




PSF AE-Sink Demo Read Me

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REV	DATE	DESCRIPTION OF CHANGE
0.90	09-Oct-2020	Initial release of PSF AE-Sink Demo Read me

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2 Terms and Abbreviations

Term	Definition
PSF	Universal Serial Bus Power Delivery Software Framework
EVB	Evaluation Board
PD	Power Delivery
IDE	Integrated Development Environment
PDO	Power Data Object
LED	Light Emitting Diode
GPIO	General Purpose Input Output

3 Introduction

Microchip's USB Power Delivery Software Framework (PSF) is a configurable USB PD solution that is compliant to USB-PD 3.0 specification.

PSF Sink application support basic USB-PD sink functionality with two modes. They are Higher wattage at higher voltage (Mode A) and Higher wattage at lower voltage (Mode B).

This document is intended to guide a user on setting up the PSF-Basic-Sink-AE to work properly with Sink version of PSF along with a demonstration of a PD device attached to the PSF-Basic-Sink-AE

4 Prerequisites

Hardware:

- 1) Microchip PSF Basic-Sink-AE
- 2) 60W Adapter
- 3) USB-C to USB-C cables
- 4) Atmel ICE Debugger Kit



- 5) FTDI Cable
- 6) Programming Adapter

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5 Setting up PSF Basic-Sink-AE for PSF AE-Sink Demo

1. Connect one end of Atmel ICE to PC using Micro-B cable and the other end to programming adapter which has five different coloured wires-Red, Purple, Black, Yellow and Blue as follows and the same is shown in the figure 5.1.

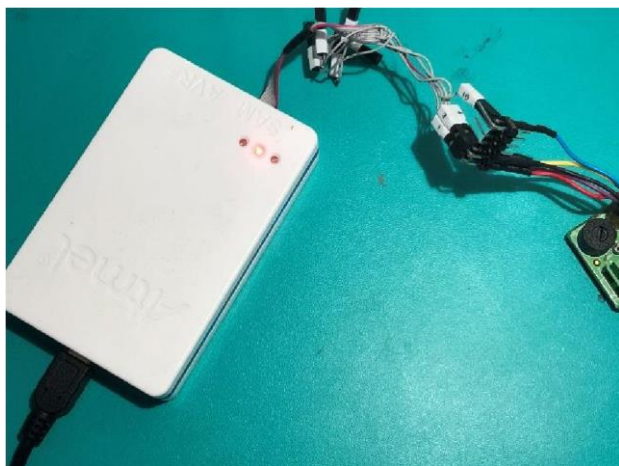


Figure 5.1

Atmel ICE pin	Programming adapter wire
Pin 1	Red
Pin 2	Purple
Pin 3	Black
Pin 4	Yellow
Pin 10	Blue

2. Connect RX, TX and GND of FTDI cable to Pin 5, Pin 4, and Pin 3 of J4 respectively as shown in the figure 5.2

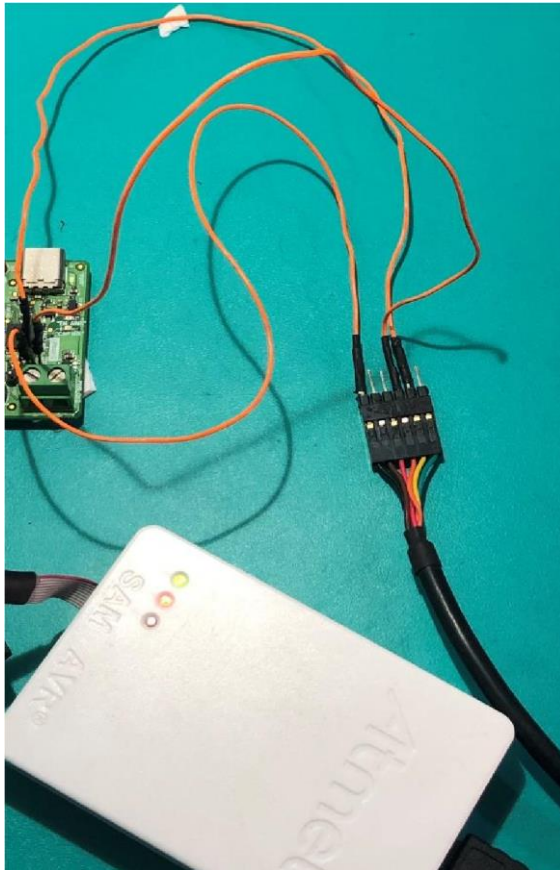
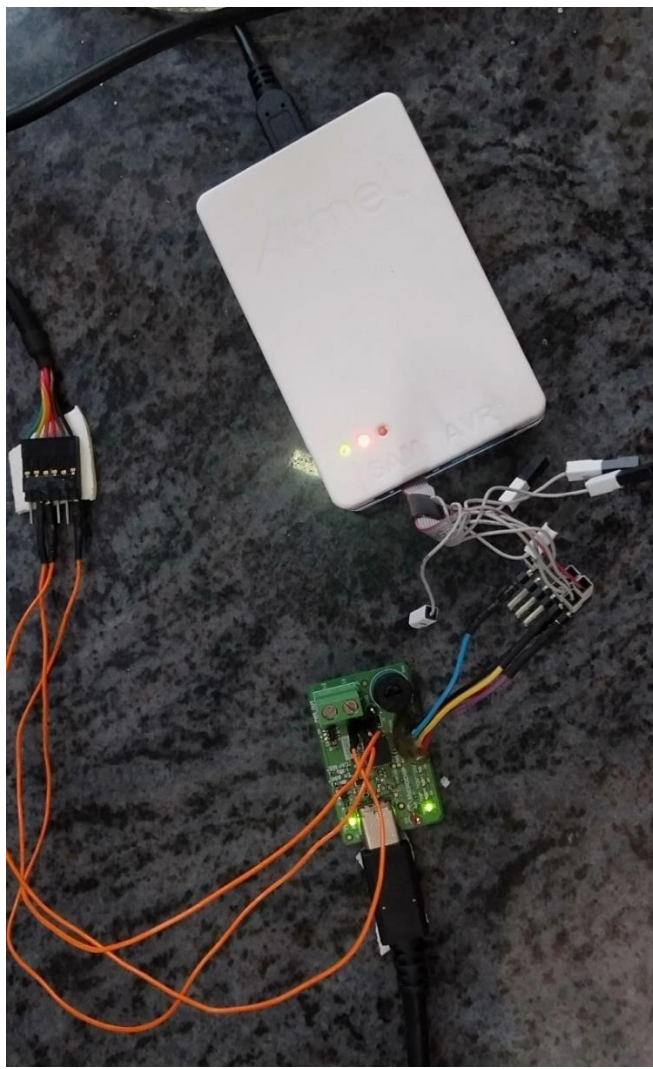


Figure 5.2

3. FTDI cable can also be connected using AVR JTAG also
4. Connect a 60W power adapter to J2 using USB-C to USB-C cable.
5. The whole connection looks like,

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6 Running the demo

Refer [Getting Started with PSF](#) document for the detailed steps on setting up the build environment, building the AE-Sink Demo PSF project and programming the hex file in the PSF Basic-Sink-AE.

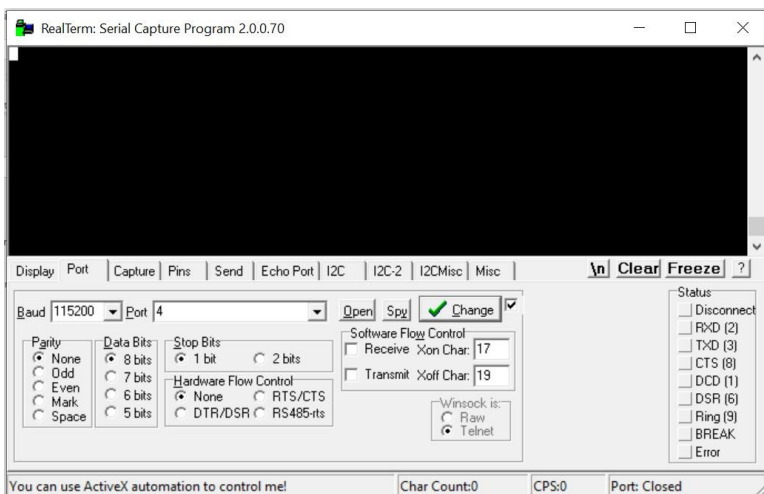
Refer Appendix 8.2 of [Getting Started with PSF](#) to change any SAMD20 Harmony configuration.

1. Program the UPD301C_Basic_Sink_AE.X file by following the steps mentioned in section 8 of [Getting Started with PSF](#)
2. Set up the Tera term/Real term setup as shown below.

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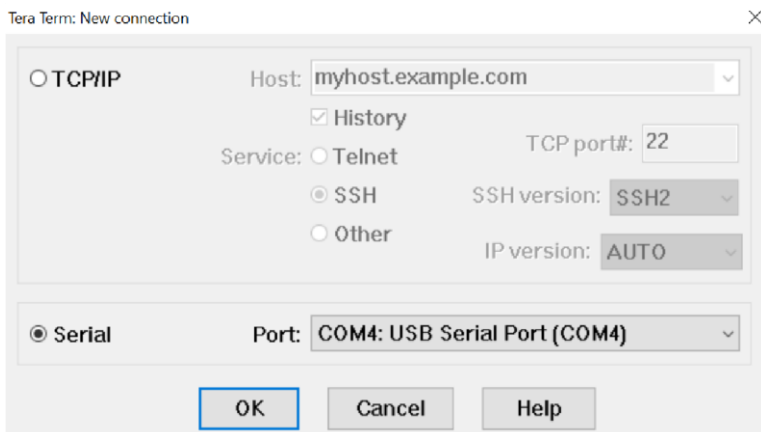
6.1.1 Real Term Setup

1. In Real Term set the baud rate to 115200
2. Set the COM port number



6.1.2 Tera Term Setup

1. Open the Tera Term and select the com port



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2. Click on setup -> serial port-> Baud Rate

Tera Term: Serial port setup and connection

Port: COM4

Speed: 115200

Data: 8 bit

Parity: none

Stop bits: 1 bit

Flow control: none

Transmit delay: 0 msec/char 0 msec/line

Device Friendly Name: USB Serial Port (COM4)
 Device Instance ID: FTDIBUS\VID_0403+PID_6001+FTA3639JA\00
 Device Manufacturer: FTDI
 Provider Name: FTDI
 Driver Date: 8-16-2017
 Driver Version: 2.12.28.0

New setting

Cancel

Help

3. Click New setting

4. Now Click on setup -> Terminal-> New-line->CR+LF->OK

Tera Term: Terminal setup

Terminal size: 80 X 24

☒ Term size = win size

☐ Auto window resize

Terminal ID: VT100

Answerback:

Coding (receive): UTF-8

Coding (transmit): UTF-8

locale: american

New-line: Receive: CR+LF Transmit: CR

☐ Local echo

☐ Auto switch (VT<->TEK)

OK

Cancel

Help

7 Expected Results

7.1 Rotor Knob

1. Once the hex file is programmed, the PWR and EN_SINK LEDs turn on and according to the PD source adapter used, the LEDs D2, D4, D5, D6 turn on.
2. Now change the positions of Rotor Knob and the following changes can be observed in the LEDs D2, D4, D5, D6.

Rotor Knob Position	Status LED
Position 0	D2
Position 1	D2, D4
Position 2	D2, D5
Position 3	D2, D6
Position 4	D2, D4, D5, D6
Position 5	D2, D4, D5, D6

7.2 PSF Control Terminal

PSF has a range of compile time and runtime configuration options for the various USB-PD features and other special features.

This release of PCT allows configuration of the following:

- Version
- PDO
- Memory
- Status Data
- Rotor knob

7.2.1 Supported commands

A list of supported commands, their description and expected results is given below.

Name	Description
get version	Gives the demo version and firmware version
get pdo	Gives the default sink pdo details

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get sr[globalcfgstatusdata]	Gives the Global config status data values
get sr[portcfgstatus]	Gives the port config status data values
get mem[memory_address][length]	Gets the value in the memory address of the firmware requested
set mem[memory_address][byte_value]	Sets the byte value at the memory address of the firmware specifies
set pdo[position][value]	Sets the pdo value at the position specified

7.2.2 get version

Description

get version command when prompted in PCT gives the current demo version and firmware version

Remarks

Version keeps changing as the firmware is updated

Example

get version

>demo version=1.00

>firmware version=1.07

7.2.3 get pdo

Description

get pdo command when prompted in PCT gives out the advertised PDOs or the default supported PDO by the firmware

Position0: (5V,3A)

Position1: (5V,3A), (9V,3A)

Position2: (5V,3A), (15V,3A)

Position3: (5V,3A), (20V,3A)

Position4: (5V,3A), (9V,3A), (15V,3A), (20V,3A) in Mode A.

Position5: (5V,3A), (9V,3A), (15V,3A), (20V,3A) in Mode B.

Remarks

If a valid PDO is newly set, get PDO command should give the newly set PDO

Example

> get pdo

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```
> AdvertisedPDO -00
```

```
Voltage=1388
```

```
Current=00f0
```

```
> AdvertisedPDO -01
```

```
Voltage=2328
```

```
Current=012c
```

Note:

get PDO displays values during run time and hence they may change.

7.2.4 get sr[globalcfgstatusdata]

Description

get sr[globalcfgstatusdata] command when prompted in PCT gives out the global config status data values

Remarks

These values keep changing as the firmware is updated

Example

```
get sr[globalcfgstatusdata]
```

```
>u8MinorVersion=2
```

```
>u8MajorVersion=1
```

7.2.5 get sr[portcfgstatus]

Description

get sr[portcfgstatus] command when prompted in PCT gives out the global config status data values

Remarks

These values keep changing as the firmware is updated

Example

```
get sr[portcfgstatus]
```

```
>u32cfgdata=238
```

Note:

get PDO displays values during run time and hence they may change.

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7.2.6 get mem[memory_address] [length]

Description

get mem[memory_address][length] command when prompted in PCT gives out the value in the memory address specified to the given length.

Remarks

The memory 2000_0000 to 20001FF0 is accessible.

Length cannot be more than 2.

Example

```
get mem[20001FA0][1]
```

```
>byte value=08
```

7.2.7 set mem[memory_address] [byte_value]

Description

set mem[memory_address][byte_value] command when prompted in PCT sets the byte value at the memory address of the firmware specifies

Remarks

The memory 2000_0000 to 20001FF0 is accessible.

Example

```
set mem[20001FA0][1]
```

7.2.8 set pdo[position][value]

Description

set mem[position][value] command when prompted in PCT by setting the rotor knob position to be modified, sets the pdo value at the position specified

Remarks

- The pdo position cannot be greater than 7
- PDO value should be as the value calculated by $((((\text{voltage})/50) \ll 10) | ((\text{current})/10))$.
- PDO values are always in ascending order
- Maximum PDO value could be 6412C(20V,3A)

Example

```
set pdo[3][5512C]
```

Important Note:

To view the PDOs supported by PSF, user should give a get PDO command. To modify a PDO user must give the position as displayed in get PDO list

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For eg:

- Set the Rotor position to 2
- Give a get pdo command to view the list of supported PDOs
- Control terminal displays the PDOs as
 - Advertised PDO-00
 - a. Voltage-1388
 - b. Current-012c
 - Advertised PDO-01
 - a. Voltage-2328
 - b. Current-012c
- Now if the user wants to set the PDO (14V,3A)
- Then user must give the command-set pdo [1] [4612c]

7.2.9 Space Bar

Description

User can interact with firmware through PCT even during the debug trace. But if the user wants to use only the PCT without debug trace, user can hit a space bar. (NOTE that the 1st space bar hit enters debug trace).

The 2nd space bar hit enters PCT with a “welcome” message and the 3rd hit gets it back to debug trace with a “goodbye” message and so on and so forth.

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