS_MEDIA_PROPERTY	Contains information of property of a media.
SYS_MEDIA_STATUS	The state of media.
SYS_MEDIA_BLOCK_COMMAND_HANDLE	Handle identifying block commands of the media.
SYS_MEDIA_BLOCK_COMMAND_HANDLE_INVALID	Defines the invalid media block command handle.

b) Module System Services

Name	Description
SYS_MODULE_INIT	Initializes a module (including device drivers) as requested by the system.
SYS_STATUS	Identifies the current status/state of a system module (including device drivers).
SYS_MODULE_INDEX	Identifies which instance of a system module should be initialized or opened.
SYS_MODULE_OBJ	Handle to an instance of a system module.

	SYS_MODULE_OBJ_INVALID	Object handle value returned if unable to initialize the requested instance of a system module.
--	--	---

a) Media System Services

SYS_MEDIA_EVENT_HANDLER Type

Pointer to the Media Event Handler function.

C

```
typedef void (* SYS_MEDIA_EVENT_HANDLER)(SYS_MEDIA_BLOCK_EVENT event,  
          SYS_MEDIA_BLOCK_COMMAND_HANDLE commandHandle, uintptr_t context);
```

Returns

None.

Description

Media Event Handler function pointer

This data type defines the required function signature for the media event handling callback function. A client must register a pointer to an event handling function whose function signature (parameter and return value types) match the types specified by this function pointer in order to receive event calls back from the driver.

Remarks

None.

Parameters

Parameters	Description
event	Identifies the type of event
commandHandle	Handle returned from the media operation requests
context	Value identifying the context of the application that registered the event handling function

SYS_MEDIA_BLOCK_EVENT Enumeration

Identifies the possible events that can result from a request.

C

```
typedef enum {  
    SYS_MEDIA_EVENT_BLOCK_COMMAND_COMPLETE,  
    SYS_MEDIA_EVENT_BLOCK_COMMAND_ERROR  
} SYS_MEDIA_BLOCK_EVENT;
```

Members

Members	Description
SYS_MEDIA_EVENT_BLOCK_COMMAND_COMPLETE	Block operation has been completed successfully.
SYS_MEDIA_EVENT_BLOCK_COMMAND_ERROR	There was an error during the block operation

Description

SYS Media Events

This enumeration identifies the possible events that can result from a media.

Remarks

One of these values is passed in the "event" parameter of the event handling callback function that client registered with the driver by setting the event handler when a block request is completed.

SYS_MEDIA_COMMAND_STATUS Enumeration

The enumeration for status of buffer

C

```
typedef enum {
    SYS_MEDIA_COMMAND_COMPLETED = 0,
    SYS_MEDIA_COMMAND_QUEUED = 1,
    SYS_MEDIA_COMMAND_IN_PROGRESS = 2,
    SYS_MEDIA_COMMAND_UNKNOWN = -1
} SYS_MEDIA_COMMAND_STATUS;
```

Members

Members	Description
SYS_MEDIA_COMMAND_COMPLETED = 0	Done OK and ready
SYS_MEDIA_COMMAND_QUEUED = 1	Scheduled but not started
SYS_MEDIA_COMMAND_IN_PROGRESS = 2	Currently being in transfer
SYS_MEDIA_COMMAND_UNKNOWN = -1	Unknown buffer

Description

Status of buffer

This enumeration contains the various status of buffer.

Remarks

None.

SYS_MEDIA_GEOMETRY Structure

Contains all the geometrical information of a media device.

C

```
typedef struct {
    SYS_MEDIA_PROPERTY mediaProperty;
    uint32_t numReadRegions;
    uint32_t numWriteRegions;
    uint32_t numEraseRegions;
    SYS_MEDIA_REGION_GEOMETRY * geometryTable;
} SYS_MEDIA_GEOMETRY;
```

Members

Members	Description
SYS_MEDIA_PROPERTY mediaProperty;	Properties of a Media. For a device, if multiple properties are applicable, they can be ORed
uint32_t numReadRegions;	Number of Read Regions
uint32_t numWriteRegions;	Number of Write Regions
uint32_t numEraseRegions;	Number of Erase Regions
SYS_MEDIA_REGION_GEOMETRY * geometryTable;	Pointer to the table containing the geometry information

Description

SYS Media Device Geometry

This structure contains all the geometrical information of a media device. the structure also has property of the media like media is one time programmable (OTP) or Read Only etc.

Remarks

A memory device can have multiple erase block regions. Sum of all the regions is the total memory size of the device.

SYS_MEDIA_GEOMETRY_TABLE_ERASE_ENTRY Macro

C

```
#define SYS_MEDIA_GEOMETRY_TABLE_ERASE_ENTRY ( 2 )
```

Description

Erase Region Geometry Table Index Numbers

SYS_MEDIA_GEOMETRY_TABLE_READ_ENTRY Macro

C

```
#define SYS_MEDIA_GEOMETRY_TABLE_READ_ENTRY ( 0 )
```

Description

Read Region Geometry Table Index Numbers

SYS_MEDIA_GEOMETRY_TABLE_WRITE_ENTRY Macro

C

```
#define SYS_MEDIA_GEOMETRY_TABLE_WRITE_ENTRY ( 1 )
```

Description

Write Region Geometry Table Index Numbers

SYS_MEDIA_REGION_GEOMETRY Structure

Contains information of a sys media region.

C

```
typedef struct {
    uint32_t blockSize;
    uint32_t numBlocks;
} SYS_MEDIA_REGION_GEOMETRY;
```

Members

Members	Description
uint32_t blockSize;	Size of a each block in Bytes
uint32_t numBlocks;	Number of Blocks of identical size within the Region

Description

SYS Media Region Geometry Structure

This structure contains the information of a sys media region.

Remarks

A media can have multiple regions. Sum of size of all the regions is the total memory size of the media. Each region is further divided into blocks of identical size.

SYS_MEDIA_PROPERTY Enumeration

Contains information of property of a media.

C

```
typedef enum {
    SYS_MEDIA_SUPPORTS_BYTE_WRITES = 0x01,
    SYS_MEDIA_SUPPORTS_READ_ONLY = 0x02,
    SYS_MEDIA_SUPPORTS_ONE_TIME_PROGRAMMING = 0x04,
    SYS_MEDIA_READ_IS_BLOCKING = 0x08,
    SYS_MEDIA_WRITE_IS_BLOCKING = 0x10
} SYS_MEDIA_PROPERTY;
```

Members

Members	Description
SYS_MEDIA_SUPPORTS_BYTE_WRITES = 0x01	Media supports Byte Write
SYS_MEDIA_SUPPORTS_READ_ONLY = 0x02	Media supports only Read operation
SYS_MEDIA_SUPPORTS_ONE_TIME_PROGRAMMING = 0x04	Media supports OTP (One Time Programming)
SYS_MEDIA_READ_IS_BLOCKING = 0x08	Read in blocking
SYS_MEDIA_WRITE_IS_BLOCKING = 0x10	Write is blocking

Description

SYS Media Property Structure

This structure contains the information of property of a media device.

Remarks

For a device, if multiple properties are applicable, they can be ORed together and used.

SYS_MEDIA_STATUS Enumeration

The state of media.

C

```
typedef enum {
    SYS_MEDIA_DETACHED,
    SYS_MEDIA_ATTACHED
} SYS_MEDIA_STATUS;
```

Members

Members	Description
SYS_MEDIA_DETACHED	Media is detached
SYS_MEDIA_ATTACHED	Media is attached

Description

Status of media

This enumeration states if the media is attached or not

Remarks

None.

SYS_MEDIA_BLOCK_COMMAND_HANDLE Type

Handle identifying block commands of the media.

C

```
typedef uintptr_t SYS_MEDIA_BLOCK_COMMAND_HANDLE;
```

Description

SYS Media Block Command Handle

A block command handle is returned by a call to the Read, Write, or Erase functions. This handle allows the application to track the completion of the operation. The handle is returned back to the client by the "event handler callback" function registered with the driver.

The handle assigned to a client request expires when the client has been notified of the completion of the operation (after event handler function that notifies the client returns) or after the buffer has been retired by the driver if no event handler callback was set.

Remarks

None.

SYS_MEDIA_BLOCK_COMMAND_HANDLE_INVALID Macro

Defines the invalid media block command handle.

C

```
#define SYS_MEDIA_BLOCK_COMMAND_HANDLE_INVALID
```

Description

Invalid media block command handle

This value defines invalid handle for the media block command. It is returned by read/write/erase routines when the request could not be taken.

Remarks

None.

b) Module System Services

SYS_MODULE_INIT Union

Initializes a module (including device drivers) as requested by the system.

C

```
typedef union {
    uint8_t value;
    struct {
        uint8_t reserved : 4;
    } sys;
} SYS_MODULE_INIT;
```

Members

Members	Description
uint8_t reserved : 4;	Module-definable field, module-specific usage

Description

System Module Init

This structure provides the necessary data to initialize or reinitialize a module (including device drivers). The structure can be extended in a module specific way as to carry module specific initialization data.

Remarks

This structure is used in the device driver routines DRV__Initialize and DRV__Reinitialize that are defined by each device driver.

SYS_STATUS Enumeration

Identifies the current status/state of a system module (including device drivers).

C

```
typedef enum {
    SYS_STATUS_ERROR_EXTENDED = -10,
    SYS_STATUS_ERROR = -1,
    SYS_STATUS_UNINITIALIZED = 0,
    SYS_STATUS_BUSY = 1,
    SYS_STATUS_READY = 2,
    SYS_STATUS_READY_EXTENDED = 10
} SYS_STATUS;
```

Members

Members	Description
SYS_STATUS_ERROR_EXTENDED = -10	Indicates that a non-system defined error has occurred. The caller must call the extended status routine for the module in question to identify the error.
SYS_STATUS_ERROR = -1	An unspecified error has occurred.
SYS_STATUS_UNINITIALIZED = 0	The module has not yet been initialized
SYS_STATUS_BUSY = 1	An operation is currently in progress
SYS_STATUS_READY = 2	Any previous operations have succeeded and the module is ready for additional operations
SYS_STATUS_READY_EXTENDED = 10	Indicates that the module is in a non-system defined ready/run state. The caller must call the extended status routine for the module in question to identify the state.

Description

System Module Status

This enumeration identifies the current status/state of a system module (including device drivers).

Remarks

This enumeration is the return type for the system-level status routine defined by each device driver or system module (for example, [DRV_I2C_Status](#)).

SYS_MODULE_INDEX Type

Identifies which instance of a system module should be initialized or opened.

C

```
typedef unsigned short int SYS_MODULE_INDEX;
```

Description

System Module Index

This data type identifies to which instance of a system module a call to that module's "Initialize" and "Open" routines refers.

Remarks

Each individual module will usually define macro names for the index values it supports (e.g., DRV_TMR_INDEX_1, DRV_TMR_INDEX_2, ...).

SYS_MODULE_OBJ Type

Handle to an instance of a system module.

C

```
typedef uintptr_t SYS_MODULE_OBJ;
```

Description

System Module Object

This data type is a handle to a specific instance of a system module (such as a device driver).

Remarks

Code outside of a specific module should consider this as an opaque type (much like a void *). Do not make any assumptions about base type as it may change in the future or about the value stored in a variable of this type.

SYS_MODULE_OBJ_INVALID Macro

Object handle value returned if unable to initialize the requested instance of a system module.

C

```
#define SYS_MODULE_OBJ_INVALID ((SYS_MODULE_OBJ) -1)
```

Description

System Module Object Invalid

This is the object handle value returned if unable to initialize the requested instance of a system module.

Remarks

Do not rely on the actual value of this constant. It may change in future implementations.

OSAL Library Help

This section describes the Operating System Abstraction Layer (OSAL) that is available in MPLAB Harmony.

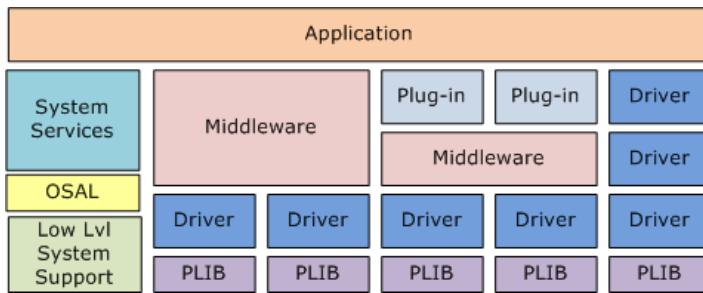
Introduction

The Operating System Abstraction Layer (OSAL) provides a consistent interface to allow MPLAB Harmony-compliant libraries to take advantage of Operating System constructs when running in an OS environment or when operating without one. It is designed to take care of the underlying differences between the available OS Kernels or when no kernel is present.

Description

The OSAL provides the interface to commonly available Real-Time Operating Systems (RTOS) such that MPLAB Harmony libraries may be written using a single interface to a minimal set of OS features needed to provide thread safety. The OSAL interface can be implemented appropriately to support almost any desired RTOS. For systems where no RTOS is available, or desired, a bare version of the OSAL supports either polled or interrupt-driven environments running directly on the hardware. This allows applications designed using MPLAB Harmony libraries to be executed in all three common embedded environments: polled (shared multi-tasking), interrupt-driven, or RTOS-based.

 **Note:** It is possible to make RTOS independent applications using the OSAL. However, as explained in the following section, that is not its purpose. Use and selection of an RTOS is usually determined by the availability of its unique features. And, utilizing those features will, of course, make an application OS-specific.



Scope

By design, the OSAL is a minimal API intended only to enable thread-safe operation for MPLAB Harmony libraries. It only exposes a very small subset of the capabilities of an operating system so that MPLAB Harmony libraries can use semaphores, mutexes, and critical sections (and a few other things) necessary to protect shared resources (data structures, peripheral registers, and other memory objects) from corruption by unsynchronized access by multiple threads. This is done to allow MPLAB Harmony libraries to be made compatible with the largest variety of operating systems, by using a minimal subset of some of the most common OS features. The OSAL is not intended to provide a complete abstraction of an RTOS, which is what you would normally do to implement a complete application. Abstracting an entire operating system is a much more complex task that is roughly equivalent to defining your own RTOS.

The OSAL is not designed to replace a commercial kernel, and therefore, the user is encouraged to use any of the specific features of their chosen RTOS in order to achieve best performance. As such, the OSAL can be considered to be an Operating System Compatibility Layer offering MPLAB Harmony-compliant libraries the required common functions to ensure correct operation in both RTOS and non-RTOS environments.

The common interface presented by the OSAL is designed to offer a set of services typically found on micro-kernel and mini-scheduler systems. Because of this it has no aspirations to provide an equivalent set of capabilities as those found on large multi-tasking systems such as μ CLinux™. The common services are designed to allow MPLAB Harmony to implement thread-safe Drivers and Middleware. The design intention is that drivers will use the minimal set of OSAL features necessary to ensure that they can safely operate in a multi-threaded environment yet can also compile and run correctly when no underlying RTOS is present. The range of features used by a driver is typically limited to these OSAL features (see the [Library Interface](#) section):

- Semaphore Functions
- Mutex Functions
- Critical Section Functions

Supported RTOS

RTOS	Release Type
FreeRTOS v10.0.1	Production

Using the Library

This section describes the basic architecture of the OSAL Library and provides information and examples on its use.

Description

Interface Header File: `osal.h`

The interface to the OSAL Library is defined in the `osal.h` header file. Any C language source (.c) file that uses the OSAL System Service library should include `osal.h`.

Library File: `osal_<vendor-specified RTOS name>.c` (i.e., FreeRTOS, etc.)

The OSAL Library consists of a basic implementation and individual ports of the OSAL to target operating systems. The basic implementation is used when any of the Third-Party Library RTOS is not instantiated.

When an RTOS is being used (i.e. if any of Third-Party Library RTOS is instantiated, Ex: FreeRTOS) then an external implementation file which provides the required interface wrappers should be added to the project. For instance for the FreeRTOS operating system the file `osal_freertos.c` should be added, while for the Micrium µC/OS-III operating system the file `osal_uicos3.c` should be added.

The basic implementation and some generic ports are provided with the Library, however, it is the responsibility of third-party vendors to supply an implementation file for operating systems that are not already supported.

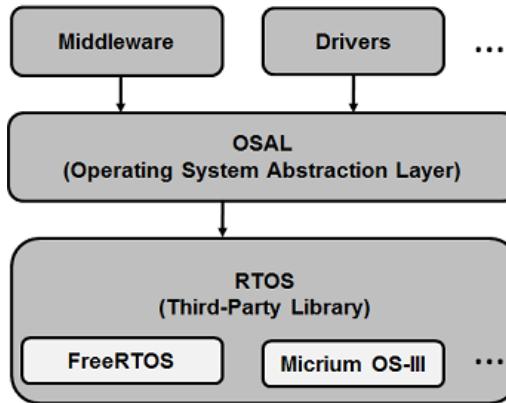
Abstraction Model

The OSAL Library provides a predefined set of functions and types that match common synchronization and communication services that an RTOS will typically provide. It is designed to be a lightweight abstraction model and deliberately excludes the much broader depth and breadth of services that a fully fledged RTOS provides. As such the interface defines only those core functions necessary for the MPLAB Harmony Drivers and middleware to operate in a multi-threaded environment.

Description

The common interface can easily be ported to many host Real-Time Operating Systems (RTOS) by third parties and the set of functions provides a basic level of RTOS compatibility. Where a specific RTOS does not implement a given architectural feature (e.g., events), the OSAL port for that RTOS should endeavor to imitate that feature using the constructs that are available. Although it is recognized that this may have a detrimental effect on the performance of that system it does allow MPLAB Harmony developers the broadest scope for using RTOS features in their designs.

The following diagram illustrates the OSAL Abstraction model.



Library Overview

This section provides an overview of the OSAL Library.

Description

The OSAL Library provides a defined interface such that driver and middleware developers will be able to create MPLAB Harmony code that can safely operate in a multi-threaded environment when a supported RTOS is present yet will still compile and function correctly when MPLAB Harmony is being used in a non-RTOS environment with an interrupt or non-interrupt driven application model.

At the application layer, the developer is encouraged to use the specific features of a chosen RTOS once it has been selected since this is likely to provide a more effective and rich programming environment.

The OSAL Library is deliberately designed to be a thin layer over an underlying RTOS, which presents a predefined interface to the common features used by the majority of Real-Time Operating Systems, which includes:

Library Interface Section	Description
Semaphore Functions	Binary and counting semaphores.
Mutex Functions	Thread and resource locking mechanism.
Critical Section Functions	Application and scheduler locking mechanism.
Memory Allocation Functions	Memory allocation primitives or wrappers.
OSAL Control Functions	OSAL initialization.

One of the primary design guidelines is that a host operating system may not be present and so any operations that the OSAL presents are designed to compile out to safe default implementations if no RTOS is present. This can mean the following:

- Implementing a dummy function that mimics typical RTOS behavior
- Implementing a `#define` or inline function that returns a 'safe' generic return value, such as 'true' or a 'call succeeded' status
- Returning a `OSAL_RESULT_NOT_IMPLEMENTED` value to indicate an unsupported operation
- Throwing an `OSAL_ASSERT` failure to indicate a terminal error that prevents operation under specific circumstances

How the Library Works

This section provides information on how the OSAL Library works.

Semaphores

The semaphore implements a method for thread synchronization. This synchronization can be either between one thread and another or between an ISR and a thread. A semaphore once signalled will unblock the highest priority thread currently pending on it.

Description

A semaphore can be used to lock a shared resource, although it is more normal to use a mutex for such an activity. Once obtained a semaphore should be posted back to enable it to be retaken at a later time or in another thread.

```
/* mainline code prior to OS start */
/* declare a variable of type semaphore handle */
OSAL_SEM_DECLARE(semSync);
/* create the semaphore */
OSAL_SEM_Create(&semSync, OSAL_SEM_TYPE_BINARY, 0, 0);

/* thread one */
...
/* take the semaphore without waiting */
OSAL_SEM_Pend(semSync, 0);
... perform some actions
/* return the semaphore */
OSAL_SEM_Post(semSync);
...

/* thread two must not execute until thread one has finished its operations*/
...
```

```
/* block on the semaphore */
OSAL_SEM_Pend(semSync, OSAL_WAIT_FOREVER);
... perform some more actions
/* return the semaphore */
OSAL_SEM_Post(semSync);
```

A semaphore can be signalled multiple times and so provides a method for an ISR to release a thread waiting on it. Even though the blocked thread never returns the semaphore, because the asynchronous ISR repeatedly posts it the next time the thread wants to pend on the semaphore it will be available. By moving the majority of interrupt service processing from the ISR to a high priority thread the system response time is improved and the eventual processing can take advantage of OSAL features such as mutexes and queues which would normally be harder to implement inside the ISR. This technique is known as deferred interrupt processing.

```
/* an example interrupt handler called from an ISR that performs task synchronization using a
semaphore */
void _ISRTasksRX(void) /* N.B. pseudo-code ISR */
{
    ...
    _DRV_USART_InterruptSourceStatusClear(_DRV_USART_GET_INT_SRC_RX(_DRV_USART_OBJ(dObj,
rxInterruptSource)));
    /* Release the receive semaphore unblocking any tasks */
    OSAL_SEM_PostISR(_DRV_USART_OBJ(dObj, rxSemID));
}
/* DRV_USART_TasksRX */
```

Mutex Operation

A mutex or mutual exclusion is used to protect a shared resource from access by multiple threads at the same time. A shared resource may be a common data structure in RAM or it may be a hardware peripheral. In either case a mutex can be used to ensure the integrity of the entire resource by only allowing one thread to access it at a time.

Description

The library must be written in such a way that before the shared resources is accessed the mutex has to be obtained. Once obtained the accesses should occur, and once complete the mutex should then be released. While no restrictions are enforced the sequence of operations between the lock and unlock should ideally take as few lines of code as possible to ensure good system performance.

The mutex may be implemented as a form of binary semaphore but an underlying RTOS will often add other features. It is normal to add the restriction that a mutex may only be unlocked from the thread that originally obtained the lock in the first place. The RTOS may also provide features to mitigate priority inversion problems (where a high priority thread blocks on a lower priority one holding a mutex) by providing priority inheritance allowing lower priority threads to be temporarily raised to complete and release a locked mutex.

```
/* perform operations on a shared data structure */
struct myDataStructure {
    uint16_t x;
    uint8_t y;
} myDataStructure;

...
OSAL_MUTEX_DECLARE(mutexDS);
OSAL_MUTEX_Create(&mutexDS);

...
/* wait 2 seconds to obtain the mutex */
if (OSAL_MUTEX_Lock(mutexDS, 2000) == OSAL_RESULT_TRUE)
{
    /* operate on the data structure */
    myDataStructure.x = 32;
    OSAL_MUTEX_Unlock(mutexDS);
}
```

Critical Section Operation

This section describes how critical sections are used.

Description

Critical sections are used to form sequences of code that must operate in an atomic manner. The interface allows for the possibility of two types of critical section.

- When the critical section is entered all interrupts on the microcontroller are disabled. This prevents the protected sequence of code from being interrupted and ensures the complete atomicity of the operation. This is denoted by the OSAL_CRIT_TYPE_HIGH value
- When the critical section is entered the RTOS scheduler is disabled. In this second case other threads are prevented from running however interrupts can still occur which allows any asynchronous events to still be received and for the temporal accuracy of the RTOS scheduler to be maintained. This is denoted by the OSAL_CRIT_TYPE_LOW value

Since the behavior in the two cases is different the type of critical section must be identified in both the call to enter and leave.

```
/* enter and leave a critical section disabling interrupts */
OSAL_CRIT_Enter(OSAL_CRIT_TYPE_HIGH);
/* perform an atomic sequence of code */
...
/* leave the critical section */
OSAL_CRIT_Leave(OSAL_CRIT_TYPE_HIGH);
```

The underlying RTOS may not support the second scenario, in which case the OSAL implementation will default to disabling all interrupts.

Memory Operation

This section describes the memory operation using the OSAL Library.

Description

The OSAL Library provides an interface to a memory allocation mechanism. The memory required for dynamic instantiation of variables is normally provided by allocating it from the heap. However the standard C library implementation of malloc and free are not considered thread safe and so OSAL specific functions must be used if MPLAB Harmony or the application requires dynamic memory during operation.

When operating without an underlying RTOS the OSAL memory allocators default to using standard malloc and free functions. However, when operating with an RTOS the calls will defer to the specific scheme used by the RTOS. This may involve multiple memory pools or it may simply involve adding a critical section around calls to malloc and free. It is left to the implementation to define the most appropriate scheme.

```
/* allocate a large buffer */
uint8_t* buffer;

buffer = OSAL_Malloc(8000);
if (buffer != NULL)
{
    ... manipulate the buffer
    /* free the buffer */
    OSAL_Free(buffer);
    buffer = NULL;
}
```

OSAL Operation

This section describes the OSAL control features.

Description

When the OSAL is using an underlying RTOS it may be necessary to allow the RTOS to perform one-time initialization before any calls to it are made. For instance, the RTOS might implement multiple memory pools for managing queues and semaphores, and it must be given the chance to create these pools before any of the objects are created. For this reason the application program

should call `OSAL_Initialize` early on and certainly before any MPLAB Harmony drivers or middleware is initialized (since these may also create OSAL objects at creation time).

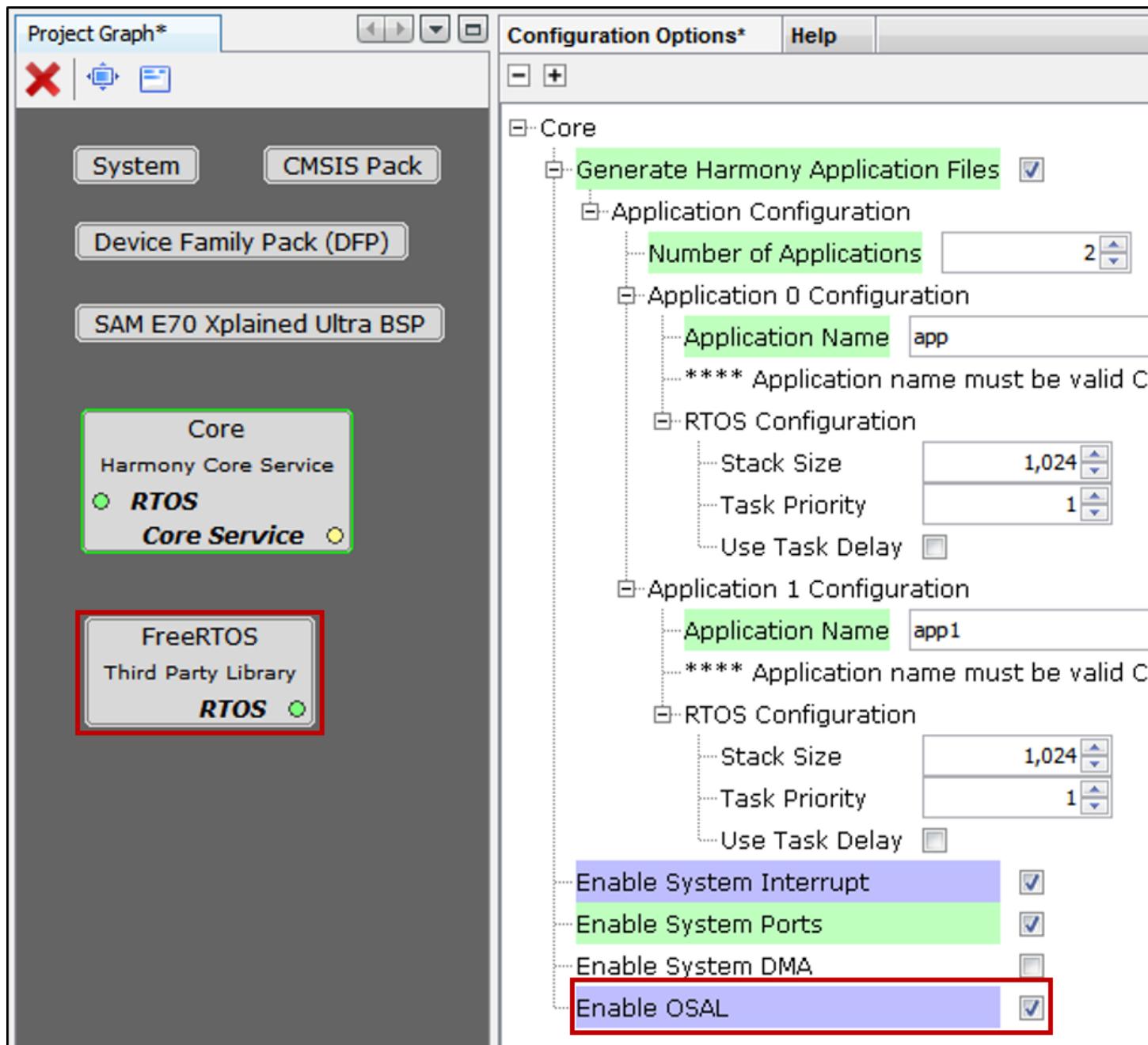
Once the OSAL is initialized and any other remaining parts of the system are configured correctly, the specific RTOS can be started.

Configuring the Library

This section provides information on how to configure the OSAL component.

Description

The OSAL can be configured through the MHC. The following figure shows the MHC configuration window for configuring the OSAL and a brief description of various configuration options.



The OSAL can be enabled by the user in two ways:

1. User can manually enable OSAL which is part of Harmony Core component.

2. OSAL will get auto enabled and set to "BareMetal" when Middleware or any Driver is instantiated. If any Third-Party Library i.e. RTOS is added then the respective OSAL Layer code will get generated. For instance if user instantiates FreeRTOS, then OSAL is set to "FreeRTOS" and "osal_freertos.c" code will get generated during code generation.

Building the Library

This section lists the files that are available in the OSAL Library.

Description

The following three tables list and describe the header (.h) and source (.c) files that implement this library. The parent folder for these files is <install-dir>/osal.

Interface File(s)

This table lists and describes the header files that must be included (i.e., using #include) by any code that uses this library for the selected RTOS.

Source File Name	Description
/osal.h	This file provides the interface definitions of the OSAL Library.

Required File(s)

 **MHC** *All of the required files are automatically added into the MPLAB X IDE project by the MHC when the library is selected for use.*

This table lists and describes the source and header files that must be included in the MPLAB X IDE project to build this library.

Source File Name	Description
/src/osal.c	Source files added to the project if using the "BareMetal" OSAL basic implementation used when no RTOS is present.
/src/osal_impl_basic.h	
/src/osal_freertos.c	Source files added to the project if using the FreeRTOS implementation for compatibility with the current version 10.0.1 of the FreeRTOS operating system from Amazon.
/src/osal_freertos.h	
/src/osal_uicos3.c	Source files added to the project if using the µC/OS-III implementation for compatibility with the µC/OS-III operating system from Micrium.
/src/osal/uicos3.h	

Optional File(s)

There are no optional files for the OSAL Library.

Library Interface

a) Semaphore Functions

	Name	Description
≡◊	OSAL_SEM_Create	Creates an OSAL Semaphore.
≡◊	OSAL_SEM_Delete	Deletes an OSAL Semaphore.
≡◊	OSAL_SEM_Pend	Waits on a semaphore. Returns true if the semaphore was obtained within the time limit.
≡◊	OSAL_SEM_Post	Posts a semaphore or increments a counting semaphore.
≡◊	OSAL_SEM_PostISR	Posts a semaphore or increments a counting semaphore from within an Interrupt Service Routine (ISR).
≡◊	OSAL_SEM_GetCount	Returns the current value of a counting semaphore.

b) Mutex Functions

	Name	Description
≡◊	OSAL_MUTEX_Create	Creates a mutex.
≡◊	OSAL_MUTEX_Delete	Deletes a mutex.
≡◊	OSAL_MUTEX_Lock	Locks a mutex.
≡◊	OSAL_MUTEX_Unlock	Unlocks a mutex.

c) Critical Section Functions

	Name	Description
≡	OSAL_CRIT_Enter	Enters a critical section with the specified severity level.
≡	OSAL_CRIT_Leave	Leaves a critical section with the specified severity level.

d) Memory Allocation Functions

	Name	Description
≡	OSAL_Malloc	Allocates memory using the OSAL default allocator.
≡	OSAL_Free	Deallocates a block of memory and return to the default pool.

e) OSAL Control Functions

	Name	Description
≡	OSAL_Initialize	Performs OSAL initialization.
≡	OSAL_Name	Obtains the name of the underlying RTOS.

f) Data Types and Constants

	Name	Description
≡	OSAL_CRIT_TYPE	Enumerated type representing the possible types of critical section.
≡	OSAL_RESULT	Enumerated type representing the general return value from OSAL functions.
≡	OSAL_SEM_TYPE	Enumerated type representing the possible types of semaphore.
	OSAL_SEM_DECLARE	Declares an OSAL semaphore.
	OSAL_MUTEX_DECLARE	Declares an OSAL mutex.
	_OSAL_H	This is macro _OSAL_H.

Description

This section describes the APIs of the OSAL Library. Refer to each section for a description.

a) Semaphore Functions

OSAL_SEM_Create Function

Creates an OSAL Semaphore.

C

```
OSAL_RESULT OSAL_SEM_Create(OSAL_SEM_HANDLE_TYPE* semID, OSAL_SEM_TYPE type, uint8_t maxCount,
                            uint8_t initialCount);
```

Returns

- OSAL_RESULT_TRUE - Semaphore created
- OSAL_RESULT_FALSE - Semaphore creation failed
- semID - Updated with valid semaphore handle if call was successful

Description

This function creates an OSAL binary or counting semaphore. If OSAL_SEM_TYPE_BINARY is specified, the maxcount and initialCount values are ignored.

Remarks

None.

Preconditions

Semaphore must have been declared.

Example

```
OSAL_SEM_Create(&mySemID, OSAL_SEM_TYPE_COUNTING, 10, 5);
```

Parameters

Parameters	Description
semID	Pointer to the Semaphore ID
type	If OSAL_SEM_TYPE_BINARY, create a binary semaphore. If OSAL_SEM_TYPE_COUNTING, create a counting semaphore with the specified count values.
maxCount	Maximum value for a counting semaphore (ignored for a BINARY semaphore). This parameter is ignored for Express Logic ThreadX, SEGGER embOS, and Micrium/OS-III as these RTOS libraries do not support this parameter.
initialCount	Starting count value for the semaphore (ignored for a BINARY semaphore) This should be less than or equal to maxCount when used with a RTOS library that supports the maxCount parameter (i.e., FreeRTOS and OPENRTOS)

Function

```
OSAL_RESULT OSAL_SEM_Create(OSAL_SEM_HANDLE_TYPE* semID, OSAL_SEM_TYPE type,
uint8_t maxCount, uint8_t initialCount)
```

OSAL_SEM_Delete Function

Deletes an OSAL Semaphore.

C

```
OSAL_RESULT OSAL_SEM_Delete(OSAL_SEM_HANDLE_TYPE* semID);
```

Returns

- OSAL_RESULT_TRUE - Semaphore deleted
- OSAL_RESULT_FALSE - Semaphore deletion failed

Description

This function deletes an OSAL semaphore.

Remarks

None.

Preconditions

Semaphore must have been created.

Example

```
OSAL_SEM_Delete(&mySemID);
```

Parameters

Parameters	Description
semID	Pointer to the Semaphore ID

Function

```
OSAL_RESULT OSAL_SEM_Delete(OSAL_SEM_HANDLE_TYPE* semID)
```

OSAL_SEM_Pend Function

Waits on a semaphore. Returns true if the semaphore was obtained within the time limit.

C

```
OSAL_RESULT OSAL_SEM_Pend(OSAL_SEM_HANDLE_TYPE* semID, uint16_t waitMS);
```

Returns

- OSAL_RESULT_TRUE - Semaphore obtained
- OSAL_RESULT_FALSE - Semaphore not obtained or time-out occurred

Description

This function is a blocking function call that waits (i.e., pends) on a semaphore. The function will return true if the semaphore has been obtained, or false if it was not available or the time limit was exceeded.

Remarks

None.

Preconditions

Semaphore must have been created.

Example

```
if (OSAL_SEM_Pend(&semUARTRX, 50) == OSAL_RESULT_TRUE)
{
    // character available
    c = DRV_USART_ReadByte(drvID);
    ...
}
else
{
    // character not available, resend prompt
    ...
}
```

Parameters

Parameters	Description
semID	Pointer to the Semaphore ID
waitMS	Time limit to wait in milliseconds: <ul style="list-style-type: none"> • 0 - do not wait • OSAL_WAIT_FOREVER - return only when semaphore is obtained • Other values - time-out delay

Function

```
OSAL_RESULT OSAL_SEM_Pend(OSAL_SEM_HANDLE_TYPE* semID, uint16_t waitMS)
```

OSAL_SEM_Post Function

Posts a semaphore or increments a counting semaphore.

C

```
OSAL_RESULT OSAL_SEM_Post(OSAL_SEM_HANDLE_TYPE* semID);
```

Returns

- OSAL_RESULT_TRUE - Semaphore posted
- OSAL_RESULT_FALSE - Semaphore not posted

Description

This function posts a binary semaphore or increments a counting semaphore. The highest priority task currently blocked on the semaphore will be released and made ready to run.

Remarks

None.

Preconditions

Semaphore must have been created.

Example

```
OSAL_SEM_Post(&semSignal);
```

Parameters

Parameters	Description
semID	The semID

Function

OSAL_RESULT OSAL_SEM_Post(OSAL_SEM_HANDLE_TYPE* semID)

OSAL_SEM_PostISR Function

Posts a semaphore or increments a counting semaphore from within an Interrupt Service Routine (ISR).

C

```
OSAL_RESULT OSAL_SEM_PostISR(OSAL_SEM_HANDLE_TYPE* semID);
```

Returns

- OSAL_RESULT_TRUE - Semaphore posted
- OSAL_RESULT_FALSE - Semaphore not posted

Description

This function posts a binary semaphore or increments a counting semaphore. The highest priority task currently blocked on the semaphore will be released and made ready to run. This form of the post function should be used inside an ISR.

Remarks

This version of the **OSAL_SEM_Post** function should be used if the program is, or may be, operating inside an ISR. The OSAL will take the necessary steps to ensure correct operation possibly disabling interrupts or entering a critical section. The exact requirements will depend upon the particular RTOS being used.

Preconditions

Semaphore must have been created.

Example

```
void __ISR(UART_2_VECTOR) _UART2RXHandler()
{
    char c;

    // read the character
    c = U2RXREG;
    // clear the interrupt flag
    IFS1bits.U2IF = 0;
    // post a semaphore indicating a character has been received
    OSAL_SEM_PostISR(&semSignal);

}
```

Parameters

Parameters	Description
semID	Pointer to the Semaphore ID

Function

`OSAL_RESULT OSAL_SEM_PostISR(OSAL_SEM_HANDLE_TYPE* semID)`

OSAL_SEM_GetCount Function

Returns the current value of a counting semaphore.

C

```
uint8_t OSAL_SEM_GetCount(OSAL_SEM_HANDLE_TYPE* semID);
```

Returns

- 0 - Semaphore is unavailable
- 1-255 - Current value of the counting semaphore

Description

This function returns the current value of a counting semaphore. The value returned is assumed to be a single value ranging from 0-255.

Remarks

None.

Preconditions

Semaphore must have been created.

Example

```
uint8_t semCount;

semCount = OSAL_SEM_GetCount(semUART);

if (semCount > 0)
{
    // obtain the semaphore
    if (OSAL_SEM_Pend(&semUART) == OSAL_RESULT_TRUE)
    {
        // perform processing on the comm channel
        ...
    }
}
else
{
    // no comm channels available
    ...
}
```

Parameters

Parameters	Description
semID	Pointer to the Semaphore ID

Function

`uint8_t OSAL_SEM_GetCount(OSAL_SEM_HANDLE_TYPE* semID)`

b) Mutex Functions

OSAL_MUTEX_Create Function

Creates a mutex.

C

```
OSAL_RESULT OSAL_MUTEX_Create(OSAL_MUTEX_HANDLE_TYPE* mutexID);
```

Returns

- OSAL_RESULT_TRUE - Mutex successfully created
- OSAL_RESULT_FALSE - Mutex failed to be created

Description

This function creates a mutex, allocating storage if required and placing the mutex handle into the passed parameter.

Remarks

None.

Preconditions

Mutex must have been declared.

Example

```
OSAL_MUTEX_HANDLE_TYPE mutexData;

OSAL_MUTEX_Create(&mutexData);
...
if (OSAL_MUTEX_Lock(&mutexData, 1000) == OSAL_RESULT_TRUE)
{
    // manipulate the shared data
    ...
}
```

Parameters

Parameters	Description
mutexID	Pointer to the mutex handle

Function

[OSAL_RESULT](#) OSAL_MUTEX_Create(OSAL_MUTEX_HANDLE_TYPE* mutexID)

OSAL_MUTEX_Delete Function

Deletes a mutex.

C

```
OSAL_RESULT OSAL_MUTEX_Delete(OSAL_MUTEX_HANDLE_TYPE* mutexID);
```

Returns

- OSAL_RESULT_TRUE - Mutex successfully deleted
- OSAL_RESULT_FALSE - Mutex failed to be deleted

Description

This function deletes a mutex and frees associated storage if required.

Remarks

None.

Preconditions

None.

Example

```
OSAL_MUTEX_Delete(&mutexData);
```

Parameters

Parameters	Description
mutexID	Pointer to the mutex handle

Function

[OSAL_RESULT OSAL_MUTEX_Delete\(OSAL_MUTEX_HANDLE_TYPE* mutexID\)](#)

OSAL_MUTEX_Lock Function

Locks a mutex.

C

```
OSAL_RESULT OSAL_MUTEX_Lock(OSAL_MUTEX_HANDLE_TYPE* mutexID, uint16_t waitMS);
```

Returns

- OSAL_RESULT_TRUE - Mutex successfully obtained
- OSAL_RESULT_FALSE - Mutex failed to be obtained or time-out occurred

Description

This function locks a mutex, waiting for the specified time-out. If it cannot be obtained or the time-out period elapses 'false' is returned.

Remarks

None.

Preconditions

Mutex must have been created.

Example

```
...
if (OSAL_MUTEX_Lock(&mutexData, 1000) == OSAL_RESULT_TRUE)
{
    // manipulate the shared data
    ...

    // unlock the mutex
    OSAL_MUTEX_Unlock(&mutexData);
}
```

Parameters

Parameters	Description
mutexID	Pointer to the mutex handle
waitMS	Time-out value in milliseconds: <ul style="list-style-type: none"> • 0, do not wait return immediately • OSAL_WAIT_FOREVER, wait until mutex is obtained before returning • Other values, time-out delay

Function

[OSAL_RESULT OSAL_MUTEX_Lock\(OSAL_MUTEX_HANDLE_TYPE* mutexID, uint16_t waitMS\)](#)

OSAL_MUTEX_Unlock Function

Unlocks a mutex.

C

```
OSAL_RESULT OSAL_MUTEX_Unlock(OSAL_MUTEX_HANDLE_TYPE* mutexID);
```

Returns

- OSAL_RESULT_TRUE - Mutex released
- OSAL_RESULT_FALSE - Mutex failed to be released or error occurred

Description

This function unlocks a previously obtained mutex.

Remarks

None.

Preconditions

Mutex must have been created.

Example

```
...
if (OSAL_MUTEX_Lock(&mutexData, 1000) == OSAL_RESULT_TRUE)
{
    // manipulate the shared data
    ...

    // unlock the mutex
    OSAL_MUTEX_Unlock(&mutexData);
}
```

Parameters

Parameters	Description
mutexID	Pointer to the mutex handle

Function

[OSAL_RESULT](#) OSAL_MUTEX_Unlock(OSAL_MUTEX_HANDLE_TYPE* mutexID)

c) Critical Section Functions

OSAL_CRIT_Enter Function

Enters a critical section with the specified severity level.

C

```
OSAL_CRITSECT_DATA_TYPE OSAL_CRIT_Enter(OSAL_CRIT_TYPE severity);
```

Returns

A data type of OSAL_CRITSECT_DATA_TYPE, this value represents the state of interrupts before entering the critical section.

Description

This function enters a critical section of code. It is assumed that the sequence of operations bounded by the enter and leave critical section operations is treated as one atomic sequence that will not be disturbed. This function should be paired with

[OSAL_CRIT_Leave\(\)](#).

Remarks

The sequence of operations bounded by the OSAL_CRIT_Enter and [OSAL_CRIT_Leave](#) form a critical section. The severity level defines whether the RTOS should perform task locking or completely disable all interrupts.

Preconditions

None.

Example

```
OSAL_CRITSECT_DATA_TYPE IntState;
// prevent other tasks preempting this sequence of code
IntState = OSAL_CRIT_Enter(OSAL_CRIT_TYPE_HIGH);
// modify the peripheral
DRV_USART_Reinitialize( objUSART, &initData );
OSAL_CRIT_Leave(OSAL_CRIT_TYPE_HIGH, IntState);
```

Parameters

Parameters	Description
severity	OSAL_CRIT_TYPE_LOW, The RTOS should disable all other running tasks effectively locking the scheduling mechanism. OSAL_CRIT_TYPE_HIGH, The RTOS should disable all possible interrupts sources including the scheduler ensuring that the sequence of code operates without interruption. The state of interrupts are returned to the user before they are disabled.

Function

OSAL_CRITSECT_DATA_TYPE void OSAL_CRIT_Enter([OSAL_CRIT_TYPE](#) severity)

OSAL_CRIT_Leave Function

Leaves a critical section with the specified severity level.

C

```
void OSAL_CRIT_Leave(OSAL_CRIT_TYPE severity, OSAL_CRITSECT_DATA_TYPE status);
```

Returns

None.

Description

This function leaves a critical section of code. It is assumed that the sequence of operations bounded by the enter and leave critical section operations is treated as one atomic sequence that will not be disturbed. The severity should match the severity level used in the corresponding [OSAL_CRIT_Enter](#) call to ensure that the RTOS carries out the correct action.

Remarks

The sequence of operations bounded by the [OSAL_CRIT_Enter](#) and [OSAL_CRIT_Leave](#) form a critical section. The severity level defines whether the RTOS should perform task locking or completely disable all interrupts.

Preconditions

None.

Example

```
OSAL_CRITSECT_DATA_TYPE IntState;
// prevent other tasks preempting this sequence of code
intState = OSAL_CRIT_Enter(OSAL_CRIT_TYPE_LOW);
// modify the peripheral
DRV_USART_Reinitialize( objUSART, &initData );
OSAL_CRIT_Leave(OSAL_CRIT_TYPE_LOW, IntState);
```

Parameters

Parameters	Description
severity	OSAL_CRIT_TYPE_LOW, The scheduler will be unlocked, if no other nested calls to OSAL_CRIT_ENTER have been made. OSAL_CRIT_TYPE_HIGH, Interrupts are returned to the state passed into this function. The state should be saved by an earlier call to OSAL_CRIT_Enter .
status	The value which will be used to set the state of global interrupts, if OSAL_CRIT_TYPE_HIGH is passed in.

Function

```
void OSAL_CRIT_Leave( OSAL\_CRIT\_TYPE severity, OSAL_CRITSECT_DATA_TYPE status)
```

d) Memory Allocation Functions

OSAL_Malloc Function

Allocates memory using the OSAL default allocator.

C

```
void* OSAL_Malloc(size_t size);
```

Returns

Pointer to the block of allocated memory. NULL is returned if memory could not be allocated.

Description

This function allocates a block of memory from the default allocator from the underlying RTOS. If no RTOS is present, it defaults to malloc. Many operating systems incorporate their own memory allocation scheme, using pools, blocks or by wrapping the standard C library functions in a critical section. Since a MPLAB Harmony application may not know what target OS is being used (if any), this function ensures that the correct thread-safe memory allocator will be used.

Remarks

None.

Preconditions

None.

Example

```
// create a working array
uint8_t* pData;

pData = OSAL_Malloc(32);
if (pData != NULL)
{
    ...
}
```

Parameters

Parameters	Description
size	Size of the requested memory block in bytes

Function

```
void* OSAL_Malloc(size_t size)
```

OSAL_Free Function

Deallocates a block of memory and return to the default pool.

C

```
void OSAL_Free(void* pData);
```

Returns

None.

Description

This function deallocates memory and returns it to the default pool. In an RTOS-based application, the memory may have been allocated from multiple pools or simply from the heap. In non-RTOS applications, this function calls the C standard function free.

Remarks

None.

Preconditions

None.

Example

```
// create a working array
uint8_t* pData;

pData = OSAL_Malloc(32);
if (pData != NULL)
{
    ...

    // deallocate the memory
    OSAL_Free(pData);
    // and prevent it accidentally being used again
    pData = NULL;
}
```

Parameters

Parameters	Description
pData	Pointer to the memory block to be set free

Function

```
void OSAL_Free(void* pData)
```

e) OSAL Control Functions

OSAL_Initialize Function

Performs OSAL initialization.

C

```
OSAL_RESULT OSAL_Initialize();
```

Returns

OSAL_RESULT_TRUE - Initialization completed successfully.

Description

This function performs OSAL initialization. This function should be called near the start of main in an application that will use an underlying RTOS. This permits the RTOS to perform any one time initialization before the application attempts to create drivers or other items that may use the RTOS. Typical actions performed by OSAL_Initialize would be to allocate and prepare any memory pools for later use.

Remarks

None.

Preconditions

None.

Example

```
int main()
{
    OSAL_Initialize();

    App_Init();
    OSAL_Start();
}
```

Function

[OSAL_RESULT OSAL_Initialize\(\)](#)

OSAL_Name Function

Obtains the name of the underlying RTOS.

C

```
const char* OSAL_Name();
```

Returns

const char* - Name of the underlying RTOS or NULL

Description

This function returns a const char* to the textual name of the RTOS. The name is a NULL terminated string.

Remarks

None.

Preconditions

None.

Example

```
// get the RTOS name
const char* sName;

sName = OSAL_Name();
sprintf(buff, "RTOS: %s", sName);
```

Function

const char* OSAL_Name()

f) Data Types and Constants

OSAL_CRIT_TYPE Enumeration

Enumerated type representing the possible types of critical section.

C

```
enum OSAL_CRIT_TYPE {
    OSAL_CRIT_TYPE_LOW,
    OSAL_CRIT_TYPE_HIGH
};
```

Description

OSAL Critical Type

This enum represents possible critical section types.

OSAL_CRIT_TYPE_LOW - Low priority critical section, can be formed by locking the scheduler (if supported by RTOS)
OSAL_CRIT_TYPE_HIGH - High priority critical section, will be formed by disabling all interrupts.

Remarks

Critical section types.

OSAL_RESULT Enumeration

Enumerated type representing the general return value from OSAL functions.

C

```
enum OSAL_RESULT {
    OSAL_RESULT_NOT_IMPLEMENTED = -1,
    OSAL_RESULT_FALSE = 0,
    OSAL_RESULT_TRUE = 1
};
```

Description

OSAL Result type

This enum represents possible return types from OSAL functions.

Remarks

These enum values are the possible return values from OSAL functions where a standard success/fail type response is required. The majority of OSAL functions will return this type with a few exceptions.

OSAL_SEM_TYPE Enumeration

Enumerated type representing the possible types of semaphore.

C

```
enum OSAL_SEM_TYPE {
    OSAL_SEM_TYPE_BINARY,
    OSAL_SEM_TYPE_COUNTING
};
```

Description

OSAL Semaphore Type

This enum represents possible semaphore types.

OSAL_SEM_TYPE_BINARY - Simple binary type that can be taken once

OSAL_SEM_TYPE_COUNTING - Complex type that can be taken set number of times defined at creation time

Remarks

Binary and counting semaphore type.

OSAL_SEM_DECLARE Macro

Declares an OSAL semaphore.

C

```
#define OSAL_SEM_DECLARE(semID) OSAL_SEM_HANDLE_TYPE semID
```

Description

OSAL_SEM_Declare(semID)

This function declares a data item of type OSAL_SEM_HANDLE_TYPE.

Remarks

None.

OSAL_MUTEX_DECLARE Macro

Declares an OSAL mutex.

C

```
#define OSAL_MUTEX_DECLARE(mutexID) OSAL_MUTEX_HANDLE_TYPE mutexID
```

Description

OSAL_MUTEX_Declare(mutexID)

This function declares a data item of type OSAL_MUTEX_HANDLE_TYPE.

Remarks

None.

// DOM-IGNORE-BEGIN

Place the definition of the OSAL_MUTEX_Declare macro inside each specific implementation file. Not all implementation files use the same definition. The type for each individual RTOS is different, and to handle this properly in the code, each implementation must define its own declaration. ****REMOVE THIS NOTE AND THE DOM STATEMENTS IF USING THIS API IN A FILE THAT IS INCLUDED IN THE MPLAB HARMONY INSTALLATION**** // DOM-IGNORE-END

_OSAL_H Macro

C

```
#define _OSAL_H
```

Description

This is macro _OSAL_H.

Applications Help

This section provides help for the Drivers, System Service, Middleware applications that are available in the Microchip 32 bit Harmony Core Package (CORE).

Refer to each applications help section

Driver Applications

This section provides help for the Driver applications.

I2C Driver Applications

Async

Name	Description
i2c_eeprom	This example application shows how to use the I ² C driver in asynchronous mode to perform operations on the EEPROM.
i2c_multi_slave	This example application shows how to use the I ² C driver in asynchronous mode to communicate with the external EEPROM and temperature sensor.

Sync

Name	Description
i2c_eeprom	This example application shows how to use the I ² C driver in synchronous mode to perform operations on the EEPROM.
i2c_multi_slave	This example application shows how to use the I ² C driver in synchronous mode to communicate with the external EEPROM and temperature sensor.

Description

This section provides help for the I²C driver applications.

Async

i2c_eeprom

This example application shows how to use the I²C driver in asynchronous mode to perform operations on the EEPROM.

Description

This example uses the I²C driver in asynchronous mode to communicate with the EEPROM to perform write and read operations in both Bare-Metal and RTOS environment.

The application communicates with the following EEPROMs based on the project configurations selected.

- External AT24CM02 EEPROM
- On-Board AT24MAC402

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/i2c/async/i2c_eeprom/firmware
------------------	--

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mk_gp_db.X	PIC32MK General Purpose (GP) Development Board
pic32mx470_curiosity.X	PIC32MX Curiosity Development Board
pic32mx_xlp_sk.X	PIC32MX XLP Starter Kit
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_l21_xpro.X	SAM L21 Xplained Pro Evaluation Kit
sam_v71_xult.X	SAM V71 Xplained Ultra Evaluation Kit
sam_v71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek.IAR	SAM9X60 evaluation kit
sam_9x60_ek_freertos.IAR	SAM9X60 evaluation kit + FreeRTOS

MPLAB Harmony Configuration

This section provides information on the MHC configurations.

Description

Components used:

- I²C Driver (Asynchronous mode)

The following components used may vary based on the project configuration selected:

- TWIHS or SERCOM or FLEXCOM PLIB or I²C BB (I2C Bit-bang library)
- Board Support Package (BSP)
- Timer
- FreeRTOS

Other MHC Settings:

- Configure Pins for TWIHS or SERCOM or FLEXCOM peripheral library in Pin Settings based on project configuration selected
- Configure EEPROM write protect pin in Pin Settings

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mk_gp_db.X

- **Hardware Used**

- PIC32MK General Purpose (GP) Development Board

- **Hardware Setup**

- Connect micro USB cable to the 'Debug USB' connector(J12) on the board to the computer.

- Install an [EEPROM 3 click](#) board on to the mikroBUS socket J8 of **PIC32MK General Purpose (GP) Development Board**

2. Project pic32mx470_curiosity.X

- **Hardware Used**

- [PIC32MX Curiosity Development Board](#)

- [EEPROM 3 click](#) board

- **Hardware Setup**

- Connect mini USB cable to the 'Debug USB' connector(J3) on the board to the computer.

- Install an [EEPROM 3 click](#) board on to the mikroBUS socket J5 of **PIC32MX Curiosity Development Board**

- **Note:** Ensure that the series resistors on the mikroBUS headers are of value **0 Ohms**.

3. Project pic32mx_xlp_sk.X

- **Hardware Used**

- [PIC32MX XLP Starter Kit](#)

- **Hardware Setup**

- Connect micro USB cable to the 'Debug USB' connector(J9) on the board to the computer.

- Install an [EEPROM 3 click](#) board on to the mikroBUS socket J5 of **PIC32MX XLP Starter Kit**

4. Project sam_c21n_xpro.X.

- **Hardware Used:**

- [SAM C21N Xplained Pro Evaluation Kit](#)

- **Hardware Setup:**

- Install an [EEPROM 3 click](#) board on to the [mikroBUS Xplained Pro](#) board

- Connect the [mikroBUS Xplained Pro](#) board to the EXT2 header of the [SAM C21N Xplained Pro Evaluation Kit](#)

5. Project sam_e54_xpro_freertos.X.

- **Hardware Used:**

- [SAM E54 Xplained Pro Evaluation Kit](#)

- **Hardware Setup:**

- No special hardware setup required, [SAM E54 Xplained Pro Evaluation Kit](#) has on-board EEPROM

6. Project sam_e70_xult.X.

7. Project sam_e70_xult_freertos.X.

- **Hardware Used:**

- [SAM E70 Xplained Ultra Evaluation Kit](#)

- **Hardware Setup:**

- No special hardware setup required, [SAM E70 Xplained Ultra Evaluation Kit](#) has an On-Board EEPROM

8. Project sam_l21_xpro.X

- **Hardware Used**

- [SAM L21 Xplained Pro Evaluation Kit](#)

- **Hardware Setup**

- Install an [EEPROM 3 click](#) board on to the [mikroBUS Xplained Pro](#) board

- Connect the [mikroBUS Xplained Pro](#) board to the EXT1 header of the [SAM L21 Xplained Pro Evaluation Kit](#)

9. Project sam_v71_xult.X.**10. Project sam_v71_xult_freertos.X.****• Hardware Used:**

- SAM V71 Xplained Ultra Evaluation Kit

• Hardware Setup:

- No special hardware setup required, [SAM V71 Xplained Ultra Evaluation Kit](#) has on-board EEPROM

11. Project sam_a5d2_xult_freertos.IAR**• Hardware Used**

- [SAM A5D2 Xplained Ultra board](#)
- SD Card with FAT32 file system

• Hardware Setup

- Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - No special hardware setup required, [SAM A5D2 Xplained Ultra board](#) has an On-Board EEPROM

12. Project sam_9x60_ek.IAR**13. Project sam_9x60_ek_freertos.IAR****• Hardware Used**

- SAM 9X60 Evaluation Kit board
- [EEPROM 3 click](#) board
- SD Card with FAT32 file system

• Hardware Setup

- Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
 - Insert [EEPROM 3 click](#) board into MIKROBUS Connector J15.
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Note: Reset push button on SAM9X60 EK is labeled as SW3

Running the Application

This section provides information on how to run the application.

Description**MPLAB X IDE**

1. Connect a USB cable to the DEBUG port.
2. Build and program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED is turned ON when the data read from EEPROM matches with the written data

The following table provides the LED name:

Kit Name	LED Name
PIC32MK General Purpose (GP) Development Board	LED 1
PIC32MX Curiosity Development Board	LED 1
PIC32MX XLP Starter Kit	LED 1 (Red)
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0

SAM E70 Xplained Ultra Evaluation Kit	LED 1
SAM L21 Xplained Pro Evaluation Kit	LED 0
SAM V71 Xplained Ultra Evaluation Kit	LED 0

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED is turned ON when the data read from EEPROM matches with the written data

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)
SAM9X60 evaluation kit	RGB_LED (Green)

i2c_multi_slave

This example application shows how to use the I²C driver in asynchronous mode to communicate with the external EEPROM and temperature sensor.

Description

The application demonstrates the multi-client feature of the I²C driver in asynchronous mode. The example uses a [IO1 Xplained Pro Extension Kit](#) that has a temperature sensor and an EEPROM interfaced on the same I²C bus.

Two application tasks are created which act as clients to the same instance of the I²C driver:

APP_I2C_TEMP_SENSOR_Tasks:

- Reads temperature every 1 second, prints on console and notifies the EEPROM client
- The Time System Service is used to generate a callback every 1 second

APP_I2C_EEPROM_Tasks:

- Writes temperature values to the EEPROM once the temperature read complete notification is received
- Reads and prints the last five saved temperature data back from the EEPROM when user enters any key on the console.

Building the Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/driver/i2c/async/i2c_multi_slave/firmware
------------------	---

To build the application, refer to the following table and open the appropriate project file in the MPLAB X IDE:

Project Name	Description
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit
sam_d20_xpro.X	SAM D20 Xplained Pro Evaluation Kit
sam_d21_xpro.X	SAM D21 Xplained Pro Evaluation Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit

sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_l21_xpro.X	SAM L21 Xplained Pro Evaluation Kit
sam_l22_xpro.X	SAM L22 Xplained Pro Evaluation Kit
sam_v71_xult.X	SAM V71 Xplained Ultra Evaluation Kit
sam_v71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- I²C Driver (Asynchronous mode). The Number of Clients is set to 2
- Time System Service
- TC peripheral library
- System Console

The following components used may vary based on the project configuration selected:

- TWIHS or SERCOM peripheral library
- USART or SERCOM peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Settings:

- Configure Pins for TWIHS or SERCOM peripheral library in Pin Settings based on project configuration selected
- Configure Pins for USART or SERCOM peripheral library in Pin Settings based on project configuration selected

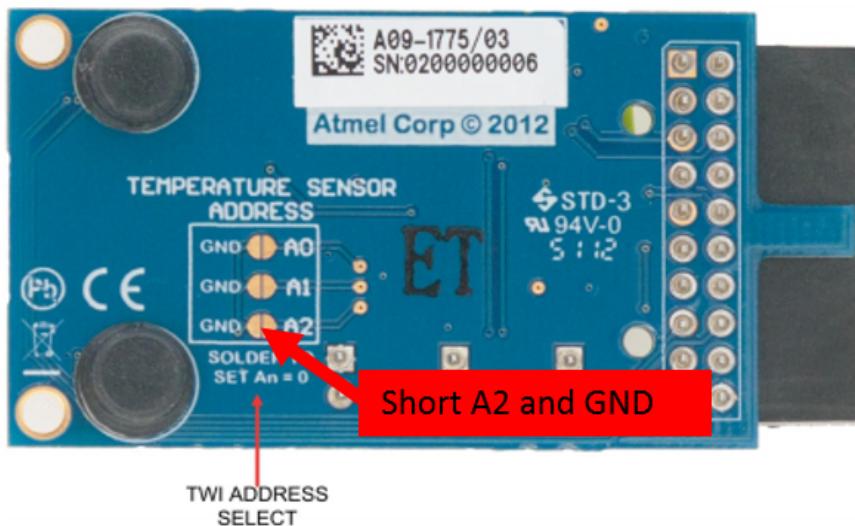
Hardware Setup

This section describes how to configure the supported hardware.

Description

Common Hardware Setup:

- [IO1 Xplained Pro Extension Kit](#) Address select:



- The A2 address line of TWI must be soldered to GND. This is done to modify the address of the the EEPROM on [IO1 Xplained Pro Extension Kit](#)
- The modification changes the address of the temperature sensor to **0x4B** and the EEPROM to **0x50**

1. Project `sam_c21n_xpro.X`.

- **Hardware Used:**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Connect the [IO1 Xplained Pro Extension Kit](#) to the EXT2 header of the [SAM C21N Xplained Pro Evaluation Kit](#)

2. Project `sam_d20_xpro.X`.

- **Hardware Used:**
 - [SAM D20 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Connect the [IO1 Xplained Pro Extension Kit](#) to the EXT2 header of the [SAM D20 Xplained Pro Evaluation Kit](#)

3. Project `sam_d21_xpro.X`.

- **Hardware Used:**
 - [SAM D21 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Connect the [IO1 Xplained Pro Extension Kit](#) to the EXT2 header of the [SAM D21 Xplained Pro Evaluation Kit](#)

4. Project `sam_e54_xpro.X`.

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Connect the [IO1 Xplained Pro Extension Kit](#) to the EXT2 header of the [SAM E54 Xplained Pro Evaluation Kit](#)

5. Project `sam_e70_xult.X`.

6. Project `sam_e70_xult_freertos.X`.

- **Hardware Used:**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup:**
 - Connect the [IO1 Xplained Pro Extension Kit](#) to the EXT1 header of the [SAM E70 Xplained Ultra Evaluation Kit](#)

7. Project `sam_i21_xpro.X`

- **Hardware Used**

- [SAM L21 Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - Connect the [IO1 Xplained Pro Extension Kit](#) to the EXT1 header of the [SAM L21 Xplained Pro Evaluation Kit](#)

8. Project sam_l22_xpro.X

- **Hardware Used**
 - [SAM L22 Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - Connect the [IO1 Xplained Pro Extension Kit](#) to the EXT1 header of the [SAM L22 Xplained Pro Evaluation Kit](#)

9. Project sam_v71_xult.X.

10. Project sam_v71_xult_freertos.X.

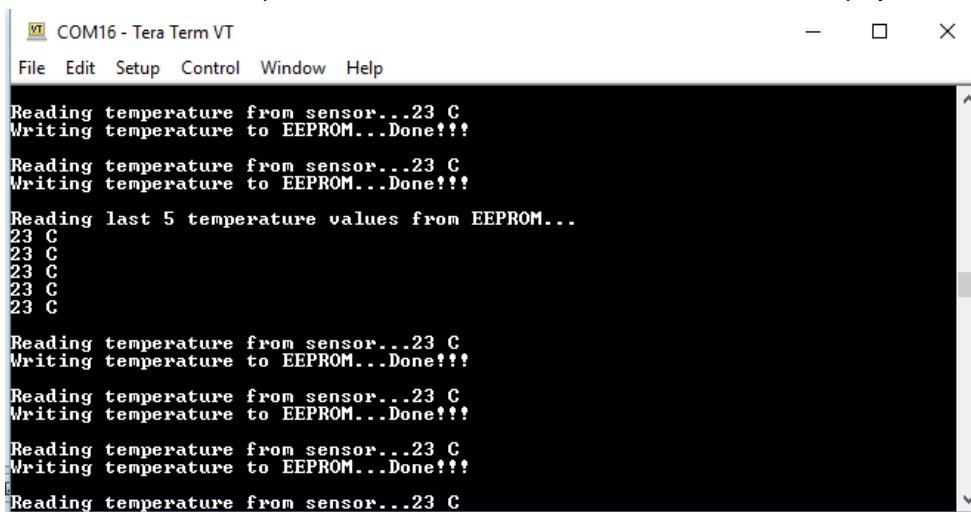
- **Hardware Used:**
 - [SAM V71 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup:**
 - Connect the [IO1 Xplained Pro Extension Kit](#) to the EXT1 header of the [SAM V71 Xplained Ultra Evaluation Kit](#)

Running the Application

This section provides information on how to run the application using the MPLAB X IDE.

Description

1. Connect a micro USB cable to the DEBUG port.
2. Open the Terminal application (Ex.:Tera term) on the computer.
 - Configure the DEBUG port settings as follows:
 - Baud : 115200
 - Data : 8 Bits
 - Parity : None
 - Stop : 1 Bit
 - Flow Control : None
3. Build and program the application using the MPLAB X IDE.
4. Observe the temperature values getting printed on the terminal application every 1 second and temperature value written into EEPROM notification as shown below:
5. Press any key on the terminal, last 5 temperature values will be read from the EEPROM and displayed as shown below.



```
Reading temperature from sensor...23 C
Writing temperature to EEPROM...Done!!!
Reading temperature from sensor...23 C
Writing temperature to EEPROM...Done!!!
Reading last 5 temperature values from EEPROM...
23 C
23 C
23 C
23 C
23 C

Reading temperature from sensor...23 C
Writing temperature to EEPROM...Done!!!
Reading temperature from sensor...23 C
Writing temperature to EEPROM...Done!!!
Reading temperature from sensor...23 C
Writing temperature to EEPROM...Done!!!
Reading temperature from sensor...23 C
Writing temperature to EEPROM...Done!!!
Reading temperature from sensor...23 C
```

Sync

i2c_eeprom

This example application shows how to use the I²C driver in synchronous mode to perform operations on the EEPROM.

Description

This example uses the I²C driver in synchronous mode to communicate with the EEPROM to perform write and read operations in an RTOS environment.

The application communicates with the following EEPROM's based on the project configurations selected.

- External AT24CM02 EEPROM
- On-Board AT24MAC402

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/i2c/sync/i2c_eeprom/firmware
------------------	---

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mx470_curiosity_freertos.X	PIC32MX Curiosity Development Board + FreeRTOS
sam_c21n_xpro_freertos.X	SAM C21N Xplained Pro Evaluation Kit + FreeRTOS
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek_freertos.IAR	SAM9X60 evaluation kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- I²C Driver (Synchronous mode)
- FreeRTOS

The following components used may vary based on the project configuration selected:

- TWIHS or SERCOM or FLEXCOM peripheral library

- Board Support Package (BSP)

Other MHC Settings:

- Configure Pins for TWIHS or SERCOM or FLEXCOM peripheral library in Pin Settings based on project configuration selected
- Configure EEPROM write protect pin in Pin Settings

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mx_470_curiosity_freertos.X

- **Hardware Used:**
 - PIC32MX Curiosity Development Board
 - EEPROM 3 click board
- **Hardware Setup:**
 - Connect mini USB cable to the 'Debug USB' connector(J3) on the board to the computer.
 - Install an [EEPROM 3 click](#) board on to the mikroBUS socket J5 of [PIC32MX Curiosity Development Board](#)
 - **Note:** Ensure that the series resistors on the mikroBUS headers are of value **0 Ohms**.

2. Project sam_c21n_xpro_freertos.X.

- **Hardware Used:**
 - SAM C21N Xplained Pro Evaluation Kit
 - EEPROM 3 click board
 - mikroBUS Xplained Pro board
- **Hardware Setup:**
 - Install an [EEPROM 3 click](#) board to the [mikroBUS Xplained Pro](#) board
 - Connect the [mikroBUS Xplained Pro](#) board to the EXT2 header of the [SAM C21N Xplained Pro Evaluation Kit](#)

3. Project sam_e54_xpro_freertos.X.

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - No special hardware setup required, [SAM E54 Xplained Pro Evaluation Kit](#) has on-board EEPROM

4. Project sam_e70_xult_freertos.X.

- **Hardware Used:**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup:**
 - No special hardware setup required, [SAM E70 Xplained Ultra Evaluation Kit](#) has on-board EEPROM

5. Project sam_a5d2_xult_freertos.IAR

- **Hardware Used**
 - [SAM A5D2 Xplained Ultra board](#)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card

- Insert the SD card into the SDMMC1 slot on the board
- No special hardware setup required, [SAM A5D2 Xplained Ultra board](#) has an On-Board EEPROM

6. Project sam_9x60_ek_freertos.IAR

- **Hardware Used**
 - SAM 9X60 Evaluation Kit board
 - [EEPROM 3 click](#) board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
 - Insert [EEPROM 3 click](#) board into MIKROBUS Connector J15.
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Note: Reset push button on SAM9X60 EK is labeled as SW3

Running the Application

This section provides information on how to run the application.

Description

MPLAB X IDE

1. Connect a USB cable to the DEBUG port.
2. Build and program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED is turned ON when the data read from EEPROM matches with the written data

The following table provides the LED name:

Kit Name	LED Name
PIC32MX Curiosity Development Board	LED 1
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED is turned ON when the data read from EEPROM matches with the written data

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)
SAM9X60 evaluation kit	RGB_LED (Green)

i2c_multi_slave

This example application shows how to use the I²C driver in synchronous mode to communicate with the external EEPROM and

temperature sensor.

Description

The application demonstrates the multi-client feature of the I²C driver in synchronous mode. The application uses a [IO1 Xplained Pro Extension Kit](#) that has a temperature sensor and an EEPROM interfaced on the same I²C bus.

Two application threads are created which act as clients to the same instance of the I²C driver:

APP_I2C_TEMP_SENSOR_Tasks:

- Remains in blocked state for 1 second
- Once unblocked, reads the temperature from the temperature sensor and posts a semaphore thereby unblocking the second (EEPROM) thread

APP_I2C_EEPROM_Tasks:

- Remains blocked on a semaphore until a new temperature data is available
- Once unblocked, writes the temperature data to the EEPROM
- Reads and prints the last five saved temperature values from the EEPROM when user inputs a key on the console.

Note:

Temperature data is written to the same EEPROM memory locations.

Building the Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/driver/i2c/sync/i2c_multi_slave/firmware
------------------	--

To build the application, refer to the following table and open the appropriate project file in the MPLAB X IDE:

Project Name	Description
sam_c21n_xpro_freertos.X	SAM C21N Xplained Pro Evaluation Kit + FreeRTOS
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_v71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- I²C Driver (Synchronous mode). The Number of Clients is set to 2
- SYS Console
- FreeRTOS

The following components used may vary based on the project configuration selected:

- TWIHS or SERCOM peripheral library
- USART or SERCOM peripheral library
- Board Support Package (BSP)

Other MHC Settings:

- Configure Pins for TWIHS or SERCOM peripheral library in Pin Settings based on project configuration selected
- Configure Pins for USART or SERCOM peripheral library in Pin Settings based on project configuration selected

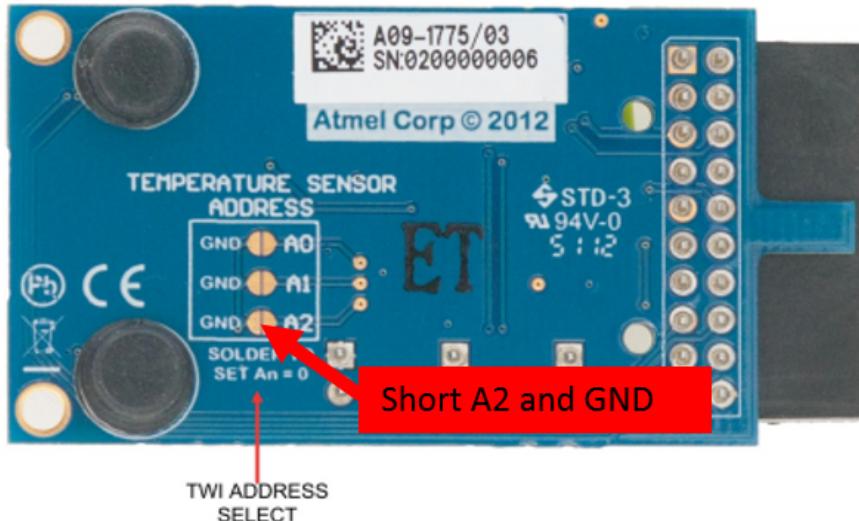
Hardware Setup

This section describes how to configure the supported hardware.

Description

Common Hardware Setup:

- IO1 Xplained Pro Extension Kit Address select:



- The A2 address line of TWI must be soldered to GND. This is done to modify the address of the the EEPROM on [IO1 Xplained Pro Extension Kit](#)
- The modification changes the address of the temperature sensor to **0x4B** and the EEPROM to **0x50**

1. Project `sam_c21n_xpro_freertos.X`.

- Hardware Used:**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
- Hardware Setup:**
 - Connect the [IO1 Xplained Pro Extension Kit](#) to the EXT2 header of the [SAM C21N Xplained Pro Evaluation Kit](#)

2. Project `sam_e54_xpro_freertos.X`.

- Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
- Hardware Setup:**
 - Connect the [IO1 Xplained Pro Extension Kit](#) to the EXT2 header of the [SAM E54 Xplained Pro Evaluation Kit](#)

3. Project `sam_e70_xult_freertos.X`.

- Hardware Used:**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
- Hardware Setup:**
 - Connect the [IO1 Xplained Pro Extension Kit](#) to the EXT1 header of the [SAM E70 Xplained Ultra Evaluation Kit](#)

4. Project `sam_v71_xult_freertos.X`.

- Hardware Used:**

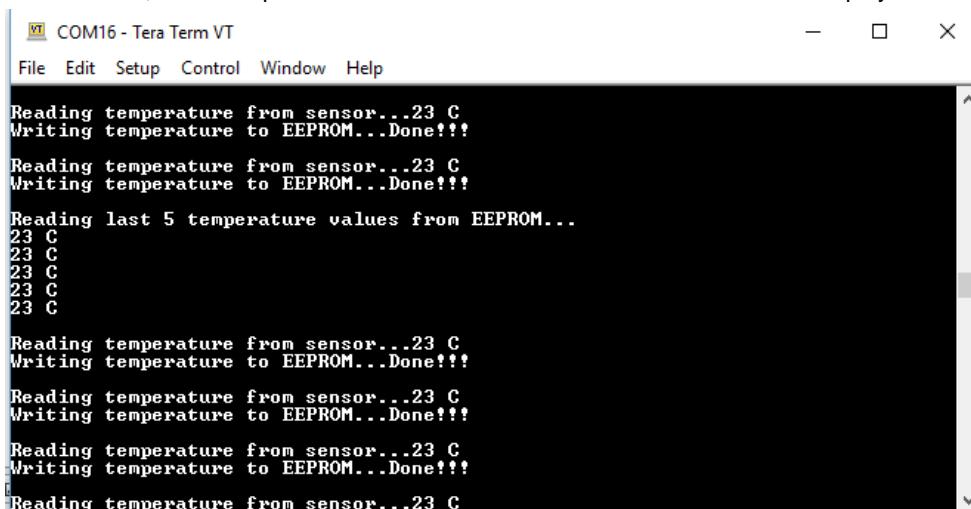
- [SAM V71 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup:**
 - Connect the [IO1 Xplained Pro Extension Kit](#) to the EXT1 header of the [SAM V71 Xplained Ultra Evaluation Kit](#)

Running the Application

This section provides information on how to run the application using the MPLAB X IDE.

Description

1. Connect a micro USB cable to the DEBUG port.
2. Open the Terminal application (Ex.:Tera term) on the computer.
 - Configure the DEBUG port settings as follows:
 - Baud : 115200
 - Data : 8 Bits
 - Parity : None
 - Stop : 1 Bit
 - Flow Control : None
3. Build and program the application using the MPLAB X IDE.
4. Observe the temperature values getting printed on the terminal application every 1 second and temperature value written into EEPROM notification as shown below:
5. Press any key on the terminal, last 5 temperature values will be read from the EEPROM and displayed as shown below.



```
VT COM16 - Tera Term VT
File Edit Setup Control Window Help
Reading temperature from sensor...23 C
Writing temperature to EEPROM...Done!!!
Reading temperature from sensor...23 C
Writing temperature to EEPROM...Done!!!
Reading last 5 temperature values from EEPROM...
23 C
23 C
23 C
23 C
23 C
Reading temperature from sensor...23 C
Writing temperature to EEPROM...Done!!!
Reading temperature from sensor...23 C
Writing temperature to EEPROM...Done!!!
Reading temperature from sensor...23 C
Writing temperature to EEPROM...Done!!!
Reading temperature from sensor...23 C
```

I2C EEPROM Driver Applications

This section provides help for the I2C EEPROM driver applications.

AT24 Driver Applications

This section provides help for the AT24 driver applications.

at24_eeprom_read_write

This example application shows how to use the AT24 driver to perform read and write operations on AT24 series of EEPROM.

Description

This example uses the AT24 driver to communicate with I²C based AT24 series EEPROMs to perform write and read operations

in both Bare-Metal and RTOS environment.

The application communicates with following EEPROMs based on project configurations selected.

- External AT24CM02 EEPROM
- On-Board AT24MAC402

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core\apps\driver\i2c_eeprom\at24\at24_eeprom_read_write\firmware
-------------------------	---

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mx470_curiosity.X	PIC32MX Curiosity Development Board
pic32mx_xlp_sk.X	PIC32MX XLP Starter Kit
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit
sam_d20_xpro.X	SAM D20 Xplained Pro Evaluation Kit
sam_d21_xpro.X	SAM D21 Xplained Pro Evaluation Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_v71_xult.X	SAM V71 Xplained Ultra Evaluation Kit
sam_v71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek.IAR	SAM9X60 evaluation kit
sam_9x60_ek_freertos.IAR	SAM9X60 evaluation kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Refer to the MHC project graph for the configurations of the various components used.

Components used:

- AT24 Driver
- The following components used may vary based on the project configuration selected:
- TWIHS or SERCOM or FLEXCOM peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Settings:

- Configure Pins for TWIHS or SERCOM or FLEXCOM peripheral library in Pin Settings based on project configuration selected
- Configure EEPROM write protect pin in Pin Settings

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mx470_curiosity.X

- **Hardware Used**
 - [PIC32MX Curiosity Development Board](#)
 - [EEPROM 3 click board](#)
- **Hardware Setup**
 - Connect mini USB cable to the 'Debug USB' connector(J3) on the board to the computer.
 - Install an [EEPROM 3 click](#) board on to the mikroBUS socket J5 of [PIC32MX Curiosity Development Board](#)
 - **Note:** Ensure that the series resistors on the mikroBUS headers are of value **0 Ohms**.

2. Project pic32mx_xlp_sk.X

- **Hardware Used**
 - [PIC32MX XLP Starter Kit](#)
- **Hardware Setup**
 - Connect micro USB cable to the 'Debug USB' connector(J9) on the board to the computer.
 - Install an [EEPROM 3 click](#) board on to the mikroBUS socket J5 of [PIC32MX XLP Starter Kit](#)

3. Project sam_c21n_xpro.X.

- **Hardware Used:**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Install an [EEPROM 3 click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect the [mikroBUS Xplained Pro](#) board to the EXT2 header of the [SAM C21N Xplained Pro Evaluation Kit](#)

4. Project sam_d20_xpro.X.

- **Hardware Used:**
 - [SAM D20 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Install an [EEPROM 3 click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect the [mikroBUS Xplained Pro](#) board to the EXT2 header of the [SAM D20 Xplained Pro Evaluation Kit](#)

5. Project sam_d21_xpro.X.

- **Hardware Used:**
 - SAM D21 Xplained Pro Evaluation Kit
- **Hardware Setup:**
 - Install an [EEPROM 3 click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect the [mikroBUS Xplained Pro](#) board to the EXT2 header of the [SAM D21 Xplained Pro Evaluation Kit](#)

6. Project sam_e54_xpro.X.

- **Hardware Used:**
 - SAM E54 Xplained Pro Evaluation Kit
- **Hardware Setup:**
 - No special hardware setup required, [SAM E54 Xplained Pro Evaluation Kit](#) has an On-Board EEPROM

7. Project sam_e70_xult.X.

8. Project sam_e70_xult_freertos.X.

- **Hardware Used:**
 - SAM E70 Xplained Ultra Evaluation Kit
- **Hardware Setup:**
 - No special hardware setup required, [SAM E70 Xplained Ultra Evaluation Kit](#) has an On-Board EEPROM

9. Project sam_v71_xult.X.

10. Project sam_v71_xult_freertos.X.

- **Hardware Used:**
 - SAM V71 Xplained Ultra Evaluation Kit
- **Hardware Setup:**
 - No special hardware setup required, [SAM V71 Xplained Ultra Evaluation Kit](#) has an On-Board EEPROM

11. Project sam_a5d2_xult.IAR

12. Project sam_a5d2_xult_freertos.IAR

- **Hardware Used**
 - SAM A5D2 Xplained Ultra board
 - EEPROM 3 click
 - mikroBUS Xplained Pro
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Install an [EEPROM 3 click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect the [mikroBUS Xplained Pro](#) board to the EXT1 header of the [SAM A5D2 Xplained Ultra](#) board

13. Project sam_9x60_ek.IAR

14. Project sam_9x60_ek_freertos.IAR

- **Hardware Used**
 - SAM 9X60 Evaluation Kit board
 - [EEPROM 3 click](#) board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board

- Insert [EEPROM 3 click](#) board into MIKROBUS Connector J15.
- Connect the Debug USB port on the board to the computer using a micro USB cable
- Note: Reset push button on SAM9X60 EK is labeled as SW3

Running the Application

This section provides information on how to run the application.

Description

MPLAB X IDE

1. Connect a USB cable to the DEBUG port.
2. Build and program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED is turned ON when the data read from EEPROM matches with the written data

The following table provides the LED name:

Kit Name	LED Name
PIC32MX Curiosity Development Board	LED 1
PIC32MX XLP Starter Kit	LED 1 (Red)
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM D20 Xplained Pro Evaluation Kit	LED 0
SAM D21 Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1
SAM V71 Xplained Ultra Evaluation Kit	LED 0

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED is turned ON when the data read from EEPROM matches with the written data

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)
SAM9X60 evaluation kit	RGB_LED (Green)

Memory Driver Applications

Async

Name	Description
nvm_sst26_read_write	This example application shows how to use the Memory driver in asynchronous mode to perform block operations on the NVM and the SST26 media's.
mx25l_at25df_read_write	This example application shows how to use the Memory driver in asynchronous mode to perform block operations on the MX25L QSPI flash and the AT25DF SPI flash media.

Sync

Name	Description
nvm_sst26_read_write	This example application shows how to use the Memory driver in synchronous mode to perform block operations on the NVM and the SST26 media's.
mx25l_at25df_read_write	This example application shows how to use the Memory driver in synchronous mode to perform block operations on the MX25L QSPI flash and the AT25DF SPI flash media.

Description

This section provides help for the Memory driver applications.

Async

[nvm_sst26_read_write](#)

This example application shows how to use the Memory driver in asynchronous mode to perform block operations on the NVM and the SST26 media's.

Description

This application uses multi instances of the Memory driver to communicate with the NVM and the SST26 Flash memories in asynchronous mode of operation in both RTOS and Bare-Metal environment.

It performs block Erase/Write/Read operations on both the media's.

The application consists of five tasks which are called through the SYS_Tasks() routine in Bare-Metal environment and though RTOS thread context in RTOS environment.

1. DRV_MEMORY_0_Tasks() : Manages the state machine of the Memory driver instance 0.
2. DRV_MEMORY_1_Tasks() : Manages the state machine of the Memory driver instance 1.
3. APP_SST26_Tasks() : Performs operations on the SST26 QSPI/SQI Flash memory.
4. APP_NVM_Tasks() : Performs operations on the NVM.
5. APP_MONITOR_Tasks(): Monitors the state of above two Tasks.

Building The Application

This section provides information on how to build an application.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/driver/memory/async/nvm_sst26_read_write/firmware
------------------	---

Below table shows the list of project names to be used with different development boards. Open the project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mz_das_sk_freertos.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit + FreeRTOS
pic32mz_ef_sk.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- Memory driver two instances
 - Instance 0 connected to the SST26 Driver
 - Instance 1 connected to the EFC or NVM peripheral library
- SST26 driver

The following components used may vary based on the project configuration selected:

- QSPI or SQI peripheral library
- EFC or NVM peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC configurations:

- Enable Memory Protection Unit (MPU) for the QSPI Flash memory region
- Enable Memory Protection Unit (MPU) for reserving Internal Flash region for the NVM operations

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project `pic32mz_das_sk_freertos.X`.

- **Hardware Used**
 - [PIC32MZ Embedded Graphics with Stacked DRAM \(DA\) Starter Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

2. Project `pic32mz_ef_sk.X`.

- **Hardware Used**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

3. Project `sam_e70_xult.X`.

4. Project `sam_e70_xult_freertos.X`.

- **Hardware Used**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

Running The Application

This section provides information on how to run the application.

Description

Running project with MPLAB X IDE

1. Connect a micro/mini USB cable to the DEBUG port.
2. Build and program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED is turned ON when the data read from each media matches with the data written in them

The following table provides the LED name:

Kit Name	LED Name
PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit	LED 3
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 3
SAM E70 Xplained Ultra Evaluation Kit	LED 1

mx25l_at25df_read_write

This example application shows how to use the Memory driver in asynchronous mode to perform block operations on the MX25L QSPI flash and the AT25DF SPI flash media.

Description

This application uses multi instances of the Memory driver to communicate with the AT25DF SPI flash and the MX25L QSPI flash memories in asynchronous mode of operation in both RTOS and Bare-Metal environment.

It performs block Erase/Write/Read operations on both the media.

The application consists of five tasks which are called through the SYS_Tasks() routine in Bare-Metal environment and though RTOS thread context in RTOS environment.

1. DRV_MEMORY_0_Tasks() : Manages the state machine of the Memory driver instance 0.
2. DRV_MEMORY_1_Tasks() : Manages the state machine of the Memory driver instance 1.
3. APP_MX25L_Tasks() : Performs operations on the MX25L QSPI Flash memory.
4. APP_AT25DF_Tasks() : Performs operations on the AT25DF SPI flash memory.
5. APP_MONITOR_Tasks(): Monitors the state of above two Tasks.

Building The Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/memory/async/mx25l_at25df_read_write/firmware
------------------	--

To build the application, refer to the following table and open the appropriate project file in their respective IDEs.

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra Evaluation kit
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra Evaluation kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- Memory driver two instances
 - Instance 0 connected to the MX25L QSPI flash
 - Instance 1 connected to the AT25DF SPI flash

The following components used may vary based on the project configuration selected:

- QSPI peripheral library
- SPI peripheral library
- Board Support Package (BSP)
- FreeRTOS

NOTE: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project sam_a5d2_xult_freertos.IAR

2. Project sam_a5d2_xult.IAR

- **Hardware Used**
 - [SAM A5D2 Xplained Ultra board](#)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Make sure that the jumper JP9 is removed (jumper pins are not shorted)

Running The Application

This section provides information on how to run the application.

Description

Running project with IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED is turned ON when the data read from each media matches with the data written in them

The following table provides the LED name:

Kit Name	LED Name
SAMA5D2 Xplained Ultra Evaluation kit	RGB_LED(Green)

Sync

nvm_sst26_read_write

This example application shows how to use the Memory driver in synchronous mode to perform block operations on the NVM and the SST26 media's.

Description

This application uses multi instances of the Memory driver to communicate with the NVM and the SST26 Flash memories in synchronous mode of operation in RTOS Environment.

It performs block Erase/Write/Read operations on both the media's.

The application consists of three tasks which are called in the RTOS thread context:

1. APP_SST26_Tasks() : Performs operations on the SST26 QSPI/SQI Flash Memory.
2. APP_NVM_Tasks() : Performs operations on the NVM.
3. APP_MONITOR_Tasks(): Monitors the state of above two Tasks.

Building The Application

This section provides information on how to build an application.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/driver/memory/sync/nvm_sst26_read_write/firmware
------------------	--

Below table shows the list of project names to be used with different development boards. Open the project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mz_ef_sk_freertos.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit + FreeRTOS
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- Memory driver two instances
- Instance 0 connected to the SST26 Driver

- Instance 1 connected to the EFC or NVM peripheral library
- SST26 driver
- System Timer Service for polling the status of at regular intervals
- TC peripheral library
- FreeRTOS

The components used may vary based on the project configuration selected:

- QSPI or SPI peripheral library
- EFC or NVM peripheral library
- Board Support Package (BSP)

Other MHC Configurations:

- Enable Memory Protection Unit (MPU) for the QSPI Flash memory region
- Enable Memory Protection Unit (MPU) for reserving Internal Flash region for the NVM operations

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. **Project pic32mz_ef_sk_freertos.X.**
 - **Hardware Used**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
 - **Hardware Setup**
 - No Special hardware Setup Required
2. **Project sam_e70_xult_freertos.X.**
 - **Hardware Used**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
 - **Hardware Setup**
 - No special hardware setup required

Running The Application

This section provides information on how to run the application.

Description

Running project with MPLAB X IDE

1. Connect a micro/mini USB cable to the DEBUG port.
2. Build and program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED blinks when the data read from each media matches with the data written in them

The following table provides the LED name:

Kit Name	LED Name
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 3
SAM E70 Xplained Ultra Evaluation Kit	LED 1

mx25l_at25df_read_write

This example application shows how to use the Memory driver in synchronous mode to perform block operations on the MX25L QSPI flash and the AT25DF SPI flash media.

Description

This application uses multi instances of the Memory driver to communicate with the MX25L QSPI flash and the AT25DF SPI Flash memories in synchronous mode of operation in RTOS Environment.

It performs block Erase/Write/Read operations on both the media.

The application consists of three tasks which are called in the RTOS thread context:

1. APP_MX25L_Tasks() : Performs operations on the MX25L QSPI Flash Memory.
2. APP_AT25DF_Tasks() : Performs operations on the AT25DF Flash Memory.
3. APP_MONITOR_Tasks(): Monitors the state of above two Tasks.

Building The Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/memory/sync/mx25l_at25df_read_write/firmware
------------------	---

To build the application, refer to the following table and open the appropriate project file in their respective IDEs.

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra Evaluation kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- Memory driver two instances
 - Instance 0 connected to the MX25L QSPI flash
 - Instance 1 connected to the AT25DF SPI flash

The following components used may vary based on the project configuration selected:

- QSPI peripheral library
- SPI peripheral library
- Board Support Package (BSP)
- FreeRTOS

NOTE: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project `sam_a5d2_xult_freertos.IAR`

- **Hardware Used**
 - [SAM A5D2 Xplained Ultra board](#)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Make sure that the jumper JP9 is removed (jumper pins are not shorted)

Running The Application

This section provides information on how to run the application.

Description

Running project with IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED is turned ON when the data read from each media matches with the data written in them

The following table provides the LED name:

Kit Name	LED Name
SAMA5D2 Xplained Ultra Evaluation kit	RGB_LED(Green)

SDMMC Driver Applications

Async

Name	Description
sdmmc_read_write	This application writes 60KB (61440 bytes) of data starting at the SD Card memory location 0x2000, using the SDMMC driver. The application then reads and verifies the written data.

Description

This Section provides help for the SDMMC driver Applications.

Async

sdmmc_read_write

This application writes 60KB (61440 bytes) of data starting at the SD Card memory location 0x2000, using the SDMMC driver. The application then reads and verifies the written data.

Description

This example uses the SDMMC driver in asynchronous mode in both Bare-Metal and RTOS environment to perform Block Erase/Write/Read operations operations on SD-Card.

Building The Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/sdmmc/async/sdmmc_read_write/firmware
------------------	--

Below table shows the list of project names to be used with different development boards. Open the project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mz_das_sk.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Kit
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Kit + FreeRTOS
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_V71_xult.X	SAM V71 Xplained Ultra Evaluation Kit
sam_V71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek.IAR	SAM9X60 Evaluation Kit
sam_9x60_ek_freertos.IAR	SAM9X60 Evaluation Kit + FreeRTOS

MPLAB Harmony Configuration

This section provides information on the MHC configurations.

Description

Components Used:

- SDMMC Driver (Asynchronous mode)
- System Timer Service

- Timer peripheral library

The following components used may vary based on the project configuration selected:

- HSMCI or SDHC or SDMMC peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Settings:

- Configure the Pins for the HSMCI or SDHC or SDMMC peripheral in the Pin Settings
- Configure DMA channels for transmit and receive

NOTE: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mz_das_sk.X

- **Hardware Used**
 - [PIC32MZ DA Family Starter Kit](#)
- **Hardware Setup**
 - Insert MicroSD Card in the MicroSD Card slot (J10) on the development board

2. Project sam_9x60_ek.IAR

3. Project sam_9x60_ek_freertos.IAR

- **Hardware Used**
 - SAM9X60 Evaluation Kit
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC J5 connector on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable

4. Project sam_a5d2_xult.IAR

5. Project sam_a5d2_xult_freertos.IAR

- **Hardware Used**
 - [SAM A5D2 Xplained Ultra board](#)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable

6. Project sam_e54_xpro.X.

7. Project sam_e54_xpro_freertos.X.

- **Hardware Used**
 - [SAM E54 Xplained Pro Evaluation Kit](#)

- **Hardware Setup**
 - Insert SD Card in the SD Card slot on the evaluation kit
8. **Project sam_e70_xult.X.**
9. **Project sam_e70_xult_freertos.X.**
- **Hardware Used**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
 - **Hardware Setup**
 - Insert MicroSD Card in the MicroSD Card slot on the evaluation kit

10. **Project sam_V71_xult.X.**
11. **Project sam_V71_xult_freertos.X.**

- **Hardware Used**
 - [SAM V71 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup**
 - Insert SD Card in the SD Card slot on the evaluation kit

Running The Application

This section provides information on how to run an application.

Description

Running project with MPLAB X IDE

1. Connect a USB cable to the DEBUG port.
2. Build and program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED is turned ON when the read data from the SD Card matches with the written data

The following table provides the LED name:

Kit Name	LED Name
PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit	LED 1
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1
SAM V71 Xplained Ultra Evaluation Kit	LED 0

Running project with IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Copy the output binary(harmony.bin) into the SD card configured as per the [hardware setup](#)
3. Insert the SD card into the SDMMC slot
4. Reset the board to run the application
5. The LED indicates the success or failure.
 - The LED is turned ON when the read data from the SD Card matches with the written data

Kit Name	LED Name
SAMA5D2 Xplained Ultra Evaluation Kit	RGB_LED(Green)
SAM9X60 Evaluation Kit	RGB_LED(Green)

NOTE: This demo application performs a raw read-write operation on the SD card. This causes the partition information to be

overwritten causing the SD card file system to be corrupted. Hence resetting the board will not re-run the application demo (Board will fail to boot since it cannot find a valid partition). To repeat the demo we need to reformat SD card and prepare it as defined by the hardware setup.

SDSPI Driver Applications

Async

Name	Description
sdspi_read_write	This application writes 4KB (4096 bytes) of data starting at the SD Card memory location 0x2000, using the SDSPI driver. The application then reads and verifies the written data.

Sync

Name	Description
sdspi_read_write	This application writes 10KB (10240 bytes) of data starting at the SD Card memory location 0x2000, using the SDSPI driver in synchronous mode. The application then reads and verifies the written data.

Description

This section provides help for the SPI based SD-Card (SDSPI) driver applications.

Sync

sdspi_read_write

This application writes 10KB (10240 bytes) of data starting at the SD Card memory location 0x2000, using the SDSPI driver in synchronous mode. The application then reads and verifies the written data.

Description

This example uses the SDSPI driver in synchronous mode in an RTOS environment. The synchronous mode of the SDSPI driver performs blocking read and write operations. The SDSPI driver is configured to use DMA. A separate RTOS thread is created by the MHC to run the SDSPI task routine. This task routine checks for the SD-Card attach/detach status and initializes the SD-Card making it ready for the application to submit read and write requests.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/sdspi/sync/sdspi_read_write/firmware
------------------	--

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mz_ef_sk_freertos.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit + FreeRTOS
sam_c21n_xpro_freertos.X	SAM C21N Xplained Pro Evaluation Kit + FreeRTOS

sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS

MPLAB Harmony Configuration

This section provides information on the MHC configurations.

Description

Components Used:

- SDSPI Driver (Synchronous mode)
- DMA peripheral library
- Time System Service
- FreeRTOS

The following components used may vary based on the project configuration selected:

- SPI or SERCOM
- Timer peripheral library or Core timer
- Board Support Package (BSP)

Other MHC Settings:

- Configure pins for the SPI Peripheral in Pin Settings
- Configure the SD Card Chip Select pin in Pin Settings

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mz_ef_sk_freertos.X.

- Hardware Used:**
 - PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
 - MultiMedia Expansion Board II (for microSD card slot)
- Hardware Setup:**
 - Connect the [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#) to the [MultiMedia Expansion Board II](#)
 - Insert the microSD card in the microSD card slot J8 on [MultiMedia Expansion Board II](#)

2. Project sam_c21n_xpro_freertos.X.

- Hardware Used:**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
 - [IO1 Xplained PRO Extension Kit](#) (for microSD card slot)
- Hardware Setup:**

- Connect the [IO1 Xplained PRO Extension Kit](#) to the EXT1 header of the [SAM C21N Xplained Pro Evaluation Kit](#)
- Insert microSD card on the [IO1 Xplained PRO Extension Kit](#)

3. Project [sam_e54_xpro_freertos.X](#).

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
 - [IO1 Xplained PRO Extension Kit](#) (for microSD card slot)
- **Hardware Setup:**
 - Connect the [IO1 Xplained PRO Extension Kit](#) to the EXT1 header of the [SAM E54 Xplained Pro Evaluation Kit](#)
 - Insert microSD card on the [IO1 Xplained PRO Extension Kit](#)

4. Project [sam_e70_xult_freertos.X](#).

- **Hardware Used:**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
 - [IO1 Xplained PRO Extension Kit](#) (for microSD card slot)
- **Hardware Setup:**
 - Connect the [IO1 Xplained PRO Extension Kit](#) to the EXT1 header of the [SAM E70 Xplained Ultra Evaluation Kit](#)
 - Insert microSD card on the [IO1 Xplained PRO Extension Kit](#)

5. Project [sam_a5d2_xult_freertos.IAR](#)

- **Hardware Used**
 - [SAM A5D2 Xplained Ultra board](#)
 - [IO1 Xplained PRO Extension Kit](#) (for microSD card slot)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Connect the [IO1 Xplained PRO Extension Kit](#) to the EXT1 header of the [SAM A5D2 Xplained Ultra board](#)
 - Insert microSD card on the [IO1 Xplained PRO Extension Kit](#)

Running the Application

This section provides information on how to run the application.

Description

MPLAB X IDE

1. Connect a USB cable to the DEBUG port.
2. Build and program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED is turned ON when the read data from the SD card matches with the written data

The following table provides the LED name:

Kit Name	LED Name
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 1
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED is turned ON when the read data from the SD card matches with the written data

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)

Async

sdspi_read_write

This application writes 4KB (4096 bytes) of data starting at the SD Card memory location 0x2000, using the SDSPI driver. The application then reads and verifies the written data.

Description

This example uses the SDSPI driver in asynchronous mode. The asynchronous mode of the SDSPI driver performs non-blocking read and write operations. The SDSPI driver is configured to use DMA.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/sdspi/async/sdspi_read_write/firmware
------------------	--

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
sam_d21_xpro.X	SAM D21 Xplained Pro Evaluation Kit

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS

MPLAB Harmony Configuration

This section provides information on the MHC configurations.

Description

Components Used:

- SDSPI Driver (Asynchronous mode)
- DMA peripheral library
- Time System Service

The following components used may vary based on the project configuration selected:

- SPI or SERCOM
- Timer peripheral library or Core timer
- Board Support Package (BSP)

Other MHC Settings:

- Configure pins for the SPI Peripheral in Pin Settings
- Configure the SD Card Chip Select pin in Pin Settings

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project `sam_d21_xpro.X`.

- **Hardware Used:**
 - SAM D21 Xplained Pro Evaluation Kit
 - IO1 Xplained PRO Extension Kit (for microSD card slot)
- **Hardware Setup:**
 - Connect the [IO1 Xplained PRO Extension Kit](#) to the EXT1 header of the [SAM D21 Xplained Pro Evaluation Kit](#)
 - Insert microSD card on the [IO1 Xplained PRO Extension Kit](#)

2. Project `sam_a5d2_xult_freertos.IAR`

- **Hardware Used**
 - SAM A5D2 Xplained Ultra board
 - IO1 Xplained PRO Extension Kit (for microSD card slot)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Connect the [IO1 Xplained PRO Extension Kit](#) to the EXT1 header of the [SAM A5D2 Xplained Ultra board](#)
 - Insert microSD card on the [IO1 Xplained PRO Extension Kit](#)

Running the Application

This section provides information on how to run the application.

Description

MPLAB X IDE

1. Connect a USB cable to the DEBUG port.

2. Build and program the application using the MPLAB X IDE.
 3. The LED indicates the success or failure.
 - The LED is turned ON when the read data from the SD card matches with the written data
- The following table provides the LED name:

Kit Name	LED Name
SAM D21 Xplained Pro Evaluation Kit	LED 0

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED is turned ON when the read data from the SD card matches with the written data

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)

SPI Driver Applications

Async

Name	Description
spi_multi_instance	This example demonstrates how to use multiple instances of the SPI driver in asynchronous mode to communicate with multiple EEPROMs.
spi_multi_slave	This example demonstrates how to use single instance of the SPI driver in asynchronous mode to communicate with multiple EEPROMs.
spi_self_loopback_multi_client	This example demonstrates how to use the SPI driver in asynchronous mode to achieve self-loop back between multiple clients.

Sync

Name	Description
spi_multi_instance	This example demonstrates how to use multiple instances of the SPI driver in synchronous mode to communicate with multiple EEPROMs in an RTOS environment.
spi_multi_slave	This example demonstrates how to use single instance of the SPI driver in synchronous mode to communicate with multiple EEPROMs in an RTOS environment.
spi_self_loopback_multi_client	This example demonstrates how to use the SPI driver in synchronous mode to achieve self-loop back between multiple clients in RTOS environment.

Description

This section provides help for the SPI driver applications.

Async

spi_multi_instance

This example demonstrates how to use multiple instances of the SPI driver in asynchronous mode to communicate with multiple EEPROMs.

Description

This example writes and reads data to and from two separate EEPROM connected over two different SPI bus by using multi instance feature of the driver. The example also demonstrates how to setup two different EEPROM transfers at different baud rates.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/spi/async/spi_multi_instance/firmware
-------------------------	---

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mx470_curiosity.X	PIC32MX Curiosity Development Board
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_l21_xpro.X	SAM L21 Xplained Pro Evaluation Kit
sam_l22_xpro.X	SAM L22 Xplained Pro Evaluation Kit

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- SPI Driver (Asynchronous mode)

The following components used may vary based on the project configuration selected:

- SERCOM peripheral library
- Board Support Package (BSP)

Other MHC settings:

- Configure the SERCOM related Pins and SERCOM Chip Select Pins in the Pin Settings

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project **pic32mx470_curiosity.X**

- **Hardware Used**
 - [PIC32MX Curiosity Development Board](#)

- Two [EEPROM 4 Click](#) boards
- **Hardware Setup**
 - Connect mini USB cable to the 'Debug USB' connector(J3) on the board to the computer.
 - Install two [EEPROM 4 Click](#) boards on to the two mikroBUS sockets(J5 & J10) of PIC32MX Curiosity Development Board.
 - **Note:** Ensure that the series resistors on the mikroBUS headers are of value **0 Ohms**.

2. Project [sam_c21n_xpro.X](#).

- **Hardware Used:**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
 - Two [EEPROM 4 Click](#) boards
 - Two [mikroBUS Xplained Pro](#) boards
- **Hardware Setup:**
 - Install two [EEPROM 4 Click](#) boards on to two [mikroBUS Xplained Pro](#) boards
 - Connect the two [mikroBUS Xplained Pro](#) boards to the "EXT1" and "EXT2" headers of the [SAM C21N Xplained Pro Evaluation Kit](#)

3. Project [sam_e54_xpro.X](#).

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
 - Two [EEPROM 4 Click](#) boards
 - Two [mikroBUS Xplained Pro](#) boards
- **Hardware Setup:**
 - Install two [EEPROM 4 Click](#) boards on to two [mikroBUS Xplained Pro](#) boards
 - Connect the two [mikroBUS Xplained Pro](#) boards to the "EXT1" and "EXT2" headers of the [SAM E54 Xplained Pro Evaluation Kit](#)

4. Project [sam_l21_xpro.X](#)

- **Hardware Used**
 - [SAM L21 Xplained Pro Evaluation Kit](#)
 - Two [EEPROM 4 Click](#) boards
 - Two [mikroBUS Xplained Pro](#) boards
- **Hardware Setup**
 - Install two [EEPROM 4 Click](#) boards on to two [mikroBUS Xplained Pro](#) boards
 - Connect the two [mikroBUS Xplained Pro](#) boards to the "EXT1" and "EXT2" headers of the [SAM L21 Xplained Pro Evaluation Kit](#)

5. Project [sam_l22_xpro.X](#)

- **Hardware Used**
 - [SAM L22 Xplained Pro Evaluation Kit](#)
 - Two [EEPROM 4 Click](#) boards
 - Two [mikroBUS Xplained Pro](#) boards
- **Hardware Setup**
 - Install two [EEPROM 4 Click](#) boards on to two [mikroBUS Xplained Pro](#) boards
 - Connect the two [mikroBUS Xplained Pro](#) boards to the "EXT1" and "EXT2" headers of the [SAM L22 Xplained Pro Evaluation Kit](#)

Running the Application

This section provides information on how to run the application.

Description

MPLAB X IDE

1. Connect a micro USB cable to the DEBUG port.
2. Build and Program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED is turned ON when the data read from the EEPROMs matches with the data written to the EEPROMs

The following table provides the LED name:

Kit Name	LED Name
PIC32MX Curiosity Development Board	LED 1
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM L21 Xplained Pro Evaluation Kit	LED 0
SAM L22 Xplained Pro Evaluation Kit	LED 0

spi_multi_slave

This example demonstrates how to use single instance of the SPI driver in asynchronous mode to communicate with multiple EEPROMs.

Description

This example write and read data to and from two separate EEPROM connected over the same SPI bus by using the multi client feature of the driver. The example also demonstrates how to setup two different EEPROM transfers at different baud rates.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/spi/async/spi_multi_slave/firmware
------------------	---

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_v71_xult.X	SAM V71 Xplained Ultra Evaluation Kit
sam_v71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek.IAR	SAM9X60 evaluation kit

sam_9x60_ek_freertos.IAR	SAM9X60 evaluation kit + FreeRTOS
--------------------------	-----------------------------------

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- SPI Driver (Asynchronous mode)

The following components used may vary based on the project configuration selected:

- SERCOM or SPI or FLEXCOM peripheral library
- Board Support Package (BSP)
- FreeRTOS

- Other MHC settings:
 - Configure the Pins for the SPI peripheral in the Pin Settings
 - Configure the SPI Chip Select, Hold and Write Protect Pins for both the EEPROMs
 - Enable DMA for Transmit and Receive (DMA Channels for transmit and receive gets allocated automatically by MHC)

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project sam_e54_xpro.X.

- Hardware Used:**
 - SAM E54 Xplained Pro Evaluation Kit
 - Two EEPROM 4 Click boards
 - Two mikroBUS Xplained Pro boards
- Hardware Setup:**
 - Install EEPROM 4 Click boards on to the mikroBUS Xplained Pro boards
 - Connect mikroBUS Xplained Pro boards on to the "EXT2" and "EXT3" headers of the SAM E54 Xplained Pro Evaluation Kit

2. Project sam_e70_xult.X.

3. Project sam_e70_xult_freertos.X.

- Hardware Used:**
 - SAM E70 Xplained Ultra Evaluation Kit
 - Two EEPROM 4 Click boards
 - One mikroBUS Xplained Pro board
- Hardware Setup:**
 - Install one EEPROM 4 Click board on to the click slot provided on SAM E70 Xplained Ultra Evaluation Kit
 - Install another EEPROM 4 Click board on to the mikroBUS Xplained Pro board
 - Connect mikroBUS Xplained Pro board to the EXT2 headers of the SAM E70 Xplained Ultra Evaluation Kit
 - Connect a jumper between LED2 and PB08 on J203 header of SAM E70 Xplained Ultra Evaluation Kit

4. Project sam_v71_xult.X.

5. Project sam_v71_xult_freertos.X.

- **Hardware Used:**
 - SAM V71 Xplained Ultra Evaluation Kit
 - Two EEPROM 4 Click boards
 - Two mikroBUS Xplained Pro boards
- **Hardware Setup:**
 - Install EEPROM 4 Click boards on to the mikroBUS Xplained Pro boards
 - Connect mikroBUS Xplained Pro boards on to the "EXT1" and "EXT2" headers of the SAM V71 Xplained Ultra Evaluation Kit

6. Project sam_a5d2_xult.IAR

7. Project sam_a5d2_xult_freertos.IAR

- **Hardware Used**
 - SAM A5D2 Xplained Ultra board
 - Two EEPROM 4 Click boards
 - Two mikroBUS Xplained Pro board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Install EEPROM 4 Click boards on to the mikroBUS Xplained Pro boards
 - Connect mikroBUS Xplained Pro boards on to the "EXT1" and "EXT2" headers of the SAM A5D2 Xplained Ultra board

8. Project sam_9x60_ek.IAR

9. Project sam_9x60_ek_freertos.IAR

- **Hardware Used**
 - SAM 9X60 Evaluation Kit board
 - Two EEPROM 4 Click boards
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
 - Insert one EEPROM 4 Click board into MIKROBUS connector J15
 - Connect another EEPROM 4 Click board to J17 connector as per below **Pin Connections** using jumper wires
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Note: Reset push button on SAM9X60 EK is labeled as SW3
- **Pin Connections**

J17 Connector Pins	EEPROM 4 CLICK Pins
PIN 15	HLD
PIN 24	WP
PIN 26	CS
PIN 23	SCK
PIN 19	SDI
PIN 21	SDO
PIN 6	GND
PIN 1	3V3

Running the Application

This section provides information on how to run an application.

Description

MPLAB X IDE

1. Connect a micro USB cable to the DEBUG port.
2. Build and Program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED turns ON when the data read from the EEPROMs matches with the data written to the EEPROMs.

The following table provides the LED name:

Kit Name	LED Name
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 2
SAM V71 Xplained Ultra Evaluation Kit	LED 0

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED turns ON when the data read from the EEPROMs matches with the data written to the EEPROMs.

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)
SAM9X60 evaluation kit	RGB_LED (Green)

spi_self_loopback_multi_client

This example demonstrates how to use the SPI driver in asynchronous mode to achieve self-loop back between multiple clients.

Description

This example writes and reads back the same data (self loop back) for two different clients connected over the same SPI bus by using the multi client feature of the driver. It uses the request (write and read request) queuing feature of the asynchronous driver and does not waste CPU bandwidth in waiting for previous request completion. The example also demonstrates how to setup two different client transfers at different baud rates.

This example performs self loop back only once after a power on reset. Success is indicated when a successful self loop back is reported by both the clients. After the loop back test is complete, the application remains in the idle state.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/spi/async/spi_self_loopback_multi_client/firmware
------------------	--

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mx_xlp_sk.X	PIC32MX XLP Starter Kit
pic32mz_das_sk.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit (Crypto)
pic32mz_ef_sk.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit
sam_d20_xpro.X	SAM D20 Xplained Pro Evaluation Kit
sam_d21_xpro.X	SAM D21 Xplained Pro Evaluation Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_v71_xult.X	SAM V71 Xplained Ultra Evaluation Kit
sam_v71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS
pic32mk_gp_db.X	PIC32MK General Purpose Development Board

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek.IAR	SAM9X60 evaluation kit
sam_9x60_ek_freertos.IAR	SAM9X60 evaluation kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- SPI Driver (Asynchronous mode)

The following components used may vary based on the project configuration selected:

- SERCOM or SPI or FLEXCOM peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC settings:

- Configure the Pins for the SPI peripheral in the Pin Settings
- Configure the SPI Chip Select Pins in the Pin Settings

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mx_xlp_sk.X

- **Hardware Used**
 - [PIC32MX XLP Starter Kit](#)
- **Hardware Setup**
 - Connect micro USB cable to the 'Debug USB' connector(J9) on the board to the computer.
 - Use jumper wire to connect "Pin 5 of J5" to "Pin 6 of J5"
 - SDI1 is mapped to RC8 that is routed to "Pin 5 of J5"
 - SDO1 is mapped to RA8 that is routed to "Pin 6 of J5"
 - Connect a micro USB cable to the USB DEBUG port J19

2. Project pic32mz_das_sk.X.

- **Hardware Used:**
 - [PIC32MZ Embedded Graphics with Stacked DRAM \(DA\) Starter Kit \(Crypto\)](#)
- **Hardware Setup:**
 - Use jumper wire to connect "Pin 21 of J15" to "Pin 19 of J15"
 - SDI2 is mapped to RD7 that is routed to "Pin 21 of J15"
 - SDO2 is mapped to RG8 that is routed to "Pin 19 of J15"
 - Connect a micro USB cable to the USB DEBUG port J19

3. Project pic32mz_ef_sk.X.

- **Hardware Used:**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
- **Hardware Setup:**
 - Use jumper wire to connect "Pin 7 of J12" to "Pin 37 of J12"
 - SDI3 is mapped to RA14 that is routed to "Pin 7 of J12"
 - SDO3 is mapped to RD10 that is routed to "Pin 37 of J12"
 - Connect a mini USB cable to the USB DEBUG port J3

4. Project sam_c21n_xpro.X.

- **Hardware Used:**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Use jumper wire to connect "Pin 16 of EXT2 header" to "Pin 17 of EXT2 header"
 - SERCOM5 PAD2 signal as MOSI signal and it is mapped to PB00 that is routed to "Pin 16 of EXT2 header"
 - SERCOM5 PAD0 signal as MISO signal and it is mapped to PB02 that is routed to "Pin 17 of EXT2 header"
 - Connect a micro USB cable to the DEBUG port.

5. Project sam_d20_xpro.X.

6. Project sam_d21_xpro.X.

- **Hardware Used:**
 - [SAM D20 Xplained Pro Evaluation Kit](#) or [SAM D21 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Use jumper wire to Connect "Pin 16 of EXT2 header" to "Pin 17 of EXT2 header"
 - SERCOM1 PAD2 signal as MOSI signal and it is mapped to PA18 that is routed to "Pin 16 of EXT2 header"

- SERCOM1 PAD0 signal as MISO signal and it is mapped to PA16 that is routed to "Pin 17 of EXT2 header"
- Connect a micro USB cable to the DEBUG port.

7. Project sam_e54_xpro.X.

- **Hardware Used:**
 - SAM E54 Xplained Pro Evaluation Kit
- **Hardware Setup:**
 - Use jumper wire to connect "Pin 16 of EXT2 header" to "Pin 17 of EXT2 header"
 - SERCOM6 PAD0 signal as MOSI signal and it is mapped to PC04 that is routed to "Pin 16 of EXT2 header"
 - SERCOM6 PAD3 signal as MISO signal and it is mapped to PC07 that is routed to "Pin 17 of EXT2 header"
 - Connect a micro USB cable to the DEBUG port.

8. Project sam_e70_xult.X.

9. Project sam_e70_xult_freertos.X.

- **Hardware Used:**
 - SAM E70 Xplained Ultra Evaluation Kit
- **Hardware Setup:**
 - Use jumper wire to Connect "Pin 16 of EXT1 header" to "Pin 17 of EXT1 header"
 - SPI0 MOSI signal is mapped to PD21 that is routed to "Pin 16 of EXT1 header"
 - SPI0 MISO signal is mapped to PD20 that is routed to "Pin 17 of EXT1 header"
 - Connect a micro USB cable to the DEBUG port.

10. Project sam_v71_xult.X.

11. Project sam_v71_xult_freertos.X.

- **Hardware Used:**
 - SAM V71 Xplained Ultra Evaluation Kit
- **Hardware Setup:**
 - Use jumper wire to Connect "Pin 16 of EXT1 header" to "Pin 17 of EXT1 header"
 - SPI0 MOSI signal is mapped to PD21 that is routed to "Pin 16 of EXT1 header"
 - SPI0 MISO signal is mapped to PD20 that is routed to "Pin 17 of EXT1 header"
 - Connect a micro USB cable to the DEBUG port.

12. Project sam_a5d2_xult.IAR

13. Project sam_a5d2_xult_freertos.IAR

- **Hardware Used**
 - SAM A5D2 Xplained Ultra board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Use jumper wire to Connect "Pin 16 of EXT1 header" to "Pin 17 of EXT1 header"
 - SPI1 MOSI signal is mapped to PD26 that is routed to "Pin 16 of EXT1 header"
 - SPI1 MISO signal is mapped to PD27 that is routed to "Pin 17 of EXT1 header"

14. Project pic32mk_gp_db.X.

- **Hardware Used:**
 - PIC32MK General Purpose Development Kit
- **Hardware Setup:**
 - Use jumper wire to Connect MOSI and MISO lines of J1 connector
 - SPI6 MOSI signal is mapped to RB0

- SPI6 MISO signal is mapped to RG9
- Connect a micro USB cable to the DEBUG port.

15. Project sam_9x60_ek.IAR

16. Project sam_9x60_ek_freertos.IAR

• Hardware Used

- SAM 9X60 Evaluation Kit board
- SD Card with FAT32 file system

• Hardware Setup

- Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
- Use jumper wire to Connect "Pin 19 of J17 Connector" to "Pin 21 of J17 Connector"
 - FLEXCOM4 MOSI signal is mapped to PA12 that is routed to "Pin 19 of J17 Connector"
 - FLEXCOM4 MISO signal is mapped to PA11 that is routed to "Pin 21 of J17 Connector"
- Connect the Debug USB port on the board to the computer using a micro USB cable
- Note: Reset push button on SAM9X60 EK is labeled as SW3

Running the Application

This section provides information on how to run an application.

Description

MPLAB X IDE

1. Build and Program the application using the MPLAB X IDE.
2. The LED indicates the success or failure.
 - The LED turns ON on Success and remains OFF on Failure

The following table provides the LED name:

Kit Name	LED Name
PIC32MX XLP Starter Kit	LED 1 (Red)
PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit (Crypto)	LED 1
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 1
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM D20 Xplained Pro Evaluation Kit	LED 0
SAM D21 Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1
SAM V71 Xplained Ultra Evaluation Kit	LED 0
PIC32MK General Purpose Development Board	LED 2

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED turns ON on Success and remains OFF on Failure

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)
SAM9X60 evaluation kit	RGB_LED (Green)

Sync

spi_multi_instance

This example demonstrates how to use multiple instances of the SPI driver in synchronous mode to communicate with multiple EEPROMs in an RTOS environment.

Description

This example writes and reads data to and from two separate EEPROMs connected over different SPI buses by using the multi instance feature of a synchronous SPI driver. The example also demonstrates how to setup two different instance transfers at different baud rates.

The example has three RTOS threads for the purpose:

1. **APP_EEPROM1_Tasks:** This thread performs write-read operation on the first EEPROM every 1 second.
2. **APP_EEPROM2_Tasks:** This thread performs write-read operation on the second EEPROM every 1 second.
3. **APP_MONITOR_Tasks:** This thread checks the status of transfers on both the EEPROMs and toggles LED if the transfers are successful. It checks the status of the transfers every 100 milliseconds.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/spi/sync/spi_multi_instance/firmware
------------------	---

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mx470_curiosity_freertos.X	PIC32MX Curiosity Development Board + FreeRTOS
sam_c21n_xpro_freertos.X	SAM C21N Xplained Pro Evaluation Kit + FreeRTOS
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- SPI Driver (Synchronous mode)

The following components used may vary based on the project configuration selected:

- SERCOM peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC settings:

- Configure the Pins for the SPI peripheral in the Pin Settings
- Configure the SPI Chip Select, Hold and Write Protect Pins of both the EEPROMs
- Enable DMA for Transmit and Receive (DMA Channels for transmit and receive automatically gets allocated)

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project `pic32mx_470_curiosity_freertos.X`

- **Hardware Used**
 - [PIC32MX Curiosity Development Board](#)
 - Two [EEPROM 4 Click boards](#)
- **Hardware Setup**
 - Connect mini USB cable to the 'Debug USB' connector(J3) on the board to the computer.
 - Install two [EEPROM 4 Click](#) boards on to the two mikroBUS sockets(J5 & J10) of PIC32MX Curiosity Development Board.
 - **Note:** Ensure that the series resistors on the mikroBUS headers are of value **0 Ohms**.

2. Project `sam_c21n_xpro_freertos.X`.

- **Hardware Used:**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
 - Two [EEPROM 4 Click boards](#)
 - Two [mikroBUS Xplained Pro boards](#)
- **Hardware Setup:**
 - Install two [EEPROM 4 Click](#) boards on to the two [mikroBUS Xplained Pro](#) boards
 - Connect two [mikroBUS Xplained Pro](#) boards to the "EXT1" and "EXT2" headers of the [SAM C21N Xplained Pro Evaluation Kit](#)

3. Project `sam_e54_xpro_freertos.X`.

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
 - Two [EEPROM 4 Click boards](#)
 - Two [mikroBUS Xplained Pro boards](#)
- **Hardware Setup:**
 - Install two [EEPROM 4 Click](#) boards on to the two [mikroBUS Xplained Pro](#) boards
 - Connect two [mikroBUS Xplained Pro](#) boards to the "EXT1" and "EXT2" headers of the [SAM E54 Xplained Pro Evaluation Kit](#)

Running the Application

This section provides information on how to run the application.

Description

MPLAB X IDE

1. Connect a micro USB cable to the DEBUG port.
2. Build and Program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED turns ON when the data read from the EEPROMs matches with the data written to the EEPROMs

The following table provides the LED name:

Kit Name	LED Name
PIC32MX Curiosity Development Board	LED 1
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0

spi_multi_slave

This example demonstrates how to use single instance of the SPI driver in synchronous mode to communicate with multiple EEPROMs in an RTOS environment.

Description

This example writes and reads data to and from two separate EEPROMs connected over the same SPI bus by using the multi client feature of a synchronous SPI driver. The example also demonstrates how to setup two different client transfers at two different baud rates.

The example has three RTOS threads for the purpose:

1. **APP_EEPROM1_Tasks:** This thread performs write-read operation on the first EEPROM
2. **APP_EEPROM2_Tasks:** This thread performs write-read operation on the second EEPROM
3. **APP_MONITOR_Tasks:** This thread checks the status of the EEPROM transfers and turns on the LED if the transfers are successful

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/spi/sync/spi_multi_slave/firmware
------------------	--

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS

sam_v71_xult_freertos.X

SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek_freertos.IAR	SAM9X60 evaluation kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- SPI Driver (Synchronous mode)
- The following components used may vary based on the project configuration selected:
- SERCOM or SPI or FLEXCOM peripheral library
 - Board Support Package (BSP)
 - FreeRTOS

Other MHC settings:

- Configure the Pins for the SPI peripheral in the Pin Settings
- Configure the SPI Chip Select, Hold and Write Protect Pins of both the EEPROMs
- Enable DMA for Transmit and Receive (DMA Channels for transmit and receive automatically gets allocated by MHC)

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project sam_e54_xpro_freertos.X.

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
 - Two [EEPROM 4 Click](#) boards
 - Two [mikroBUS Xplained Pro](#) boards
- **Hardware Setup:**
 - Install [EEPROM 4 Click](#) boards on to the [mikroBUS Xplained Pro](#) boards
 - Connect [mikroBUS Xplained Pro](#) boards on to the "EXT2" and "EXT3" headers of the [SAM E54 Xplained Pro Evaluation Kit](#)

2. Project sam_e70_xult_freertos.X.

- **Hardware Used:**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
 - Two [EEPROM 4 Click](#) boards
 - One [mikroBUS Xplained Pro](#) board

- **Hardware Setup:**

- Install one [EEPROM 4 Click](#) board on to the click slot provided on [SAM E70 Xplained Ultra Evaluation Kit](#)
- Install another [EEPROM 4 Click](#) board on to the [mikroBUS Xplained Pro](#) board
- Connect [mikroBUS Xplained Pro](#) board to the EXT2 headers of the [SAM E70 Xplained Ultra Evaluation Kit](#)
- Connect a jumper between **LED2** and PB08 on J203 header of [SAM E70 Xplained Ultra Evaluation Kit](#)

3. Project [sam_v71_xult_freertos.X](#)

- **Hardware Used:**

- [SAM V71 Xplained Ultra Evaluation Kit](#)
- Two [EEPROM 4 Click](#) boards
- Two [mikroBUS Xplained Pro](#) boards

- **Hardware Setup:**

- Install [EEPROM 4 Click](#) boards on to the [mikroBUS Xplained Pro](#) boards
- Connect [mikroBUS Xplained Pro](#) boards on to the "EXT1" and "EXT2" headers of the [SAM V71 Xplained Ultra Evaluation Kit](#)

4. Project [sam_a5d2_xult_freertos.IAR](#)

- **Hardware Used**

- [SAM A5D2 Xplained Ultra board](#)
- Two [EEPROM 4 Click](#) boards
- Two [mikroBUS Xplained Pro](#) board
- SD Card with FAT32 file system

- **Hardware Setup**

- Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
- Install [EEPROM 4 Click](#) boards on to the [mikroBUS Xplained Pro](#) boards
- Connect [mikroBUS Xplained Pro](#) boards on to the "EXT1" and "EXT2" headers of the [SAM A5D2 Xplained Ultra board](#)

5. Project [sam_9x60_ek_freertos.IAR](#)

- **Hardware Used**

- [SAM 9X60 Evaluation Kit board](#)
- Two [EEPROM 4 Click](#) boards
- SD Card with FAT32 file system

- **Hardware Setup**

- Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
- Insert one [EEPROM 4 Click](#) board into MIKROBUS connector J15
- Connect another [EEPROM 4 Click](#) board to J17 connector as per below **Pin Connections** using jumper wires
- Connect the Debug USB port on the board to the computer using a micro USB cable
- Note: Reset push button on SAM9X60 EK is labeled as SW3

- **Pin Connections**

J17 Connector Pins	EEPROM 4 CLICK Pins
PIN 15	HLD
PIN 24	WP
PIN 26	CS
PIN 23	SCK
PIN 19	SDI

PIN 21	SDO
PIN 6	GND
PIN 1	3V3

Running the Application

This section provides information on how to run an application.

Description

MPLAB X IDE

1. Connect a micro USB cable to the DEBUG port.
2. Build and Program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED turns ON when the data read from the EEPROMs matches with the data written to the EEPROMs

The following table provides the LED name:

Kit Name	LED Name
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 2
SAM V71 Xplained Ultra Evaluation Kit	LED 0

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED turns ON when the data read from the EEPROMs matches with the data written to the EEPROMs

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)
SAM9X60 evaluation kit	RGB_LED (Green)

spi_self_loopback_multi_client

This example demonstrates how to use the SPI driver in synchronous mode to achieve self-loop back between multiple clients in RTOS environment.

Description

This example writes and reads back the same data (self loop back) for two different clients connected over the same SPI bus by using the multi client feature of a synchronous SPI driver. The example also demonstrates how to setup two different client transfers at two different baud rates.

The example has three RTOS threads for the purpose:

1. **APP_CLIENT1_Tasks:** This thread opens the SPI driver instance and performs a continuous loop back transfer. If the loop back is successful, the loop back is repeated every 100 ms. In case of an error, the thread closes the driver and suspends itself.
2. **APP_CLIENT2_Tasks:** This thread opens the SPI driver instance and performs a continuous loop back transfer. If the loop back is successful, the loop back is repeated every 100 ms. In case of an error, the thread closes the driver and suspends itself.
3. **APP_MONITOR_Tasks:** This thread checks the status of loop back done by the two client tasks and toggles LED if the loop back transfer status reported by both the clients is successful.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/spi/sync/spi_self_loopback_multi_client/firmware
------------------	---

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mz_das_sk_freertos.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit (Crypto) + FreeRTOS
pic32mz_ef_sk_freertos.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit + FreeRTOS
sam_c21n_xpro_freertos.X	SAM C21N Xplained Pro Evaluation Kit + FreeRTOS
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
pic32mk_gp_db.X	PIC32MK General Purpose Development Board

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek_freertos.IAR	SAM9X60 evaluation kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- SPI Driver (Synchronous mode)

The following components used may vary based on the project configuration selected:

- SERCOM or SPI or FLEXCOM peripheral library
- SERCOM or SPI or FLEXCOM peripheral library in Interrupt mode
- Board Support Package (BSP)
- FreeRTOS

Other MHC settings:

- Configure the Pins for the SPI peripheral in the Pin Settings
- Configure the SPI Chip Select Pins in the Pin Settings
- Enable DMA for Transmit and Receive (DMA Channels for transmit and receive automatically gets allocated)

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project `pic32mz_das_sk.X`.

- **Hardware Used:**
 - [PIC32MZ Embedded Graphics with Stacked DRAM \(DA\) Starter Kit \(Crypto\)](#)
- **Hardware Setup:**
 - Use jumper wire to connect "Pin 21 of J15" to "Pin 19 of J15"
 - SDI2 is mapped to RD7 that is routed to "Pin 21 of J15"
 - SDO2 is mapped to RG8 that is routed to "Pin 19 of J15"
 - Connect a micro USB cable to the USB DEBUG port J19

2. Project `pic32mz_ef_sk.X`.

- **Hardware Used:**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
- **Hardware Setup:**
 - Use jumper wire to connect "Pin 7 of J12" to "Pin 37 of J12"
 - SDI3 is mapped to RA14 that is routed to "Pin 7 of J12"
 - SDO3 is mapped to RD10 that is routed to "Pin 37 of J12"
 - Connect a mini USB cable to the USB DEBUG port J3

3. Project `sam_c21n_xpro_freertos.X`.

- **Hardware Used:**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Use jumper wire to Connect "Pin 16 of EXT2 header" to "Pin 17 of EXT2 header"
 - SERCOM5 PAD2 signal as MOSI signal and it is mapped to PB00 that is routed to "Pin 16 of EXT2 header"
 - SERCOM5 PAD0 signal as MISO signal and it is mapped to PB02 that is routed to "Pin 17 of EXT2 header"
 - Connect a micro USB cable to the DEBUG port.

4. Project `sam_e54_xpro_freertos.X`.

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Use jumper wire to connect "Pin 16 of EXT2 header" to "Pin 17 of EXT2 header"
 - SERCOM6 PAD0 signal as MOSI signal and it is mapped to PC04 that is routed to "Pin 16 of EXT2 header"
 - SERCOM6 PAD3 signal as MISO signal and it is mapped to PC07 that is routed to "Pin 17 of EXT2 header"
 - Connect a micro USB cable to the DEBUG port.

5. Project `sam_e70_xult_freertos.X`.

- **Hardware Used:**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup:**
 - Use jumper wire to Connect "Pin 16 of EXT1 header" to "Pin 17 of EXT1 header"
 - SPI0 MOSI signal is mapped to PD21 that is routed to "Pin 16 of EXT1 header"
 - SPI0 MISO signal is mapped to PD20 that is routed to "Pin 17 of EXT1 header"
 - Connect a micro USB cable to the DEBUG port.

6. Project sam_a5d2_xult_freertos.IAR

- **Hardware Used**
 - SAM A5D2 Xplained Ultra board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Use jumper wire to Connect "Pin 16 of EXT1 header" to "Pin 17 of EXT1 header"
 - SPI1 MOSI signal is mapped to PD26 that is routed to "Pin 16 of EXT1 header"
 - SPI1 MISO signal is mapped to PD27 that is routed to "Pin 17 of EXT1 header"

7. Project pic32mk_gp_db.X.

- **Hardware Used:**
 - [PIC32MK General Purpose Development Kit](#)
- **Hardware Setup:**
 - Use jumper wire to Connect MOSI and MISO lines of J1 connector
 - SPI6 MOSI signal is mapped to RB0
 - SPI6 MISO signal is mapped to RG9
 - Connect a micro USB cable to the DEBUG port.

8. Project sam_9x60_ek_freertos.IAR

- **Hardware Used**
 - SAM 9X60 Evaluation Kit board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
 - Use jumper wire to Connect "Pin 19 of J17 Connector" to "Pin 21 of J17 Connector"
 - FLEXCOM4 MOSI signal is mapped to PA12 that is routed to "Pin 19 of J17 Connector"
 - FLEXCOM4 MISO signal is mapped to PA11 that is routed to "Pin 21 of J17 Connector"
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Note: Reset push button on SAM9X60 EK is labeled as SW3

Running the Application

This section provides information on how to run an application.

Description

MPLAB X IDE

1. Build and Program the application using the MPLAB X IDE.
2. The LED indicates the success or failure.
 - The LED blinks on Success

The following table provides the LED name:

Kit Name	LED Name
PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit (Crypto)	LED 1
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 1

SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1
PIC32MK General Purpose Development Board	LED 2

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED turns ON on Success and remains OFF on Failure

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)
SAM9X60 evaluation kit	RGB_LED (Green)

SPI EEPROM Driver Applications

This section provides help for the SPI EEPROM driver applications.

AT25 Driver Applications

This section provides help for the AT25 driver applications.

at25_eeprom_read_write

This example application shows how to use the AT25 driver to perform read and write operations on AT25 series of EEPROM.

Description

This example uses the AT25 driver to communicate with the SPI based AT25 series of external EEPROMs to perform write and read operations in both Bare-Metal and RTOS environment.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/driver/spi_eeprom/at25/at25_eeprom_read_write/firmware
-------------------------	---

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mx470_curiosity.X	PIC32MX Curiosity Development Board

pic32mx_xlp_sk.X	PIC32MX XLP Starter Kit
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit
sam_d20_xpro.X	SAM D20 Xplained Pro Evaluation Kit
sam_d21_xpro.X	SAM D21 Xplained Pro Evaluation Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_v71_xult.X	SAM V71 Xplained Ultra Evaluation Kit
sam_v71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS
pic32mk_gp_db.X	PIC32MK General Purpose Development Board

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek.IAR	SAM9X60 evaluation kit
sam_9x60_ek_freertos.IAR	SAM9X60 evaluation kit + FreeRTOS

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

- AT25 Driver
- The following components used may vary based on the project configuration selected:
- SPI or SERCOM or FLEXCOM peripheral library
 - Board Support Package (BSP)
 - FreeRTOS

Other MHC Settings:

- Configure Pins for AT25 Chip Select, Hold Pin and Write Protect Pin in Pin Settings

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mx470_curiosty.X

- Hardware Used**
 - PIC32MX Curiosity Development Board

- One [EEPROM 4 Click](#) board.
- **Hardware Setup**
 - Connect mini USB cable to the 'Debug USB' connector(J3) on the board to the computer.
 - Install one [EEPROM 4 Click](#) board on to the mikroBUS socket J5 of [PIC32MX Curiosity Development Board](#).
 - **Note:** Ensure that the series resistors on the mikroBUS headers are of value **0 Ohms**.

2. Project [pic32mx_xlp_sk.X](#)

- **Hardware Used**
 - [PIC32MX XLP Starter Kit](#)
 - One [EEPROM 4 Click](#) board.
- **Hardware Setup**
 - Connect mini USB cable to the 'Debug USB' connector(J9) on the board to the computer.
 - Install one [EEPROM 4 Click](#) board on to the mikroBUS socket J5 of [PIC32MX XLP Starter Kit](#).

3. Project [sam_c21n_xpro.X](#).

- **Hardware Used:**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Install an [EEPROM 4 Click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect [mikroBUS Xplained Pro](#) board to the EXT2 header of the [SAM C21N Xplained Pro Evaluation Kit](#)

4. Project [sam_d20_xpro.X](#).

- **Hardware Used:**
 - [SAM D20 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Install an [EEPROM 4 Click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect the [mikroBUS Xplained Pro](#) board to the EXT2 header of the [SAM D20 Xplained Pro Evaluation Kit](#)

5. Project [sam_d21_xpro.X](#).

- **Hardware Used:**
 - [SAM D21 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Install an [EEPROM 4 Click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect the [mikroBUS Xplained Pro](#) board to the EXT2 header of the [SAM D21 Xplained Pro Evaluation Kit](#)

6. Project [sam_e54_xpro.X](#).

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Install an [EEPROM 4 Click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect [mikroBUS Xplained Pro](#) board to the EXT2 header of the [SAM E54 Xplained Pro Evaluation Kit](#)

7. Project [sam_e70_xult.X](#).

8. Project [sam_e70_xult_freertos.X](#).

- **Hardware Used:**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup:**
 - Install [EEPROM 4 Click](#) board to the click slot provided on the [SAM E70 Xplained Ultra Evaluation Kit](#)
 - Connect a jumper between **LED2** and PB08 on J203 header of [SAM E70 Xplained Ultra Evaluation Kit](#)

9. Project [sam_v71_xult.X](#).

10. Project [sam_v71_xult_freertos.X](#).

- **Hardware Used:**
 - SAM V71 Xplained Ultra Evaluation Kit
- **Hardware Setup:**
 - Install an [EEPROM 4 Click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect [mikroBUS Xplained Pro](#) board to the EXT1 header of the [SAM V71 Xplained Ultra Evaluation Kit](#)

11. Project sam_a5d2_xult.IAR

12. Project sam_a5d2_xult_freertos.IAR

- **Hardware Used**
 - SAM A5D2 Xplained Ultra board
 - EEPROM 4 Click
 - mikroBUS Xplained Pro
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Install an [EEPROM 4 Click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect [mikroBUS Xplained Pro](#) board to the EXT1 header of the [SAM A5D2 Xplained Ultra board](#)

13. Project pic32mk_gp_db.X.

- **Hardware Used:**
 - PIC32MK General Purpose Development Kit
 - EEPROM 4 Click
- **Hardware Setup:**
 - Install [EEPROM 4 Click](#) board on to the J1 click board slot provided on [PIC32MK General Purpose Development Kit](#)

14. Project sam_9x60_ek.IAR

15. Project sam_9x60_ek_freertos.IAR

- **Hardware Used**
 - SAM 9X60 Evaluation Kit board
 - [EEPROM 4 Click](#) board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
 - Insert [EEPROM 4 Click](#) board into MIKROBUS Connector J15.
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Note: Reset push button on SAM9X60 EK is labeled as SW3

Running the Application

This section provides information on how to run the application.

Description

MPLAB X IDE

1. Connect a USB cable to the DEBUG port.
2. Build and program the application using the MPLAB X IDE.

3. The LED indicates the success or failure.

- The LED is turned ON when the value read from EEPROM matches with the written data

The following table provides the LED name:

Kit Name	LED Name
PIC32MX Curiosity Development Board	LED 1
PIC32MX XLP Starter Kit	LED 1 (Red)
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM D20 Xplained Pro Evaluation Kit	LED 0
SAM D21 Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 2
SAM V71 Xplained Ultra Evaluation Kit	LED 0
PIC32MK General Purpose Development Board	LED 2

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED is turned ON when the value read from EEPROM matches with the written data

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)
SAM9X60 evaluation kit	RGB_LED (Green)

SPI Flash Driver Applications

This section provides help for the SPI Flash driver applications.

AT25DF Applications

This section provides help for the AT25DF SPI flash driver applications.

at25df_flash_read_write

This example application shows how to use the AT25DF SPI flash driver to perform block operations on the on-board AT25DF Flash memory.

Description

This application uses the AT25DF SPI flash driver to Erase/Write/Read on the On-Board AT25DF Flash memory using the SPI peripheral library. The application consists of APP_Tasks() which is called through SYS_Tasks() routine.

Building The Application

This section provides information on how to build an application.

Description

The parent folder for all projects for this application is given below:

Application Path	csp/apps/driver/spi_flash/at25df/at25df_flash_read_write/firmware
------------------	--

Below table shows the list of project names to be used with different development boards. Open the project in their respective IDEs.

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit

MPLAB Harmony Configurations

This topic provides information on the MHC configurations.

Description

Components used:

The components used may vary based on the project configuration selected:

- AT25DF driver

The following components used may vary based on the project configuration selected:

- SPI peripheral library
- Board Support Package (BSP)

NOTE: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project sam_a5d2_xult_freertos.IAR

- **Hardware Used**
 - [SAM A5D2 Xplained Ultra board](#)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Make sure that the jumper JP9 is removed (jumper pins are not shorted)

Running The Application

This section provides information on how to run an application.

Description

Running project with IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED toggles with 1 second delay if the demo executes successfully.
 - LED turns on and stays on if the demo executes with error.

The following table provides the LED name:

Kit Name	LED Name
SAMA5D2 Xplained Ultra Evaluation kit	RGB_LED(Green)

SQI Flash Driver Applications

This section provides help for the SQI Flash driver applications.

MX25L Applications

This section provides help for the MX25L QSPI flash driver applications.

mx25l_flash_read_write

This example application shows how to use the MX25L QSPI flash driver to perform block operations on the on-board MX25L QSPI Flash memory.

Description

This application uses the MX25L QSPI flash driver to Erase/Write/Read on the On-Board MX25L QSPI Flash memory using the QSPI peripheral library. The application consists of APP_Tasks() which is called through SYS_Tasks() routine.

Building The Application

This section provides information on how to build an application.

Description

The parent folder for all projects for this application is given below:

Application Path	csp/apps/driver/sqi_flash/mx25l/mx25l_flash_read_write/firmware
------------------	---

Below table shows the list of project names to be used with different development boards. Open the project in their respective IDEs.

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit

MPLAB Harmony Configurations

This topic provides information on the MHC configurations.

Description

Components used:

The components used may vary based on the project configuration selected:

- MX25L driver

The following components used may vary based on the project configuration selected:

- QSPI peripheral library
- Board Support Package (BSP)

NOTE: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project sam_a5d2_xult_freertos.IAR

- **Hardware Used**
 - [SAM A5D2 Xplained Ultra board](#)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Make sure that the jumper JP9 is removed (jumper pins are not shorted)

Running The Application

This section provides information on how to run an application.

Description

Running project with IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED toggles with 1 second delay if the demo executes successfully.
 - LED turns on and stays on if the demo executes with error.

The following table provides the LED name:

Kit Name	LED Name
SAMA5D2 Xplained Ultra Evaluation kit	RGB_LED(Green)

SST26 Driver Applications

This section provides help for the SST26 driver applications.

sst26_flash_read_write

This example application shows how to use the SST26 driver to perform block operations on the On-Board SST26 Flash memory.

Description

This application uses the SST26 driver to Erase/Write/Read on the On-Board SST26 Flash memory using the QSPI or SQI peripheral library.

The application consists of APP_SST26_Tasks() which is called through SYS_Tasks() routine.

Building The Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/driver/sqi_flash/sst26/sst26_flash_read_write/firmware
------------------	--

To build the application, refer to the following table and open the appropriate project file in the MPLAB X IDE:

Project Name	Description
pic32mz_ef_sk.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit

MPLAB Harmony Configuration

This topic provides information on the MHC configurations.

Description

Components used:

The components used may vary based on the project configuration selected:

- SST26 Driver

The following components used may vary based on the project configuration selected:

- QSPI or SQI peripheral library
- Board Support Package (BSP)

Other MHC Configurations:

- Enable Memory Protection Unit (MPU) for the QSPI Flash memory region

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. **Project pic32mz_ef_sk.X.**
 - **Hardware Used**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
 - **Hardware Setup**
 - No Special hardware Setup Required
2. **Project sam_e70_xult.X.**
 - **Hardware Used**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
 - **Hardware Setup**
 - No Special hardware Setup Required

Running The Application

This section provides information on how to run the application using the MPLAB X IDE.

Description

1. Connect a micro/mini USB cable to the DEBUG port.
2. Build and program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED is turned ON when the data read from SST26 flash matches with the data written in it.

The following table provides the LED name:

Kit Name	LED Name
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 3
SAM E70 Xplained Ultra Evaluation Kit	LED 1

USART Driver Applications

Async

Name	Description
uart_echo	This example echoes the received characters over the console using the USART driver in asynchronous mode.
uart_multi_instance	This example echoes the received characters over the two consoles using the USART driver in asynchronous mode.

Sync

Name	Description
uart_echo	This example echoes the received characters over the console using the USART driver in synchronous mode.
uart_multi_instance	This example echoes the received characters over the two consoles using the USART driver in synchronous mode with DMA enabled.

Description

This section provides help for the USART Driver applications.

Async

uart_echo

This example echoes the received characters over the console using the USART driver in asynchronous mode.

Description

This example uses the USART driver in asynchronous mode in both Bare-Metal and RTOS environment to communicate over the console. It receives and echo's back the characters entered by the user.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core\apps\driver\uart\async\uart_echo\firmware
------------------	--

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mk_gp_db.X	PIC32MK GP Development Kit
pic32mx470_curiosity.X	PIC32MX Curiosity Development Board
pic32mx_xlp_sk.X	PIC32MX XLP Starter Kit
pic32mz_das_sk.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit (Crypto)
pic32mz_ef_sk.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_l21_xpro.X	SAM L21 Xplained Pro Evaluation Kit
sam_l22_xpro.X	SAM L22 Xplained Pro Evaluation Kit
sam_v71_xult.X	SAM V71 Xplained Ultra Evaluation Kit
sam_v71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek.IAR	SAM9X60 evaluation kit
sam_9x60_ek_freertos.IAR	SAM9X60 evaluation kit + FreeRTOS

MPLAB Harmony Configurations

This section provides information on the MHC configurations.

Description

Components Used:

- USART Driver (Asynchronous mode)

The following components vary based on the project configuration selected:

- USART or SERCOM or UART or DBGU peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Settings:

- Configure the Pins for the USART or SERCOM or UART or DBGU peripheral in the Pin Settings

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mk_gp_db.X.

- Hardware Used:

- [PIC32MK GP Development Kit](#)

- Hardware Setup:

- Connect a micro USB cable to the USART-USB port J25
- For programming, connect a micro USB cable to the USB Debug port J12

2. Project pic32mx470_curiosity.X

- Hardware Used

- [PIC32MX Curiosity Development Board](#)

- Hardware Setup

- Connect mini USB cable to the 'Debug USB' connector(J3) on the board to the computer.
- Install an [USB UART click](#) board on to the mikroBUS socket J5
- Connect mini USB cable to the [USB UART click](#) board. This will enumerate the USB to UART port.
- Note:** Ensure that the series resistors on the mikroBUS headers are of value **0 Ohms**.

3. Project pic32mx_xlp_sk.X

- Hardware Used

- [PIC32MX XLP Starter Kit](#)

- Hardware Setup

- Connect micro USB cable to the 'Debug USB' connector(J9) on the board to the computer.
- Install an [USB UART click](#) board on to the mikroBUS socket J5
- Connect mini USB cable to the [USB UART click](#) board. This will enumerate the USB to UART port.

4. Project pic32mz_das_sk.X.

- Hardware Used:

- [PIC32MZ Embedded Graphics with Stacked DRAM \(DA\) Starter Kit \(Crypto\)](#)
- **Hardware Setup:**
 - Connect a micro USB cable to the USART-USB port J5
 - For programming, connect a micro USB cable to the USB Debug port J19

5. Project [pic32mz_ef_sk.X](#).

- **Hardware Used:**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
- **Hardware Setup:**
 - Connect a mini USB cable to the USART-USB port J11
 - For programming, connect a mini USB cable to the USB Debug port J3

6. Project [sam_c21n_xpro.X](#).

- **Hardware Used:**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Connect a micro USB cable to the DEBUG port

7. Project [sam_e54_xpro.X](#).

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Connect a micro USB cable to the DEBUG port

8. Project [sam_e70_xult.X](#).

9. Project [sam_e70_xult_freertos.X](#).

- **Hardware Used:**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup:**
 - Connect a micro USB cable to the DEBUG port

10. Project [sam_l21_xpro.X](#)

- **Hardware Used**
 - [SAM L21 Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - Connect a micro USB cable to the DEBUG port

11. Project [sam_l22_xpro.X](#)

- **Hardware Used**
 - [SAM L22 Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - Connect a micro USB cable to the DEBUG port

12. Project [sam_v71_xult.X](#).

13. Project [sam_v71_xult_freertos.X](#).

- **Hardware Used:**
 - [SAM V71 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup:**
 - Connect a micro USB cable to the DEBUG port

14. Project [sam_a5d2_xult.IAR](#)

15. Project [sam_a5d2_xult_freertos.IAR](#)

- **Hardware Used**
 - SAM A5D2 Xplained Ultra board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Short jumper JP2(DEBUG_DIS)
 - Connect the Debug USB port on the board to the computer using a micro USB cable

16. Project sam_9x60_ek.IAR

17. Project sam_9x60_ek_freertos.IAR

- **Hardware Used**
 - SAM 9X60 Evaluation Kit board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Note: Reset push button on SAM9X60 EK is labeled as SW3

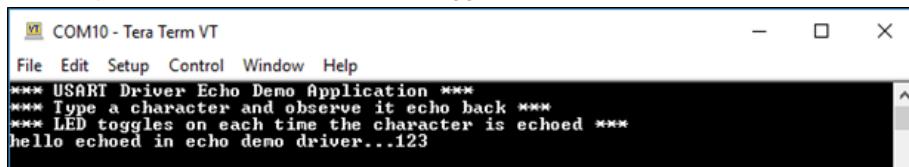
Running the Application

This section provides information on how to run the application.

Description

MPLAB X IDE

1. Open the Terminal application (Ex.:Tera Term) on the computer.
2. Configure the serial port settings as follows:
 - Baud : 115200
 - Data : 8 Bits
 - Parity : None
 - Stop : 1 Bit
 - Flow Control : None
3. Build and program the application using the MPLAB X IDE.
4. Type a character and observe the output on the console as shown below:
 - If success the character typed echoes back and an LED toggles on each time the character is echoed.



The following table provides the LED name:

Kit Name	LED Name
PIC32MK GP Development Kit	LED 1
PIC32MX Curiosity Development Board	LED 1
PIC32MX XLP Starter Kit	LED 1 (Red)

PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit (Crypto)	LED 1
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 1
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1
SAM L21 Xplained Pro Evaluation Kit	LED 0
SAM L22 Xplained Pro Evaluation Kit	LED 0
SAM V71 Xplained Ultra Evaluation Kit	LED 1

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Open the Terminal application (Ex.:Tera term) on the computer.
4. Connect to the USB to UART COM port and configure the serial settings as follows:
 - Baud : 115200
 - Data : 8 Bits
 - Parity : None
 - Stop : 1 Bit
 - Flow Control : None
5. Reset the board to run the application
6. Type a character and observe the output on the console:
 - If success the character typed echoes back and an LED toggles on each time the character is echoed.

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)
SAM9X60 evaluation kit	RGB_LED (Green)

uart_multi_instance

This example echoes the received characters over the two consoles using the USART driver in asynchronous mode.

Description

This example uses the USART driver in asynchronous mode in both Bare-Metal and RTOS environments to communicate over two consoles. It receives and echoes back the characters entered by the user on the respective console.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core\apps\driver\uart\async\uart_multi_instance\firmware
-------------------------	---

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mk_gp_db.X	PIC32MK GP Development Kit
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit
sam_d20_xpro.X	SAM D20 Xplained Pro Evaluation Kit
sam_d21_xpro.X	SAM D21 Xplained Pro Evaluation Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_v71_xult.X	SAM V71 Xplained Ultra Evaluation Kit
sam_v71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek.IAR	SAM9X60 evaluation kit
sam_9x60_ek_freertos.IAR	SAM9X60 evaluation kit + FreeRTOS

MPLAB Harmony Configurations

This section provides information on the MHC configurations.

Description

Components Used:

- USART Driver (Asynchronous mode)

The following components used may vary based on the project configuration selected:

- Two USART or SERCOM peripherals library. Or UART/DBGU and FLEXCOM peripherals library.
- Board Support Package (BSP)
- FreeRTOS

Other MHC Settings:

- Configure the Pins for the USART or SERCOM or UART or DBGU or FLEXCOM peripherals in the Pin Settings

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mk_gp_db.X.

• Hardware Used:

- PIC32MK GP Development Kit

- **Hardware Setup:**

- Connect a micro USB cable to the USART-USB port J25. This will enumerate the first port.
- Install an [USB UART click](#) board on to the mikroBUS socket J1
- Connect mini USB cable to the [USB UART click](#) board. This will enumerate the second port.
- For programming, connect a micro USB cable to the USB Debug port J12

2. Project `sam_c21n_xpro.X`.

- **Hardware Used:**

- [SAM C21N Xplained Pro Evaluation Kit](#)

- **Hardware Setup:**

- Connect the [mikroBUS Xplained Pro](#) board to the EXT1 header of the [SAM C21N Xplained Pro Evaluation Kit](#)
- Install an [USB UART click](#) board on to the [mikroBUS Xplained Pro](#) board
- Connect a micro USB cable to the DEBUG port. This will enumerate a first port.
- Connect mini USB cable to the [USB UART click](#) board. This will enumerate the second port.

3. Project `sam_d20_xpro.X`.

- **Hardware Used:**

- [SAM D20 Xplained Pro Evaluation Kit](#)

- **Hardware Setup:**

- Connect the [mikroBUS Xplained Pro](#) board to the EXT1 header of the [SAM D20 Xplained Pro Evaluation Kit](#)
- Install an [USB UART click](#) board on to the [mikroBUS Xplained Pro](#) board
- Connect a micro USB cable to the DEBUG port. This will enumerate a first port.
- Connect mini USB cable to the [USB UART click](#) board. This will enumerate the second port.

4. Project `sam_d21_xpro.X`.

- **Hardware Used:**

- [SAM D21 Xplained Pro Evaluation Kit](#)

- **Hardware Setup:**

- Connect the [mikroBUS Xplained Pro](#) board to the EXT1 header of the [SAM D21 Xplained Pro Evaluation Kit](#)
- Install an [USB UART click](#) board on to the [mikroBUS Xplained Pro](#) board
- Connect a micro USB cable to the DEBUG port. This will enumerate a first port.
- Connect mini USB cable to the [USB UART click](#) board. This will enumerate the second port.

5. Project `sam_e54_xpro.X`.

- **Hardware Used:**

- [SAM E54 Xplained Pro Evaluation Kit](#)

- **Hardware Setup:**

- Connect the [mikroBUS Xplained Pro](#) board to the EXT1 header of the [SAM E54 Xplained Pro Evaluation Kit](#)
- Install an [USB UART click](#) board on to the [mikroBUS Xplained Pro](#) board
- Connect a micro USB cable to the DEBUG port. This will enumerate a first port.
- Connect mini USB cable to the [USB UART click](#) board. This will enumerate the second port.

6. Project `sam_e70_xult.X`.

7. Project `sam_e70_xult_freertos.X`.

- **Hardware Used:**

- [SAM E70 Xplained Ultra Evaluation Kit](#)

- **Hardware Setup:**

- Connect a [USB UART click](#) board to the mikroBus header of the [SAM E70 Xplained Ultra Evaluation Kit](#)
- Connect a micro USB cable to the DEBUG port. This will enumerate a first port.
- Connect mini USB cable to the [USB UART click](#) board. This will enumerate the second port.

8. Project `sam_v71_xult.X`.

9. Project sam_v71_xult_freertos.X.

- **Hardware Used:**
 - SAM V71 Xplained Ultra Evaluation Kit
- **Hardware Setup:**
 - Connect the mikroBUS Xplained Pro board to the EXT1 header of the SAM V71 Xplained Ultra board
 - Install an [USB UART click](#) board on to the mikroBUS Xplained Pro board
 - Connect a micro USB cable to the DEBUG port. This will enumerate a first port.
 - Connect mini USB cable to the [USB UART click](#) board. This will enumerate the second port.

10. Project sam_a5d2_xult.IAR

11. Project sam_a5d2_xult_freertos.IAR

- **Hardware Used**
 - SAM A5D2 Xplained Ultra board
 - [USB UART Click board](#)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Short jumper JP2(DEBUG_DIS)
 - Connect [USB UART Click board](#) to [SAM A5D2 Xplained Ultra board](#) as per below **Pin Connections**
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Connect the Mini USB connector on the [USB UART Click board](#) to the computer using a Mini USB cable
- **Pin Connections**

SAM A5D2 Xplained Ultra board Pins	USB UART Click board Pins
F0_TXD, J22 connector	RX
F0_RXD, J22 connector	TX
PIN 20, XPRO EXT2 connector	3.3V
PIN 19, XPRO EXT2 connector	GND

12. Project sam_9x60_ek.IAR

13. Project sam_9x60_ek_freertos.IAR

- **Hardware Used**
 - SAM 9X60 Evaluation Kit board
 - [USB UART Click board](#)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
 - Insert [USB UART Click board](#) into MIKROBUS Connector J15
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Connect the Mini USB connector on the [USB UART Click board](#) to the computer using a Mini USB cable
 - Note: Reset push button on SAM9X60 EK is labeled as SW3

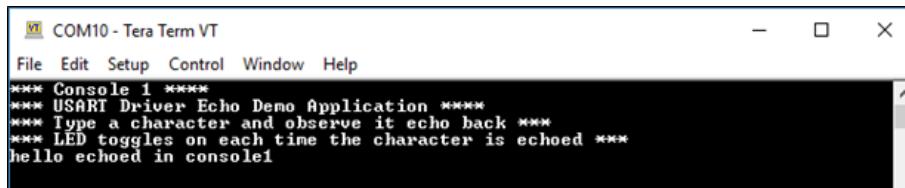
Running the Application

This section provides information on how to run the application.

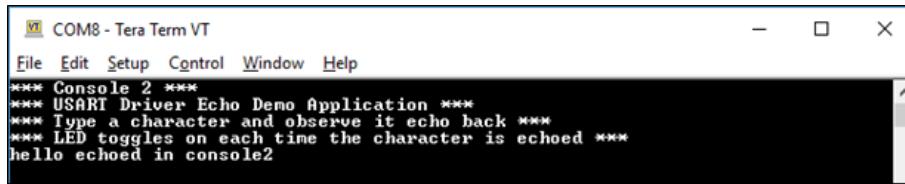
Description

MPLAB X IDE

1. Open the Terminal application (Ex.:Tera Term) on the computer for two COM ports.
2. Configure the serial port settings as follows:
 - Baud : 115200
 - Data : 8 Bits
 - Parity : None
 - Stop : 1 Bit
 - Flow Control : None
3. Build and program the application using the MPLAB X IDE.
4. Type a character and observe the output on the two consoles as shown below:
 - If success the character typed echoes back and an LED toggles on each time the character is echoed.



Output on Console 1



Output on Console 2

The following table provides the LED name:

Kit Name	LED Name
PIC32MK GP Development Kit	LED 1
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM D20 Xplained Pro Evaluation Kit	LED 0
SAM D21 Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1
SAM V71 Xplained Ultra Evaluation Kit	LED 1

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Open the Terminal application (Ex.:Tera term) on the computer for both COM Ports.
4. Connect to the USB to UART COM port and configure the serial settings for both COM Ports as follows :
 - Baud : 115200
 - Data : 8 Bits
 - Parity : None
 - Stop : 1 Bit

- Flow Control : None
5. Reset the board to run the application
6. Type a character and observe the output on the console:
- If success the character typed echoes back and an LED toggles on each time the character is echoed.

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)
SAM9X60 evaluation kit	RGB_LED (Green)

Sync

uart_echo

This example echoes the received characters over the console using the USART driver in synchronous mode.

Description

This example uses the USART driver in synchronous mode in an RTOS environment to communicate over the console. It receives and echoes back the characters entered by the user.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core\apps\driver\uart\sync\uart_echo\firmware
------------------	---

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mx470_curiosity_freertos.X	PIC32MX Curiosity Development Board + FreeRTOS
pic32mz_das_sk_freertos.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit (Crypto) + FreeRTOS
pic32mz_ef_sk_freertos.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit + FreeRTOS
sam_c21n_xpro_freertos.X	SAM C21N Xplained Pro Evaluation Kit + FreeRTOS
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS

sam_9x60_ek_freertos.IAR	SAM9X60 evaluation kit + FreeRTOS
--------------------------	-----------------------------------

MPLAB Harmony Configurations

This section provides information on the MHC configurations.

Description

Components Used:

- USART Driver (Synchronous mode)
- FreeRTOS

The following components used may vary based on the project configuration selected:

- USART or SERCOM or UART or DBGU peripheral library
- Board Support Package (BSP)

Other MHC Settings:

- Configure the Pins for the USART or SERCOM or UART or DBGU peripheral in the Pin Settings

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project `pic32mx_470_curiosity_freertos.X`

- **Hardware Used:**
 - [PIC32MX Curiosity Development Board](#)
- **Hardware Setup:**
 - Connect mini USB cable to the 'Debug USB' connector(J3) on the board to the computer.
 - Install an [USB UART click](#) board on to the mikroBUS socket J5
 - Connect mini USB cable to the [USB UART click](#) board. This will enumerate the USB to UART port.
 - **Note:** Ensure that the series resistors on the mikroBUS headers are of value **0 Ohms**.

2. Project `pic32mz_das_sk_freertos.X`.

- **Hardware Used:**
 - [PIC32MZ Embedded Graphics with Stacked DRAM \(DA\) Starter Kit \(Crypto\)](#)
- **Hardware Setup:**
 - Connect a micro USB cable to the USART-USB port J5
 - For programming, connect a micro USB cable to the USB Debug port J19

3. Project `pic32mz_ef_sk_freertos.X`.

- **Hardware Used:**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
- **Hardware Setup:**
 - Connect a mini USB cable to the USART-USB port J11
 - For programming, connect a mini USB cable to the USB Debug port J3

4. Project sam_c21n_xpro_freertos.X.

- **Hardware Used:**
 - SAM C21N Xplained Pro Evaluation Kit
- **Hardware Setup:**
 - Connect a micro USB cable to the DEBUG port

5. Project sam_e54_xpro_freertos.X.

- **Hardware Used:**
 - SAM E54 Xplained Pro Evaluation Kit
- **Hardware Setup:**
 - Connect a micro USB cable to the DEBUG port

6. Project sam_e70_xult_freertos.X.

- **Hardware Used:**
 - SAM E70 Xplained Ultra Evaluation Kit
- **Hardware Setup:**
 - Connect a micro USB cable to the DEBUG port

7. Project sam_a5d2_xult_freertos.IAR

- **Hardware Used**
 - SAM A5D2 Xplained Ultra board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Short jumper JP2(DEBUG_DIS)
 - Connect the Debug USB port on the board to the computer using a micro USB cable

8. Project sam_9x60_ek_freertos.IAR

- **Hardware Used**
 - SAM 9X60 Evaluation Kit board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Note: Reset push button on SAM9X60 EK is labeled as SW3

Running the Application

This section provides information on how to run the application.

Description**MPLAB X IDE**

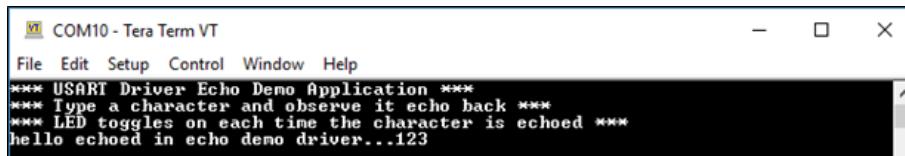
1. Open the Terminal application (Ex.:Tera Term) on the computer.
2. Configure the serial port settings as follows:
 - Baud : 115200

- Data : 8 Bits
- Parity : None
- Stop : 1 Bit
- Flow Control : None

3. Build and program the application using the MPLAB X IDE.

4. Type a character and observe the output on the console as shown below:

- If success the character typed echoes back and an LED toggles on each time the character is echoed



The following table provides the LED name:

Kit Name	LED Name
PIC32MX Curiosity Development Board	LED 1
PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit (Crypto)	LED 1
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 1
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench

2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)

3. Open the Terminal application (Ex.:Tera term) on the computer.

4. Connect to the USB to UART COM port and configure the serial settings as follows:

- Baud : 115200
- Data : 8 Bits
- Parity : None
- Stop : 1 Bit
- Flow Control : None

5. Reset the board to run the application

6. Type a character and observe the output on the console:

- If success the character typed echoes back and an LED toggles on each time the character is echoed.

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)
SAM9X60 evaluation kit	RGB_LED (Green)

uart_multi_instance

This example echoes the received characters over the two consoles using the USART driver in synchronous mode with DMA enabled.

Description

This example uses the USART driver in synchronous mode in an RTOS environment with DMA enabled to communicate over two consoles. It receives and echoes back the characters entered by the user on the respective console.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core\apps\driver\USART\sync\USART_multi_instance\firmware
------------------	---

The following tables provide the project name to be used with the different development kits. Open the required project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
sam_c21n_xpro_freertos.X	SAM C21N Xplained Pro Evaluation Kit + FreeRTOS
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_v71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek_freertos.IAR	SAM9X60 evaluation kit + FreeRTOS

MPLAB Harmony Configurations

This section provides information on the MHC configurations.

Description

Components Used:

- USART Driver (Synchronous mode)
- FreeRTOS

The following components used may vary based on the project configuration selected:

- Two USART or SERCOM peripherals library. Or UART/DBGU and FLEXCOM peripherals library.
- Board Support Package (BSP)

Other MHC Settings:

- Configure the Pins for the USART or SERCOM or UART or DBGU or FLEXCOM peripherals in the Pin Settings
- Configure the DMA transmit or receive channels for USART or SERCOM or UART or DBGU or FLEXCOM peripherals

Note: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project `sam_c21n_xpro_freertos.X`.

- **Hardware Used:**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Connect the [mikroBUS Xplained Pro](#) board to the EXT1 header of the [SAM C21N Xplained Pro Evaluation Kit](#)
 - Install an [USB UART click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect a micro USB cable to the DEBUG port. This will enumerate a first port.
 - Connect mini USB cable to the [USB UART click](#) board. This will enumerate the second port.

2. Project `sam_e54_xpro_freertos.X`.

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Connect the [mikroBUS Xplained Pro](#) board to the EXT1 header of the [SAM E54 Xplained Pro Evaluation Kit](#)
 - Install an [USB UART click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect a micro USB cable to the DEBUG port. This will enumerate a first port.
 - Connect mini USB cable to the [USB UART click](#) board. This will enumerate the second port.

3. Project `sam_e70_xult_freertos.X`.

- **Hardware Used:**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup:**
 - Connect a [USB UART click](#) board to the mikroBus header of the [SAM E70 Xplained Ultra Evaluation Kit](#)
 - Connect a micro USB cable to the DEBUG port. This will enumerate a first port.
 - Connect mini USB cable to the [USB UART click](#) board. This will enumerate the second port.

4. Project `sam_v71_xult_freertos.X`.

- **Hardware Used:**
 - [SAM V71 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup:**
 - Connect the [mikroBUS Xplained Pro](#) board to the EXT1 header of the [SAM V71 Xplained Ultra board](#)
 - Install an [USB UART click](#) board on to the [mikroBUS Xplained Pro](#) board
 - Connect a micro USB cable to the DEBUG port. This will enumerate a first port.
 - Connect mini USB cable to the [USB UART click](#) board. This will enumerate the second port.

5. Project `sam_a5d2_xult_freertos.IAR`

- **Hardware Used**
 - [SAM A5D2 Xplained Ultra board](#)
 - [USB UART Click board](#)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card

- Insert the SD card into the SDMMC1 slot on the board
- Short jumper JP2(DEBUG_DIS)
- Connect [USB UART Click board](#) to [SAM A5D2 Xplained Ultra board](#) as per below **Pin Connections**
- Connect the Debug USB port on the board to the computer using a micro USB cable
- Connect the Mini USB connector on the [USB UART Click board](#) to the computer using a Mini USB cable
- **Pin Connections**

SAM A5D2 Xplained Ultra board Pins	USB UART Click board Pins
F0_TXD, J22 connector	RX
F0_RXD, J22 connector	TX
PIN 20, XPRO EXT2 connector	3.3V
PIN 19, XPRO EXT2 connector	GND

6. Project sam_9x60_ek_freertos.IAR

- **Hardware Used**
 - SAM 9X60 Evaluation Kit board
 - [USB UART Click board](#)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
 - Insert [USB UART Click board](#) into MIKROBUS Connector J15
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Connect the Mini USB connector on the [USB UART Click board](#) to the computer using a Mini USB cable
 - Note: Reset push button on SAM9X60 EK is labeled as SW3

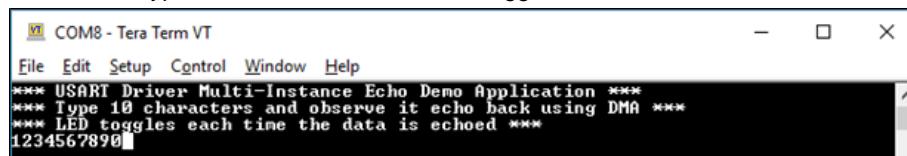
Running the Application

This section provides information on how to run the application.

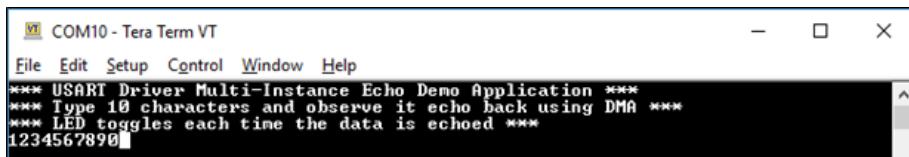
Description

MPLAB X IDE

1. Open the Terminal application (Ex.:Tera Term) on the computer for two COM ports.
2. Configure the serial port settings as follows:
 - Baud : 115200
 - Data : 8 Bits
 - Parity : None
 - Stop : 1 Bit
 - Flow Control : None
3. Build and program the application using the MPLAB X IDE.
4. Type ten characters and observe it echo back using DMA in two consoles as shown below:
 - If success the ten characters typed echoes back and an LED toggles on each time the ten characters are echoed.



Output of Console 1



Output of Console 2

The following table provides the LED name:

Kit Name	LED Name
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1
SAM V71 Xplained Ultra Evaluation Kit	LED 1

IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Open the Terminal application (Ex.:Tera term) on the computer for both COM Ports.
4. Connect to the USB to UART COM port and configure the serial settings for both COM Ports as follows :
 - Baud : 115200
 - Data : 8 Bits
 - Parity : None
 - Stop : 1 Bit
 - Flow Control : None
5. Reset the board to run the application
6. Type 10 characters and observe the output on the console:
 - If success typed 10 characters echoes back and an LED toggles on each time the 10 characters are echoed.

The following table provides the LED name.

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Green)
SAM9X60 evaluation kit	RGB_LED (Green)

File System Applications

This section provides help for the File System applications.

nvm_fat

This application shows an example of implementing a FAT disk in the device internal Flash memory.

Description

File System Operations on NVM:

- The application contains a FAT disk image consisting of a Master Boot Record (MBR) sector, Logical Boot Sector, File Allocation Table, and Root Directory Area, placed in the internal Flash memory (NVM)
- The application opens an existing file named **FILE.TXT** and performs following file system related operations:
 - [SYS_FS_FileStat](#)
 - [SYS_FS_FileSize](#)
 - [SYS_FS_FileSeek](#)
 - [SYS_FS_FileEOF](#)

- Performs read on the file and checks if string "**Data**" is present. If present it continues to next step or it fails the application
- Finally, the string "**Hello World**" is written to this file. The string is then read and compared with the string that was written to the file. If the string compare is successful, An LED indication is provided.

File system layer uses:

- Memory driver to communicate with underlying NVM media.

Building The Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/fs/nvm_fat/firmware
------------------	-------------------------------

To build the application, refer to the following table and open the appropriate project file in the MPLAB X IDE:

Project Name	Description
pic32mk_gp_db.X	PIC32MK GP Development Kit
pic32mx470_curiosity.X	PIC32MX Curiosity Development Board
pic32mz_das_sk.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit
pic32mz_ef_sk.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
pic32mz_ef_sk_freertos.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit + FreeRTOS
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit
sam_d20_xpro.X	SAM D20 Xplained Pro Evaluation Kit
sam_d21_xpro.X	SAM D21 Xplained Pro Evaluation Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_l21_xpro.X	SAM L21 Xplained Pro Evaluation Kit
sam_l22_xpro.X	SAM L22 Xplained Pro Evaluation Kit
sam_V71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

MPLAB Harmony Configuration

This section provides information on the MHC configurations.

Description

Components used:

- File System configured to use FAT Format
- Memory Driver connected to EFC or NVMCTRL or NVM peripheral library
 - For Bare-Metal it is configured to asynchronous mode
 - For RTOS it is configured to synchronous mode

The following components used may vary based on the project configuration selected:

- EFC or NVMCTRL or NVM peripheral library
- Timer System Service only when Memory driver is configured in synchronous mode

- TC peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Configurations:

- If Cache is enabled, create a non-cacheable memory region for NVM using MPU

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mk_gp_db.X.

- **Hardware Used**
 - [PIC32MK GP Development Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

2. Project pic32mx470_curiosity.X

- **Hardware Used**
 - [PIC32MX Curiosity Development Board](#)
- **Hardware Setup**
 - No Special hardware Setup Required
 - **Note:** Ensure that the series resistors on the mikroBUS headers are of value **0 Ohms**.

3. Project pic32mz_das_sk.X.

- **Hardware Used**
 - [PIC32MZ Embedded Graphics with Stacked DRAM \(DA\) Starter Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

4. Project pic32mz_ef_sk.X.

5. Project pic32mz_ef_sk_freertos.X.

- **Hardware Used**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

6. Project sam_c21n_xpro.X.

- **Hardware Used**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

7. Project sam_d20_xpro.X.

- **Hardware Used**
 - [SAM D20 Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

8. Project sam_d21_xpro.X.

- **Hardware Used**
 - [SAM D21 Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

9. Project sam_e54_xpro.X.

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

10. Project sam_e70_xult.X.**11. Project sam_e70_xult_freertos.X.**

- **Hardware Used**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

12. Project sam_l21_xpro.X

- **Hardware Used**
 - [SAM L21 Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

13. Project sam_l22_xpro.X

- **Hardware Used**
 - [SAM L22 Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

14. Project sam_v71_xult_freertos.X.

- **Hardware Used**
 - [SAM V71 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

Running The Application

This section provides information on how to run the application using the MPLAB X IDE.

Description

1. Connect a micro/mini USB cable to the DEBUG port.
2. Build and Program the application using the MPLAB X IDE.
3. Press Switch to start the file operations
4. The LED is turned ON when the File "FILE.TXT" has the app data "Hello World" written in it

The following table provides the LED name:

Kit Name	LED Name	Switch Name
PIC32MK GP Development Kit	LED 3	SW1

PIC32MX Curiosity Development Board	LED 1	SW1
PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit	LED 3	SW1
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 3	SW1
SAM C21N Xplained Pro Evaluation Kit	LED 0	SW0
SAM D20 Xplained Pro Evaluation Kit	LED 0	SW0
SAM D21 Xplained Pro Evaluation Kit	LED 0	SW0
SAM E54 Xplained Pro Evaluation Kit	LED 0	SW0
SAM E70 Xplained Ultra Evaluation Kit	LED 1	SW0
SAM L21 Xplained Pro Evaluation Kit	LED 0	SW0
SAM L22 Xplained Pro Evaluation Kit	LED 0	SW0
SAM V71 Xplained Ultra Evaluation Kit	LED 0	SW0

nvm_mpfs

This application shows an example of implementing a MPFS disk in device Internal Flash memory.

Description

File System Operations on NVM:

- The application contains a MPFS disk image in the internal Flash memory. The disk image contains two files named:
 - FILE.txt**, Size = **11 Bytes**. The content of the file is: "**Hello World**"
 - TEST.txt**, Size = **10 Bytes**. The content of the file is: "**1234567890**"
- The application performs following file system related operations:
 - SYS_FS_FileRead**
 - SYS_FS_FileStat**
 - SYS_FS_FileSize**
 - SYS_FS_FileSeek**
 - SYS_FS_FileEOF**
- The contents of both the files are read and compared with the expected strings as mentioned above. If the string compare is successful, An LED indication is provided.

File system layer uses:

- Memory driver to communicate with underlying NVM media

Building The Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/fs/nvm_mpfs/firmware
------------------	---------------------------------------

To build the application, refer to the following table and open the appropriate project file in the MPLAB X IDE:

Project Name	Description
pic32mz_das_sk.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit
pic32mz_ef_sk.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit

sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_V71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

MPLAB Harmony Configuration

This section provides information on the MHC configurations.

Description

Components used:

- File System configured to use MPFS Format
- Memory Driver connected to EFC or NVMCTRL or NVM peripheral library
 - For Bare-Metal it is configured to asynchronous mode
 - For RTOS it is configured to synchronous mode

The following components used may vary based on the project configuration selected:

- EFC or NVMCTRL or NVM peripheral library
- Timer System Service only when Memory driver is configured in synchronous mode
- TC peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Configurations:

- If Cache is enabled, create a non-cacheable memory region for NVM using MPU

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project `pic32mz_das_sk.X`.

- Hardware Used**
 - [PIC32MZ Embedded Graphics with Stacked DRAM \(DA\) Starter Kit](#)
- Hardware Setup**
 - No Special hardware Setup Required

2. Project `pic32mz_ef_sk.X`.

- Hardware Used**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
- Hardware Setup**
 - No Special hardware Setup Required

3. Project `sam_c21n_xpro.X`.

- Hardware Used**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
- Hardware Setup**
 - No Special hardware Setup Required

4. Project sam_e54_xpro.X.

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

5. Project sam_e70_xult.X.**6. Project sam_e70_xult_freertos.X.**

- **Hardware Used**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

7. Project sam_v71_xult_freertos.X.

- **Hardware Used**
 - [SAM V71 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

Running The Application

This section provides information on how to run the application using the MPLAB X IDE.

Description

1. Connect a micro/mini USB cable to the DEBUG port.
2. Build and Program the application using the MPLAB X IDE.
3. The LED is turned ON when the following criteria is satisfied.
 - File "FILE.txt" has the string "**Hello World**" in it
 - File "TEST.txt" has the string "**1234567890**" in it

The following table provides the LED name:

Kit Name	LED Name
PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit	LED 3
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 3
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1
SAM V71 Xplained Ultra Evaluation Kit	LED 0

nvm_sdmmc_fat_multi_disk

This application shows an example of using the MPLAB Harmony File System to access files across multiple media (NVM, SDMMC).

Description**File System Operations on NVM and SD Card:**

- The application contains a FAT disk image consisting of a Master Boot Record (MBR) sector, Logical Boot Sector, File Allocation Table, and Root Directory Area, placed in the internal Flash memory (NVM)
- A SD card is used as another disk, which might have FAT16 or FAT32 implemented on it (dependent on the formatting of SD

card)

- The application searches the NVM media for a file named **FILE.TXT**, opens and reads the contents of the file in NVM and copies the contents to the file, **FILE.TXT**, in the SD card
- Once the copy is successful, an addition string "**Test is successful**" is added to the file. If the write operation is successful, LED indication is provided

File system layer uses:

- Memory driver to communicate with underlying NVM media.
- SDMMC Driver to communicate to SD Card

Building The Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/fs/nvm_sdmmc_fat_multi_disk/firmware
------------------	--

To build the application, refer to the following table and open the appropriate project file in the MPLAB X IDE:

Project Name	Description
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_V71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

MPLAB Harmony Configuration

This section provides information on the MHC configurations.

Description

Components used:

- File System:
 - FAT Format for SD Card
 - FAT Format for NVM
- Memory Driver connected to NVM Media
 - For Bare-Metal it is configured to asynchronous Mode
 - For RTOS it is configured to synchronous Mode
- SDMMC Driver
- Timer System Service
- TC peripheral library

The following components used may vary based on the project configuration selected:

- EFC or NVMCTRL peripheral library
- HSMCI or SDHC peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Configurations:

- If Cache is enabled, create a non-cacheable memory region for NVM using MPU
- Enable XDMAC channels for SDMMC Transmit/Receive

Hardware Setup

This section describes how to configure the supported hardware.

Description

Common Hardware Setup:

- Create a file named **FILE.txt** in a SD Card containing some random data

1. Project **sam_e54_xpro.X**.

2. Project **sam_e54_xpro_freertos.X**.

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

3. Project **sam_e70_xult.X**.

4. Project **sam_e70_xult_freertos.X**.

- **Hardware Used**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

5. Project **sam_V71_xult_freertos.X**.

- **Hardware Used**
 - [SAM V71 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

Running The Application

This section provides information on how to run the application using the MPLAB X IDE.

Description

1. Connect a micro USB cable to the DEBUG port.
2. Build and Program the application using the MPLAB X IDE.
3. Insert the SD Card in the SD Card slot of the Device.
4. The LED is turned ON when the content from the NVM media is copied to SD Card successfully.

The following table provides the LED name:

Kit Name	LED Name
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1
SAM V71 Xplained Ultra Evaluation Kit	LED 0

4. If Success, Insert the SD Card on to your host PC

5. **FILE.txt** should have the content "**This data from NVM Disk Test is successful**".

nvm_sdspi_fat_multi_disk

This application shows an example of using the MPLAB Harmony File System to access files across multiple media (NVM, SDSPI).

Description

File System Operations on NVM and SD Card:

- The application contains a FAT disk image consisting of a Master Boot Record (MBR) sector, Logical Boot Sector, File Allocation Table, and Root Directory Area, placed in the internal Flash memory (NVM)
- A SD card is used as another disk, which might have FAT16 or FAT32 implemented on it (dependent on the formatting of SD card)
- The application searches the NVM media for a named **FILE.TXT**, opens and reads the contents of the file in NVM and copies the contents to the file, **FILE.TXT**, in the SD card
- Once the copy is successful, an addition string "**Test is successful**" is added to the file. If the write operation is successful, LED indication is provided.

File system layer uses:

- Memory driver to communicate with underlying NVM media.
- SDSPI Driver to communicate to SD Card over SPI.

Building the Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/fs/nvm_sdspi_fat_multi_disk/firmware
------------------	--

To build the application, refer to the following table and open the appropriate project file in the MPLAB X IDE:

Project Name	Description
pic32mz_ef_sk_freertos.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit + FreeRTOS
sam_c21n_xpro_freertos.X	SAM C21N Xplained Pro Evaluation Kit + FreeRTOS
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS

MPLAB Harmony Configuration

This section provides information on the MHC configurations.

Description

Components used:

The components used may vary based on the project configuration selected:

- File System
 - FAT Format for SDCARD
 - FAT Format for NVM

- SDSPI driver configured to synchronous mode
- Memory driver connected to NVM Media and configured to synchronous mode
- Timer System Service
- TC peripheral library

The following components used may vary based on the project configuration selected:

- EFC or NVMCTRL or NVM peripheral library
- SPI or SERCOM peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Configurations:

- If Cache is enabled, create a non-cacheable memory region for NVM using MPU
- Configure the SD Card chip select pin in Pin Settings

Hardware Setup

This section describes how to configure the supported hardware.

Description

Common Hardware Setup:

- Create a file named **FILE.txt** in a micro-SD Card containing some random data
1. **Project pic32mz_ef_sk_freertos.X.**
 - **Hardware Used**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
 - [Multimedia Expansion Board II](#)
 - **Hardware Setup**
 - Mount the [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#) on to the [Multimedia Expansion Board II](#)
 - Insert the micro-SD Card in the micro-SD Card slot of the [Multimedia Expansion Board II](#)
 2. **Project sam_c21n_xpro_freertos.X.**
 - **Hardware Used**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
 - [IO1 Xplained Pro Extension Kit](#)
 - **Hardware Setup**
 - Connect [IO1 Xplained Pro Extension Kit](#) to the EXT1 header of [SAM C21N Xplained Pro Evaluation Kit](#)
 - Insert the micro-SD Card in the micro-SD Card slot of the [IO1 Xplained Pro Extension Kit](#)
 3. **Project sam_e54_xpro_freertos.X.**
 - **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
 - [IO1 Xplained Pro Extension Kit](#)
 - **Hardware Setup**
 - Connect [IO1 Xplained Pro Extension Kit](#) to the EXT1 header of [SAM E54 Xplained Pro Evaluation Kit](#)
 - Insert the micro-SD Card in the micro-SD Card slot of the [IO1 Xplained Pro Extension Kit](#)
 4. **Project sam_e70_xult_freertos.X.**
 - **Hardware Used**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
 - [IO1 Xplained Pro Extension Kit](#)

- **Hardware Setup**

- Connect [IO1 Xplained Pro Extension Kit](#) to the EXT1 connector of [SAM E70 Xplained Ultra Evaluation Kit](#)
- Insert the micro-SD Card in the micro-SD Card slot of the [IO1 Xplained Pro Extension Kit](#)

Running the Application

This section provides information on how to run the application using the MPLAB X IDE.

Description

1. Connect a micro/mini USB cable to the DEBUG port.
2. Build and Program the application using the MPLAB X IDE.
3. The LED is turned ON when the content from the NVM media is copied to SD-Card successfully.

The following table provides the LED name:

Kit Name	LED Name
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 1
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1

4. If Success, Insert the SD Card on to your host PC
5. **FILE.txt** should have the content "**This data from NVM Disk Test is successful**".

nvm_sqi_fat

This application shows an example of using the MPLAB Harmony File System to access multiple files across multiple media (NVM, SQI FLASH).

Description

File System Operations on NVM:

- The application contains a FAT disk image consisting of a Master Boot Record (MBR) sector, Logical Boot Sector, File Allocation Table, and Root Directory Area, placed in the internal Flash memory (NVM)
- The application opens an existing file named **FILE.TXT** and performs following file system related operations:
 - [SYS_FS_FileStat](#)
 - [SYS_FS_FileSize](#)
 - [SYS_FS_FileSeek](#)
 - [SYS_FS_FileEOF](#)
- Finally, the string "**Hello World**" is written to this file. The string is then read and compared with the string that was written to the file.

File System Operations on the On-Board SST26 Flash Memory:

- Performs a [SYS-FS_FormatDisk](#).
- Opens a **newfile.txt** on the sst26 flash
- Write and reads back 4KB of data on **newfile.txt**
- Verifies the Data Read back

File system layer uses:

- One instance of the Memory driver is used to communicate with underlying NVM media
- One instance of the Memory driver is used to communicate with the On-Board QSPI or SQI Flash memory

The Application Consists of three tasks which are called in RTOS Thread Context:

1. APP_SST26_Tasks() : Performs File Operations on QSPI or SQI Flash memory
2. APP_NVM_Tasks() : Performs File Operations on NVM.
3. APP_MONITOR_Tasks(): Monitors the state of above two Tasks

Building The Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/fs/nvm_sqi_fat/firmware
-------------------------	--

To build the application, refer to the following table and open the appropriate project file in the MPLAB X IDE:

Project Name	Description
pic32mz_das_sk_freertos.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit + FreeRTOS
pic32mz_ef_sk_freertos.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit + FreeRTOS
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS

MPLAB Harmony Configuration

This section provides information on the MHC configurations.

Description

Components used:

The components used may vary based on the project configuration selected:

- File System:
 - FAT Format for SST26 Flash
 - FAT Format for NVM
- Memory Driver 2 Instances in synchronous Mode
 - Instance 0 connected to SST26 Driver
 - Instance 1 connected to EFC or NVM PLIB
- SST26 Driver

The following components used may vary based on the project configuration selected:

- QSPI or SQI peripheral library
- EFC or NVMCTRL or NVM peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Configurations:

- If Cache is enabled, create a non-cacheable memory region for NVM using MPU
- Enable MPU for QSPI Flash region for SST26 media operations

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project **pic32mz_das_sk_freertos.X**.
 - **Hardware Used**
 - [PIC32MZ Embedded Graphics with Stacked DRAM \(DA\) Starter Kit](#)
 - **Hardware Setup**
 - No Special hardware Setup Required
2. Project **pic32mz_ef_sk_freertos.X**.
 - **Hardware Used**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
 - **Hardware Setup**
 - No Special hardware Setup Required
3. Project **sam_e70_xult_freertos.X**.
 - **Hardware Used**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
 - **Hardware Setup**
 - No Special hardware Setup Required

Running The Application

This section provides information on how to run the application using the MPLAB X IDE.

Description

1. Connect a micro/mini USB cable to the DEBUG port.
2. Build and Program the application using the MPLAB X IDE.
3. The LED toggles when the following criteria is satisfied.
 - For NVM media: File "**FILE.TXT**" has the app data "**Hello World**" written in it
 - For SST26 media: 4KB of data has successfully been written and read back from file "**newfile.txt**"

The following table provides the LED name:

Kit Name	LED Name
PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit	LED 3
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 3
SAM E70 Xplained Ultra Evaluation Kit	LED 1

sdmmc_fat

This application shows an example of using the MPLAB Harmony File System to access and modify the contents of a SD card using the SDMMC driver.

Description

File System Operations on the SD Card:

- The application opens a file named **FILE_TOO_LONG_NAME_EXAMPLE_123.JPG** on the SD card
- Reads the content of the file and creates a directory named **Dir1**
- Inside the directory, writes the copied content into another file **Dir1/FILE_TOO_LONG_NAME_EXAMPLE_123.JPG**

The image file could be any arbitrary JPEG (image) file chosen by the user and then renamed to **FILE_TOO_LONG_NAME_EXAMPLE_123.JPG**.

The reason for choosing a JPEG file for test purposes is that the duplicate file, **Dir1/FILE_TOO_LONG_NAME_EXAMPLE_123.JPG** created by the demonstration could be easily verified for correctness.

If the new file inside **Dir1** opens for viewing on the computer and matches to original image, the test is deemed to have passed. Otherwise, if the file does not open (i.e., is corrupted), the test will be considered to have failed.

File system layer uses:

- SDMMC Driver to communicate to SD Card

Building The Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/fs/sdmmc_fat/firmware
------------------	---------------------------------

Below table shows the list of project names to be used with different development boards. Open the project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mz_das_sk.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_V71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS
sam_9x60_ek.IAR	SAM9X60 Evaluation Kit
sam_9x60_ek_freertos.IAR	SAM9X60 Evaluation Kit + FreeRTOS

MPLAB Harmony Configuration

This section provides information on the MHC configurations.

Description

Components used:

- File System:
 - FAT Format for SDCARD
 - SDMMC Driver

- Timer System Service
- TC peripheral library

The following components used may vary based on the project configuration selected:

- HSMCI or SDHC peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Configurations:

- Enable XDMAC channels for SDMMC Transmit/Receive

Hardware Setup

This section describes how to configure the supported hardware.

Description

Common Hardware Setup:

- Create a new JPEG file in the SD Card with name **FILE_TOO_LONG_NAME_EXAMPLE_123.JPG**
1. **Project pic32mz_das_sk.X**
 - **Hardware Used**
 - [PIC32MZ DA Family Starter Kit](#)
 - **Hardware Setup**
 - No Special hardware Setup Required
 2. **Project sam_e54_xpro.X.**
 3. **Project sam_e54_xpro_freertos.X.**
 - **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
 - **Hardware Setup**
 - No Special hardware Setup Required
 4. **Project sam_e70_xult.X.**
 5. **Project sam_e70_xult_freertos.X.**
 - **Hardware Used**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
 - **Hardware Setup**
 - No Special hardware Setup Required
 6. **Project sam_V71_xult_freertos.X.**
 - **Hardware Used**
 - [SAM V71 Xplained Ultra Evaluation Kit](#)
 - **Hardware Setup**
 - No Special hardware Setup Required
 7. **Project sam_a5d2_xult_freertos.IAR**
 8. **Project sam_a5d2_xult.IAR**
 - **Hardware Used**
 - [SAM A5D2 Xplained Ultra board](#)
 - SD Card with FAT32 file system
 - **Hardware Setup**
 - Setup the SD card

- Download harmony MPU bootstrap loader from this [location](#)
- Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
- Insert the SD card into the SDMMC1 slot on the board
- Connect the Debug USB port on the board to the computer using a micro USB cable

9. Project sam_9x60_ek.IAR

10. Project sam_9x60_ek_freertos.IAR

• Hardware Used

- SAM9X60 Evaluation Kit
- SD Card with FAT32 file system

• Hardware Setup

- Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC J5 connector on the board
- Connect the Debug USB port on the board to the computer using a micro USB cable
- Note: Reset push button on SAM9X60-EK board label as SW3

Running The Application

This section provides information on how to run the application using the MPLAB X IDE.

Description

Running project with MPLAB X IDE

1. Connect a micro USB cable to the DEBUG port.
2. Build and Program the application using MPLAB X IDE.
3. Insert the SD Card in the SD Card slot of the Device.
4. The LED is turned ON if there was no error during creating the directory and copying the file into it.

The following table provides the LED name:

Kit Name	LED Name
PIC32MZ Embedded Graphics with Stacked DRAM (DA)Starter Kit	LED 1
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1
SAM V71 Xplained Ultra Evaluation Kit	LED 0

4. If LED is ON, Insert the SD Card on to your host PC.
5. SD-Card should have the file **Dir1/FILE_TOO_LONG_NAME_EXAMPLE_123.JPG** and should match the original image.

Running project with IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED is turned ON if there was no error during creating the directory and copying the file into it.

The following table provides the LED name:

Kit Name	LED Name
SAMA5D2 Xplained Ultra Evaluation kit	RGB_LED(Green)
SAM9X60 Evaluation Kit	RGB_LED(Green)

5. If LED is ON, Insert the SD Card on to your host PC.

6. SD-Card should have the file **Dir1/FILE_TOO_LONG_NAME_EXAMPLE_123.JPG** and should match the original image.

sdspi_fat

This application shows an example of using the MPLAB Harmony File System to access and modify the contents of a SD card using the SDSPI driver.

Description

File System Operations on the SD Card:

- The application opens a file named **FILE_TOO_LONG_NAME_EXAMPLE_123.JPG** on the SD card
- Reads the content of the file and creates a directory named **Dir1**
- Inside the directory, writes the copied content into another file **Dir1/FILE_TOO_LONG_NAME_EXAMPLE_123.JPG**

The image file could be any arbitrary JPEG (image) file chosen by the user and then renamed to **FILE_TOO_LONG_NAME_EXAMPLE_123.JPG**.

The reason for choosing a JPEG file for test purposes is that the duplicate file, **Dir1/FILE_TOO_LONG_NAME_EXAMPLE_123.JPG** created by the demonstration could be easily verified for correctness.

If the new file inside **Dir1** opens for viewing on the computer and matches to original image, the test is deemed to have passed. Otherwise, if the file does not open (i.e., is corrupted), the test will be considered to have failed.

Note:

Since the application creates a directory named **Dir1**, it is important that the a folder with the same name does not exist on the SD card. If a directory named **Dir1** is already present on the SD card, the application will **fail**.

File system layer uses:

- SDSPI Driver to communicate to SD Card over SPI interface.

Building the Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/fs/sdspi_fat/firmware
------------------	---------------------------------

To build the application, refer to the following table and open the appropriate project file in the MPLAB X IDE:

Project Name	Description
pic32mx470_curiosity.X	PIC32MX Curiosity Development Board
pic32mx470_curiosity_freertos.X	PIC32MX Curiosity Development Board + FreeRTOS
pic32mz_ef_sk.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
pic32mz_ef_sk_freertos.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit + FreeRTOS
sam_c21n_xpro_freertos.X	SAM C21N Xplained Pro Evaluation Kit + FreeRTOS
sam_d21_xpro.X	SAM D21 Xplained Pro Evaluation Kit
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit

sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_l21_xpro_freertos.X	SAM L21 Xplained Pro Evaluation Kit + FreeRTOS
sam_l22_xpro_freertos.X	SAM L22 Xplained Pro Evaluation Kit +FreeRTOS

MPLAB Harmony Configuration

This section provides information on MHC configuration.

Description

Components used:

The components used may vary based on the project configuration selected:

- File System
 - FAT Format for SDCARD
- SDSPI driver in Asynchronous or Synchronous mode
- Time System Service
- TC peripheral library

The following components used may vary based on the project configuration selected:

- SPI or SERCOM peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Configurations:

- Configure the SD Card chip select pin in Pin Settings

Hardware Setup

This section describes how to configure the supported hardware.

Description

Common Hardware Setup:

- Create a new JPEG file in the SD Card with name **FILE_TOO_LONG_NAME_EXAMPLE_123.JPG**
1. **Project pic32mx470_curiosity.X**
 2. **Project pic32mx_470_curiosity_freertos.X**
 - **Hardware Used**
 - [PIC32MX Curiosity Development Board](#)
 - [SD-Card Click Board](#)
 - **Hardware Setup**
 - Connect mini USB cable to the 'Debug USB' connector(J3) on the board to the computer.
 - Install [SD-Card Click Board](#) on to the mikroBUS socket J5 of [PIC32MX Curiosity Development Board](#).
 - Insert the micro-SD Card in the micro-SD Card slot of the [SD-Card Click Board](#)
 - **Note:** Ensure that the series resistors on the mikroBUS headers are of value **0 Ohms**.
 3. **Project pic32mz_ef_sk.X.**
 4. **Project pic32mz_ef_sk_freertos.X.**
 - **Hardware Used**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
 - [Multimedia Expansion Board II](#)

- **Hardware Setup**
 - Mount the [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#) on to the [Multimedia Expansion Board II](#)
 - Insert the micro-SD Card in the micro-SD Card slot of the [Multimedia Expansion Board II](#)

5. Project [sam_c21n_xpro_freertos.X](#).

- **Hardware Used**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
 - [IO1 Xplained Pro Extension Kit](#)
- **Hardware Setup**
 - Connect [IO1 Xplained Pro Extension Kit](#) to the EXT1 header of [SAM C21N Xplained Pro Evaluation Kit](#)
 - Insert the micro-SD Card in the micro-SD Card slot of the [IO1 Xplained Pro Extension Kit](#)

6. Project [sam_d21_xpro.X](#).

- **Hardware Used**
 - [SAM D21 Xplained Pro Evaluation Kit](#)
 - [IO1 Xplained Pro Extension Kit](#)
- **Hardware Setup**
 - Connect [IO1 Xplained Pro Extension Kit](#) to the EXT1 header of [SAM D21 Xplained Pro Evaluation Kit](#)
 - Insert the micro-SD Card in the micro-SD Card slot of the [IO1 Xplained Pro Extension Kit](#)

7. Project [sam_e54_xpro_freertos.X](#).

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
 - [IO1 Xplained Pro Extension Kit](#)
- **Hardware Setup**
 - Connect [IO1 Xplained Pro Extension Kit](#) to the EXT1 header of [SAM E54 Xplained Pro Evaluation Kit](#)
 - Insert the micro-SD Card in the micro-SD Card slot of the [IO1 Xplained Pro Extension Kit](#)

8. Project [sam_e70_xult.X](#).

9. Project [sam_e70_xult_freertos.X](#).

- **Hardware Used**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
 - [IO1 Xplained Pro Extension Kit](#)
- **Hardware Setup**
 - Connect [IO1 Xplained Pro Extension Kit](#) to the EXT1 connector of [SAM E70 Xplained Ultra Evaluation Kit](#)
 - Insert the micro-SD Card in the micro-SD Card slot of the [IO1 Xplained Pro Extension Kit](#)

10. Project [sam_l21_xpro.X](#)

- **Hardware Used**
 - [SAM L21 Xplained Pro Evaluation Kit](#)
 - [IO1 Xplained Pro Extension Kit](#)
- **Hardware Setup**
 - Connect [IO1 Xplained Pro Extension Kit](#) to the EXT2 connector of [SAM L21 Xplained Pro Evaluation Kit](#)
 - Insert the micro-SD Card in the micro-SD Card slot of the [IO1 Xplained Pro Extension Kit](#)
 -

11. Project [sam_l22_xpro.X](#)

- **Hardware Used**
 - [SAM L22 Xplained Pro Evaluation Kit](#)
 - [IO1 Xplained Pro Extension Kit](#)
- **Hardware Setup**
 - Connect [IO1 Xplained Pro Extension Kit](#) to the EXT1 connector of [SAM L22 Xplained Pro Evaluation Kit](#)
 - Insert the micro-SD Card in the micro-SD Card slot of the [IO1 Xplained Pro Extension Kit](#)

Running the Application

This section provides information on how to run the application using the MPLAB X IDE.

Description

1. Connect a micro/mini USB cable to the DEBUG port.
2. Build and Program the application using MPLAB X IDE.
3. Press the switch to start the application.
4. The LED is turned ON if there was no error during creating the directory and copying the file into it.

The following table provides the LED name:

Kit Name	LED Name	Switch Name
PIC32MX Curiosity Development Board	LED 1	S1
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 1	SW1
SAM C21N Xplained Pro Evaluation Kit	LED 0	SW0
SAM D21 Xplained Pro Evaluation Kit	LED 0	SW0
SAM E54 Xplained Pro Evaluation Kit	LED 0	SW0
SAM E70 Xplained Ultra Evaluation Kit	LED 1	SW0
SAM L21 Xplained Pro Evaluation Kit	LED 0	SW0
SAM L22 Xplained Pro Evaluation Kit	LED 0	SW0

4. If LED is ON, Insert the SD Card on to your host PC.
5. SD Card should have the file **Dir1/FILE_TOO_LONG_NAME_EXAMPLE_123.JPG** and should match the original image.

spi_flash_fat

This application shows an example of using the MPLAB Harmony File System to access and modify the contents of a flash memory using SPI Flash driver.

Description

File System Operations on the On-Board SPI Flash Memory:

- Performs a SYS-FS_FormatDisk
- Opens a **newfile.txt** on the at25df flash
- Write and reads back 4KB of data on **newfile.txt**
- Verifies the Data Read back

File system layer uses:

- Memory driver to communicate with the On-Board SPI Flash Memory

Building The Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all projects for this application is given below:

Application Path	csp/apps/fs/spi_flash_fat/firmware
------------------	---

Below table shows the list of project names to be used with different development boards. Open the project in their respective IDEs.

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS

MPLAB Harmony Configurations

This section provides information on the MHC configurations.

Description

Components used:

The components used may vary based on the project configuration selected:

- FAT format for AT25DF flash
- AT25DF driver

The following components used may vary based on the project configuration selected:

- SPI peripheral library
- Timer System Service
- TC peripheral library
- Board Support Package (BSP)

NOTE: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project sam_a5d2_xult_freertos.IAR

2. Project sam_a5d2_xult.IAR

- **Hardware Used**
 - [SAM A5D2 Xplained Ultra board](#)
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Make sure that the jumper JP9 is removed (jumper pins are not shorted)

Running The Application

This section provides information on how to run the application using the MPLAB X IDE.

Description

Running project with IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED is turned ON if data has successfully been written and read back from file "newfile.txt"

The following table provides the LED name:

Kit Name	LED Name
SAMA5D2 Xplained Ultra Evaluation kit	RGB_LED(Green)

sqi_flash_fat

This application shows an example of using the MPLAB Harmony File System to access SQI based flash media.

Description

File System Operations on the On-Board SQI Flash Memory:

- Performs a SYS-FS_FormatDisk
- Opens a **newfile.txt** on the sst26 flash
- Write and reads back 4KB of data on **newfile.txt**
- Verifies the Data Read back

File system layer uses:

- Memory driver to communicate with the On-Board QSPI or SQI Flash Memory

Building The Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core/apps/fs/sqi_flash_fat/firmware

Below table shows the list of project names to be used with different development boards. Open the project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mz_das_sk.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit
pic32mz_ef_sk.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
pic32mz_ef_sk_freertos.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit + FreeRTOS
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit + FreeRTOS

MPLAB Harmony Configuration

This section provides information on the MHC configurations.

Description

Components used:

The components used may vary based on the project configuration selected:

- File System:
 - FAT Format for SST26/MX25L Flash
- Memory Driver connected to SST26/MX25L Driver
 - For Bare-Metal it is configured to asynchronous mode
 - For RTOS it is configured to synchronous mode
- SST26 / MX25L driver

The following components used may vary based on the project configuration selected:

- QSPI or SQI peripheral library
- System Timer Service for Polling the status of at regular intervals for RTOS configuration
- TC peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Configurations:

- Enable MPU for QSPI Flash region for SST26 Media operations

NOTE: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mz_das_sk.X.

- **Hardware Used**
 - [PIC32MZ Embedded Graphics with Stacked DRAM \(DA\) Starter Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

2. Project pic32mz_ef_sk.X.

3. Project pic32mz_ef_sk_freertos.X.

- **Hardware Used**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
- **Hardware Setup**
 - No Special hardware Setup Required

4. Project sam_e70_xult.X.

5. Project sam_e70_xult_freertos.X.

- **Hardware Used**
 - SAM E70 Xplained Ultra Evaluation Kit
- **Hardware Setup**
 - No Special hardware Setup Required

6. Project sam_a5d2_xult_freertos.IAR

7. Project sam_a5d2_xult.IAR

- **Hardware Used**
 - SAM A5D2 Xplained Ultra board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin) into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Make sure that the jumper JP9 is removed (jumper pins are not shorted)

Running The Application

This section provides information on how to run the application using the MPLAB X IDE.

Description

Running project with MPLAB X IDE

1. Connect a micro/mini USB cable to the DEBUG port.
2. Build and Program the application using MPLAB X IDE.
3. The LED is turned ON if data has successfully been written and read back from file "**newfile.txt**"

The following table provides the LED name:

Kit Name	LED Name
PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit	LED 3
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 3
SAM E70 Xplained Ultra Evaluation Kit	LED 1

Running project with IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED is turned ON if data has successfully been written and read back from file "**newfile.txt**"

The following table provides the LED name:

Kit Name	LED Name
SAMA5D2 Xplained Ultra Evaluation kit	RGB_LED(Green)

RTOS Applications

This section provides help for the RTOS applications.

FreeRTOS Applications

This section provides descriptions of the FreeRTOS RTOS demonstrations.

basic_freertos

This example application blinks an LED on a starter kit to show the FreeRTOS threads that are running and to indicate status.

Description

This demonstration creates three tasks and a queue. Task1 sends message to Task2 and Task3 to unblock and toggle an LED. Task1 priority is low compared to Task2 and Task3 which shares same priority.

- **Task1:** This task sends the data (i.e. delay, the amount of time for which the task need blocked) to Task2 and Task3 using a queue, then Task1 blocks itself for 200ms to allow other tasks to schedule and run.
- **Task2:** This task blocks until it receives the data from queue, if the Task2 receives the expected delay (i.e. 1000ms) from Task1 then toggles the LED and blocks itself for the amount of delay received.
- **Task3:** This task blocks until it receives the data from queue, if the Task3 receives the expected delay (i.e. 100ms) from Task1 then toggles the LED and blocks itself for the amount of delay received.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core\apps\rtos\freertos\basic_freertos\firmware
------------------	---

Below table shows the list of project names to be used with different development boards. Open the project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mk_gp_db.X	PIC32MK General Purpose (GP) Development Board
pic32mx470_curiosity.X	PIC32MX Curiosity Development Board
pic32mx_xlp_sk.X	PIC32MX XLP Starter Kit
pic32mz_das_sk.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit
pic32mz_ef_sk.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit
sam_d20_xpro.X	SAM D20 Xplained Pro Evaluation Kit
sam_d21_xpro.X	SAM D21 Xplained Pro Evaluation Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_l21_xpro.X	SAM L21 Xplained Pro Evaluation Kit
sam_l22_xpro.X	SAM L22 Xplained Pro Evaluation Kit
sam_v71_xult.X	SAM V71 Xplained Ultra Evaluation Kit

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_9x60_ek.IAR	SAM9X60 evaluation kit

MPLAB Harmony Configurations

This section provides information on the MHC configurations.

Description

Components Used:

- FreeRTOS

The following components used may vary based on the project configuration selected:

- Board Support Package (BSP)

NOTE: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mk_gp_db.X

- Hardware Used**
 - PIC32MK General Purpose (GP) Development Board
- Hardware Setup**
 - No Special hardware Setup Required

2. Project pic32mx470_curiosity.X

- Hardware Used**
 - PIC32MX Curiosity Development Board
- Hardware Setup**
 - Connect mini USB cable to the 'Debug USB' connector(J3) on the board to the computer.

3. Project pic32mx_xlp_sk.X

- Hardware Used:**
 - PIC32MX XLP Starter Kit
- Hardware Setup:**
 - Connect micro USB cable to the 'Debug USB' connector(J9) on the board to the computer.

4. Project pic32mz_das_sk.X.

- Hardware Used**
 - PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit
- Hardware Setup**
 - No Special hardware Setup Required

5. Project pic32mz_ef_sk.X.

- Hardware Used**
 - PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
- Hardware Setup**

- No Special hardware Setup Required

6. Project sam_c21n_xpro.X

- **Hardware Used:**
 - SAM C21N Xplained Pro Evaluation Kit
- **Hardware Setup:**
 - No special hardware setup is required

7. Project sam_d20_xpro.X.

- **Hardware Used:**
 - SAM D20 Xplained Pro Evaluation Kit
- **Hardware Setup:**
 - No special hardware setup is required

8. Project sam_d21_xpro.X.

- **Hardware Used:**
 - SAM D21 Xplained Pro Evaluation Kit
- **Hardware Setup:**
 - No special hardware setup is required

9. Project sam_e54_xpro.X.

- **Hardware Used:**
 - SAM E54 Xplained Pro Evaluation Kit
- **Hardware Setup:**
 - No special hardware setup is required

10. Project sam_e70_xult.X.

- **Hardware Used:**
 - SAM E70 Xplained Ultra Evaluation Kit
- **Hardware Setup**
 - No Special hardware Setup Required

11. Project sam_l21_xpro.X

- **Hardware Used**
 - SAM L21 Xplained Pro Evaluation Kit
- **Hardware Setup**
 - No Special hardware Setup Required

12. Project sam_l22_xpro.X

- **Hardware Used**
 - SAM L22 Xplained Pro Evaluation Kit
- **Hardware Setup**
 - No Special hardware Setup Required
 -

13. Project sam_v71_xult.X.

- **Hardware Used:**
 - SAM V71 Xplained Ultra Evaluation Kit
- **Hardware Setup:**
 - No special hardware setup is required

14. Project sam_a5d2_xult.IAR

- **Hardware Used**

- SAM A5D2 Xplained Ultra board
- SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable

15. Project sam_9x60_ek.IAR

- **Hardware Used**
 - SAM 9X60 Evaluation Kit board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Note: Reset push button on SAM9X60 EK is labeled as SW3

Running the Application

This section provides information on how to run an application.

Description

Running project with MPLAB X IDE

1. Connect a micro/mini USB to the DEBUG port.
2. Build and program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED toggles on success i.e. each time when the Task2 or Task3 receives a valid message

The following table provides the LED name:

Kit Name	LED Name
PIC32MK General Purpose (GP) Development Board	LED 1
PIC32MX Curiosity Development Board	LED 1
PIC32MX XLP Starter Kit	LED 1 (Red)
PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit	LED 1
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 1
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM D20 Xplained Pro Evaluation Kit	LED 0
SAM D21 Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1
SAM L21 Xplained Pro Evaluation Kit	LED 0
SAM L22 Xplained Pro Evaluation Kit	LED 0
SAM V71 Xplained Ultra Evaluation Kit	LED 0

Running project with IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Reset the board to run the application
4. The LED indicates the success or failure.
 - The LED toggles on success i.e. each time when the Task2 or Task3 receives a valid message

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED (Blue)
SAM9X60 evaluation kit	RGB_LED (Green)

task_notification_freertos

This example application is to illustrate the FreeRTOS Task Notification feature which is used as a light weight binary semaphore. This demonstration application toggles an LED for every 500ms.

Description

This demonstration creates two tasks that send notifications back and forth to each other.

- Task2 blocks to wait for Task1 to notify and will be blocked for 500ms
- Task1 sends a notification to Task2, bringing it out of the blocked state, toggles an LED
- Task1 blocks to wait for Task2 to notify
- Task2 sends notification to Task1, bringing it out of the blocked state

Above steps will be repeated. i.e. an LED toggles for every 500ms

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	core\apps\rtos\freertos\task_notification_freertos\firmware
-------------------------	--

Below table shows the list of project names to be used with different development boards. Open the project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mk_gp_db.X	PIC32MK General Purpose (GP) Development Board
pic32mx470_curiosity.X	PIC32MX Curiosity Development Board
pic32mz_das_sk.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit
pic32mz_ef_sk.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_v71_xult.X	SAM V71 Xplained Ultra Evaluation Kit

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_9x60_ek.IAR	SAM9X60 evaluation kit

MPLAB Harmony Configurations

This section provides information on the MHC configurations.

Description

Components Used:

- FreeRTOS

The following components used may vary based on the project configuration selected:

- Board Support Package (BSP)

NOTE: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project pic32mk_gp_db.X

- Hardware Used**
 - PIC32MK General Purpose (GP) Development Board
- Hardware Setup**
 - No Special hardware Setup Required

2. Project pic32mx470_curiosity.X

- Hardware Used**
 - PIC32MX Curiosity Development Board
- Hardware Setup**
 - Connect mini USB cable to the 'Debug USB' connector(J3) on the board to the computer.

3. Project pic32mz_das_sk.X.

- Hardware Used**
 - PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit
- Hardware Setup**
 - No Special hardware Setup Required

4. Project pic32mz_ef_sk.X.

- Hardware Used**
 - PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
- Hardware Setup**
 - No Special hardware Setup Required

5. Project sam_c21n_xpro.X.

- Hardware Used:**
 - SAM C21N Xplained Pro Evaluation Kit
- Hardware Setup:**

- No special hardware setup is required

6. Project sam_e54_xpro.X.

- **Hardware Used:**
 - SAM E54 Xplained Pro Evaluation Kit
- **Hardware Setup:**
 - No special hardware setup is required

7. Project sam_e70_xult.X.

- **Hardware Used:**
 - SAM E70 Xplained Ultra Evaluation Kit
- **Hardware Setup:**
 - No special hardware setup is required

8. Project sam_v71_xult.X.

- **Hardware Used:**
 - SAM V71 Xplained Ultra Evaluation Kit
- **Hardware Setup:**
 - No special hardware setup is required

9. Project sam_a5d2_xult.IAR

- **Hardware Used**
 - SAM A5D2 Xplained Ultra board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable

10. Project sam_9x60_ek.IAR

- **Hardware Used**
 - SAM 9X60 Evaluation Kit board
 - SD Card with FAT32 file system
- **Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC connector J5 on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable
 - Note: Reset push button on SAM9X60 EK is labeled as SW3

Running the Application

This section provides information on how to run an application.

Description

Running project with MPLAB X IDE

1. Connect a micro/mini USB to the DEBUG port.

2. Build and program the application using the MPLAB X IDE.

3. The LED indicates the success or failure.

- The LED toggles on success for every 500ms

The following table provides the LED name:

Kit Name	LED Name
PIC32MK General Purpose (GP) Development Board	LED 1
PIC32MX Curiosity Development Board	LED 1
PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit	LED 1
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 1
SAM C21N Xplained Pro Evaluation Kit	LED 0
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1
SAM V71 Xplained Ultra Evaluation Kit	LED 0

Running project with IAR Embedded work bench

1. Build the project using IAR Embedded Workbench

2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)

3. Reset the board to run the application

4. The LED indicates the success or failure.

- The LED toggles on success for every 500ms

Kit Name	LED Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED(Blue)
SAM9X60 evaluation kit	RGB_LED(Green)

Micrium OS III Applications

This section provides descriptions of the Micrium OS III RTOS demonstrations which are located in "[micrium_uco3](#)" repository.

Legal Disclaimer

The source code for this demonstration is not freely distributed. To obtain the proper licensing agreement go to the Micrium website: <http://www.micrium.com>.

The Micrium µC/OS-III source has to be installed in the following location for the demonstrations to work.

Micrium OS III Source Path	thirdparty_micrium/MicriumOSIII/Software
----------------------------	--

basic

This example application blinks an LED on a starter kit to show the Micrium OS III threads that are running and to indicate status.

Description

This demonstration creates a tasks which toggle an LED for every 500ms.

Legal Disclaimer

The source code for this demonstration is not freely distributed. To obtain the proper licensing agreement go to the Micrium website: <http://www.micrium.com>.

The Micrium µC/OS-III source has to be installed in the following location for the demonstrations to work.

Micrium OS III Source Path	thirdparty_micrium/MicriumOSIII/Software
-----------------------------------	---

Building the Application

This section provides information on how to build an application using the MPLAB X IDE.

Description

The parent folder for all the MPLAB X projects for this application is given below:

Application Path	micrium_ucos3\apps\basic\firmware
-------------------------	--

To build the application, refer to the following table and open the appropriate project file in the MPLAB X IDE.

Project Name	Description
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit

Note:

Make sure the Micrium µC/OS-III source code is installed in <Harmony3_Path>/thirdparty_micrium/MicriumOSIII/Software and then regenerate the code for demonstration to work.

MPLAB Harmony Configurations

This section provides information on the MHC configurations.

Description

Components Used:

- Micrium OS III

The following components used may vary based on the project configuration selected:

- Board Support Package (BSP)

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project sam_e54_xpro.X.

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - No special hardware setup is required

2. Project sam_e70_xult.X.

- **Hardware Used:**
 - SAM E70 Xplained Ultra Evaluation Kit
- **Hardware Setup**
 - No Special hardware Setup Required

Running the Application

This section provides information on how to run an application using the MPLAB X IDE.

Description

1. Connect a micro USB to the DEBUG port.
2. Build and program the application using the MPLAB X IDE.
3. The LED indicates the success or failure.
 - The LED toggles on success i.e. for every 500ms.

The following table provides the LED name:

Kit Name	LED Name
SAM E54 Xplained Pro Evaluation Kit	LED 0
SAM E70 Xplained Ultra Evaluation Kit	LED 1

System Services Applications

This section provides help for the System Services applications.

Time System Service Applications

This section provides help for the Time System Service applications.

sys_time_multiclient

This example application demonstrates the multi-client system timer functionality.

Description

This application demonstrates timer functionality (with two clients to the Time System Service) by periodically printing a message on console every two seconds and blinking an LED every one second.

Delay, counter and single shot timer functionality is demonstrated on a switch press.

On a switch press, the application reads the current value of the 64 bit counter (say, count 1). It then starts a delay of 500 milliseconds and waits for the delay to expire. Once the delay has expired, the application again reads the current value of the 64 bit counter (say, count 2) and calculates the difference between the two counter values.

The difference count indicates the time spent for the delay and is printed on the console as, "Delay time = x ms", where x is the delay value and is equal to 500 milliseconds in the given example.

The application then starts a single shot timer of 100 milliseconds. When the single shot timer expires, a message is printed on the console that says "Single shot timer of 100 ms expired". This message is printed only once on every switch press.

Building the Application

This section provides information on how to build an application.

Description

The parent folder for all the projects for this application is given below:

Application Path	core/apps/system/time/sys_time_multiclient/firmware
-------------------------	--

Below table shows the list of project names to be used with different development boards. Open the project in their respective IDEs.

MPLAB X IDE Projects

Project Name	Description
pic32mk_gp_db.X	PIC32MK GP Development Kit
pic32mx470_curiosity.X	PIC32MX Curiosity Development Board
pic32mz_das_sk.X	PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit (Crypto)
pic32mz_ef_sk.X	PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit
sam_c21n_xpro.X	SAM C21N Xplained Pro Evaluation Kit
sam_d20_xpro.X	SAM D20 Xplained Pro Evaluation Kit
sam_d21_xpro.X	SAM D21 Xplained Pro Evaluation Kit
sam_e54_xpro.X	SAM E54 Xplained Pro Evaluation Kit
sam_e54_xpro_freertos.X	SAM E54 Xplained Pro Evaluation Kit + FreeRTOS
sam_e70_xult.X	SAM E70 Xplained Ultra Evaluation Kit
sam_e70_xult_freertos.X	SAM E70 Xplained Ultra Evaluation Kit + FreeRTOS
sam_l21_xpro.X	SAM L21 Xplained Pro Evaluation Kit
sam_l22_xpro.X	SAM L22 Xplained Pro Evaluation Kit
sam_v71_xult.X	SAM V71 Xplained Ultra Evaluation Kit
sam_v71_xult_freertos.X	SAM V71 Xplained Ultra Evaluation Kit + FreeRTOS

IAR Embedded Workbench Projects

Project Name	Description
sam_a5d2_xult_freertos.IAR	SAMA5D2 Xplained Ultra evaluation kit
sam_9x60_ek.IAR	SAM9X60 Evaluation Kit

MPLAB Harmony Configuration

This section provides information on the MHC configurations.

Description

Components Used:

- Time System Service
- STDIO

The following components used may vary based on the project configuration selected.

- TC peripheral library Or Core timer
- USART, SERCOM or UART peripheral library
- Board Support Package (BSP)
- FreeRTOS

Other MHC Settings:

- Configure pins for the USART, SERCOM, UART or DBGU peripheral in Pin Settings

NOTE: For projects that use IAR Embedded work bench as IDE, the harmony project file should be opened using MHC plugin (standalone mode) to access the project graph.

Hardware Setup

This section describes how to configure the supported hardware.

Description

1. Project sam_9x60_ek.IAR

- Hardware Used**
 - SAM9X60 Evaluation Kit
 - SD Card with FAT32 file system
- Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC0 slot on the board
 - Connect the Debug USB (J22) port on the board to the computer

using a micro USB cable

2. Project sam_a5d2_xult_freertos.IAR

- Hardware Used**
 - SAM A5D2 Xplained Ultra board
 - SD Card with FAT32 file system
- Hardware Setup**
 - Setup the SD card
 - Download harmony MPU bootstrap loader from this [location](#)
 - Copy the downloaded boot loader binary(boot.bin) and generated application binary (harmony.bin)into the SD card
 - Insert the SD card into the SDMMC1 slot on the board
 - Connect the Debug USB port on the board to the computer using a micro USB cable

3. Project pic32mk_gp_db.X.

- Hardware Used:**
 - PIC32MK GP Development Kit
- Hardware Setup:**
 - Connect a micro USB cable to the USART-USB port J25
 - For programming, connect a micro USB cable to the USB Debug port J12

4. Project pic32mx470_curiosity.X

- Hardware Used**
 - PIC32MX Curiosity Development Board
- Hardware Setup**
 - Connect mini USB cable to the 'Debug USB' connector(J3) on the board to the computer.
 - Install an [USB UART click](#) board on to the mikroBUS socket J5
 - Connect mini USB cable to the [USB UART click](#) board. This will enumerate the USB to UART port.
 - Note:** Ensure that the series resistors on the mikroBUS headers are of value **0 Ohms**.

5. Project pic32mz_das_sk.X.

- Hardware Used:**

- [PIC32MZ Embedded Graphics with Stacked DRAM \(DA\) Starter Kit \(Crypto\)](#)
- **Hardware Setup:**
 - Connect a micro USB cable to the USART-USB port J5
 - For programming, connect a micro USB cable to the USB Debug port J19

6. Project `pic32mz_ef_sk.X`.

- **Hardware Used:**
 - [PIC32MZ Embedded Connectivity with FPU \(EF\) Starter Kit](#)
- **Hardware Setup:**
 - Connect a mini USB cable to the USART-USB port J11
 - For programming, connect a mini USB cable to the USB Debug port J3

7. Project: `sam_c21n_xpro.X`.

- **Hardware Used:**
 - [SAM C21N Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Connect a micro USB to the DEBUG port

8. Project: `sam_d20_xpro.X`.

- **Hardware Used:**
 - [SAM D20 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Connect a micro USB to the DEBUG port

9. Project: `sam_d21_xult.X`.

- **Hardware Used:**
 - [SAM D21 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Connect a micro USB to the DEBUG port

10. Project `sam_e54_xpro.X`.

11. Project `sam_e54_xpro_freertos.X`.

- **Hardware Used:**
 - [SAM E54 Xplained Pro Evaluation Kit](#)
- **Hardware Setup:**
 - Connect a micro USB to the DEBUG port

12. Project: `sam_e70_xult.X`.

13. Project: `sam_e70_xult_freertos.X`.

- **Hardware Used:**
 - [SAM E70 Xplained Ultra Evaluation Kit](#)
- **Hardware Setup:**
 - Connect a micro USB to the DEBUG port

14. Project `sam_l21_xpro.X`

- **Hardware Used**
 - [SAM L21 Xplained Pro Evaluation Kit](#)
- **Hardware Setup**
 - Connect a micro USB to the DEBUG port

15. Project `sam_l22_xpro.X`

- **Hardware Used**

- SAM L22 Xplained Pro Evaluation Kit
- **Hardware Setup**
- Connect a micro USB to the DEBUG port

16. **Project: sam_v71_xult.X.**

17. **Project: sam_v71_xult_freertos.X.**

- **Hardware Used:**
 - SAM V71 Xplained Ultra Evaluation Kit
- **Hardware Setup:**
 - Connect a micro USB to the DEBUG port

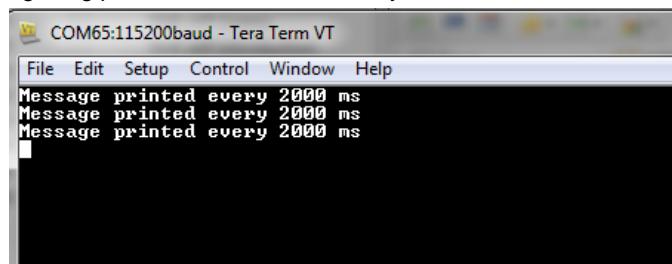
Running the Application

This section provides information on how to run an application.

Description

Running project with MPLAB X IDE

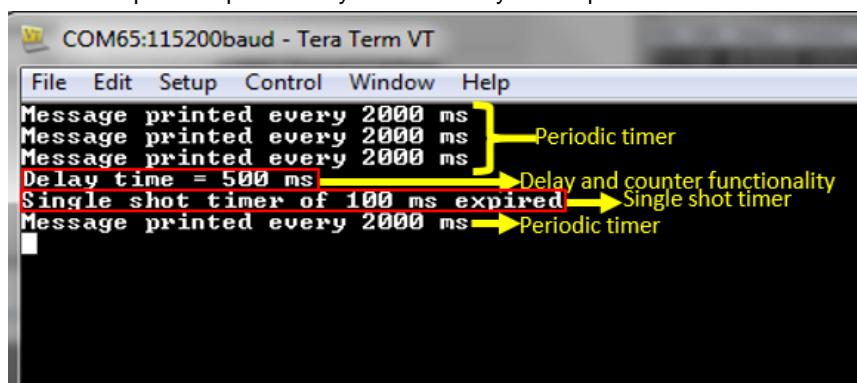
1. Open the Terminal application (Ex.:Tera Term) on the computer.
2. Configure the serial port settings as follows:
 - Baud : 115200
 - Data : 8 Bits
 - Parity : None
 - Stop : 1 Bit
 - Flow Control : None
3. Build and program the application using the MPLAB X IDE.
4. Observe the following message getting printed on the console every two seconds



```
COM65:115200baud - Tera Term VT
File Edit Setup Control Window Help
Message printed every 2000 ms
Message printed every 2000 ms
Message printed every 2000 ms
```

6. Press the switch and observe the following output on the terminal (highlighted in red box).

- "Delay time = 500 ms" indicates the amount of time spent during the delay
- "Single shot timer of 100 ms expired" is printed only once on every switch press



```
COM65:115200baud - Tera Term VT
File Edit Setup Control Window Help
Message printed every 2000 ms
Message printed every 2000 ms
Message printed every 2000 ms
Delay time = 500 ms
Single shot timer of 100 ms expired
Message printed every 2000 ms
```

Periodic timer

Delay and counter functionality

Single shot timer

Periodic timer

NOTE: Printing of the output messages are asynchronous events and hence their ordering is not guaranteed. Image provided in above step is for illustration purpose only.

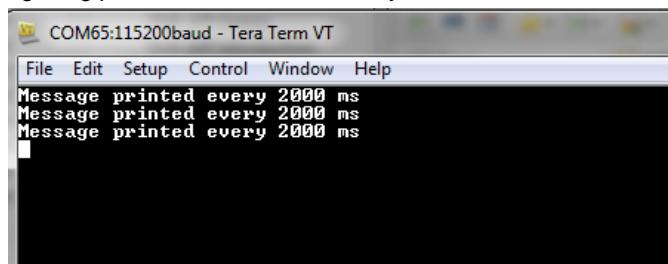
7. The LED indicates the periodic timer functionality.
- The LED is toggled periodically every one second

The following table provides the LED and Switch name:

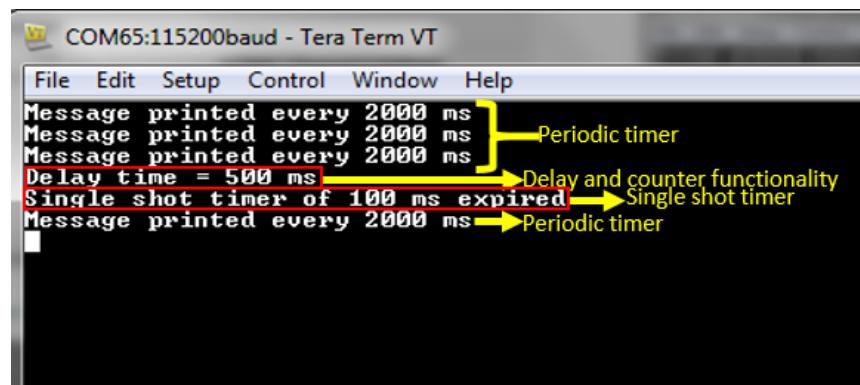
Kit Name	LED Name	Switch Name
PIC32MK GP Development Kit	LED 1	S1
PIC32MX Curiosity Development Board	LED 1	S1
PIC32MZ Embedded Graphics with Stacked DRAM (DA) Starter Kit (Crypto)	LED 1	SW1
PIC32MZ Embedded Connectivity with FPU (EF) Starter Kit	LED 1	SW1
SAM C21N Xplained Pro Evaluation Kit	LED 0	SW0
SAM D20 Xplained Pro Evaluation Kit	LED 0	SW0
SAM D21 Xplained Pro Evaluation Kit	LED 0	SW0
SAM E54 Xplained Pro Evaluation Kit	LED 0	SW0
SAM E70 Xplained Ultra Evaluation Kit	LED 1	SW0
SAM L21 Xplained Pro Evaluation Kit	LED 0	SW0
SAM L22 Xplained Pro Evaluation Kit	LED 0	SW0
SAM V71 Xplained Ultra Evaluation Kit	LED 0	SW1

Running project with IAR Embedded work bench

1. Build the project using IAR Embedded Workbench
2. Use the output binary file (harmony.bin) to setup the board as detailed in [hardware setup](#)
3. Open the Terminal application (Ex.:Tera Term) on the computer
4. Configure the serial port settings as follows:
 - Baud : 115200
 - Data : 8 Bits
 - Parity : None
 - Stop : 1 Bit
 - Flow Control : None
5. Reset the board to run the application
6. Observe the following message getting printed on the console every two seconds



7. Press the switch and observe the following output on the terminal (highlighted in red box).
 - "Delay time = 500 ms" indicates the amount of time spent during the delay
 - "Single shot timer of 100 ms expired" is printed only once on every switch press



```
COM65:115200baud - Tera Term VT
File Edit Setup Control Window Help
Message printed every 2000 ms
Message printed every 2000 ms
Message printed every 2000 ms
Delay time = 500 ms
Single shot timer of 100 ms expired
Message printed every 2000 ms
```

NOTE: Printing of the output messages are asynchronous events and hence their ordering is not guaranteed. Image provided in above step is for illustration purpose only.

8. The LED indicates the periodic timer functionality

- The LED is toggled periodically every one second

The following table provides the LED and Switch name:

Kit Name	LED Name	Switch Name
SAMA5D2 Xplained Ultra evaluation kit	RGB_LED(Blue)	PB_USER
SAM9X60 Evaluation Kit	D7(Blue)	SW1

Third-Party Products

MPLAB Harmony enables seamless integration of third-party solutions, such as RTOS, Middleware, Drivers, and so on, into the software framework.

Third-Party Products Overview

This section provides an overview of the third-party products included in the MPLAB Harmony.

Introduction

This section provides an overview of the third-party products included in the MPLAB Harmony.

Description

MPLAB Harmony is a flexible, abstracted, fully integrated firmware development platform for PIC32 and SAM microcontrollers, which enables seamless integration of third-party solutions, such as RTOS, Middleware, Drivers, and so on, into the software framework.

Important Licensing Information

Micrium:

The source code for the Micrium µC/OS-III demonstrations is not freely distributed. To obtain the source code and proper licensing agreement go to the Micrium website: <http://www.micrium.com>.

Software License Agreement

This section provides information on Third-Party Products Software licence agreement.

Description

Refer to the MPLAB Harmony Integrated Software Framework Software License Agreement for complete licensing information. A copy of this agreement is available in the <install-dir>/doc folder of your MPLAB Harmony installation.

FreeRTOS Library Help

This section provides information on the FreeRTOS™ Library.

Introduction

This topic provides an overview of the FreeRTOS Library in MPLAB Harmony.

Description

FreeRTOS is a small footprint, portable, preemptive, open source, real time kernel that has been designed specifically for use on micro-controllers that makes small, low-power edge devices easy to program, deploy, secure, connect, and manage.

More Information

For more information, please read the FreeRTOS Quick Start Guide, which is available at: <http://www.freertos.org/FreeRTOS-quick-start-guide.html>. Additional information is also available from the Microchip Third-Party RTOS web page: <http://www.microchip.com/devtoolthirdparty/>

Demonstrations

See [FreeRTOS Applications](#) for information.

Micrium OS III Library Help

This section provides information on the Micrium µC/OS-III™ Library.

Introduction

This topic provides an overview of the Micrium µC/OS-III Library in MPLAB Harmony.

Description

Micrium µC/OS-III are highly portable, ROMable, scalable, preemptive, real-time, deterministic, multitasking kernels for microprocessors, microcontrollers and DSPs.

More Information

For more information, please read the related documentation, which is available at: <https://doc.micrium.com/display/osiiidoc/>.

Additional information is also available from the Microchip Third-Party RTOS web page:

<http://www.microchip.com/devtoolthirdparty/>

Demonstrations

See [Micrium RTOS Applications](#) for information.

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