MCUXpresso SDK API Reference Manual

NXP Semiconductors

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Chapter 1
Introduction

The MCUXpresso Software Development Kit (MCUXpresso SDK) is a collection of software enablement for NXP Microcontrollers that includes peripheral drivers, multicore support, USB stack, and integrated RTOS support for FreeRTOS^{TM} . In addition to the base enablement, the MCUXpresso SDK is augmented with demo applications, driver example projects, and API documentation to help users quickly leverage the support provided by MCUXpresso SDK. The KEx Web UI is available to provide access to all MCUXpresso SDK packages. See the *MCUXpresso Software Development Kit (SDK) Release Notes* (document MCUXSDKRN) in the Supported Devices section at `MCUXpresso-SDK: Software Development Kit for MCUXpresso` for details.

The MCUXpresso SDK is built with the following runtime software components:

- ARM® and DSP standard libraries, and CMSIS-compliant device header files which provide direct access to the peripheral registers.
- Peripheral drivers that provide stateless, high-performance, ease-of-use APIs. Communication drivers provide higher-level transactional APIs for a higher-performance option.
- RTOS wrapper driver built on on top of MCUXpresso SDK peripheral drivers and leverage native RTOS services to better comply to the RTOS cases.
- Real time operation systems (RTOS) for FreeRTOS OS.
- Stacks and middleware in source or object formats including:
  - A USB device, host, and OTG stack with comprehensive USB class support.
  - CMSIS-DSP, a suite of common signal processing functions.
  - The MCUXpresso SDK comes complete with software examples demonstrating the usage of the peripheral drivers, RTOS wrapper drivers, middleware, and RTOSes.

  All demo applications and driver examples are provided with projects for the following toolchains:
  - IAR Embedded Workbench
  - Keil MDK
  - MCUXpresso IDE

The peripheral drivers and RTOS driver wrappers can be used across multiple devices within the product family without modification. The configuration items for each driver are encapsulated into C language data structures. Device-specific configuration information is provided as part of the MCUXpresso SDK and need not be modified by the user. If necessary, the user is able to modify the peripheral driver and RTOS wrapper driver configuration during runtime. The driver examples demonstrate how to configure the drivers by passing the proper configuration data to the APIs. The folder structure is organized to reduce the total number of includes required to compile a project.

The rest of this document describes the API references in detail for the peripheral drivers and RTOS wrapper drivers. For the latest version of this and other MCUXpresso SDK documents, see the `kex.nxp.com/apidoc`.

Deliverable	Location
Demo Applications	<install_dir>/boards/<board_name>/demo_-apps
Driver Examples	<install_dir>/boards/<board_name>/driver_-examples
Documentation	<install_dir>/docs
Middleware	<install_dir>/middleware
Drivers	<install_dir>/<device_name>/drivers/
CMSIS Standard ARM Cortex-M Headers, math and DSP Libraries	<install_dir>/CMSIS
Device Startup and Linker	<install_dir>/<device_name>/<toolchain>/
MCUXpresso SDK Utilities	<install_dir>/devices/<device_name>/utilities
RTOS Kernel Code	<install_dir>/rtos

Table 2: MCUXpresso SDK Folder Structure

Chapter 2
Driver errors status

- kStatus_SMC_StopAbort = 3900
- kStatus_SPI_Busy = 1400
- kStatus_SPI_Idle = 1401
- kStatus_SPI_Error = 1402
- kStatus_NOTIFIER_ErrorNotificationBefore = 9800
- kStatus_NOTIFIER_ErrorNotificationAfter = 9801

Chapter 3
Architectural Overview

This chapter provides the architectural overview for the MCUXpresso Software Development Kit (MCU-Xpresso SDK). It describes each layer within the architecture and its associated components.

Overview

The MCUXpresso SDK architecture consists of five key components listed below.

1. The ARM Cortex Microcontroller Software Interface Standard (CMSIS) CORE compliance device-specific header files, SOC Header, and CMSIS math/DSP libraries.
2. Peripheral Drivers
3. Real-time Operating Systems (RTOS)
4. Stacks and Middleware that integrate with the MCUXpresso SDK
5. Demo Applications based on the MCUXpresso SDK

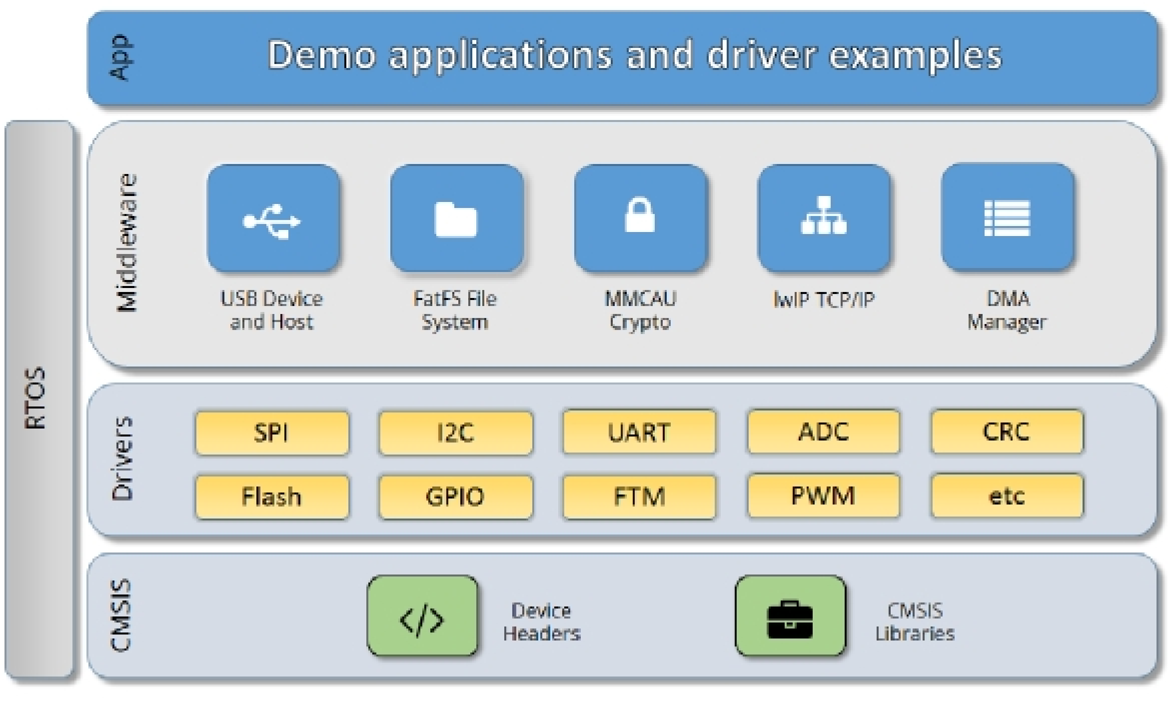

Figure 1: MCUXpresso SDK Block Diagram

MCU header files

Each supported MCU device in the MCUXpresso SDK has an overall System-on Chip (SoC) memory-mapped header file. This header file contains the memory map and register base address for each peripheral and the IRQ vector table with associated vector numbers. The overall SoC header file provides a access to the peripheral registers through pointers and predefined bit masks. In addition to the overall SoC memory-mapped header file, the MCUXpresso SDK includes a feature header file for each device. The feature header file allows NXP to deliver a single software driver for a given peripheral. The feature file ensures that the driver is properly compiled for the target SOC.

CMSIS Support

Along with the SoC header files and peripheral extension header files, the MCUXpresso SDK also includes common CMSIS header files for the ARM Cortex-M core and the math and DSP libraries from the latest CMSIS release. The CMSIS DSP library source code is also included for reference.

MCUXpresso SDK Peripheral Drivers

The MCUXpresso SDK peripheral drivers mainly consist of low-level functional APIs for the MCU product family on-chip peripherals and also of high-level transactional APIs for some bus drivers/DM-A driver/eDMA driver to quickly enable the peripherals and perform transfers.

All MCUXpresso SDK peripheral drivers only depend on the CMSIS headers, device feature files, fsl_-common.h, and fsl_clock.h files so that users can easily pull selected drivers and their dependencies into projects. With the exception of the clock/power-relevant peripherals, each peripheral has its own driver. Peripheral drivers handle the peripheral clock gating/ungating inside the drivers during initialization and deinitialization respectively.

Low-level functional APIs provide common peripheral functionality, abstracting the hardware peripheral register accesses into a set of stateless basic functional operations. These APIs primarily focus on the control, configuration, and function of basic peripheral operations. The APIs hide the register access details and various MCU peripheral instantiation differences so that the application can be abstracted from the low-level hardware details. The API prototypes are intentionally similar to help ensure easy portability across supported MCUXpresso SDK devices.

Transactional APIs provide a quick method for customers to utilize higher-level functionality of the peripherals. The transactional APIs utilize interrupts and perform asynchronous operations without user intervention. Transactional APIs operate on high-level logic that requires data storage for internal operation context handling. However, the Peripheral Drivers do not allocate this memory space. Rather, the user passes in the memory to the driver for internal driver operation. Transactional APIs ensure the NVIC is enabled properly inside the drivers. The transactional APIs do not meet all customer needs, but provide a baseline for development of custom user APIs.

Note that the transactional drivers never disable an NVIC after use. This is due to the shared nature of interrupt vectors on devices. It is up to the user to ensure that NVIC interrupts are properly disabled after usage is complete.

Interrupt handling for transactional APIs

A double weak mechanism is introduced for drivers with transactional API. The double weak indicates two levels of weak vector entries. See the examples below:

```
        PUBWEAK SPI0_IRQHandler
        PUBWEAK SPI0_DriverIRQHandler
SPI0_IRQHandler
```

```
LDR     R0, =SPI0_DriverIRQHandler
BX      R0
```

The first level of the weak implementation are the functions defined in the vector table. In the devices/<-DEVICE_NAME>/<TOOLCHAIN>/startup_<DEVICE_NAME>.s/.S file, the implementation of the first layer weak function calls the second layer of weak function. The implementation of the second layer weak function (ex. SPI0_DriverIRQHandler) jumps to itself (B .). The MCUXpresso SDK drivers with transactional APIs provide the reimplementation of the second layer function inside of the peripheral driver. If the MCUXpresso SDK drivers with transactional APIs are linked into the image, the SPI0_-DriverIRQHandler is replaced with the function implemented in the MCUXpresso SDK SPI driver.

The reason for implementing the double weak functions is to provide a better user experience when using the transactional APIs. For drivers with a transactional function, call the transactional APIs and the drivers complete the interrupt-driven flow. Users are not required to redefine the vector entries out of the box. At the same time, if users are not satisfied by the second layer weak function implemented in the MCU-Xpresso SDK drivers, users can redefine the first layer weak function and implement their own interrupt handler functions to suit their implementation.

The limitation of the double weak mechanism is that it cannot be used for peripherals that share the same vector entry. For this use case, redefine the first layer weak function to enable the desired peripheral interrupt functionality. For example, if the MCU's UART0 and UART1 share the same vector entry, redefine the UART0_UART1_IRQHandler according to the use case requirements.

Feature Header Files

The peripheral drivers are designed to be reusable regardless of the peripheral functional differences from one MCU device to another. An overall Peripheral Feature Header File is provided for the MCUXpresso SDK-supported MCU device to define the features or configuration differences for each sub-family device.

Application

See the *Getting Started with MCUXpresso SDK* document (MCUXSDKGSUG).

Chapter 4
Trademarks

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Chapter 5
ADC16: 16-bit SAR Analog-to-Digital Converter Driver

5.1 Overview

The MCUXpresso SDK provides a peripheral driver for the 16-bit SAR Analog-to-Digital Converter (A-DC16) module of MCUXpresso SDK devices.

5.2 Typical use case

5.2.1 Polling Configuration

```
    adc16_config_t adc16ConfigStruct;
    adc16_channel_config_t adc16ChannelConfigStruct;

    ADC16_Init(DEMO_ADC16_INSTANCE);
    ADC16_GetDefaultConfig(&adc16ConfigStruct);
    ADC16_Configure(DEMO_ADC16_INSTANCE, &adc16ConfigStruct);
    ADC16_EnableHardwareTrigger(DEMO_ADC16_INSTANCE, false);
#if defined(FSL_FEATURE_ADC16_HAS_CALIBRATION) && FSL_FEATURE_ADC16_HAS_CALIBRATION
    if (kStatus_Success == ADC16_DoAutoCalibration(DEMO_ADC16_INSTANCE))
    {
        PRINTF("ADC16_DoAutoCalibration() Done.\r\n");
    }
    else
    {
        PRINTF("ADC16_DoAutoCalibration() Failed.\r\n");
    }
#endif // FSL_FEATURE_ADC16_HAS_CALIBRATION

    adc16ChannelConfigStruct.channelNumber = DEMO_ADC16_USER_CHANNEL;
    adc16ChannelConfigStruct.enableInterruptOnConversionCompleted =
      false;
#if defined(FSL_FEATURE_ADC16_HAS_DIFF_MODE) && FSL_FEATURE_ADC16_HAS_DIFF_MODE
    adc16ChannelConfigStruct.enableDifferentialConversion = false;
#endif // FSL_FEATURE_ADC16_HAS_DIFF_MODE

    while(1)
    {
        GETCHAR(); // Input any key in terminal console.
        ADC16_ChannelConfigure(DEMO_ADC16_INSTANCE, DEMO_ADC16_CHANNEL_GROUP, &adc16ChannelConfigStruct);
        while (kADC16_ChannelConversionDoneFlag !=
      ADC16_ChannelGetStatusFlags(DEMO_ADC16_INSTANCE, DEMO_ADC16_CHANNEL_GROUP))
        {
        }
        PRINTF("ADC Value: %d\r\n", ADC16_ChannelGetConversionValue(DEMO_ADC16_INSTANCE,
      DEMO_ADC16_CHANNEL_GROUP));
    }
```

5.2.2 Interrupt Configuration

```
    volatile bool g_Adc16ConversionDoneFlag = false;
    volatile uint32_t g_Adc16ConversionValue;
    volatile uint32_t g_Adc16InterruptCount = 0U;
```

```
    // ...

    adc16_config_t adc16ConfigStruct;
    adc16_channel_config_t adc16ChannelConfigStruct;

    ADC16_Init(DEMO_ADC16_INSTANCE);
    ADC16_GetDefaultConfig(&adc16ConfigStruct);
    ADC16_Configure(DEMO_ADC16_INSTANCE, &adc16ConfigStruct);
    ADC16_EnableHardwareTrigger(DEMO_ADC16_INSTANCE, false);
#if defined(FSL_FEATURE_ADC16_HAS_CALIBRATION) && FSL_FEATURE_ADC16_HAS_CALIBRATION
    if (ADC16_DoAutoCalibration(DEMO_ADC16_INSTANCE))
    {
        PRINTF("ADC16_DoAutoCalibration() Done.\r\n");
    }
    else
    {
        PRINTF("ADC16_DoAutoCalibration() Failed.\r\n");
    }
#endif // FSL_FEATURE_ADC16_HAS_CALIBRATION

    adc16ChannelConfigStruct.channelNumber = DEMO_ADC16_USER_CHANNEL;
    adc16ChannelConfigStruct.enableInterruptOnConversionCompleted =
      true; // Enable the interrupt.
#if defined(FSL_FEATURE_ADC16_HAS_DIFF_MODE) && FSL_FEATURE_ADC16_HAS_DIFF_MODE
    adc16ChannelConfigStruct.enableDifferentialConversion = false;
#endif // FSL_FEATURE_ADC16_HAS_DIFF_MODE

    while(1)
    {
        GETCHAR(); // Input a key in the terminal console.
        g_Adc16ConversionDoneFlag = false;
        ADC16_ChannelConfigure(DEMO_ADC16_INSTANCE, DEMO_ADC16_CHANNEL_GROUP, &adc16ChannelConfigStruct);
        while (!g_Adc16ConversionDoneFlag)
        {
        }
        PRINTF("ADC Value: %d\r\n", g_Adc16ConversionValue);
        PRINTF("ADC Interrupt Count: %d\r\n", g_Adc16InterruptCount);
    }

    // ...

    void DEMO_ADC16_IRQHandler(void)
    {
        g_Adc16ConversionDoneFlag = true;
        // Read the conversion result to clear the conversion completed flag.
        g_Adc16ConversionValue = ADC16_ChannelConversionValue(DEMO_ADC16_INSTANCE, DEMO_ADC16_CHANNEL_GROUP
      );
        g_Adc16InterruptCount++;
    }
```

Data Structures

- struct adc16_config_t
  ADC16 converter configuration. More...
- struct adc16_hardware_compare_config_t
  ADC16 Hardware comparison configuration. More...
- struct adc16_channel_config_t
  ADC16 channel conversion configuration. More...

Enumerations

- enum _adc16_channel_status_flags { kADC16_ChannelConversionDoneFlag = ADC_SC1_COCO_MASK }

Channel status flags.

- enum _adc16_status_flags {
kADC16_ActiveFlag = ADC_SC2_ADACT_MASK,
kADC16_CalibrationFailedFlag = ADC_SC3_CALF_MASK }
Converter status flags.
- enum adc16_channel_mux_mode_t {
kADC16_ChannelMuxA = 0U,
kADC16_ChannelMuxB = 1U }
Channel multiplexer mode for each channel.
- enum adc16_clock_divider_t {
kADC16_ClockDivider1 = 0U,
kADC16_ClockDivider2 = 1U,
kADC16_ClockDivider4 = 2U,
kADC16_ClockDivider8 = 3U }
Clock divider for the converter.
- enum adc16_resolution_t {
kADC16_Resolution8or9Bit = 0U,
kADC16_Resolution12or13Bit = 1U,
kADC16_Resolution10or11Bit = 2U,
kADC16_ResolutionSE8Bit = kADC16_Resolution8or9Bit,
kADC16_ResolutionSE12Bit = kADC16_Resolution12or13Bit,
kADC16_ResolutionSE10Bit = kADC16_Resolution10or11Bit }
Converter's resolution.
- enum adc16_clock_source_t {
kADC16_ClockSourceAlt0 = 0U,
kADC16_ClockSourceAlt1 = 1U,
kADC16_ClockSourceAlt2 = 2U,
kADC16_ClockSourceAlt3 = 3U,
kADC16_ClockSourceAsynchronousClock = kADC16_ClockSourceAlt3 }
Clock source.
- enum adc16_long_sample_mode_t {
kADC16_LongSampleCycle24 = 0U,
kADC16_LongSampleCycle16 = 1U,
kADC16_LongSampleCycle10 = 2U,
kADC16_LongSampleCycle6 = 3U,
kADC16_LongSampleDisabled = 4U }
Long sample mode.
- enum adc16_reference_voltage_source_t {
kADC16_ReferenceVoltageSourceVref = 0U,
kADC16_ReferenceVoltageSourceValt = 1U }
Reference voltage source.
- enum adc16_hardware_average_mode_t {
kADC16_HardwareAverageCount4 = 0U,
kADC16_HardwareAverageCount8 = 1U,
kADC16_HardwareAverageCount16 = 2U,
kADC16_HardwareAverageCount32 = 3U,
kADC16_HardwareAverageDisabled = 4U }

Hardware average mode.
- enum adc16_hardware_compare_mode_t {
kADC16_HardwareCompareMode0 = 0U,
kADC16_HardwareCompareMode1 = 1U,
kADC16_HardwareCompareMode2 = 2U,
kADC16_HardwareCompareMode3 = 3U }
Hardware compare mode.

Driver version

- #define FSL_ADC16_DRIVER_VERSION (MAKE_VERSION(2, 0, 0))
ADC16 driver version 2.0.0.

Initialization

- void ADC16_Init (ADC_Type *base, const adc16_config_t *config)
Initializes the ADC16 module.
- void ADC16_Deinit (ADC_Type *base)
De-initializes the ADC16 module.
- void ADC16_GetDefaultConfig (adc16_config_t *config)
Gets an available pre-defined settings for the converter's configuration.
- status_t ADC16_DoAutoCalibration (ADC_Type *base)
Automates the hardware calibration.
- static void ADC16_SetOffsetValue (ADC_Type *base, int16_t value)
Sets the offset value for the conversion result.

Advanced Features

- static void ADC16_EnableHardwareTrigger (ADC_Type *base, bool enable)
Enables the hardware trigger mode.
- void ADC16_SetChannelMuxMode (ADC_Type *base, adc16_channel_mux_mode_t mode)
Sets the channel mux mode.
- void ADC16_SetHardwareCompareConfig (ADC_Type *base, const adc16_hardware_compare_-config_t *config)
Configures the hardware compare mode.
- void ADC16_SetHardwareAverage (ADC_Type *base, adc16_hardware_average_mode_t mode)
Sets the hardware average mode.
- uint32_t ADC16_GetStatusFlags (ADC_Type *base)
Gets the status flags of the converter.
- void ADC16_ClearStatusFlags (ADC_Type *base, uint32_t mask)
Clears the status flags of the converter.

Conversion Channel

- void ADC16_SetChannelConfig (ADC_Type *base, uint32_t channelGroup, const adc16_channel-_config_t *config)
Configures the conversion channel.
- static uint32_t ADC16_GetChannelConversionValue (ADC_Type *base, uint32_t channelGroup)
Gets the conversion value.
- uint32_t ADC16_GetChannelStatusFlags (ADC_Type *base, uint32_t channelGroup)

Gets the status flags of channel.

5.3 Data Structure Documentation

5.3.1 struct adc16_config_t

Data Fields

- adc16_reference_voltage_source_t referenceVoltageSource
  Select the reference voltage source.
- adc16_clock_source_t clockSource
  Select the input clock source to converter.
- bool enableAsynchronousClock
  Enable the asynchronous clock output.
- adc16_clock_divider_t clockDivider
  Select the divider of input clock source.
- adc16_resolution_t resolution
  Select the sample resolution mode.
- adc16_long_sample_mode_t longSampleMode
  Select the long sample mode.
- bool enableHighSpeed
  Enable the high-speed mode.
- bool enableLowPower
  Enable low power.
- bool enableContinuousConversion
  Enable continuous conversion mode.

5.3.1.0.0.1 Field Documentation

5.3.1.0.0.1.1 adc16_reference_voltage_source_t adc16_config_t::referenceVoltageSource

5.3.1.0.0.1.2 adc16_clock_source_t adc16_config_t::clockSource

5.3.1.0.0.1.3 bool adc16_config_t::enableAsynchronousClock

5.3.1.0.0.1.4 adc16_clock_divider_t adc16_config_t::clockDivider

5.3.1.0.0.1.5 adc16_resolution_t adc16_config_t::resolution

5.3.1.0.0.1.6 adc16_long_sample_mode_t adc16_config_t::longSampleMode

5.3.1.0.0.1.7 bool adc16_config_t::enableHighSpeed

5.3.1.0.0.1.8 bool adc16_config_t::enableLowPower

5.3.1.0.0.1.9 bool adc16_config_t::enableContinuousConversion

5.3.2 struct adc16_hardware_compare_config_t

Data Fields

- adc16_hardware_compare_mode_t hardwareCompareMode
  Select the hardware compare mode.
- int16_t value1
  Setting value1 for hardware compare mode.
- int16_t value2
  Setting value2 for hardware compare mode.

5.3.2.0.0.2 Field Documentation

5.3.2.0.0.2.1 adc16_hardware_compare_mode_t adc16_hardware_compare_config_t::hardware-CompareMode

See "adc16_hardware_compare_mode_t".

5.3.2.0.0.2.2 int16_t adc16_hardware_compare_config_t::value1

5.3.2.0.0.2.3 int16_t adc16_hardware_compare_config_t::value2

5.3.3 struct adc16_channel_config_t

Data Fields

- uint32_t channelNumber
  Setting the conversion channel number.
- bool enableInterruptOnConversionCompleted

Generate an interrupt request once the conversion is completed.

5.3.3.0.0.3 Field Documentation

5.3.3.0.0.3.1 uint32_t adc16_channel_config_t::channelNumber

The available range is 0-31. See channel connection information for each chip in Reference Manual document.

5.3.3.0.0.3.2 bool adc16_channel_config_t::enableInterruptOnConversionCompleted

5.4 Macro Definition Documentation

5.4.1 #define FSL_ADC16_DRIVER_VERSION (MAKE_VERSION(2, 0, 0))

5.5 Enumeration Type Documentation

5.5.1 enum _adc16_channel_status_flags

Enumerator

kADC16_ChannelConversionDoneFlag Conversion done.

5.5.2 enum _adc16_status_flags

Enumerator

kADC16_ActiveFlag Converter is active.
kADC16_CalibrationFailedFlag Calibration is failed.

5.5.3 enum adc16_channel_mux_mode_t

For some ADC16 channels, there are two pin selections in channel multiplexer. For example, ADC0_SE4a and ADC0_SE4b are the different channels that share the same channel number.

Enumerator

kADC16_ChannelMuxA For channel with channel mux a.
kADC16_ChannelMuxB For channel with channel mux b.

5.5.4 enum adc16_clock_divider_t

Enumerator

kADC16_ClockDivider1 For divider 1 from the input clock to the module.

kADC16_ClockDivider2 For divider 2 from the input clock to the module.
kADC16_ClockDivider4 For divider 4 from the input clock to the module.
kADC16_ClockDivider8 For divider 8 from the input clock to the module.

5.5.5 enum adc16_resolution_t

Enumerator

kADC16_Resolution8or9Bit Single End 8-bit or Differential Sample 9-bit.
kADC16_Resolution12or13Bit Single End 12-bit or Differential Sample 13-bit.
kADC16_Resolution10or11Bit Single End 10-bit or Differential Sample 11-bit.
kADC16_ResolutionSE8Bit Single End 8-bit.
kADC16_ResolutionSE12Bit Single End 12-bit.
kADC16_ResolutionSE10Bit Single End 10-bit.

5.5.6 enum adc16_clock_source_t

Enumerator

kADC16_ClockSourceAlt0 Selection 0 of the clock source.
kADC16_ClockSourceAlt1 Selection 1 of the clock source.
kADC16_ClockSourceAlt2 Selection 2 of the clock source.
kADC16_ClockSourceAlt3 Selection 3 of the clock source.
kADC16_ClockSourceAsynchronousClock Using internal asynchronous clock.

5.5.7 enum adc16_long_sample_mode_t

Enumerator

kADC16_LongSampleCycle24 20 extra ADCK cycles, 24 ADCK cycles total.
kADC16_LongSampleCycle16 12 extra ADCK cycles, 16 ADCK cycles total.
kADC16_LongSampleCycle10 6 extra ADCK cycles, 10 ADCK cycles total.
kADC16_LongSampleCycle6 2 extra ADCK cycles, 6 ADCK cycles total.
kADC16_LongSampleDisabled Disable the long sample feature.

5.5.8 enum adc16_reference_voltage_source_t

Enumerator

kADC16_ReferenceVoltageSourceVref For external pins pair of VrefH and VrefL.
kADC16_ReferenceVoltageSourceValt For alternate reference pair of ValtH and ValtL.

5.5.9 enum adc16_hardware_average_mode_t

Enumerator

kADC16_HardwareAverageCount4 For hardware average with 4 samples.
kADC16_HardwareAverageCount8 For hardware average with 8 samples.
kADC16_HardwareAverageCount16 For hardware average with 16 samples.
kADC16_HardwareAverageCount32 For hardware average with 32 samples.
kADC16_HardwareAverageDisabled Disable the hardware average feature.

5.5.10 enum adc16_hardware_compare_mode_t

Enumerator

kADC16_HardwareCompareMode0 x < value1.
kADC16_HardwareCompareMode1 x > value1.
kADC16_HardwareCompareMode2 if value1 <= value2, then x < value1 || x > value2; else, value1 > x > value2.
kADC16_HardwareCompareMode3 if value1 <= value2, then value1 <= x <= value2; else x >= value1 || x <= value2.

5.6 Function Documentation

5.6.1 void ADC16_Init (ADC_Type * *base*, const adc16_config_t * *config*)

Parameters

base	ADC16 peripheral base address.
config	Pointer to configuration structure. See "adc16_config_t".

5.6.2 void ADC16_Deinit (ADC_Type * *base*)

Parameters

base	ADC16 peripheral base address.

5.6.3 void ADC16_GetDefaultConfig (adc16_config_t * *config*)

This function initializes the converter configuration structure with available settings. The default values are as follows.

```
*   config->referenceVoltageSource     = kADC16_ReferenceVoltageSourceVref
      ;
*   config->clockSource                = kADC16_ClockSourceAsynchronousClock
      ;
*   config->enableAsynchronousClock    = true;
*   config->clockDivider               = kADC16_ClockDivider8;
*   config->resolution                 = kADC16_ResolutionSE12Bit;
*   config->longSampleMode             = kADC16_LongSampleDisabled;
*   config->enableHighSpeed            = false;
*   config->enableLowPower             = false;
*   config->enableContinuousConversion = false;
*
```

Parameters

config	Pointer to the configuration structure.

5.6.4 status_t ADC16_DoAutoCalibration (ADC_Type * *base*)

This auto calibration helps to adjust the plus/minus side gain automatically. Execute the calibration before using the converter. Note that the hardware trigger should be used during the calibration.

Parameters

base	ADC16 peripheral base address.

Returns

Execution status.

Return values

kStatus_Success	Calibration is done successfully.
kStatus_Fail	Calibration has failed.

5.6.5 static void ADC16_SetOffsetValue (ADC_Type * *base,* int16_t *value*) [inline], [static]

This offset value takes effect on the conversion result. If the offset value is not zero, the reading result is subtracted by it. Note, the hardware calibration fills the offset value automatically.

Parameters

base	ADC16 peripheral base address.
value	Setting offset value.

5.6.6 static void ADC16_EnableHardwareTrigger (ADC_Type ∗ *base,* bool *enable*) [inline], [static]

Parameters

base	ADC16 peripheral base address.
enable	Switcher of the hardware trigger feature. "true" means enabled, "false" means not enabled.

5.6.7 void ADC16_SetChannelMuxMode (ADC_Type ∗ *base,* adc16_channel_mux_mode_t *mode*)

Some sample pins share the same channel index. The channel mux mode decides which pin is used for an indicated channel.

Parameters

base	ADC16 peripheral base address.
mode	Setting channel mux mode. See "adc16_channel_mux_mode_t".

5.6.8 void ADC16_SetHardwareCompareConfig (ADC_Type ∗ *base,* const adc16_hardware_compare_config_t ∗ *config*)

The hardware compare mode provides a way to process the conversion result automatically by using hardware. Only the result in the compare range is available. To compare the range, see "adc16_hardware-_compare_mode_t" or the appopriate reference manual for more information.

Parameters

base	ADC16 peripheral base address.
config	Pointer to the "adc16_hardware_compare_config_t" structure. Passing "NULL" disables the feature.

5.6.9 void ADC16_SetHardwareAverage (ADC_Type ∗ *base*, adc16_hardware_average_mode_t *mode*)

The hardware average mode provides a way to process the conversion result automatically by using hardware. The multiple conversion results are accumulated and averaged internally making them easier to read.

Parameters

base	ADC16 peripheral base address.
mode	Setting the hardware average mode. See "adc16_hardware_average_mode_t".

5.6.10 uint32_t ADC16_GetStatusFlags (ADC_Type ∗ *base*)

Parameters

base	ADC16 peripheral base address.

Returns

Flags' mask if indicated flags are asserted. See "_adc16_status_flags".

5.6.11 void ADC16_ClearStatusFlags (ADC_Type ∗ *base*, uint32_t *mask*)

Parameters

base	ADC16 peripheral base address.
mask	Mask value for the cleared flags. See "_adc16_status_flags".

5.6.12 void ADC16_SetChannelConfig (ADC_Type ∗ *base*, uint32_t *channelGroup*, const adc16_channel_config_t ∗ *config*)

This operation triggers the conversion when in software trigger mode. When in hardware trigger mode, this API configures the channel while the external trigger source helps to trigger the conversion.

Note that the "Channel Group" has a detailed description. To allow sequential conversions of the ADC to be triggered by internal peripherals, the ADC has more than one group of status and control registers, one for each conversion. The channel group parameter indicates which group of registers are used, for example, channel group 0 is for Group A registers and channel group 1 is for Group B registers. The channel groups are used in a "ping-pong" approach to control the ADC operation. At any point, only one of the channel groups is actively controlling ADC conversions. The channel group 0 is used for both software and hardware trigger modes. Channel group 1 and greater indicates multiple channel group registers for use only in hardware trigger mode. See the chip configuration information in the appropriate MCU reference manual for the number of SC1n registers (channel groups) specific to this device. Channel group 1 or greater are not used for software trigger operation. Therefore, writing to these channel groups does not initiate a new conversion. Updating the channel group 0 while a different channel group is actively controlling a conversion is allowed and vice versa. Writing any of the channel group registers while that specific channel group is actively controlling a conversion aborts the current conversion.

Parameters

base	ADC16 peripheral base address.
channelGroup	Channel group index.
config	Pointer to the "adc16_channel_config_t" structure for the conversion channel.

5.6.13 static uint32_t ADC16_GetChannelConversionValue (ADC_Type ∗ *base*, uint32_t *channelGroup*) [inline], [static]

Parameters

base	ADC16 peripheral base address.
channelGroup	Channel group index.

Returns

Conversion value.

5.6.14 uint32_t ADC16_GetChannelStatusFlags (ADC_Type ∗ *base*, uint32_t *channelGroup*)

Parameters

base	ADC16 peripheral base address.
channelGroup	Channel group index.

Returns

Flags' mask if indicated flags are asserted. See "_adc16_channel_status_flags".

Chapter 6
CMP: Analog Comparator Driver

6.1 Overview

The MCUXpresso SDK provides a peripheral driver for the Analog Comparator (CMP) module of MCUXpresso SDK devices.

The CMP driver is a basic comparator with advanced features. The APIs for the basic comparator enable the CMP to compare the two voltages of the two input channels and create the output of the comparator result. The APIs for advanced features can be used as the plug-in functions based on the basic comparator. They can process the comparator's output with hardware support.

6.2 Typical use case

6.2.1 Polling Configuration

```
int main(void)
{
    cmp_config_t mCmpConfigStruct;
    cmp_dac_config_t mCmpDacConfigStruct;

    // ...

    // Configures the comparator.
    CMP_Init(DEMO_CMP_INSTANCE);
    CMP_GetDefaultConfig(&mCmpConfigStruct);
    CMP_Configure(DEMO_CMP_INSTANCE, &mCmpConfigStruct);

    // Configures the DAC channel.
    mCmpDacConfigStruct.referenceVoltageSource =
      kCMP_VrefSourceVin2; // VCC.
    mCmpDacConfigStruct.DACValue = 32U; // Half voltage of logic high-level.
    CMP_SetDACConfig(DEMO_CMP_INSTANCE, &mCmpDacConfigStruct);
    CMP_SetInputChannels(DEMO_CMP_INSTANCE, DEMO_CMP_USER_CHANNEL, DEMO_CMP_DAC_CHANNEL
      );

    while (1)
    {
        if (0U != (kCMP_OutputAssertEventFlag &
      CMP_GetStatusFlags(DEMO_CMP_INSTANCE)))
        {
            // Do something.
        }
        else
        {
            // Do something.
        }
    }
}
```

6.2.2 Interrupt Configuration

```
volatile uint32_t g_CmpFlags = 0U;

// ...

void DEMO_CMP_IRQ_HANDLER_FUNC(void)
{
    g_CmpFlags = CMP_GetStatusFlags(DEMO_CMP_INSTANCE);
    CMP_ClearStatusFlags(DEMO_CMP_INSTANCE, kCMP_OutputRisingEventFlag |
      kCMP_OutputFallingEventFlag);
    if (0U != (g_CmpFlags & kCMP_OutputRisingEventFlag))
    {
        // Do something.
    }
    else if (0U != (g_CmpFlags & kCMP_OutputFallingEventFlag))
    {
        // Do something.
    }
}

int main(void)
{
    cmp_config_t mCmpConfigStruct;
    cmp_dac_config_t mCmpDacConfigStruct;

    // ...
    EnableIRQ(DEMO_CMP_IRQ_ID);
    // ...

    // Configures the comparator.
    CMP_Init(DEMO_CMP_INSTANCE);
    CMP_GetDefaultConfig(&mCmpConfigStruct);
    CMP_Configure(DEMO_CMP_INSTANCE, &mCmpConfigStruct);

    // Configures the DAC channel.
    mCmpDacConfigStruct.referenceVoltageSource =
      kCMP_VrefSourceVin2; // VCC.
    mCmpDacConfigStruct.DACValue = 32U; // Half voltage of logic high-level.
    CMP_SetDACConfig(DEMO_CMP_INSTANCE, &mCmpDacConfigStruct);
    CMP_SetInputChannels(DEMO_CMP_INSTANCE, DEMO_CMP_USER_CHANNEL, DEMO_CMP_DAC_CHANNEL
      );

    // Enables the output rising and falling interrupts.
    CMP_EnableInterrupts(DEMO_CMP_INSTANCE,
      kCMP_OutputRisingInterruptEnable |
      kCMP_OutputFallingInterruptEnable);

    while (1)
    {
    }
}
```

Data Structures

- struct cmp_config_t
  Configures the comparator. More...
- struct cmp_filter_config_t
  Configures the filter. More...
- struct cmp_dac_config_t
  Configures the internal DAC. More...

Enumerations

- enum _cmp_interrupt_enable {
  kCMP_OutputRisingInterruptEnable = CMP_SCR_IER_MASK,
  kCMP_OutputFallingInterruptEnable = CMP_SCR_IEF_MASK }
  Interrupt enable/disable mask.
- enum _cmp_status_flags {
  kCMP_OutputRisingEventFlag = CMP_SCR_CFR_MASK,
  kCMP_OutputFallingEventFlag = CMP_SCR_CFF_MASK,
  kCMP_OutputAssertEventFlag = CMP_SCR_COUT_MASK }
  Status flags' mask.
- enum cmp_hysteresis_mode_t {
  kCMP_HysteresisLevel0 = 0U,
  kCMP_HysteresisLevel1 = 1U,
  kCMP_HysteresisLevel2 = 2U,
  kCMP_HysteresisLevel3 = 3U }
  CMP Hysteresis mode.
- enum cmp_reference_voltage_source_t {
  kCMP_VrefSourceVin1 = 0U,
  kCMP_VrefSourceVin2 = 1U }
  CMP Voltage Reference source.

Driver version

- #define FSL_CMP_DRIVER_VERSION (MAKE_VERSION(2, 0, 0))
  CMP driver version 2.0.0.

Initialization

- void CMP_Init (CMP_Type ∗base, const cmp_config_t ∗config)
  Initializes the CMP.
- void CMP_Deinit (CMP_Type ∗base)
  De-initializes the CMP module.
- static void CMP_Enable (CMP_Type ∗base, bool enable)
  Enables/disables the CMP module.
- void CMP_GetDefaultConfig (cmp_config_t ∗config)
  Initializes the CMP user configuration structure.
- void CMP_SetInputChannels (CMP_Type ∗base, uint8_t positiveChannel, uint8_t negativeChannel)
  Sets the input channels for the comparator.

Advanced Features

- void CMP_SetFilterConfig (CMP_Type ∗base, const cmp_filter_config_t ∗config)
  Configures the filter.
- void CMP_SetDACConfig (CMP_Type ∗base, const cmp_dac_config_t ∗config)
  Configures the internal DAC.
- void CMP_EnableInterrupts (CMP_Type ∗base, uint32_t mask)
  Enables the interrupts.
- void CMP_DisableInterrupts (CMP_Type ∗base, uint32_t mask)
  Disables the interrupts.

Results

- uint32_t CMP_GetStatusFlags (CMP_Type *base)
  Gets the status flags.
- void CMP_ClearStatusFlags (CMP_Type *base, uint32_t mask)
  Clears the status flags.

6.3 Data Structure Documentation

6.3.1 struct cmp_config_t

Data Fields

- bool enableCmp
  Enable the CMP module.
- cmp_hysteresis_mode_t hysteresisMode
  CMP Hysteresis mode.
- bool enableHighSpeed
  Enable High-speed (HS) comparison mode.
- bool enableInvertOutput
  Enable the inverted comparator output.
- bool useUnfilteredOutput
  Set the compare output(COUT) to equal COUTA(true) or COUT(false).
- bool enablePinOut
  The comparator output is available on the associated pin.
- bool enableTriggerMode
  Enable the trigger mode.

6.3.1.0.0.4 Field Documentation

6.3.1.0.0.4.1 bool cmp_config_t::enableCmp

6.3.1.0.0.4.2 cmp_hysteresis_mode_t cmp_config_t::hysteresisMode

6.3.1.0.0.4.3 bool cmp_config_t::enableHighSpeed

6.3.1.0.0.4.4 bool cmp_config_t::enableInvertOutput

6.3.1.0.0.4.5 bool cmp_config_t::useUnfilteredOutput

6.3.1.0.0.4.6 bool cmp_config_t::enablePinOut

6.3.1.0.0.4.7 bool cmp_config_t::enableTriggerMode

6.3.2 struct cmp_filter_config_t

Data Fields

- uint8_t filterCount
  Filter Sample Count.

- uint8_t filterPeriod
  Filter Sample Period.

6.3.2.0.0.5 Field Documentation

6.3.2.0.0.5.1 uint8_t cmp_filter_config_t::filterCount

Available range is 1-7; 0 disables the filter.

6.3.2.0.0.5.2 uint8_t cmp_filter_config_t::filterPeriod

The divider to the bus clock. Available range is 0-255.

6.3.3 struct cmp_dac_config_t

Data Fields

- cmp_reference_voltage_source_t referenceVoltageSource
  Supply voltage reference source.
- uint8_t DACValue
  Value for the DAC Output Voltage.

6.3.3.0.0.6 Field Documentation

6.3.3.0.0.6.1 cmp_reference_voltage_source_t cmp_dac_config_t::referenceVoltageSource

6.3.3.0.0.6.2 uint8_t cmp_dac_config_t::DACValue

Available range is 0-63.

6.4 Macro Definition Documentation

6.4.1 #define FSL_CMP_DRIVER_VERSION (MAKE_VERSION(2, 0, 0))

6.5 Enumeration Type Documentation

6.5.1 enum _cmp_interrupt_enable

Enumerator

kCMP_OutputRisingInterruptEnable Comparator interrupt enable rising.
kCMP_OutputFallingInterruptEnable Comparator interrupt enable falling.

6.5.2 enum _cmp_status_flags

Enumerator

kCMP_OutputRisingEventFlag Rising-edge on the comparison output has occurred.
kCMP_OutputFallingEventFlag Falling-edge on the comparison output has occurred.
kCMP_OutputAssertEventFlag Return the current value of the analog comparator output.

6.5.3 enum cmp_hysteresis_mode_t

Enumerator

kCMP_HysteresisLevel0 Hysteresis level 0.
kCMP_HysteresisLevel1 Hysteresis level 1.
kCMP_HysteresisLevel2 Hysteresis level 2.
kCMP_HysteresisLevel3 Hysteresis level 3.

6.5.4 enum cmp_reference_voltage_source_t

Enumerator

kCMP_VrefSourceVin1 Vin1 is selected as a resistor ladder network supply reference Vin.
kCMP_VrefSourceVin2 Vin2 is selected as a resistor ladder network supply reference Vin.

6.6 Function Documentation

6.6.1 void CMP_Init (CMP_Type * *base,* const cmp_config_t * *config*)

This function initializes the CMP module. The operations included are as follows.

- Enabling the clock for CMP module.
- Configuring the comparator.
- Enabling the CMP module. Note that for some devices, multiple CMP instances share the same clock gate. In this case, to enable the clock for any instance enables all CMPs. See the appropriate MCU reference manual for the clock assignment of the CMP.

Parameters

base	CMP peripheral base address.
config	Pointer to the configuration structure.

6.6.2 void CMP_Deinit (CMP_Type * *base*)

This function de-initializes the CMP module. The operations included are as follows.

- Disabling the CMP module.
- Disabling the clock for CMP module.

This function disables the clock for the CMP. Note that for some devices, multiple CMP instances share the same clock gate. In this case, before disabling the clock for the CMP, ensure that all the CMP instances are not used.

Parameters

base	CMP peripheral base address.

6.6.3 static void CMP_Enable (CMP_Type * *base*, bool *enable*) [inline], [static]

Parameters

base	CMP peripheral base address.
enable	Enables or disables the module.

6.6.4 void CMP_GetDefaultConfig (cmp_config_t * *config*)

This function initializes the user configuration structure to these default values.

```
*   config->enableCmp           = true;
*   config->hysteresisMode      = kCMP_HysteresisLevel0;
*   config->enableHighSpeed     = false;
*   config->enableInvertOutput  = false;
*   config->useUnfilteredOutput = false;
*   config->enablePinOut        = false;
*   config->enableTriggerMode   = false;
*
```

Parameters

config	Pointer to the configuration structure.

6.6.5 void CMP_SetInputChannels (CMP_Type ∗ *base,* uint8_t *positiveChannel,* uint8_t *negativeChannel*)

This function sets the input channels for the comparator. Note that two input channels cannot be set the same way in the application. When the user selects the same input from the analog mux to the positive and negative port, the comparator is disabled automatically.

Parameters

base	CMP peripheral base address.
positive-Channel	Positive side input channel number. Available range is 0-7.
negative-Channel	Negative side input channel number. Available range is 0-7.

6.6.6 void CMP_SetFilterConfig (CMP_Type ∗ *base,* const cmp_filter_config_t ∗ *config*)

Parameters

base	CMP peripheral base address.
config	Pointer to the configuration structure.

6.6.7 void CMP_SetDACConfig (CMP_Type ∗ *base,* const cmp_dac_config_t ∗ *config*)

Parameters

base	CMP peripheral base address.

config	Pointer to the configuration structure. "NULL" disables the feature.

6.6.8 void CMP_EnableInterrupts (CMP_Type ∗ *base,* uint32_t *mask*)

Parameters

base	CMP peripheral base address.
mask	Mask value for interrupts. See "_cmp_interrupt_enable".

6.6.9 void CMP_DisableInterrupts (CMP_Type ∗ *base,* uint32_t *mask*)

Parameters

base	CMP peripheral base address.
mask	Mask value for interrupts. See "_cmp_interrupt_enable".

6.6.10 uint32_t CMP_GetStatusFlags (CMP_Type ∗ *base*)

Parameters

base	CMP peripheral base address.

Returns

Mask value for the asserted flags. See "_cmp_status_flags".

6.6.11 void CMP_ClearStatusFlags (CMP_Type ∗ *base,* uint32_t *mask*)

Parameters

base	CMP peripheral base address.
mask	Mask value for the flags. See "_cmp_status_flags".

Chapter 7
COP: Watchdog Driver

7.1 Overview

The MCUXpresso SDK provides a peripheral driver for the Computer Operating Properly module (COP) of MCUXpresso SDK devices.

7.2 Typical use case

```
cop_config_t config;
COP_GetDefaultConfig(&config);
config.timeoutCycles = kCOP_2Power8CyclesOr2Power16Cycles;
COP_Init(sim_base,&config);
```

Data Structures

- struct cop_config_t
  Describes COP configuration structure. More...

Enumerations

- enum cop_clock_source_t {
  kCOP_LpoClock = 0U,
  kCOP_McgIrClock = 1U,
  kCOP_OscErClock = 2U,
  kCOP_BusClock = 3U }
  COP clock source selection.
- enum cop_timeout_cycles_t {
  kCOP_2Power5CyclesOr2Power13Cycles = 1U,
  kCOP_2Power8CyclesOr2Power16Cycles = 2U,
  kCOP_2Power10CyclesOr2Power18Cycles = 3U }
  Define the COP timeout cycles.
- enum cop_timeout_mode_t {
  kCOP_ShortTimeoutMode = 0U,
  kCOP_LongTimeoutMode = 1U }
  Define the COP timeout mode.

Driver version

- #define FSL_COP_DRIVER_VERSION (MAKE_VERSION(2, 0, 0))
  COP driver version 2.0.0.

COP refresh sequence.

- #define COP_FIRST_BYTE_OF_REFRESH (0x55U)

First byte of refresh sequence.
- #define COP_SECOND_BYTE_OF_REFRESH (0xAAU)
  Second byte of refresh sequence.

COP Functional Operation

- void COP_GetDefaultConfig (cop_config_t ∗config)
  Initializes the COP configuration structure.
- void COP_Init (SIM_Type ∗base, const cop_config_t ∗config)
  Initializes the COP module.
- static void COP_Disable (SIM_Type ∗base)
  De-initializes the COP module.
- void COP_Refresh (SIM_Type ∗base)
  Refreshes the COP timer.

7.3 Data Structure Documentation

7.3.1 struct cop_config_t

Data Fields

- bool enableWindowMode
  COP run mode: window mode or normal mode.
- cop_timeout_mode_t timeoutMode
  COP timeout mode: long timeout or short timeout.
- bool enableStop
  Enable or disable COP in STOP mode.
- bool enableDebug
  Enable or disable COP in DEBUG mode.
- cop_clock_source_t clockSource
  Set COP clock source.
- cop_timeout_cycles_t timeoutCycles
  Set COP timeout value.

7.4 Macro Definition Documentation

7.4.1 #define FSL_COP_DRIVER_VERSION (MAKE_VERSION(2, 0, 0))

7.5 Enumeration Type Documentation

7.5.1 enum cop_clock_source_t

Enumerator

kCOP_LpoClock COP clock sourced from LPO.
kCOP_McgIrClock COP clock sourced from MCGIRCLK.
kCOP_OscErClock COP clock sourced from OSCERCLK.
kCOP_BusClock COP clock sourced from Bus clock.

7.5.2 enum cop_timeout_cycles_t

Enumerator

kCOP_2Power5CyclesOr2Power13Cycles 2^5 or 2^13 clock cycles
kCOP_2Power8CyclesOr2Power16Cycles 2^8 or 2^16 clock cycles
kCOP_2Power10CyclesOr2Power18Cycles 2^10 or 2^18 clock cycles

7.5.3 enum cop_timeout_mode_t

Enumerator

kCOP_ShortTimeoutMode COP selects long timeout.
kCOP_LongTimeoutMode COP selects short timeout.

7.6 Function Documentation

7.6.1 void COP_GetDefaultConfig (cop_config_t * *config*)

This function initializes the COP configuration structure to default values. The default values are:

```
*   copConfig->enableWindowMode = false;
*   copConfig->timeoutMode = kCOP_LongTimeoutMode;
*   copConfig->enableStop = false;
*   copConfig->enableDebug = false;
*   copConfig->clockSource = kCOP_LpoClock;
*   copConfig->timeoutCycles = kCOP_2Power10CyclesOr2Power18Cycles;
*
```

Parameters

config	Pointer to the COP configuration structure.

See Also

cop_config_t

7.6.2 void COP_Init (SIM_Type * *base,* const cop_config_t * *config*)

This function configures the COP. After it is called, the COP starts running according to the configuration. Because all COP control registers are write-once only, the COP_Init function and the COP_Disable function can be called only once. A second call has no effect.

Example:

```
*   cop_config_t config;
*   COP_GetDefaultConfig(&config);
*   config.timeoutCycles = kCOP_2Power8CyclesOr2Power16Cycles
      ;
*   COP_Init(sim_base,&config);
*
```

Parameters

base	SIM peripheral base address.
config	The configuration of COP.

7.6.3 static void COP_Disable (SIM_Type * *base*) [inline], [static]

This dedicated function is not provided. Instead, the COP_Disable function can be used to disable the COP.

Disables the COP module.

This function disables the COP Watchdog. Note: The COP configuration register is a write-once after reset. To disable the COP Watchdog, call this function first.

Parameters

base	SIM peripheral base address.

7.6.4 void COP_Refresh (SIM_Type * *base*)

This function feeds the COP.

Parameters

base	SIM peripheral base address.

Chapter 8
C90TFS Flash Driver

8.1 Overview

The flash provides the C90TFS Flash driver of MCUXpresso SDK devices with the C90TFS Flash module inside. The flash driver provides general APIs to handle specific operations on C90TFS/FTFx Flash module. The user can use those APIs directly in the application. In addition, it provides internal functions called by the driver. Although these functions are not meant to be called from the user's application directly, the APIs can still be used.

Data Structures

- struct flash_execute_in_ram_function_config_t
  Flash execute-in-RAM function information. More...
- struct flash_swap_state_config_t
  Flash Swap information. More...
- struct flash_swap_ifr_field_config_t
  Flash Swap IFR fields. More...
- union flash_swap_ifr_field_data_t
  Flash Swap IFR field data. More...
- union pflash_protection_status_low_t
  PFlash protection status - low 32bit. More...
- struct pflash_protection_status_t
  PFlash protection status - full. More...
- struct flash_prefetch_speculation_status_t
  Flash prefetch speculation status. More...
- struct flash_protection_config_t
  Active flash protection information for the current operation. More...
- struct flash_access_config_t
  Active flash Execute-Only access information for the current operation. More...
- struct flash_operation_config_t
  Active flash information for the current operation. More...
- struct flash_config_t
  Flash driver state information. More...

Typedefs

- typedef void(∗ flash_callback_t)(void)
  A callback type used for the Pflash block.

Enumerations

- enum flash_margin_value_t {
  kFLASH_MarginValueNormal,
  kFLASH_MarginValueUser,
  kFLASH_MarginValueFactory,

kFLASH_MarginValueInvalid }
Enumeration for supported flash margin levels.
- enum flash_security_state_t {
kFLASH_SecurityStateNotSecure,
kFLASH_SecurityStateBackdoorEnabled,
kFLASH_SecurityStateBackdoorDisabled }
Enumeration for the three possible flash security states.
- enum flash_protection_state_t {
kFLASH_ProtectionStateUnprotected,
kFLASH_ProtectionStateProtected,
kFLASH_ProtectionStateMixed }
Enumeration for the three possible flash protection levels.
- enum flash_execute_only_access_state_t {
kFLASH_AccessStateUnLimited,
kFLASH_AccessStateExecuteOnly,
kFLASH_AccessStateMixed }
Enumeration for the three possible flash execute access levels.
- enum flash_property_tag_t {
kFLASH_PropertyPflashSectorSize = 0x00U,
kFLASH_PropertyPflashTotalSize = 0x01U,
kFLASH_PropertyPflashBlockSize = 0x02U,
kFLASH_PropertyPflashBlockCount = 0x03U,
kFLASH_PropertyPflashBlockBaseAddr = 0x04U,
kFLASH_PropertyPflashFacSupport = 0x05U,
kFLASH_PropertyPflashAccessSegmentSize = 0x06U,
kFLASH_PropertyPflashAccessSegmentCount = 0x07U,
kFLASH_PropertyFlexRamBlockBaseAddr = 0x08U,
kFLASH_PropertyFlexRamTotalSize = 0x09U,
kFLASH_PropertyDflashSectorSize = 0x10U,
kFLASH_PropertyDflashTotalSize = 0x11U,
kFLASH_PropertyDflashBlockSize = 0x12U,
kFLASH_PropertyDflashBlockCount = 0x13U,
kFLASH_PropertyDflashBlockBaseAddr = 0x14U,
kFLASH_PropertyEepromTotalSize = 0x15U,
kFLASH_PropertyFlashMemoryIndex = 0x20U,
kFLASH_PropertyFlashCacheControllerIndex = 0x21U }
Enumeration for various flash properties.
- enum _flash_execute_in_ram_function_constants {
kFLASH_ExecuteInRamFunctionMaxSizeInWords = 16U,
kFLASH_ExecuteInRamFunctionTotalNum = 2U }
Constants for execute-in-RAM flash function.
- enum flash_read_resource_option_t {
kFLASH_ResourceOptionFlashIfr,
kFLASH_ResourceOptionVersionId = 0x01U }
Enumeration for the two possible options of flash read resource command.
- enum _flash_read_resource_range {

kFLASH_ResourceRangePflashIfrSizeInBytes = 256U,
kFLASH_ResourceRangeVersionIdSizeInBytes = 8U,
kFLASH_ResourceRangeVersionIdStart = 0x00U,
kFLASH_ResourceRangeVersionIdEnd = 0x07U ,
kFLASH_ResourceRangePflashSwapIfrEnd,
kFLASH_ResourceRangeDflashIfrStart = 0x800000U,
kFLASH_ResourceRangeDflashIfrEnd = 0x8003FFU }
Enumeration for the range of special-purpose flash resource.
- enum _k3_flash_read_once_index {
kFLASH_RecordIndexSwapAddr = 0xA1U,
kFLASH_RecordIndexSwapEnable = 0xA2U,
kFLASH_RecordIndexSwapDisable = 0xA3U }
Enumeration for the index of read/program once record.
- enum flash_flexram_function_option_t {
kFLASH_FlexramFunctionOptionAvailableAsRam = 0xFFU,
kFLASH_FlexramFunctionOptionAvailableForEeprom = 0x00U }
Enumeration for the two possilbe options of set FlexRAM function command.
- enum _flash_acceleration_ram_property
Enumeration for acceleration RAM property.
- enum flash_swap_function_option_t {
kFLASH_SwapFunctionOptionEnable = 0x00U,
kFLASH_SwapFunctionOptionDisable = 0x01U }
Enumeration for the possible options of Swap function.
- enum flash_swap_control_option_t {
kFLASH_SwapControlOptionIntializeSystem = 0x01U,
kFLASH_SwapControlOptionSetInUpdateState = 0x02U,
kFLASH_SwapControlOptionSetInCompleteState = 0x04U,
kFLASH_SwapControlOptionReportStatus = 0x08U,
kFLASH_SwapControlOptionDisableSystem = 0x10U }
Enumeration for the possible options of Swap control commands.
- enum flash_swap_state_t {
kFLASH_SwapStateUninitialized = 0x00U,
kFLASH_SwapStateReady = 0x01U,
kFLASH_SwapStateUpdate = 0x02U,
kFLASH_SwapStateUpdateErased = 0x03U,
kFLASH_SwapStateComplete = 0x04U,
kFLASH_SwapStateDisabled = 0x05U }
Enumeration for the possible flash Swap status.
- enum flash_swap_block_status_t {
kFLASH_SwapBlockStatusLowerHalfProgramBlocksAtZero,
kFLASH_SwapBlockStatusUpperHalfProgramBlocksAtZero }
Enumeration for the possible flash Swap block status
- enum flash_partition_flexram_load_option_t {
kFLASH_PartitionFlexramLoadOptionLoadedWithValidEepromData,
kFLASH_PartitionFlexramLoadOptionNotLoaded = 0x01U }
Enumeration for the FlexRAM load during reset option.
- enum flash_memory_index_t {

kFLASH_MemoryIndexPrimaryFlash = 0x00U,
kFLASH_MemoryIndexSecondaryFlash = 0x01U }
Enumeration for the flash memory index.
- enum flash_cache_controller_index_t {
kFLASH_CacheControllerIndexForCore0 = 0x00U,
kFLASH_CacheControllerIndexForCore1 = 0x01U }
Enumeration for the flash cache controller index.
- enum flash_prefetch_speculation_option_t
Enumeration for the two possible options of flash prefetch speculation.
- enum flash_cache_clear_process_t {
kFLASH_CacheClearProcessPre = 0x00U,
kFLASH_CacheClearProcessPost = 0x01U }
Flash cache clear process code.

Flash version

- enum _flash_driver_version_constants {
kFLASH_DriverVersionName = 'F',
kFLASH_DriverVersionMajor = 2,
kFLASH_DriverVersionMinor = 3,
kFLASH_DriverVersionBugfix = 1 }
Flash driver version for ROM.
- #define MAKE_VERSION(major, minor, bugfix) (((major) << 16) | ((minor) << 8) | (bugfix))
Constructs the version number for drivers.
- #define FSL_FLASH_DRIVER_VERSION (MAKE_VERSION(2, 3, 1))
Flash driver version for SDK.

Flash configuration

- #define FLASH_SSD_CONFIG_ENABLE_FLEXNVM_SUPPORT 1
Indicates whether to support FlexNVM in the Flash driver.
- #define FLASH_SSD_IS_FLEXNVM_ENABLED (FLASH_SSD_CONFIG_ENABLE_FLEXNVM_SUPPORT && FSL_FEATURE_FLASH_HAS_FLEX_NVM)
Indicates whether the FlexNVM is enabled in the Flash driver.
- #define FLASH_SSD_CONFIG_ENABLE_SECONDARY_FLASH_SUPPORT 1
Indicates whether to support Secondary flash in the Flash driver.
- #define FLASH_SSD_IS_SECONDARY_FLASH_ENABLED (0)
Indicates whether the secondary flash is supported in the Flash driver.
- #define FLASH_DRIVER_IS_FLASH_RESIDENT 1
Flash driver location.
- #define FLASH_DRIVER_IS_EXPORTED 0
Flash Driver Export option.

Flash status

- enum _flash_status {
kStatus_FLASH_Success = MAKE_STATUS(kStatusGroupGeneric, 0),
kStatus_FLASH_InvalidArgument = MAKE_STATUS(kStatusGroupGeneric, 4),
kStatus_FLASH_SizeError = MAKE_STATUS(kStatusGroupFlashDriver, 0),
kStatus_FLASH_AlignmentError,
kStatus_FLASH_AddressError = MAKE_STATUS(kStatusGroupFlashDriver, 2),
kStatus_FLASH_AccessError,
kStatus_FLASH_ProtectionViolation,
kStatus_FLASH_CommandFailure,
kStatus_FLASH_UnknownProperty = MAKE_STATUS(kStatusGroupFlashDriver, 6),
kStatus_FLASH_EraseKeyError = MAKE_STATUS(kStatusGroupFlashDriver, 7),
kStatus_FLASH_RegionExecuteOnly,
kStatus_FLASH_ExecuteInRamFunctionNotReady,
kStatus_FLASH_PartitionStatusUpdateFailure,
kStatus_FLASH_SetFlexramAsEepromError,
kStatus_FLASH_RecoverFlexramAsRamError,
kStatus_FLASH_SetFlexramAsRamError = MAKE_STATUS(kStatusGroupFlashDriver, 13),
kStatus_FLASH_RecoverFlexramAsEepromError,
kStatus_FLASH_CommandNotSupported = MAKE_STATUS(kStatusGroupFlashDriver, 15),
kStatus_FLASH_SwapSystemNotInUninitialized,
kStatus_FLASH_SwapIndicatorAddressError,
kStatus_FLASH_ReadOnlyProperty = MAKE_STATUS(kStatusGroupFlashDriver, 18),
kStatus_FLASH_InvalidPropertyValue,
kStatus_FLASH_InvalidSpeculationOption }
Flash driver status codes.
- #define kStatusGroupGeneric 0
Flash driver status group.
- #define **kStatusGroupFlashDriver** 1
- #define MAKE_STATUS(group, code) ((((group)∗100) + (code)))
Constructs a status code value from a group and a code number.

Flash API key

- enum _flash_driver_api_keys { kFLASH_ApiEraseKey = FOUR_CHAR_CODE('k', 'f', 'e', 'k') }
Enumeration for Flash driver API keys.
- #define FOUR_CHAR_CODE(a, b, c, d) (((d) << 24) | ((c) << 16) | ((b) << 8) | ((a)))
Constructs the four character code for the Flash driver API key.

Initialization

- status_t FLASH_Init (flash_config_t ∗config)
Initializes the global flash properties structure members.
- status_t FLASH_SetCallback (flash_config_t ∗config, flash_callback_t callback)
Sets the desired flash callback function.
- status_t FLASH_PrepareExecuteInRamFunctions (flash_config_t ∗config)
Prepares flash execute-in-RAM functions.

Erasing

- status_t FLASH_EraseAll (flash_config_t *config, uint32_t key)
  Erases entire flash.
- status_t FLASH_Erase (flash_config_t *config, uint32_t start, uint32_t lengthInBytes, uint32_t key)
  Erases the flash sectors encompassed by parameters passed into function.
- status_t FLASH_EraseAllUnsecure (flash_config_t *config, uint32_t key)
  Erases the entire flash, including protected sectors.
- status_t FLASH_EraseAllExecuteOnlySegments (flash_config_t *config, uint32_t key)
  Erases all program flash execute-only segments defined by the FXACC registers.

Programming

- status_t FLASH_Program (flash_config_t *config, uint32_t start, uint32_t *src, uint32_t lengthInBytes)
  Programs flash with data at locations passed in through parameters.
- status_t FLASH_ProgramOnce (flash_config_t *config, uint32_t index, uint32_t *src, uint32_t lengthInBytes)
  Programs Program Once Field through parameters.

Reading

Programs flash with data at locations passed in through parameters via the Program Section command.

This function programs the flash memory with the desired data for a given flash area as determined by the start address and length.

Parameters

config	A pointer to the storage for the driver runtime state.
start	The start address of the desired flash memory to be programmed. Must be word-aligned.
src	A pointer to the source buffer of data that is to be programmed into the flash.
lengthInBytes	The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_InvalidArgument	An invalid argument is provided.

kStatus_FLASH_-AlignmentError	Parameter is not aligned with specified baseline.
kStatus_FLASH_Address-Error	Address is out of range.
kStatus_FLASH_Set-FlexramAsRamError	Failed to set flexram as RAM.
kStatus_FLASH_Execute-InRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_Access-Error	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_-ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_-CommandFailure	Run-time error during command execution.
kStatus_FLASH_Recover-FlexramAsEepromError	Failed to recover FlexRAM as EEPROM.

Programs the EEPROM with data at locations passed in through parameters.

This function programs the emulated EEPROM with the desired data for a given flash area as determined by the start address and length.

Parameters

config	A pointer to the storage for the driver runtime state.
start	The start address of the desired flash memory to be programmed. Must be word-aligned.
src	A pointer to the source buffer of data that is to be programmed into the flash.
lengthInBytes	The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.

kStatus_FLASH_Address-Error	Address is out of range.
kStatus_FLASH_Set-FlexramAsEepromError	Failed to set flexram as eeprom.
kStatus_FLASH_-ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_Recover-FlexramAsRamError	Failed to recover the FlexRAM as RAM.

- status_t FLASH_ReadResource (flash_config_t *config, uint32_t start, uint32_t *dst, uint32_t lengthInBytes, flash_read_resource_option_t option)
  Reads the resource with data at locations passed in through parameters.
- status_t FLASH_ReadOnce (flash_config_t *config, uint32_t index, uint32_t *dst, uint32_t lengthInBytes)
  Reads the Program Once Field through parameters.

Security

- status_t FLASH_GetSecurityState (flash_config_t *config, flash_security_state_t *state)
  Returns the security state via the pointer passed into the function.
- status_t FLASH_SecurityBypass (flash_config_t *config, const uint8_t *backdoorKey)
  Allows users to bypass security with a backdoor key.

Verification

- status_t FLASH_VerifyEraseAll (flash_config_t *config, flash_margin_value_t margin)
  Verifies erasure of the entire flash at a specified margin level.
- status_t FLASH_VerifyErase (flash_config_t *config, uint32_t start, uint32_t lengthInBytes, flash_margin_value_t margin)
  Verifies an erasure of the desired flash area at a specified margin level.
- status_t FLASH_VerifyProgram (flash_config_t *config, uint32_t start, uint32_t lengthInBytes, const uint32_t *expectedData, flash_margin_value_t margin, uint32_t *failedAddress, uint32_t *failedData)
  Verifies programming of the desired flash area at a specified margin level.
- status_t FLASH_VerifyEraseAllExecuteOnlySegments (flash_config_t *config, flash_margin_value_t margin)
  Verifies whether the program flash execute-only segments have been erased to the specified read margin level.

Protection

- status_t FLASH_IsProtected (flash_config_t *config, uint32_t start, uint32_t lengthInBytes, flash_protection_state_t *protection_state)
  Returns the protection state of the desired flash area via the pointer passed into the function.
- status_t FLASH_IsExecuteOnly (flash_config_t *config, uint32_t start, uint32_t lengthInBytes, flash_execute_only_access_state_t *access_state)
  Returns the access state of the desired flash area via the pointer passed into the function.

Properties

- status_t FLASH_GetProperty (flash_config_t *config, flash_property_tag_t whichProperty, uint32-_t *value)
  Returns the desired flash property.
- status_t FLASH_SetProperty (flash_config_t *config, flash_property_tag_t whichProperty, uint32_t value)
  Sets the desired flash property.

Flash Protection Utilities

Prepares the FlexNVM block for use as data flash, EEPROM backup, or a combination of both and initializes the FlexRAM.

Parameters

config	Pointer to storage for the driver runtime state.
option	The option used to set FlexRAM load behavior during reset.
eepromData-SizeCode	Determines the amount of FlexRAM used in each of the available EEPROM subsystems.
flexnvm-PartitionCode	Specifies how to split the FlexNVM block between data flash memory and EEPROM backup memory supporting EEPROM functions.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	Invalid argument is provided.
kStatus_FLASH_Execute-InRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_Access-Error	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_-ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_-CommandFailure	Run-time error during command execution.

- status_t FLASH_PflashSetProtection (flash_config_t *config, pflash_protection_status_t *protect-Status)
  Sets the PFlash Protection to the intended protection status.
- status_t FLASH_PflashGetProtection (flash_config_t *config, pflash_protection_status_t *protect-Status)
  Gets the PFlash protection status.

8.2 Data Structure Documentation

8.2.1 struct flash_execute_in_ram_function_config_t

Data Fields

- uint32_t activeFunctionCount
  Number of available execute-in-RAM functions.
- uint32_t ∗ flashRunCommand
  Execute-in-RAM function: flash_run_command.
- uint32_t ∗ flashCommonBitOperation
  Execute-in-RAM function: flash_common_bit_operation.

8.2.1.0.0.7 Field Documentation

8.2.1.0.0.7.1 uint32_t flash_execute_in_ram_function_config_t::activeFunctionCount

8.2.1.0.0.7.2 uint32_t∗ flash_execute_in_ram_function_config_t::flashRunCommand

8.2.1.0.0.7.3 uint32_t∗ flash_execute_in_ram_function_config_t::flashCommonBitOperation

8.2.2 struct flash_swap_state_config_t

Data Fields

- flash_swap_state_t flashSwapState
  The current Swap system status.
- flash_swap_block_status_t currentSwapBlockStatus
  The current Swap block status.
- flash_swap_block_status_t nextSwapBlockStatus
  The next Swap block status.

8.2.2.0.0.8 Field Documentation

8.2.2.0.0.8.1 flash_swap_state_t flash_swap_state_config_t::flashSwapState

8.2.2.0.0.8.2 flash_swap_block_status_t flash_swap_state_config_t::currentSwapBlockStatus

8.2.2.0.0.8.3 flash_swap_block_status_t flash_swap_state_config_t::nextSwapBlockStatus

8.2.3 struct flash_swap_ifr_field_config_t

Data Fields

- uint16_t swapIndicatorAddress
  A Swap indicator address field.
- uint16_t swapEnableWord
  A Swap enable word field.
- uint8_t reserved0 [4]

A reserved field.

8.2.3.0.0.9 Field Documentation

8.2.3.0.0.9.1 uint16_t flash_swap_ifr_field_config_t::swapIndicatorAddress

8.2.3.0.0.9.2 uint16_t flash_swap_ifr_field_config_t::swapEnableWord

8.2.3.0.0.9.3 uint8_t flash_swap_ifr_field_config_t::reserved0[4]

8.2.4 union flash_swap_ifr_field_data_t

Data Fields

- uint32_t flashSwapIfrData [2]
  A flash Swap IFR field data .
- flash_swap_ifr_field_config_t flashSwapIfrField
  A flash Swap IFR field structure.

8.2.4.0.0.10 Field Documentation

8.2.4.0.0.10.1 uint32_t flash_swap_ifr_field_data_t::flashSwapIfrData[2]

8.2.4.0.0.10.2 flash_swap_ifr_field_config_t flash_swap_ifr_field_data_t::flashSwapIfrField

8.2.5 union pflash_protection_status_low_t

Data Fields

- uint32_t protl32b
  PROT[31:0] .
- uint8_t protsl
  PROTS[7:0] .
- uint8_t protsh
  PROTS[15:8] .

8.2.5.0.0.11 Field Documentation

8.2.5.0.0.11.1 uint32_t pflash_protection_status_low_t::protl32b

8.2.5.0.0.11.2 uint8_t pflash_protection_status_low_t::protsl

8.2.5.0.0.11.3 uint8_t pflash_protection_status_low_t::protsh

8.2.6 struct pflash_protection_status_t

Data Fields

- pflash_protection_status_low_t valueLow32b
  PROT[31:0] or PROTS[15:0].

8.2.6.0.0.12 Field Documentation

8.2.6.0.0.12.1 pflash_protection_status_low_t pflash_protection_status_t::valueLow32b

8.2.7 struct flash_prefetch_speculation_status_t

Data Fields

- flash_prefetch_speculation_option_t instructionOption
  Instruction speculation.
- flash_prefetch_speculation_option_t dataOption
  Data speculation.

8.2.7.0.0.13 Field Documentation

8.2.7.0.0.13.1 flash_prefetch_speculation_option_t flash_prefetch_speculation_status_t::instructionOption

8.2.7.0.0.13.2 flash_prefetch_speculation_option_t flash_prefetch_speculation_status_t::dataOption

8.2.8 struct flash_protection_config_t

Data Fields

- uint32_t regionBase
  Base address of flash protection region.
- uint32_t regionSize
  size of flash protection region.
- uint32_t regionCount
  flash protection region count.

8.2.8.0.0.14 Field Documentation

8.2.8.0.0.14.1 uint32_t flash_protection_config_t::regionBase

8.2.8.0.0.14.2 uint32_t flash_protection_config_t::regionSize

8.2.8.0.0.14.3 uint32_t flash_protection_config_t::regionCount

8.2.9 struct flash_access_config_t

Data Fields

- uint32_t SegmentBase
  Base address of flash Execute-Only segment.
- uint32_t SegmentSize
  size of flash Execute-Only segment.
- uint32_t SegmentCount
  flash Execute-Only segment count.

8.2.9.0.0.15 Field Documentation

8.2.9.0.0.15.1 uint32_t flash_access_config_t::SegmentBase

8.2.9.0.0.15.2 uint32_t flash_access_config_t::SegmentSize

8.2.9.0.0.15.3 uint32_t flash_access_config_t::SegmentCount

8.2.10 struct flash_operation_config_t

Data Fields

- uint32_t convertedAddress
  A converted address for the current flash type.
- uint32_t activeSectorSize
  A sector size of the current flash type.
- uint32_t activeBlockSize
  A block size of the current flash type.
- uint32_t blockWriteUnitSize
  The write unit size.
- uint32_t sectorCmdAddressAligment
  An erase sector command address alignment.
- uint32_t partCmdAddressAligment
  A program/verify part command address alignment.
- 32_t resourceCmdAddressAligment
  A read resource command address alignment.
- uint32_t checkCmdAddressAligment
  A program check command address alignment.

8.2.10.0.0.16 Field Documentation

8.2.10.0.0.16.1 uint32_t flash_operation_config_t::convertedAddress

8.2.10.0.0.16.2 uint32_t flash_operation_config_t::activeSectorSize

8.2.10.0.0.16.3 uint32_t flash_operation_config_t::activeBlockSize

8.2.10.0.0.16.4 uint32_t flash_operation_config_t::blockWriteUnitSize

8.2.10.0.0.16.5 uint32_t flash_operation_config_t::sectorCmdAddressAligment

8.2.10.0.0.16.6 uint32_t flash_operation_config_t::partCmdAddressAligment

8.2.10.0.0.16.7 uint32_t flash_operation_config_t::resourceCmdAddressAligment

8.2.10.0.0.16.8 uint32_t flash_operation_config_t::checkCmdAddressAligment

8.2.11 struct flash_config_t

An instance of this structure is allocated by the user of the flash driver and passed into each of the driver APIs.

Data Fields

- uint32_t PFlashBlockBase
  A base address of the first PFlash block.
- uint32_t PFlashTotalSize
  The size of the combined PFlash block.
- uint8_t PFlashBlockCount
  A number of PFlash blocks.
- uint8_t FlashMemoryIndex
  0 - primary flash; 1 - secondary flash
- uint8_t FlashCacheControllerIndex
  0 - Controller for core 0; 1 - Controller for core 1
- uint8_t Reserved0
  Reserved field 0.
- uint32_t PFlashSectorSize
  The size in bytes of a sector of PFlash.
- flash_callback_t PFlashCallback
  The callback function for the flash API.
- uint32_t PFlashAccessSegmentSize
  A size in bytes of an access segment of PFlash.
- uint32_t PFlashAccessSegmentCount
  A number of PFlash access segments.
- uint32_t ∗ flashExecuteInRamFunctionInfo
  An information structure of the flash execute-in-RAM function.
- uint32_t FlexRAMBlockBase
  For the FlexNVM device, this is the base address of the FlexRAM.

- uint32_t FlexRAMTotalSize
  For the FlexNVM device, this is the size of the FlexRAM.
- uint32_t DFlashBlockBase
  For the FlexNVM device, this is the base address of the D-Flash memory (FlexNVM memory)
- uint32_t DFlashTotalSize
  For the FlexNVM device, this is the total size of the FlexNVM memory;.
- uint32_t EEpromTotalSize
  For the FlexNVM device, this is the size in bytes of the EEPROM area which was partitioned from FlexRAM.

8.2.11.0.0.17 Field Documentation

8.2.11.0.0.17.1 uint32_t flash_config_t::PFlashTotalSize

8.2.11.0.0.17.2 uint8_t flash_config_t::PFlashBlockCount

8.2.11.0.0.17.3 uint32_t flash_config_t::PFlashSectorSize

8.2.11.0.0.17.4 flash_callback_t flash_config_t::PFlashCallback

8.2.11.0.0.17.5 uint32_t flash_config_t::PFlashAccessSegmentSize

8.2.11.0.0.17.6 uint32_t flash_config_t::PFlashAccessSegmentCount

8.2.11.0.0.17.7 uint32_t* flash_config_t::flashExecuteInRamFunctionInfo

8.2.11.0.0.17.8 uint32_t flash_config_t::FlexRAMBlockBase

For the non-FlexNVM device, this is the base address of the acceleration RAM memory

8.2.11.0.0.17.9 uint32_t flash_config_t::FlexRAMTotalSize

For the non-FlexNVM device, this is the size of the acceleration RAM memory

8.2.11.0.0.17.10 uint32_t flash_config_t::DFlashBlockBase

For the non-FlexNVM device, this field is unused

8.2.11.0.0.17.11 uint32_t flash_config_t::DFlashTotalSize

For the non-FlexNVM device, this field is unused

8.2.11.0.0.17.12 uint32_t flash_config_t::EEpromTotalSize

For the non-FlexNVM device, this field is unused

8.3 Macro Definition Documentation

8.3.1 #define MAKE_VERSION(*major,* *minor,* *bugfix*) (((major) << 16) | ((minor) << 8) | (bugfix))

8.3.2 #define FSL_FLASH_DRIVER_VERSION (MAKE_VERSION(2, 3, 1))

Version 2.3.1.

8.3.3 #define FLASH_SSD_CONFIG_ENABLE_FLEXNVM_SUPPORT 1

Enables the FlexNVM support by default.

8.3.4 #define FLASH_SSD_CONFIG_ENABLE_SECONDARY_FLASH_SUPPORT 1

Enables the secondary flash support by default.

8.3.5 #define FLASH_DRIVER_IS_FLASH_RESIDENT 1

Used for the flash resident application.

8.3.6 #define FLASH_DRIVER_IS_EXPORTED 0

Used for the KSDK application.

8.3.7 #define kStatusGroupGeneric 0

8.3.8 #define MAKE_STATUS(*group,* *code*) ((((group)*100) + (code)))

8.3.9 #define FOUR_CHAR_CODE(*a,* *b,* *c,* *d*) (((d) << 24) | ((c) << 16) | ((b) << 8) | ((a)))

8.4 Enumeration Type Documentation

8.4.1 enum _flash_driver_version_constants

Enumerator

kFLASH_DriverVersionName Flash driver version name.

kFLASH_DriverVersionMajor Major flash driver version.
kFLASH_DriverVersionMinor Minor flash driver version.
kFLASH_DriverVersionBugfix Bugfix for flash driver version.

8.4.2 enum _flash_status

Enumerator

kStatus_FLASH_Success API is executed successfully.
kStatus_FLASH_InvalidArgument Invalid argument.
kStatus_FLASH_SizeError Error size.
kStatus_FLASH_AlignmentError Parameter is not aligned with the specified baseline.
kStatus_FLASH_AddressError Address is out of range.
kStatus_FLASH_AccessError Invalid instruction codes and out-of bound addresses.
kStatus_FLASH_ProtectionViolation The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_CommandFailure Run-time error during command execution.
kStatus_FLASH_UnknownProperty Unknown property.
kStatus_FLASH_EraseKeyError API erase key is invalid.
kStatus_FLASH_RegionExecuteOnly The current region is execute-only.
kStatus_FLASH_ExecuteInRamFunctionNotReady Execute-in-RAM function is not available.
kStatus_FLASH_PartitionStatusUpdateFailure Failed to update partition status.
kStatus_FLASH_SetFlexramAsEepromError Failed to set FlexRAM as EEPROM.
kStatus_FLASH_RecoverFlexramAsRamError Failed to recover FlexRAM as RAM.
kStatus_FLASH_SetFlexramAsRamError Failed to set FlexRAM as RAM.
kStatus_FLASH_RecoverFlexramAsEepromError Failed to recover FlexRAM as EEPROM.
kStatus_FLASH_CommandNotSupported Flash API is not supported.
kStatus_FLASH_SwapSystemNotInUninitialized Swap system is not in an uninitialzed state.
kStatus_FLASH_SwapIndicatorAddressError The swap indicator address is invalid.
kStatus_FLASH_ReadOnlyProperty The flash property is read-only.
kStatus_FLASH_InvalidPropertyValue The flash property value is out of range.
kStatus_FLASH_InvalidSpeculationOption The option of flash prefetch speculation is invalid.

8.4.3 enum _flash_driver_api_keys

Note

The resulting value is built with a byte order such that the string being readable in expected order when viewed in a hex editor, if the value is treated as a 32-bit little endian value.

Enumerator

kFLASH_ApiEraseKey Key value used to validate all flash erase APIs.

8.4.4 enum flash_margin_value_t

Enumerator

kFLASH_MarginValueNormal Use the 'normal' read level for 1s.
kFLASH_MarginValueUser Apply the 'User' margin to the normal read-1 level.
kFLASH_MarginValueFactory Apply the 'Factory' margin to the normal read-1 level.
kFLASH_MarginValueInvalid Not real margin level, Used to determine the range of valid margin level.

8.4.5 enum flash_security_state_t

Enumerator

kFLASH_SecurityStateNotSecure Flash is not secure.
kFLASH_SecurityStateBackdoorEnabled Flash backdoor is enabled.
kFLASH_SecurityStateBackdoorDisabled Flash backdoor is disabled.

8.4.6 enum flash_protection_state_t

Enumerator

kFLASH_ProtectionStateUnprotected Flash region is not protected.
kFLASH_ProtectionStateProtected Flash region is protected.
kFLASH_ProtectionStateMixed Flash is mixed with protected and unprotected region.

8.4.7 enum flash_execute_only_access_state_t

Enumerator

kFLASH_AccessStateUnLimited Flash region is unlimited.
kFLASH_AccessStateExecuteOnly Flash region is execute only.
kFLASH_AccessStateMixed Flash is mixed with unlimited and execute only region.

8.4.8 enum flash_property_tag_t

Enumerator

kFLASH_PropertyPflashSectorSize Pflash sector size property.
kFLASH_PropertyPflashTotalSize Pflash total size property.

kFLASH_PropertyPflashBlockSize Pflash block size property.
kFLASH_PropertyPflashBlockCount Pflash block count property.
kFLASH_PropertyPflashBlockBaseAddr Pflash block base address property.
kFLASH_PropertyPflashFacSupport Pflash fac support property.
kFLASH_PropertyPflashAccessSegmentSize Pflash access segment size property.
kFLASH_PropertyPflashAccessSegmentCount Pflash access segment count property.
kFLASH_PropertyFlexRamBlockBaseAddr FlexRam block base address property.
kFLASH_PropertyFlexRamTotalSize FlexRam total size property.
kFLASH_PropertyDflashSectorSize Dflash sector size property.
kFLASH_PropertyDflashTotalSize Dflash total size property.
kFLASH_PropertyDflashBlockSize Dflash block size property.
kFLASH_PropertyDflashBlockCount Dflash block count property.
kFLASH_PropertyDflashBlockBaseAddr Dflash block base address property.
kFLASH_PropertyEepromTotalSize EEPROM total size property.
kFLASH_PropertyFlashMemoryIndex Flash memory index property.
kFLASH_PropertyFlashCacheControllerIndex Flash cache controller index property.

8.4.9 enum _flash_execute_in_ram_function_constants

Enumerator

kFLASH_ExecuteInRamFunctionMaxSizeInWords The maximum size of execute-in-RAM function.
kFLASH_ExecuteInRamFunctionTotalNum Total number of execute-in-RAM functions.

8.4.10 enum flash_read_resource_option_t

Enumerator

kFLASH_ResourceOptionFlashIfr Select code for Program flash 0 IFR, Program flash swap 0 IFR, Data flash 0 IFR.
kFLASH_ResourceOptionVersionId Select code for the version ID.

8.4.11 enum _flash_read_resource_range

Enumerator

kFLASH_ResourceRangePflashIfrSizeInBytes Pflash IFR size in byte.
kFLASH_ResourceRangeVersionIdSizeInBytes Version ID IFR size in byte.
kFLASH_ResourceRangeVersionIdStart Version ID IFR start address.
kFLASH_ResourceRangeVersionIdEnd Version ID IFR end address.

kFLASH_ResourceRangePflashSwapIfrEnd Pflash swap IFR end address.
kFLASH_ResourceRangeDflashIfrStart Dflash IFR start address.
kFLASH_ResourceRangeDflashIfrEnd Dflash IFR end address.

8.4.12 enum _k3_flash_read_once_index

Enumerator

kFLASH_RecordIndexSwapAddr Index of Swap indicator address.
kFLASH_RecordIndexSwapEnable Index of Swap system enable.
kFLASH_RecordIndexSwapDisable Index of Swap system disable.

8.4.13 enum flash_flexram_function_option_t

Enumerator

kFLASH_FlexramFunctionOptionAvailableAsRam An option used to make FlexRAM available as RAM.
kFLASH_FlexramFunctionOptionAvailableForEeprom An option used to make FlexRAM available for EEPROM.

8.4.14 enum flash_swap_function_option_t

Enumerator

kFLASH_SwapFunctionOptionEnable An option used to enable the Swap function.
kFLASH_SwapFunctionOptionDisable An option used to disable the Swap function.

8.4.15 enum flash_swap_control_option_t

Enumerator

kFLASH_SwapControlOptionIntializeSystem An option used to initialize the Swap system.
kFLASH_SwapControlOptionSetInUpdateState An option used to set the Swap in an update state.

kFLASH_SwapControlOptionSetInCompleteState An option used to set the Swap in a complete state.
kFLASH_SwapControlOptionReportStatus An option used to report the Swap status.
kFLASH_SwapControlOptionDisableSystem An option used to disable the Swap status.

8.4.16 enum flash_swap_state_t

Enumerator

kFLASH_SwapStateUninitialized Flash Swap system is in an uninitialized state.
kFLASH_SwapStateReady Flash Swap system is in a ready state.
kFLASH_SwapStateUpdate Flash Swap system is in an update state.
kFLASH_SwapStateUpdateErased Flash Swap system is in an updateErased state.
kFLASH_SwapStateComplete Flash Swap system is in a complete state.
kFLASH_SwapStateDisabled Flash Swap system is in a disabled state.

8.4.17 enum flash_swap_block_status_t

Enumerator

kFLASH_SwapBlockStatusLowerHalfProgramBlocksAtZero Swap block status is that lower half program block at zero.
kFLASH_SwapBlockStatusUpperHalfProgramBlocksAtZero Swap block status is that upper half program block at zero.

8.4.18 enum flash_partition_flexram_load_option_t

Enumerator

kFLASH_PartitionFlexramLoadOptionLoadedWithValidEepromData FlexRAM is loaded with valid EEPROM data during reset sequence.
kFLASH_PartitionFlexramLoadOptionNotLoaded FlexRAM is not loaded during reset sequence.

8.4.19 enum flash_memory_index_t

Enumerator

kFLASH_MemoryIndexPrimaryFlash Current flash memory is primary flash.
kFLASH_MemoryIndexSecondaryFlash Current flash memory is secondary flash.

8.4.20 enum flash_cache_controller_index_t

Enumerator

kFLASH_CacheControllerIndexForCore0 Current flash cache controller is for core 0.
kFLASH_CacheControllerIndexForCore1 Current flash cache controller is for core 1.

8.4.21 enum flash_cache_clear_process_t

Enumerator

kFLASH_CacheClearProcessPre Pre flash cache clear process.
kFLASH_CacheClearProcessPost Post flash cache clear process.

8.5 Function Documentation

8.5.1 status_t FLASH_Init (flash_config_t * *config*)

This function checks and initializes the Flash module for the other Flash APIs.

Parameters

config	Pointer to the storage for the driver runtime state.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_InvalidArgument	An invalid argument is provided.
kStatus_FLASH_ExecuteInRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_PartitionStatusUpdateFailure	Failed to update the partition status.

8.5.2 status_t FLASH_SetCallback (flash_config_t * *config*, flash_callback_t *callback*)

Parameters

config	Pointer to the storage for the driver runtime state.
callback	A callback function to be stored in the driver.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.

8.5.3 status_t FLASH_PrepareExecuteInRamFunctions (flash_config_t * *config*)

Parameters

config	Pointer to the storage for the driver runtime state.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.

8.5.4 status_t FLASH_EraseAll (flash_config_t * *config*, uint32_t *key*)

Parameters

config	Pointer to the storage for the driver runtime state.
key	A value used to validate all flash erase APIs.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.
kStatus_FLASH_Erase-KeyError	API erase key is invalid.
kStatus_FLASH_Execute-InRamFunctionNotReady	Execute-in-RAM function is not available.

kStatus_FLASH_Access-Error	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_-ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_-CommandFailure	Run-time error during command execution.
kStatus_FLASH_-PartitionStatusUpdate-Failure	Failed to update the partition status.

8.5.5 status_t FLASH_Erase (flash_config_t ∗ *config*, uint32_t *start*, uint32_t *lengthInBytes*, uint32_t *key*)

This function erases the appropriate number of flash sectors based on the desired start address and length.

Parameters

config	The pointer to the storage for the driver runtime state.
start	The start address of the desired flash memory to be erased. The start address does not need to be sector-aligned but must be word-aligned.
lengthInBytes	The length, given in bytes (not words or long-words) to be erased. Must be word-aligned.
key	The value used to validate all flash erase APIs.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.
kStatus_FLASH_-AlignmentError	The parameter is not aligned with the specified baseline.
kStatus_FLASH_Address-Error	The address is out of range.

kStatus_FLASH_EraseKeyError	The API erase key is invalid.
kStatus_FLASH_ExecuteInRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_AccessError	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_CommandFailure	Run-time error during the command execution.

8.5.6 status_t FLASH_EraseAllUnsecure (flash_config_t ∗ *config*, uint32_t *key*)

Parameters

config	Pointer to the storage for the driver runtime state.
key	A value used to validate all flash erase APIs.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_InvalidArgument	An invalid argument is provided.
kStatus_FLASH_EraseKeyError	API erase key is invalid.
kStatus_FLASH_ExecuteInRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_AccessError	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_ProtectionViolation	The program/erase operation is requested to execute on protected areas.

kStatus_FLASH_-CommandFailure	Run-time error during command execution.
kStatus_FLASH_-PartitionStatusUpdate-Failure	Failed to update the partition status.

8.5.7 status_t FLASH_EraseAllExecuteOnlySegments (flash_config_t * *config*, uint32_t *key*)

Parameters

config	Pointer to the storage for the driver runtime state.
key	A value used to validate all flash erase APIs.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.
kStatus_FLASH_Erase-KeyError	API erase key is invalid.
kStatus_FLASH_Execute-InRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_Access-Error	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_-ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_-CommandFailure	Run-time error during the command execution.

8.5.8 status_t FLASH_Program (flash_config_t * *config*, uint32_t *start*, uint32_t * *src*, uint32_t *lengthInBytes*)

This function programs the flash memory with the desired data for a given flash area as determined by the start address and the length.

Parameters

config	A pointer to the storage for the driver runtime state.
start	The start address of the desired flash memory to be programmed. Must be word-aligned.
src	A pointer to the source buffer of data that is to be programmed into the flash.
lengthInBytes	The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.
kStatus_FLASH_-AlignmentError	Parameter is not aligned with the specified baseline.
kStatus_FLASH_Address-Error	Address is out of range.
kStatus_FLASH_Execute-InRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_Access-Error	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_-ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_-CommandFailure	Run-time error during the command execution.

8.5.9 status_t FLASH_ProgramOnce (flash_config_t * *config*, uint32_t *index*, uint32_t * *src*, uint32_t *lengthInBytes*)

This function programs the Program Once Field with the desired data for a given flash area as determined by the index and length.

Parameters

config	A pointer to the storage for the driver runtime state.
index	The index indicating which area of the Program Once Field to be programmed.
src	A pointer to the source buffer of data that is to be programmed into the Program Once Field.
lengthInBytes	The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.
kStatus_FLASH_Execute-InRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_Access-Error	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_-ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_-CommandFailure	Run-time error during the command execution.

8.5.10 status_t FLASH_ReadResource (flash_config_t * *config,* uint32_t *start,* uint32_t * *dst,* uint32_t *lengthInBytes,* flash_read_resource_option_t *option*)

This function reads the flash memory with the desired location for a given flash area as determined by the start address and length.

Parameters

config	A pointer to the storage for the driver runtime state.
start	The start address of the desired flash memory to be programmed. Must be word-aligned.

dst	A pointer to the destination buffer of data that is used to store data to be read.
lengthInBytes	The length, given in bytes (not words or long-words), to be read. Must be word-aligned.
option	The resource option which indicates which area should be read back.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.
kStatus_FLASH_-AlignmentError	Parameter is not aligned with the specified baseline.
kStatus_FLASH_Execute-InRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_Access-Error	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_-ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_-CommandFailure	Run-time error during the command execution.

8.5.11 status_t FLASH_ReadOnce (flash_config_t * *config*, uint32_t *index*, uint32_t * *dst*, uint32_t *lengthInBytes*)

This function reads the read once feild with given index and length.

Parameters

config	A pointer to the storage for the driver runtime state.
index	The index indicating the area of program once field to be read.
dst	A pointer to the destination buffer of data that is used to store data to be read.
lengthInBytes	The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_InvalidArgument	An invalid argument is provided.
kStatus_FLASH_ExecuteInRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_AccessError	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_CommandFailure	Run-time error during the command execution.

8.5.12 status_t FLASH_GetSecurityState (flash_config_t * *config*, flash_security_state_t * *state*)

This function retrieves the current flash security status, including the security enabling state and the backdoor key enabling state.

Parameters

config	A pointer to storage for the driver runtime state.
state	A pointer to the value returned for the current security status code:

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_InvalidArgument	An invalid argument is provided.

8.5.13 status_t FLASH_SecurityBypass (flash_config_t * *config*, const uint8_t * *backdoorKey*)

If the MCU is in secured state, this function unsecures the MCU by comparing the provided backdoor key with ones in the flash configuration field.

Parameters

config	A pointer to the storage for the driver runtime state.
backdoorKey	A pointer to the user buffer containing the backdoor key.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.
kStatus_FLASH_Execute-InRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_Access-Error	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_-ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_-CommandFailure	Run-time error during the command execution.

8.5.14 status_t FLASH_VerifyEraseAll (flash_config_t * *config*, flash_margin_value_t *margin*)

This function checks whether the flash is erased to the specified read margin level.

Parameters

config	A pointer to the storage for the driver runtime state.
margin	Read margin choice.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.

kStatus_FLASH_Execute-InRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_Access-Error	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_-ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_-CommandFailure	Run-time error during the command execution.

8.5.15 status_t FLASH_VerifyErase (flash_config_t * *config*, uint32_t *start*, uint32_t *lengthInBytes*, flash_margin_value_t *margin*)

This function checks the appropriate number of flash sectors based on the desired start address and length to check whether the flash is erased to the specified read margin level.

Parameters

config	A pointer to the storage for the driver runtime state.
start	The start address of the desired flash memory to be verified. The start address does not need to be sector-aligned but must be word-aligned.
lengthInBytes	The length, given in bytes (not words or long-words), to be verified. Must be word-aligned.
margin	Read margin choice.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.
kStatus_FLASH_-AlignmentError	Parameter is not aligned with specified baseline.
kStatus_FLASH_Address-Error	Address is out of range.

kStatus_FLASH_ExecuteInRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_AccessError	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_CommandFailure	Run-time error during the command execution.

8.5.16 status_t FLASH_VerifyProgram (flash_config_t * *config*, uint32_t *start*, uint32_t *lengthInBytes*, const uint32_t * *expectedData*, flash_margin_value_t *margin*, uint32_t * *failedAddress*, uint32_t * *failedData*)

This function verifies the data programed in the flash memory using the Flash Program Check Command and compares it to the expected data for a given flash area as determined by the start address and length.

Parameters

config	A pointer to the storage for the driver runtime state.
start	The start address of the desired flash memory to be verified. Must be word-aligned.
lengthInBytes	The length, given in bytes (not words or long-words), to be verified. Must be word-aligned.
expectedData	A pointer to the expected data that is to be verified against.
margin	Read margin choice.
failedAddress	A pointer to the returned failing address.
failedData	A pointer to the returned failing data. Some derivatives do not include failed data as part of the FCCOBx registers. In this case, zeros are returned upon failure.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_InvalidArgument	An invalid argument is provided.

kStatus_FLASH_-AlignmentError	Parameter is not aligned with specified baseline.
kStatus_FLASH_Address-Error	Address is out of range.
kStatus_FLASH_Execute-InRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_Access-Error	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_-ProtectionViolation	The program/erase operation is requested to execute on protected areas.
kStatus_FLASH_-CommandFailure	Run-time error during the command execution.

8.5.17 status_t FLASH_VerifyEraseAllExecuteOnlySegments (flash_config_t * *config*, flash_margin_value_t *margin*)

Parameters

config	A pointer to the storage for the driver runtime state.
margin	Read margin choice.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.
kStatus_FLASH_Execute-InRamFunctionNotReady	Execute-in-RAM function is not available.
kStatus_FLASH_Access-Error	Invalid instruction codes and out-of bounds addresses.
kStatus_FLASH_-ProtectionViolation	The program/erase operation is requested to execute on protected areas.

kStatus_FLASH_-CommandFailure	Run-time error during the command execution.

8.5.18 status_t FLASH_IsProtected (flash_config_t * *config*, uint32_t *start*, uint32_t *lengthInBytes*, flash_protection_state_t * *protection_state*)

This function retrieves the current flash protect status for a given flash area as determined by the start address and length.

Parameters

config	A pointer to the storage for the driver runtime state.
start	The start address of the desired flash memory to be checked. Must be word-aligned.
lengthInBytes	The length, given in bytes (not words or long-words) to be checked. Must be word-aligned.
protection_-state	A pointer to the value returned for the current protection status code for the desired flash area.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.
kStatus_FLASH_-AlignmentError	Parameter is not aligned with specified baseline.
kStatus_FLASH_Address-Error	The address is out of range.

8.5.19 status_t FLASH_IsExecuteOnly (flash_config_t * *config*, uint32_t *start*, uint32_t *lengthInBytes*, flash_execute_only_access_state_t * *access_state*)

This function retrieves the current flash access status for a given flash area as determined by the start address and length.

Parameters

config	A pointer to the storage for the driver runtime state.
start	The start address of the desired flash memory to be checked. Must be word-aligned.
lengthInBytes	The length, given in bytes (not words or long-words), to be checked. Must be word-aligned.
access_state	A pointer to the value returned for the current access status code for the desired flash area.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_InvalidArgument	An invalid argument is provided.
kStatus_FLASH_AlignmentError	The parameter is not aligned to the specified baseline.
kStatus_FLASH_AddressError	The address is out of range.

8.5.20 status_t FLASH_GetProperty (flash_config_t * *config,* flash_property_tag_t *whichProperty,* uint32_t * *value*)

Parameters

config	A pointer to the storage for the driver runtime state.
whichProperty	The desired property from the list of properties in enum flash_property_tag_t
value	A pointer to the value returned for the desired flash property.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_InvalidArgument	An invalid argument is provided.
kStatus_FLASH_UnknownProperty	An unknown property tag.

8.5.21 status_t FLASH_SetProperty (flash_config_t * *config,* flash_property_tag_t *whichProperty,* uint32_t *value*)

Parameters

config	A pointer to the storage for the driver runtime state.
whichProperty	The desired property from the list of properties in enum flash_property_tag_t
value	A to set for the desired flash property.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.
kStatus_FLASH_-UnknownProperty	An unknown property tag.
kStatus_FLASH_Invalid-PropertyValue	An invalid property value.
kStatus_FLASH_Read-OnlyProperty	An read-only property tag.

8.5.22 status_t FLASH_PflashSetProtection (flash_config_t * *config*, pflash_protection_status_t * *protectStatus*)

Parameters

config	A pointer to storage for the driver runtime state.
protectStatus	The expected protect status to set to the PFlash protection register. Each bit is corresponding to protection of 1/32(64) of the total PFlash. The least significant bit is corresponding to the lowest address area of PFlash. The most significant bit is corresponding to the highest address area of PFlash. There are two possible cases as shown below: 0: this area is protected. 1: this area is unprotected.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.

kStatus_FLASH_-CommandFailure	Run-time error during command execution.

8.5.23 status_t FLASH_PflashGetProtection (flash_config_t * *config*, pflash_protection_status_t * *protectStatus*)

Parameters

config	A pointer to the storage for the driver runtime state.
protectStatus	Protect status returned by the PFlash IP. Each bit is corresponding to the protection of 1/32(64) of the total PFlash. The least significant bit corresponds to the lowest address area of the PFlash. The most significant bit corresponds to the highest address area of PFlash. There are two possible cases as shown below: 0: this area is protected. 1: this area is unprotected.

Return values

kStatus_FLASH_Success	API was executed successfully.
kStatus_FLASH_Invalid-Argument	An invalid argument is provided.

Chapter 9
GPIO: General-Purpose Input/Output Driver

9.1 Overview

Modules

- FGPIO Driver
- GPIO Driver

Data Structures

- struct gpio_pin_config_t
  The GPIO pin configuration structure. More...

Enumerations

- enum gpio_pin_direction_t {
  kGPIO_DigitalInput = 0U,
  kGPIO_DigitalOutput = 1U }
  GPIO direction definition.

Driver version

- #define FSL_GPIO_DRIVER_VERSION (MAKE_VERSION(2, 1, 1))
  GPIO driver version 2.1.1.

9.2 Data Structure Documentation

9.2.1 struct gpio_pin_config_t

Each pin can only be configured as either an output pin or an input pin at a time. If configured as an input pin, leave the outputConfig unused. Note that in some use cases, the corresponding port property should be configured in advance with the PORT_SetPinConfig().

Data Fields

- gpio_pin_direction_t pinDirection
  GPIO direction, input or output.
- uint8_t outputLogic
  Set a default output logic, which has no use in input.

9.3 Macro Definition Documentation

9.3.1 #define FSL_GPIO_DRIVER_VERSION (MAKE_VERSION(2, 1, 1))

9.4 Enumeration Type Documentation

9.4.1 enum gpio_pin_direction_t

Enumerator

kGPIO_DigitalInput Set current pin as digital input.
kGPIO_DigitalOutput Set current pin as digital output.

9.5 GPIO Driver

9.5.1 Overview

The MCUXpresso SDK provides a peripheral driver for the General-Purpose Input/Output (GPIO) module of MCUXpresso SDK devices.

9.5.2 Typical use case

9.5.2.1 Output Operation

```
/* Output pin configuration */
gpio_pin_config_t led_config =
{
    kGpioDigitalOutput,
    1,
};
/*  Sets the configuration */
GPIO_PinInit(GPIO_LED, LED_PINNUM, &led_config);
```

9.5.2.2 Input Operation

```
/*  Input pin configuration */
PORT_SetPinInterruptConfig(BOARD_SW2_PORT, BOARD_SW2_GPIO_PIN,
      kPORT_InterruptFallingEdge);
NVIC_EnableIRQ(BOARD_SW2_IRQ);
gpio_pin_config_t sw1_config =
{
    kGpioDigitalInput,
    0,
};
/* Sets the input pin configuration */
GPIO_PinInit(GPIO_SW1, SW1_PINNUM, &sw1_config);
```

GPIO Configuration

- void GPIO_PinInit (GPIO_Type ∗base, uint32_t pin, const gpio_pin_config_t ∗config)
  Initializes a GPIO pin used by the board.

GPIO Output Operations

- static void GPIO_WritePinOutput (GPIO_Type ∗base, uint32_t pin, uint8_t output)
  Sets the output level of the multiple GPIO pins to the logic 1 or 0.
- static void GPIO_SetPinsOutput (GPIO_Type ∗base, uint32_t mask)
  Sets the output level of the multiple GPIO pins to the logic 1.
- static void GPIO_ClearPinsOutput (GPIO_Type ∗base, uint32_t mask)
  Sets the output level of the multiple GPIO pins to the logic 0.
- static void GPIO_TogglePinsOutput (GPIO_Type ∗base, uint32_t mask)
  Reverses the current output logic of the multiple GPIO pins.

GPIO Input Operations

- static uint32_t GPIO_ReadPinInput (GPIO_Type *base, uint32_t pin)
  Reads the current input value of the GPIO port.

GPIO Interrupt

- uint32_t GPIO_GetPinsInterruptFlags (GPIO_Type *base)
  Reads the GPIO port interrupt status flag.
- void GPIO_ClearPinsInterruptFlags (GPIO_Type *base, uint32_t mask)
  Clears multiple GPIO pin interrupt status flags.

9.5.3 Function Documentation

9.5.3.1 void GPIO_PinInit (GPIO_Type * *base*, uint32_t *pin*, const gpio_pin_config_t * *config*)

To initialize the GPIO, define a pin configuration, as either input or output, in the user file. Then, call the GPIO_PinInit() function.

This is an example to define an input pin or an output pin configuration.

```
* // Define a digital input pin configuration,
* gpio_pin_config_t config =
* {
*   kGPIO_DigitalInput,
*   0,
* }
* //Define a digital output pin configuration,
* gpio_pin_config_t config =
* {
*   kGPIO_DigitalOutput,
*   0,
* }
*
```

Parameters

base	GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
pin	GPIO port pin number
config	GPIO pin configuration pointer

9.5.3.2 static void GPIO_WritePinOutput (GPIO_Type * *base*, uint32_t *pin*, uint8_t *output*) [inline], [static]

Parameters

base	GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
pin	GPIO pin number
output	GPIO pin output logic level. • 0: corresponding pin output low-logic level. • 1: corresponding pin output high-logic level.

9.5.3.3 static void GPIO_SetPinsOutput (GPIO_Type * *base*, uint32_t *mask*) [inline], [static]

Parameters

base	GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
mask	GPIO pin number macro

9.5.3.4 static void GPIO_ClearPinsOutput (GPIO_Type * *base*, uint32_t *mask*) [inline], [static]

Parameters

base	GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
mask	GPIO pin number macro

9.5.3.5 static void GPIO_TogglePinsOutput (GPIO_Type * *base*, uint32_t *mask*) [inline], [static]

Parameters

base	GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
mask	GPIO pin number macro

9.5.3.6 static uint32_t GPIO_ReadPinInput (GPIO_Type * *base*, uint32_t *pin*) [inline], [static]

Parameters

base	GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
pin	GPIO pin number

Return values

GPIO	port input value • 0: corresponding pin input low-logic level. • 1: corresponding pin input high-logic level.

9.5.3.7 uint32_t GPIO_GetPinsInterruptFlags (GPIO_Type ∗ *base*)

If a pin is configured to generate the DMA request, the corresponding flag is cleared automatically at the completion of the requested DMA transfer. Otherwise, the flag remains set until a logic one is written to that flag. If configured for a level sensitive interrupt that remains asserted, the flag is set again immediately.

Parameters

base	GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)

Return values

The	current GPIO port interrupt status flag, for example, 0x00010001 means the pin 0 and 17 have the interrupt.

9.5.3.8 void GPIO_ClearPinsInterruptFlags (GPIO_Type ∗ *base,* uint32_t *mask*)

Parameters

base	GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
mask	GPIO pin number macro

9.6 FGPIO Driver

9.6.1 Overview

This chapter describes the programming interface of the FGPIO driver. The FGPIO driver configures the FGPIO module and provides a functional interface to build the GPIO application.

Note

> FGPIO (Fast GPIO) is only available in a few MCUs. FGPIO and GPIO share the same peripheral but use different registers. FGPIO is closer to the core than the regular GPIO and it's faster to read and write.

9.6.2 Typical use case

9.6.2.1 Output Operation

```
/* Output pin configuration */
gpio_pin_config_t led_config =
{
    kGpioDigitalOutput,
    1,
};
/*  Sets the configuration */
FGPIO_PinInit(FGPIO_LED, LED_PINNUM, &led_config);
```

9.6.2.2 Input Operation

```
/*  Input pin configuration */
PORT_SetPinInterruptConfig(BOARD_SW2_PORT, BOARD_SW2_FGPIO_PIN,
      kPORT_InterruptFallingEdge);
NVIC_EnableIRQ(BOARD_SW2_IRQ);
gpio_pin_config_t sw1_config =
{
    kGpioDigitalInput,
    0,
};
/* Sets the input pin configuration */
FGPIO_PinInit(FGPIO_SW1, SW1_PINNUM, &sw1_config);
```

FGPIO Configuration

- void FGPIO_PinInit (FGPIO_Type ∗base, uint32_t pin, const gpio_pin_config_t ∗config)
  Initializes a FGPIO pin used by the board.

FGPIO Output Operations

- static void FGPIO_WritePinOutput (FGPIO_Type ∗base, uint32_t pin, uint8_t output)
  Sets the output level of the multiple FGPIO pins to the logic 1 or 0.

- static void FGPIO_SetPinsOutput (FGPIO_Type ∗base, uint32_t mask)
  Sets the output level of the multiple FGPIO pins to the logic 1.
- static void FGPIO_ClearPinsOutput (FGPIO_Type ∗base, uint32_t mask)
  Sets the output level of the multiple FGPIO pins to the logic 0.
- static void FGPIO_TogglePinsOutput (FGPIO_Type ∗base, uint32_t mask)
  Reverses the current output logic of the multiple FGPIO pins.

FGPIO Input Operations

- static uint32_t FGPIO_ReadPinInput (FGPIO_Type ∗base, uint32_t pin)
  Reads the current input value of the FGPIO port.

FGPIO Interrupt

- uint32_t FGPIO_GetPinsInterruptFlags (FGPIO_Type ∗base)
  Reads the FGPIO port interrupt status flag.
- void FGPIO_ClearPinsInterruptFlags (FGPIO_Type ∗base, uint32_t mask)
  Clears the multiple FGPIO pin interrupt status flag.

9.6.3 Function Documentation

9.6.3.1 void FGPIO_PinInit (FGPIO_Type ∗ *base*, uint32_t *pin*, const gpio_pin_config_t ∗ *config*)

To initialize the FGPIO driver, define a pin configuration, as either input or output, in the user file. Then, call the FGPIO_PinInit() function.

This is an example to define an input pin or an output pin configuration:

```
* // Define a digital input pin configuration,
* gpio_pin_config_t config =
* {
*   kGPIO_DigitalInput,
*   0,
* }
* //Define a digital output pin configuration,
* gpio_pin_config_t config =
* {
*   kGPIO_DigitalOutput,
*   0,
* }
*
```

Parameters

base	FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
pin	FGPIO port pin number
config	FGPIO pin configuration pointer

9.6.3.2 static void FGPIO_WritePinOutput (FGPIO_Type ∗ *base*, uint32_t *pin*, uint8_t *output*) [inline], [static]

Parameters

base	FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
pin	FGPIO pin number
output	FGPIOpin output logic level. • 0: corresponding pin output low-logic level. • 1: corresponding pin output high-logic level.

9.6.3.3 static void FGPIO_SetPinsOutput (FGPIO_Type ∗ *base*, uint32_t *mask*) [inline], [static]

Parameters

base	FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
mask	FGPIO pin number macro

9.6.3.4 static void FGPIO_ClearPinsOutput (FGPIO_Type ∗ *base*, uint32_t *mask*) [inline], [static]

Parameters

base	FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
mask	FGPIO pin number macro

9.6.3.5 static void FGPIO_TogglePinsOutput (FGPIO_Type ∗ *base*, uint32_t *mask*) [inline], [static]

Parameters

base	FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
mask	FGPIO pin number macro

9.6.3.6 static uint32_t FGPIO_ReadPinInput (FGPIO_Type * *base*, uint32_t *pin*) [inline], [static]

Parameters

base	FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
pin	FGPIO pin number

Return values

FGPIO	port input value • 0: corresponding pin input low-logic level. • 1: corresponding pin input high-logic level.

9.6.3.7 uint32_t FGPIO_GetPinsInterruptFlags (FGPIO_Type * *base*)

If a pin is configured to generate the DMA request, the corresponding flag is cleared automatically at the completion of the requested DMA transfer. Otherwise, the flag remains set until a logic one is written to that flag. If configured for a level-sensitive interrupt that remains asserted, the flag is set again immediately.

Parameters

base	FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)

Return values

The	current FGPIO port interrupt status flags, for example, 0x00010001 means the pin 0 and 17 have the interrupt.

9.6.3.8 void FGPIO_ClearPinsInterruptFlags (FGPIO_Type * *base*, uint32_t *mask*)

Parameters

base	FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
mask	FGPIO pin number macro

Chapter 10
I2C: Inter-Integrated Circuit Driver

10.1 Overview

Modules

- I2C DMA Driver
- I2C Driver
- I2C FreeRTOS Driver
- I2C eDMA Driver

10.2 I2C Driver

10.2.1 Overview

The MCUXpresso SDK provides a peripheral driver for the Inter-Integrated Circuit (I2C) module of MCUXpresso SDK devices.

The I2C driver includes functional APIs and transactional APIs.

Functional APIs target the low-level APIs. Functional APIs can be used for the I2C master/slave initialization/configuration/operation for optimization/customization purpose. Using the functional APIs requires knowing the I2C master peripheral and how to organize functional APIs to meet the application requirements. The I2C functional operation groups provide the functional APIs set.

Transactional APIs target the high-level APIs. The transactional APIs can be used to enable the peripheral quickly and also in the application if the code size and performance of transactional APIs satisfy the requirements. If the code size and performance are critical requirements, see the transactional API implementation and write custom code using the functional APIs or accessing the hardware registers.

Transactional APIs support asynchronous transfer. This means that the functions I2C_MasterTransferNonBlocking() set up the interrupt non-blocking transfer. When the transfer completes, the upper layer is notified through a callback function with the status.

10.2.2 Typical use case

10.2.2.1 Master Operation in functional method

```
i2c_master_config_t masterConfig;
uint8_t status;
status_t result = kStatus_Success;
uint8_t txBuff[BUFFER_SIZE];

/* Gets the default configuration for master. */
I2C_MasterGetDefaultConfig(&masterConfig);

/* Inititializes the I2C master. */
I2C_MasterInit(EXAMPLE_I2C_MASTER_BASEADDR, &masterConfig, I2C_MASTER_CLK);

/* Sends a start and a slave address. */
I2C_MasterStart(EXAMPLE_I2C_MASTER_BASEADDR, 7-bit slave address,
      kI2C_Write/kI2C_Read);

/* Waits for the sent out address. */
while(!((status = I2C_GetStatusFlag(EXAMPLE_I2C_MASTER_BASEADDR)) & kI2C_IntPendingFlag))
{

}

if(status & kI2C_ReceiveNakFlag)
{
    return kStatus_I2C_Nak;
}

result = I2C_MasterWriteBlocking(EXAMPLE_I2C_MASTER_BASEADDR, txBuff, BUFFER_SIZE,
      kI2C_TransferDefaultFlag);

if(result)
```

```
{
    return result;
}
```

10.2.2.2 Master Operation in interrupt transactional method

```
i2c_master_handle_t g_m_handle;
volatile bool g_MasterCompletionFlag = false;
i2c_master_config_t masterConfig;
uint8_t status;
status_t result = kStatus_Success;
uint8_t txBuff[BUFFER_SIZE];
i2c_master_transfer_t masterXfer;

static void i2c_master_callback(I2C_Type *base, i2c_master_handle_t *handle, status_t status, void *
      userData)
{
    /* Signal transfer success when received success status. */
    if (status == kStatus_Success)
    {
        g_MasterCompletionFlag = true;
    }
}

/* Gets a default configuration for master. */
I2C_MasterGetDefaultConfig(&masterConfig);

/* Initializes the I2C master. */
I2C_MasterInit(EXAMPLE_I2C_MASTER_BASEADDR, &masterConfig, I2C_MASTER_CLK);

masterXfer.slaveAddress = I2C_MASTER_SLAVE_ADDR_7BIT;
masterXfer.direction = kI2C_Write;
masterXfer.subaddress = NULL;
masterXfer.subaddressSize = 0;
masterXfer.data = txBuff;
masterXfer.dataSize = BUFFER_SIZE;
masterXfer.flags = kI2C_TransferDefaultFlag;

I2C_MasterTransferCreateHandle(EXAMPLE_I2C_MASTER_BASEADDR, &g_m_handle,
      i2c_master_callback, NULL);
I2C_MasterTransferNonBlocking(EXAMPLE_I2C_MASTER_BASEADDR, &g_m_handle, &
      masterXfer);

/*  Waits for a transfer to be completed. */
while (!g_MasterCompletionFlag)
{
}
g_MasterCompletionFlag = false;
```

10.2.2.3 Master Operation in DMA transactional method

```
i2c_master_dma_handle_t g_m_dma_handle;
dma_handle_t dmaHandle;
volatile bool g_MasterCompletionFlag = false;
i2c_master_config_t masterConfig;
uint8_t txBuff[BUFFER_SIZE];
i2c_master_transfer_t masterXfer;

static void i2c_master_callback(I2C_Type *base, i2c_master_dma_handle_t *handle, status_t status, void *
      userData)
{
    /* Signal transfer success when received success status. */
    if (status == kStatus_Success)
```

```
    {
        g_MasterCompletionFlag = true;
    }
}

/* Gets the default configuration for the master. */
I2C_MasterGetDefaultConfig(&masterConfig);

/* Initializes the I2C master. */
I2C_MasterInit(EXAMPLE_I2C_MASTER_BASEADDR, &masterConfig, I2C_MASTER_CLK);

masterXfer.slaveAddress = I2C_MASTER_SLAVE_ADDR_7BIT;
masterXfer.direction = kI2C_Write;
masterXfer.subaddress = NULL;
masterXfer.subaddressSize = 0;
masterXfer.data = txBuff;
masterXfer.dataSize = BUFFER_SIZE;
masterXfer.flags = kI2C_TransferDefaultFlag;

DMAMGR_RequestChannel((dma_request_source_t)DMA_REQUEST_SRC, 0, &dmaHandle);

I2C_MasterTransferCreateHandleDMA(EXAMPLE_I2C_MASTER_BASEADDR, &
      g_m_dma_handle, i2c_master_callback, NULL, &dmaHandle);
I2C_MasterTransferDMA(EXAMPLE_I2C_MASTER_BASEADDR, &g_m_dma_handle, &masterXfer);

/*  Wait for transfer completed. */
while (!g_MasterCompletionFlag)
{
}
g_MasterCompletionFlag = false;
```

10.2.2.4 Slave Operation in functional method

```
i2c_slave_config_t slaveConfig;
uint8_t status;
status_t result = kStatus_Success;

I2C_SlaveGetDefaultConfig(&slaveConfig); /*A default configuration 7-bit
       addressing mode*/
slaveConfig.slaveAddr = 7-bit address
slaveConfig.addressingMode = kI2C_Address7bit/
      kI2C_RangeMatch;
I2C_SlaveInit(EXAMPLE_I2C_SLAVE_BASEADDR, &slaveConfig, I2C_SLAVE_CLK);

/* Waits for an address match. */
while(!((status = I2C_GetStatusFlag(EXAMPLE_I2C_SLAVE_BASEADDR)) & kI2C_AddressMatchFlag))
{

}

/* A slave transmits; master is reading from the slave. */
if (status & kI2C_TransferDirectionFlag)
{
    result = I2C_SlaveWriteBlocking(EXAMPLE_I2C_SLAVE_BASEADDR, txBuff, BUFFER_SIZE);
}
else
{
    I2C_SlaveReadBlocking(EXAMPLE_I2C_SLAVE_BASEADDR, rxBuff, BUFFER_SIZE);
}

return result;
```

10.2.2.5 Slave Operation in interrupt transactional method

```
i2c_slave_config_t slaveConfig;
i2c_slave_handle_t g_s_handle;
volatile bool g_SlaveCompletionFlag = false;

static void i2c_slave_callback(I2C_Type *base, i2c_slave_transfer_t *xfer, void *
      userData)
{
    switch (xfer->event)
    {
        /*  Transmit request */
        case kI2C_SlaveTransmitEvent:
            /*  Update information for transmit process */
            xfer->data = g_slave_buff;
            xfer->dataSize = I2C_DATA_LENGTH;
            break;

        /*  Receives request */
        case kI2C_SlaveReceiveEvent:
            /*  Update information for received process */
            xfer->data = g_slave_buff;
            xfer->dataSize = I2C_DATA_LENGTH;
            break;

        /*  Transfer is done */
        case kI2C_SlaveCompletionEvent:
            g_SlaveCompletionFlag = true;
            break;

        default:
            g_SlaveCompletionFlag = true;
            break;
    }
}

I2C_SlaveGetDefaultConfig(&slaveConfig); /*A default configuration 7-bit
       addressing mode*/
slaveConfig.slaveAddr = 7-bit address
slaveConfig.addressingMode = kI2C_Address7bit/
      kI2C_RangeMatch;

I2C_SlaveInit(EXAMPLE_I2C_SLAVE_BASEADDR, &slaveConfig, I2C_SLAVE_CLK);

I2C_SlaveTransferCreateHandle(EXAMPLE_I2C_SLAVE_BASEADDR, &g_s_handle,
      i2c_slave_callback, NULL);

I2C_SlaveTransferNonBlocking(EXAMPLE_I2C_SLAVE_BASEADDR, &g_s_handle,
      kI2C_SlaveCompletionEvent);

/*  Waits for a transfer to be completed. */
while (!g_SlaveCompletionFlag)
{
}
g_SlaveCompletionFlag = false;
```

Data Structures

- struct i2c_master_config_t
  I2C master user configuration. More...
- struct i2c_slave_config_t
  I2C slave user configuration. More...
- struct i2c_master_transfer_t

I2C master transfer structure. More...
- struct i2c_master_handle_t
  I2C master handle structure. More...
- struct i2c_slave_transfer_t
  I2C slave transfer structure. More...
- struct i2c_slave_handle_t
  I2C slave handle structure. More...

Typedefs

- typedef void(∗ i2c_master_transfer_callback_t)(I2C_Type ∗base, i2c_master_handle_t ∗handle, status_t status, void ∗userData)
  I2C master transfer callback typedef.
- typedef void(∗ i2c_slave_transfer_callback_t)(I2C_Type ∗base, i2c_slave_transfer_t ∗xfer, void ∗userData)
  I2C slave transfer callback typedef.

Enumerations

- enum _i2c_status {
  kStatus_I2C_Busy = MAKE_STATUS(kStatusGroup_I2C, 0),
  kStatus_I2C_Idle = MAKE_STATUS(kStatusGroup_I2C, 1),
  kStatus_I2C_Nak = MAKE_STATUS(kStatusGroup_I2C, 2),
  kStatus_I2C_ArbitrationLost = MAKE_STATUS(kStatusGroup_I2C, 3),
  kStatus_I2C_Timeout = MAKE_STATUS(kStatusGroup_I2C, 4),
  kStatus_I2C_Addr_Nak = MAKE_STATUS(kStatusGroup_I2C, 5) }
  I2C status return codes.
- enum _i2c_flags {
  kI2C_ReceiveNakFlag = I2C_S_RXAK_MASK,
  kI2C_IntPendingFlag = I2C_S_IICIF_MASK,
  kI2C_TransferDirectionFlag = I2C_S_SRW_MASK,
  kI2C_RangeAddressMatchFlag = I2C_S_RAM_MASK,
  kI2C_ArbitrationLostFlag = I2C_S_ARBL_MASK,
  kI2C_BusBusyFlag = I2C_S_BUSY_MASK,
  kI2C_AddressMatchFlag = I2C_S_IAAS_MASK,
  kI2C_TransferCompleteFlag = I2C_S_TCF_MASK,
  kI2C_StopDetectFlag = I2C_FLT_STOPF_MASK << 8,
  kI2C_StartDetectFlag = I2C_FLT_STARTF_MASK << 8 }
  I2C peripheral flags.
- enum _i2c_interrupt_enable {
  kI2C_GlobalInterruptEnable = I2C_C1_IICIE_MASK,
  kI2C_StartStopDetectInterruptEnable = I2C_FLT_SSIE_MASK }
  I2C feature interrupt source.
- enum i2c_direction_t {
  kI2C_Write = 0x0U,

kI2C_Read = 0x1U }
    The direction of master and slave transfers.
- enum i2c_slave_address_mode_t {
kI2C_Address7bit = 0x0U,
kI2C_RangeMatch = 0X2U }
    Addressing mode.
- enum _i2c_master_transfer_flags {
kI2C_TransferDefaultFlag = 0x0U,
kI2C_TransferNoStartFlag = 0x1U,
kI2C_TransferRepeatedStartFlag = 0x2U,
kI2C_TransferNoStopFlag = 0x4U }
    I2C transfer control flag.
- enum i2c_slave_transfer_event_t {
kI2C_SlaveAddressMatchEvent = 0x01U,
kI2C_SlaveTransmitEvent = 0x02U,
kI2C_SlaveReceiveEvent = 0x04U,
kI2C_SlaveTransmitAckEvent = 0x08U,
kI2C_SlaveStartEvent = 0x10U,
kI2C_SlaveCompletionEvent = 0x20U,
kI2C_SlaveGenaralcallEvent = 0x40U,
kI2C_SlaveAllEvents }
    Set of events sent to the callback for nonblocking slave transfers.

Driver version

- #define FSL_I2C_DRIVER_VERSION (MAKE_VERSION(2, 0, 3))
    I2C driver version 2.0.3.

Initialization and deinitialization

- void I2C_MasterInit (I2C_Type ∗base, const i2c_master_config_t ∗masterConfig, uint32_t srcClock_Hz)
    Initializes the I2C peripheral.
- void I2C_SlaveInit (I2C_Type ∗base, const i2c_slave_config_t ∗slaveConfig, uint32_t srcClock_Hz)
    Initializes the I2C peripheral.
- void I2C_MasterDeinit (I2C_Type ∗base)
    De-initializes the I2C master peripheral.
- void I2C_SlaveDeinit (I2C_Type ∗base)
    De-initializes the I2C slave peripheral.
- void I2C_MasterGetDefaultConfig (i2c_master_config_t ∗masterConfig)
    Sets the I2C master configuration structure to default values.
- void I2C_SlaveGetDefaultConfig (i2c_slave_config_t ∗slaveConfig)
    Sets the I2C slave configuration structure to default values.
- static void I2C_Enable (I2C_Type ∗base, bool enable)
    Enables or disabless the I2C peripheral operation.

Status

- uint32_t I2C_MasterGetStatusFlags (I2C_Type ∗base)
  Gets the I2C status flags.
- static uint32_t I2C_SlaveGetStatusFlags (I2C_Type ∗base)
  Gets the I2C status flags.
- static void I2C_MasterClearStatusFlags (I2C_Type ∗base, uint32_t statusMask)
  Clears the I2C status flag state.
- static void I2C_SlaveClearStatusFlags (I2C_Type ∗base, uint32_t statusMask)
  Clears the I2C status flag state.

Interrupts

- void I2C_EnableInterrupts (I2C_Type ∗base, uint32_t mask)
  Enables I2C interrupt requests.
- void I2C_DisableInterrupts (I2C_Type ∗base, uint32_t mask)
  Disables I2C interrupt requests.

DMA Control

- static uint32_t I2C_GetDataRegAddr (I2C_Type ∗base)
  Gets the I2C tx/rx data register address.

Bus Operations

- void I2C_MasterSetBaudRate (I2C_Type ∗base, uint32_t baudRate_Bps, uint32_t srcClock_Hz)
  Sets the I2C master transfer baud rate.
- status_t I2C_MasterStart (I2C_Type ∗base, uint8_t address, i2c_direction_t direction)
  Sends a START on the I2C bus.
- status_t I2C_MasterStop (I2C_Type ∗base)
  Sends a STOP signal on the I2C bus.
- status_t I2C_MasterRepeatedStart (I2C_Type ∗base, uint8_t address, i2c_direction_t direction)
  Sends a REPEATED START on the I2C bus.
- status_t I2C_MasterWriteBlocking (I2C_Type ∗base, const uint8_t ∗txBuff, size_t txSize, uint32_t flags)
  Performs a polling send transaction on the I2C bus.
- status_t I2C_MasterReadBlocking (I2C_Type ∗base, uint8_t ∗rxBuff, size_t rxSize, uint32_t flags)
  Performs a polling receive transaction on the I2C bus.
- status_t I2C_SlaveWriteBlocking (I2C_Type ∗base, const uint8_t ∗txBuff, size_t txSize)
  Performs a polling send transaction on the I2C bus.
- void I2C_SlaveReadBlocking (I2C_Type ∗base, uint8_t ∗rxBuff, size_t rxSize)
  Performs a polling receive transaction on the I2C bus.
- status_t I2C_MasterTransferBlocking (I2C_Type ∗base, i2c_master_transfer_t ∗xfer)
  Performs a master polling transfer on the I2C bus.

Transactional

- void I2C_MasterTransferCreateHandle (I2C_Type *base, i2c_master_handle_t *handle, i2c_master_transfer_callback_t callback, void *userData)
    Initializes the I2C handle which is used in transactional functions.
- status_t I2C_MasterTransferNonBlocking (I2C_Type *base, i2c_master_handle_t *handle, i2c_master_transfer_t *xfer)
    Performs a master interrupt non-blocking transfer on the I2C bus.
- status_t I2C_MasterTransferGetCount (I2C_Type *base, i2c_master_handle_t *handle, size_t *count)
    Gets the master transfer status during a interrupt non-blocking transfer.
- void I2C_MasterTransferAbort (I2C_Type *base, i2c_master_handle_t *handle)
    Aborts an interrupt non-blocking transfer early.
- void I2C_MasterTransferHandleIRQ (I2C_Type *base, void *i2cHandle)
    Master interrupt handler.
- void I2C_SlaveTransferCreateHandle (I2C_Type *base, i2c_slave_handle_t *handle, i2c_slave_transfer_callback_t callback, void *userData)
    Initializes the I2C handle which is used in transactional functions.
- status_t I2C_SlaveTransferNonBlocking (I2C_Type *base, i2c_slave_handle_t *handle, uint32_t eventMask)
    Starts accepting slave transfers.
- void I2C_SlaveTransferAbort (I2C_Type *base, i2c_slave_handle_t *handle)
    Aborts the slave transfer.
- status_t I2C_SlaveTransferGetCount (I2C_Type *base, i2c_slave_handle_t *handle, size_t *count)
    Gets the slave transfer remaining bytes during a interrupt non-blocking transfer.
- void I2C_SlaveTransferHandleIRQ (I2C_Type *base, void *i2cHandle)
    Slave interrupt handler.

10.2.3 Data Structure Documentation

10.2.3.1 struct i2c_master_config_t

Data Fields

- bool enableMaster
    Enables the I2C peripheral at initialization time.
- bool enableStopHold
    Controls the stop hold enable.
- uint32_t baudRate_Bps
    Baud rate configuration of I2C peripheral.
- uint8_t glitchFilterWidth
    Controls the width of the glitch.

10.2.3.1.0.18 Field Documentation

10.2.3.1.0.18.1 bool i2c_master_config_t::enableMaster

10.2.3.1.0.18.2 bool i2c_master_config_t::enableStopHold

10.2.3.1.0.18.3 uint32_t i2c_master_config_t::baudRate_Bps

10.2.3.1.0.18.4 uint8_t i2c_master_config_t::glitchFilterWidth

10.2.3.2 struct i2c_slave_config_t

Data Fields

- bool enableSlave
  Enables the I2C peripheral at initialization time.
- bool enableGeneralCall
  Enables the general call addressing mode.
- bool enableWakeUp
  Enables/disables waking up MCU from low-power mode.
- bool enableBaudRateCtl
  Enables/disables independent slave baud rate on SCL in very fast I2C modes.
- uint16_t slaveAddress
  A slave address configuration.
- uint16_t upperAddress
  A maximum boundary slave address used in a range matching mode.
- i2c_slave_address_mode_t addressingMode
  An addressing mode configuration of i2c_slave_address_mode_config_t.
- uint32_t sclStopHoldTime_ns
  the delay from the rising edge of SCL (I2C clock) to the rising edge of SDA (I2C data) while SCL is high (stop condition), SDA hold time and SCL start hold time are also configured according to the SCL stop hold time.

10.2.3.2.0.19 Field Documentation

10.2.3.2.0.19.1 bool i2c_slave_config_t::enableSlave

10.2.3.2.0.19.2 bool i2c_slave_config_t::enableGeneralCall

10.2.3.2.0.19.3 bool i2c_slave_config_t::enableWakeUp

10.2.3.2.0.19.4 bool i2c_slave_config_t::enableBaudRateCtl

10.2.3.2.0.19.5 uint16_t i2c_slave_config_t::slaveAddress

10.2.3.2.0.19.6 uint16_t i2c_slave_config_t::upperAddress

10.2.3.2.0.19.7 i2c_slave_address_mode_t i2c_slave_config_t::addressingMode

10.2.3.2.0.19.8 uint32_t i2c_slave_config_t::sclStopHoldTime_ns

10.2.3.3 struct i2c_master_transfer_t

Data Fields

- uint32_t flags
  A transfer flag which controls the transfer.
- uint8_t slaveAddress
  7-bit slave address.
- i2c_direction_t direction
  A transfer direction, read or write.
- uint32_t subaddress
  A sub address.
- uint8_t subaddressSize
  A size of the command buffer.
- uint8_t *volatile data
  A transfer buffer.
- volatile size_t dataSize
  A transfer size.

10.2.3.3.0.20 Field Documentation

10.2.3.3.0.20.1 uint32_t i2c_master_transfer_t::flags

10.2.3.3.0.20.2 uint8_t i2c_master_transfer_t::slaveAddress

10.2.3.3.0.20.3 i2c_direction_t i2c_master_transfer_t::direction

10.2.3.3.0.20.4 uint32_t i2c_master_transfer_t::subaddress

Transferred MSB first.

10.2.3.3.0.20.5 uint8_t i2c_master_transfer_t::subaddressSize

10.2.3.3.0.20.6 uint8_t* volatile i2c_master_transfer_t::data

10.2.3.3.0.20.7 volatile size_t i2c_master_transfer_t::dataSize

10.2.3.4 struct _i2c_master_handle

I2C master handle typedef.

Data Fields

- i2c_master_transfer_t transfer
  I2C master transfer copy.
- size_t transferSize
  Total bytes to be transferred.
- uint8_t state
  A transfer state maintained during transfer.
- i2c_master_transfer_callback_t completionCallback
  A callback function called when the transfer is finished.
- void * userData
  A callback parameter passed to the callback function.

10.2.3.4.0.21 Field Documentation

10.2.3.4.0.21.1 i2c_master_transfer_t i2c_master_handle_t::transfer

10.2.3.4.0.21.2 size_t i2c_master_handle_t::transferSize

10.2.3.4.0.21.3 uint8_t i2c_master_handle_t::state

10.2.3.4.0.21.4 i2c_master_transfer_callback_t i2c_master_handle_t::completionCallback

10.2.3.4.0.21.5 void* i2c_master_handle_t::userData

10.2.3.5 struct i2c_slave_transfer_t

Data Fields

- i2c_slave_transfer_event_t event
  A reason that the callback is invoked.
- uint8_t *volatile data
  A transfer buffer.
- volatile size_t dataSize
  A transfer size.
- status_t completionStatus
  Success or error code describing how the transfer completed.
- size_t transferredCount
  A number of bytes actually transferred since the start or since the last repeated start.

10.2.3.5.0.22 Field Documentation

10.2.3.5.0.22.1 i2c_slave_transfer_event_t i2c_slave_transfer_t::event

10.2.3.5.0.22.2 uint8_t* volatile i2c_slave_transfer_t::data

10.2.3.5.0.22.3 volatile size_t i2c_slave_transfer_t::dataSize

10.2.3.5.0.22.4 status_t i2c_slave_transfer_t::completionStatus

Only applies for kI2C_SlaveCompletionEvent.

10.2.3.5.0.22.5 size_t i2c_slave_transfer_t::transferredCount

10.2.3.6 struct _i2c_slave_handle

I2C slave handle typedef.

Data Fields

- volatile bool isBusy
  Indicates whether a transfer is busy.
- i2c_slave_transfer_t transfer
  I2C slave transfer copy.
- uint32_t eventMask
  A mask of enabled events.
- i2c_slave_transfer_callback_t callback
  A callback function called at the transfer event.
- void * userData
  A callback parameter passed to the callback.

10.2.3.6.0.23 Field Documentation

10.2.3.6.0.23.1 volatile bool i2c_slave_handle_t::isBusy

10.2.3.6.0.23.2 i2c_slave_transfer_t i2c_slave_handle_t::transfer

10.2.3.6.0.23.3 uint32_t i2c_slave_handle_t::eventMask

10.2.3.6.0.23.4 i2c_slave_transfer_callback_t i2c_slave_handle_t::callback

10.2.3.6.0.23.5 void* i2c_slave_handle_t::userData

10.2.4 Macro Definition Documentation

10.2.4.1 #define FSL_I2C_DRIVER_VERSION (MAKE_VERSION(2, 0, 3))

10.2.5 Typedef Documentation

10.2.5.1 typedef void(* i2c_master_transfer_callback_t)(I2C_Type *base, i2c_master_handle_t *handle, status_t status, void *userData)

10.2.5.2 typedef void(* i2c_slave_transfer_callback_t)(I2C_Type *base, i2c_slave_transfer_t *xfer, void *userData)

10.2.6 Enumeration Type Documentation

10.2.6.1 enum _i2c_status

Enumerator

kStatus_I2C_Busy I2C is busy with current transfer.
kStatus_I2C_Idle Bus is Idle.
kStatus_I2C_Nak NAK received during transfer.
kStatus_I2C_ArbitrationLost Arbitration lost during transfer.
kStatus_I2C_Timeout Wait event timeout.
kStatus_I2C_Addr_Nak NAK received during the address probe.

10.2.6.2 enum _i2c_flags

The following status register flags can be cleared:

- kI2C_ArbitrationLostFlag
- kI2C_IntPendingFlag
- kI2C_StartDetectFlag
- kI2C_StopDetectFlag

Note

These enumerations are meant to be OR'd together to form a bit mask.

Enumerator

kI2C_ReceiveNakFlag I2C receive NAK flag.
kI2C_IntPendingFlag I2C interrupt pending flag.
kI2C_TransferDirectionFlag I2C transfer direction flag.
kI2C_RangeAddressMatchFlag I2C range address match flag.
kI2C_ArbitrationLostFlag I2C arbitration lost flag.
kI2C_BusBusyFlag I2C bus busy flag.
kI2C_AddressMatchFlag I2C address match flag.
kI2C_TransferCompleteFlag I2C transfer complete flag.
kI2C_StopDetectFlag I2C stop detect flag.
kI2C_StartDetectFlag I2C start detect flag.

10.2.6.3 enum _i2c_interrupt_enable

Enumerator

kI2C_GlobalInterruptEnable I2C global interrupt.
kI2C_StartStopDetectInterruptEnable I2C start&stop detect interrupt.

10.2.6.4 enum i2c_direction_t

Enumerator

kI2C_Write Master transmits to the slave.
kI2C_Read Master receives from the slave.

10.2.6.5 enum i2c_slave_address_mode_t

Enumerator

kI2C_Address7bit 7-bit addressing mode.
kI2C_RangeMatch Range address match addressing mode.

10.2.6.6 enum _i2c_master_transfer_flags

Enumerator

kI2C_TransferDefaultFlag A transfer starts with a start signal, stops with a stop signal.

kI2C_TransferNoStartFlag A transfer starts without a start signal.
kI2C_TransferRepeatedStartFlag A transfer starts with a repeated start signal.
kI2C_TransferNoStopFlag A transfer ends without a stop signal.

10.2.6.7 enum i2c_slave_transfer_event_t

These event enumerations are used for two related purposes. First, a bit mask created by OR'ing together events is passed to I2C_SlaveTransferNonBlocking() to specify which events to enable. Then, when the slave callback is invoked, it is passed the current event through its *transfer* parameter.

Note

These enumerations are meant to be OR'd together to form a bit mask of events.

Enumerator

kI2C_SlaveAddressMatchEvent Received the slave address after a start or repeated start.
kI2C_SlaveTransmitEvent A callback is requested to provide data to transmit (slave-transmitter role).
kI2C_SlaveReceiveEvent A callback is requested to provide a buffer in which to place received data (slave-receiver role).
kI2C_SlaveTransmitAckEvent A callback needs to either transmit an ACK or NACK.
kI2C_SlaveStartEvent A start/repeated start was detected.
kI2C_SlaveCompletionEvent A stop was detected or finished transfer, completing the transfer.
kI2C_SlaveGenaralcallEvent Received the general call address after a start or repeated start.
kI2C_SlaveAllEvents A bit mask of all available events.

10.2.7 Function Documentation

10.2.7.1 void I2C_MasterInit (I2C_Type * *base,* const i2c_master_config_t * *masterConfig,* uint32_t *srcClock_Hz*)

Call this API to ungate the I2C clock and configure the I2C with master configuration.

Note

This API should be called at the beginning of the application. Otherwise, any operation to the I2C module can cause a hard fault because the clock is not enabled. The configuration structure can be custom filled or it can be set with default values by using the I2C_MasterGetDefaultConfig(). After calling this API, the master is ready to transfer. This is an example.

```
* i2c_master_config_t config = {
* .enableMaster = true,
* .enableStopHold = false,
* .highDrive = false,
* .baudRate_Bps = 100000,
```

```
* .glitchFilterWidth = 0
* };
* I2C_MasterInit(I2C0, &config, 12000000U);
*
```

Parameters

base	I2C base pointer
masterConfig	A pointer to the master configuration structure
srcClock_Hz	I2C peripheral clock frequency in Hz

10.2.7.2 void I2C_SlaveInit (I2C_Type ∗ *base*, const i2c_slave_config_t ∗ *slaveConfig*, uint32_t *srcClock_Hz*)

Call this API to ungate the I2C clock and initialize the I2C with the slave configuration.

Note

This API should be called at the beginning of the application. Otherwise, any operation to the I2C module can cause a hard fault because the clock is not enabled. The configuration structure can partly be set with default values by I2C_SlaveGetDefaultConfig() or it can be custom filled by the user. This is an example.

```
* i2c_slave_config_t config = {
* .enableSlave = true,
* .enableGeneralCall = false,
* .addressingMode = kI2C_Address7bit,
* .slaveAddress = 0x1DU,
* .enableWakeUp = false,
* .enablehighDrive = false,
* .enableBaudRateCtl = false,
* .sclStopHoldTime_ns = 4000
* };
* I2C_SlaveInit(I2C0, &config, 12000000U);
*
```

Parameters

base	I2C base pointer
slaveConfig	A pointer to the slave configuration structure
srcClock_Hz	I2C peripheral clock frequency in Hz

10.2.7.3 void I2C_MasterDeinit (I2C_Type ∗ *base*)

Call this API to gate the I2C clock. The I2C master module can't work unless the I2C_MasterInit is called.

Parameters

base	I2C base pointer

10.2.7.4 void I2C_SlaveDeinit (I2C_Type * *base*)

Calling this API gates the I2C clock. The I2C slave module can't work unless the I2C_SlaveInit is called to enable the clock.

Parameters

base	I2C base pointer

10.2.7.5 void I2C_MasterGetDefaultConfig (i2c_master_config_t * *masterConfig*)

The purpose of this API is to get the configuration structure initialized for use in the I2C_Master-Configure(). Use the initialized structure unchanged in the I2C_MasterConfigure() or modify the structure before calling the I2C_MasterConfigure(). This is an example.

```
* i2c_master_config_t config;
* I2C_MasterGetDefaultConfig(&config);
*
```

Parameters

masterConfig	A pointer to the master configuration structure.

10.2.7.6 void I2C_SlaveGetDefaultConfig (i2c_slave_config_t * *slaveConfig*)

The purpose of this API is to get the configuration structure initialized for use in the I2C_SlaveConfigure(). Modify fields of the structure before calling the I2C_SlaveConfigure(). This is an example.

```
* i2c_slave_config_t config;
* I2C_SlaveGetDefaultConfig(&config);
*
```

Parameters

slaveConfig	A pointer to the slave configuration structure.

10.2.7.7 static void I2C_Enable (I2C_Type ∗ *base*, bool *enable*) [inline], [static]

Parameters

base	I2C base pointer
enable	Pass true to enable and false to disable the module.

10.2.7.8 uint32_t I2C_MasterGetStatusFlags (I2C_Type ∗ *base*)

Parameters

base	I2C base pointer

Returns

status flag, use status flag to AND _i2c_flags to get the related status.

10.2.7.9 static uint32_t I2C_SlaveGetStatusFlags (I2C_Type ∗ *base*) [inline], [static]

Parameters

base	I2C base pointer

Returns

status flag, use status flag to AND _i2c_flags to get the related status.

10.2.7.10 static void I2C_MasterClearStatusFlags (I2C_Type ∗ *base*, uint32_t *statusMask*) [inline], [static]

The following status register flags can be cleared kI2C_ArbitrationLostFlag and kI2C_IntPendingFlag.

Parameters

base	I2C base pointer
statusMask	The status flag mask, defined in type i2c_status_flag_t. The parameter can be any combination of the following values: • kI2C_StartDetectFlag (if available) • kI2C_StopDetectFlag (if available) • kI2C_ArbitrationLostFlag • kI2C_IntPendingFlagFlag

10.2.7.11 static void I2C_SlaveClearStatusFlags (I2C_Type * *base*, uint32_t *statusMask*) [inline], [static]

The following status register flags can be cleared kI2C_ArbitrationLostFlag and kI2C_IntPendingFlag

Parameters

base	I2C base pointer
statusMask	The status flag mask, defined in type i2c_status_flag_t. The parameter can be any combination of the following values: • kI2C_StartDetectFlag (if available) • kI2C_StopDetectFlag (if available) • kI2C_ArbitrationLostFlag • kI2C_IntPendingFlagFlag

10.2.7.12 void I2C_EnableInterrupts (I2C_Type * *base*, uint32_t *mask*)

Parameters

base	I2C base pointer
mask	interrupt source The parameter can be combination of the following source if defined: • kI2C_GlobalInterruptEnable • kI2C_StopDetectInterruptEnable/kI2C_StartDetectInterruptEnable • kI2C_SdaTimeoutInterruptEnable

10.2.7.13 void I2C_DisableInterrupts (I2C_Type * *base*, uint32_t *mask*)

Parameters

base	I2C base pointer
mask	interrupt source The parameter can be combination of the following source if defined: • kI2C_GlobalInterruptEnable • kI2C_StopDetectInterruptEnable/kI2C_StartDetectInterruptEnable • kI2C_SdaTimeoutInterruptEnable

10.2.7.14 static uint32_t I2C_GetDataRegAddr (I2C_Type ∗ *base*) [inline], [static]

This API is used to provide a transfer address for I2C DMA transfer configuration.

Parameters

base	I2C base pointer

Returns

data register address

10.2.7.15 void I2C_MasterSetBaudRate (I2C_Type ∗ *base,* uint32_t *baudRate_Bps,* uint32_t *srcClock_Hz*)

Parameters

base	I2C base pointer
baudRate_Bps	the baud rate value in bps
srcClock_Hz	Source clock

10.2.7.16 status_t I2C_MasterStart (I2C_Type ∗ *base,* uint8_t *address,* i2c_direction_t *direction*)

This function is used to initiate a new master mode transfer by sending the START signal. The slave address is sent following the I2C START signal.

Parameters

base	I2C peripheral base pointer
address	7-bit slave device address.
direction	Master transfer directions(transmit/receive).

Return values

kStatus_Success	Successfully send the start signal.
kStatus_I2C_Busy	Current bus is busy.

10.2.7.17 status_t I2C_MasterStop (I2C_Type * *base*)

Return values

kStatus_Success	Successfully send the stop signal.
kStatus_I2C_Timeout	Send stop signal failed, timeout.

10.2.7.18 status_t I2C_MasterRepeatedStart (I2C_Type * *base,* uint8_t *address,* i2c_direction_t *direction*)

Parameters

base	I2C peripheral base pointer
address	7-bit slave device address.
direction	Master transfer directions(transmit/receive).

Return values

kStatus_Success	Successfully send the start signal.
kStatus_I2C_Busy	Current bus is busy but not occupied by current I2C master.

10.2.7.19 status_t I2C_MasterWriteBlocking (I2C_Type * *base,* const uint8_t * *txBuff,* size_t *txSize,* uint32_t *flags*)

Parameters

base	The I2C peripheral base pointer.
txBuff	The pointer to the data to be transferred.
txSize	The length in bytes of the data to be transferred.
flags	Transfer control flag to decide whether need to send a stop, use kI2C_Transfer-DefaultFlag to issue a stop and kI2C_TransferNoStop to not send a stop.

Return values

kStatus_Success	Successfully complete the data transmission.
kStatus_I2C_Arbitration-Lost	Transfer error, arbitration lost.
kStataus_I2C_Nak	Transfer error, receive NAK during transfer.

10.2.7.20 status_t I2C_MasterReadBlocking (I2C_Type ∗ *base,* uint8_t ∗ *rxBuff,* size_t *rxSize,* uint32_t *flags*)

Note

The I2C_MasterReadBlocking function stops the bus before reading the final byte. Without stopping the bus prior for the final read, the bus issues another read, resulting in garbage data being read into the data register.

Parameters

base	I2C peripheral base pointer.
rxBuff	The pointer to the data to store the received data.
rxSize	The length in bytes of the data to be received.
flags	Transfer control flag to decide whether need to send a stop, use kI2C_Transfer-DefaultFlag to issue a stop and kI2C_TransferNoStop to not send a stop.

Return values

kStatus_Success	Successfully complete the data transmission.

kStatus_I2C_Timeout	Send stop signal failed, timeout.

10.2.7.21 status_t I2C_SlaveWriteBlocking (I2C_Type ∗ *base,* const uint8_t ∗ *txBuff,* size_t *txSize*)

Parameters

base	The I2C peripheral base pointer.
txBuff	The pointer to the data to be transferred.
txSize	The length in bytes of the data to be transferred.

Return values

kStatus_Success	Successfully complete the data transmission.
kStatus_I2C_Arbitration-Lost	Transfer error, arbitration lost.
kStataus_I2C_Nak	Transfer error, receive NAK during transfer.

10.2.7.22 void I2C_SlaveReadBlocking (I2C_Type ∗ *base,* uint8_t ∗ *rxBuff,* size_t *rxSize*)

Parameters

base	I2C peripheral base pointer.
rxBuff	The pointer to the data to store the received data.
rxSize	The length in bytes of the data to be received.

10.2.7.23 status_t I2C_MasterTransferBlocking (I2C_Type ∗ *base,* i2c_master_transfer_t ∗ *xfer*)

Note

The API does not return until the transfer succeeds or fails due to arbitration lost or receiving a NAK.

Parameters

base	I2C peripheral base address.
xfer	Pointer to the transfer structure.

Return values

kStatus_Success	Successfully complete the data transmission.
kStatus_I2C_Busy	Previous transmission still not finished.
kStatus_I2C_Timeout	Transfer error, wait signal timeout.
kStatus_I2C_Arbitration-Lost	Transfer error, arbitration lost.
kStataus_I2C_Nak	Transfer error, receive NAK during transfer.

10.2.7.24 void I2C_MasterTransferCreateHandle (I2C_Type * *base*, i2c_master_handle_t * *handle*, i2c_master_transfer_callback_t *callback*, void * *userData*)

Parameters

base	I2C base pointer.
handle	pointer to i2c_master_handle_t structure to store the transfer state.
callback	pointer to user callback function.
userData	user parameter passed to the callback function.

10.2.7.25 status_t I2C_MasterTransferNonBlocking (I2C_Type * *base*, i2c_master_handle_t * *handle*, i2c_master_transfer_t * *xfer*)

Note

Calling the API returns immediately after transfer initiates. The user needs to call I2C_MasterGet-TransferCount to poll the transfer status to check whether the transfer is finished. If the return status is not kStatus_I2C_Busy, the transfer is finished.

Parameters

base	I2C base pointer.
handle	pointer to i2c_master_handle_t structure which stores the transfer state.
xfer	pointer to i2c_master_transfer_t structure.

Return values

kStatus_Success	Successfully start the data transmission.
kStatus_I2C_Busy	Previous transmission still not finished.
kStatus_I2C_Timeout	Transfer error, wait signal timeout.

10.2.7.26 status_t I2C_MasterTransferGetCount (I2C_Type * *base*, i2c_master_handle_t * *handle*, size_t * *count*)

Parameters

base	I2C base pointer.
handle	pointer to i2c_master_handle_t structure which stores the transfer state.
count	Number of bytes transferred so far by the non-blocking transaction.

Return values

kStatus_InvalidArgument	count is Invalid.
kStatus_Success	Successfully return the count.

10.2.7.27 void I2C_MasterTransferAbort (I2C_Type * *base*, i2c_master_handle_t * *handle*)

Note

This API can be called at any time when an interrupt non-blocking transfer initiates to abort the transfer early.

Parameters

base	I2C base pointer.
handle	pointer to i2c_master_handle_t structure which stores the transfer state

10.2.7.28 void I2C_MasterTransferHandleIRQ (I2C_Type * *base*, void * *i2cHandle*)

Parameters

base	I2C base pointer.
i2cHandle	pointer to i2c_master_handle_t structure.

10.2.7.29 void I2C_SlaveTransferCreateHandle (I2C_Type * *base*, i2c_slave_handle_t * *handle*, i2c_slave_transfer_callback_t *callback*, void * *userData*)

Parameters

base	I2C base pointer.
handle	pointer to i2c_slave_handle_t structure to store the transfer state.
callback	pointer to user callback function.
userData	user parameter passed to the callback function.

10.2.7.30 status_t I2C_SlaveTransferNonBlocking (I2C_Type * *base*, i2c_slave_handle_t * *handle*, uint32_t *eventMask*)

Call this API after calling the I2C_SlaveInit() and I2C_SlaveTransferCreateHandle() to start processing transactions driven by an I2C master. The slave monitors the I2C bus and passes events to the callback that was passed into the call to I2C_SlaveTransferCreateHandle(). The callback is always invoked from the interrupt context.

The set of events received by the callback is customizable. To do so, set the *eventMask* parameter to the OR'd combination of i2c_slave_transfer_event_t enumerators for the events you wish to receive. The k-I2C_SlaveTransmitEvent and #kLPI2C_SlaveReceiveEvent events are always enabled and do not need to be included in the mask. Alternatively, pass 0 to get a default set of only the transmit and receive events that are always enabled. In addition, the kI2C_SlaveAllEvents constant is provided as a convenient way to enable all events.

Parameters

base	The I2C peripheral base address.
handle	Pointer to #i2c_slave_handle_t structure which stores the transfer state.
eventMask	Bit mask formed by OR'ing together i2c_slave_transfer_event_t enumerators to specify which events to send to the callback. Other accepted values are 0 to get a default set of only the transmit and receive events, and kI2C_SlaveAllEvents to enable all events.

Return values

#kStatus_Success	Slave transfers were successfully started.
kStatus_I2C_Busy	Slave transfers have already been started on this handle.

10.2.7.31 void I2C_SlaveTransferAbort (I2C_Type * *base*, i2c_slave_handle_t * *handle*)

Note

This API can be called at any time to stop slave for handling the bus events.

Parameters

base	I2C base pointer.
handle	pointer to i2c_slave_handle_t structure which stores the transfer state.

10.2.7.32 status_t I2C_SlaveTransferGetCount (I2C_Type * *base*, i2c_slave_handle_t * *handle*, size_t * *count*)

Parameters

base	I2C base pointer.
handle	pointer to i2c_slave_handle_t structure.
count	Number of bytes transferred so far by the non-blocking transaction.

Return values

kStatus_InvalidArgument	count is Invalid.
kStatus_Success	Successfully return the count.

10.2.7.33 void I2C_SlaveTransferHandleIRQ (I2C_Type * *base*, void * *i2cHandle*)

Parameters

base	I2C base pointer.
i2cHandle	pointer to i2c_slave_handle_t structure which stores the transfer state

10.3 I2C eDMA Driver

10.3.1 Overview

Data Structures

- struct i2c_master_edma_handle_t
  I2C master eDMA transfer structure. More...

Typedefs

- typedef void(∗ i2c_master_edma_transfer_callback_t)(I2C_Type ∗base, i2c_master_edma_handle-_t ∗handle, status_t status, void ∗userData)
  I2C master eDMA transfer callback typedef.

I2C Block eDMA Transfer Operation

- void I2C_MasterCreateEDMAHandle (I2C_Type ∗base, i2c_master_edma_handle_t ∗handle, i2c_-master_edma_transfer_callback_t callback, void ∗userData, edma_handle_t ∗edmaHandle)
  Initializes the I2C handle which is used in transcational functions.
- status_t I2C_MasterTransferEDMA (I2C_Type ∗base, i2c_master_edma_handle_t ∗handle, i2c_-master_transfer_t ∗xfer)
  Performs a master eDMA non-blocking transfer on the I2C bus.
- status_t I2C_MasterTransferGetCountEDMA (I2C_Type ∗base, i2c_master_edma_handle_-t ∗handle, size_t ∗count)
  Gets a master transfer status during the eDMA non-blocking transfer.
- void I2C_MasterTransferAbortEDMA (I2C_Type ∗base, i2c_master_edma_handle_t ∗handle)
  Aborts a master eDMA non-blocking transfer early.

10.3.2 Data Structure Documentation

10.3.2.1 struct _i2c_master_edma_handle

I2C master eDMA handle typedef.

Data Fields

- i2c_master_transfer_t transfer
  I2C master transfer structure.
- size_t transferSize
  Total bytes to be transferred.
- uint8_t nbytes
  eDMA minor byte transfer count initially configured.
- uint8_t state

I2C master transfer status.
- edma_handle_t ∗ dmaHandle
  The eDMA handler used.
- i2c_master_edma_transfer_callback_t completionCallback
  A callback function called after the eDMA transfer is finished.
- void ∗ userData
  A callback parameter passed to the callback function.

10.3.2.1.0.24 Field Documentation

10.3.2.1.0.24.1 i2c_master_transfer_t i2c_master_edma_handle_t::transfer

10.3.2.1.0.24.2 size_t i2c_master_edma_handle_t::transferSize

10.3.2.1.0.24.3 uint8_t i2c_master_edma_handle_t::nbytes

10.3.2.1.0.24.4 uint8_t i2c_master_edma_handle_t::state

10.3.2.1.0.24.5 edma_handle_t∗ i2c_master_edma_handle_t::dmaHandle

10.3.2.1.0.24.6 i2c_master_edma_transfer_callback_t i2c_master_edma_handle_t::completion-Callback

10.3.2.1.0.24.7 void∗ i2c_master_edma_handle_t::userData

10.3.3 Typedef Documentation

10.3.3.1 typedef void(∗ i2c_master_edma_transfer_callback_t)(I2C_Type ∗base, i2c_master_edma_handle_t ∗handle, status_t status, void ∗userData)

10.3.4 Function Documentation

10.3.4.1 void I2C_MasterCreateEDMAHandle (I2C_Type ∗ *base*, i2c_master_edma_-handle_t ∗ *handle*, i2c_master_edma_transfer_callback_t *callback*, void ∗ *userData*, edma_handle_t ∗ *edmaHandle*)

Parameters

base	I2C peripheral base address.
handle	A pointer to the i2c_master_edma_handle_t structure.
callback	A pointer to the user callback function.

userData	A user parameter passed to the callback function.
edmaHandle	eDMA handle pointer.

10.3.4.2 status_t I2C_MasterTransferEDMA (I2C_Type * *base,* i2c_master_edma_handle_t * *handle,* i2c_master_transfer_t * *xfer*)

Parameters

base	I2C peripheral base address.
handle	A pointer to the i2c_master_edma_handle_t structure.
xfer	A pointer to the transfer structure of i2c_master_transfer_t.

Return values

kStatus_Success	Sucessfully completed the data transmission.
kStatus_I2C_Busy	A previous transmission is still not finished.
kStatus_I2C_Timeout	Transfer error, waits for a signal timeout.
kStatus_I2C_ArbitrationLost	Transfer error, arbitration lost.
kStataus_I2C_Nak	Transfer error, receive NAK during transfer.

10.3.4.3 status_t I2C_MasterTransferGetCountEDMA (I2C_Type * *base,* i2c_master_edma_handle_t * *handle,* size_t * *count*)

Parameters

base	I2C peripheral base address.
handle	A pointer to the i2c_master_edma_handle_t structure.
count	A number of bytes transferred by the non-blocking transaction.

10.3.4.4 void I2C_MasterTransferAbortEDMA (I2C_Type * *base,* i2c_master_edma_handle_t * *handle*)

Parameters

base	I2C peripheral base address.
handle	A pointer to the i2c_master_edma_handle_t structure.

10.4 I2C DMA Driver

10.4.1 Overview

Data Structures

- struct i2c_master_dma_handle_t
  I2C master DMA transfer structure. More...

Typedefs

- typedef void(∗ i2c_master_dma_transfer_callback_t)(I2C_Type ∗base, i2c_master_dma_handle_t ∗handle, status_t status, void ∗userData)
  I2C master DMA transfer callback typedef.

I2C Block DMA Transfer Operation

- void I2C_MasterTransferCreateHandleDMA (I2C_Type ∗base, i2c_master_dma_handle_t ∗handle, i2c_master_dma_transfer_callback_t callback, void ∗userData, dma_handle_t ∗dmaHandle)
  Initializes the I2C handle which is used in transcational functions.
- status_t I2C_MasterTransferDMA (I2C_Type ∗base, i2c_master_dma_handle_t ∗handle, i2c_master_transfer_t ∗xfer)
  Performs a master DMA non-blocking transfer on the I2C bus.
- status_t I2C_MasterTransferGetCountDMA (I2C_Type ∗base, i2c_master_dma_handle_t ∗handle, size_t ∗count)
  Gets a master transfer status during a DMA non-blocking transfer.
- void I2C_MasterTransferAbortDMA (I2C_Type ∗base, i2c_master_dma_handle_t ∗handle)
  Aborts a master DMA non-blocking transfer early.

10.4.2 Data Structure Documentation

10.4.2.1 struct _i2c_master_dma_handle

I2C master DMA handle typedef.

Data Fields

- i2c_master_transfer_t transfer
  I2C master transfer struct.
- size_t transferSize
  Total bytes to be transferred.
- uint8_t state
  I2C master transfer status.
- dma_handle_t ∗ dmaHandle

The DMA handler used.
- i2c_master_dma_transfer_callback_t completionCallback
  A callback function called after the DMA transfer finished.
- void * userData
  A callback parameter passed to the callback function.

10.4.2.1.0.25 Field Documentation

10.4.2.1.0.25.1 i2c_master_transfer_t i2c_master_dma_handle_t::transfer

10.4.2.1.0.25.2 size_t i2c_master_dma_handle_t::transferSize

10.4.2.1.0.25.3 uint8_t i2c_master_dma_handle_t::state

10.4.2.1.0.25.4 dma_handle_t* i2c_master_dma_handle_t::dmaHandle

10.4.2.1.0.25.5 i2c_master_dma_transfer_callback_t i2c_master_dma_handle_t::completionCallback

10.4.2.1.0.25.6 void* i2c_master_dma_handle_t::userData

10.4.3 Typedef Documentation

10.4.3.1 typedef void(* i2c_master_dma_transfer_callback_t)(I2C_Type *base, i2c_master_dma_handle_t *handle, status_t status, void *userData)

10.4.4 Function Documentation

10.4.4.1 void I2C_MasterTransferCreateHandleDMA (I2C_Type * *base*, i2c_master_dma_handle_t * *handle*, i2c_master_dma_transfer_callback_t *callback*, void * *userData*, dma_handle_t * *dmaHandle*)

Parameters

base	I2C peripheral base address
handle	Pointer to the i2c_master_dma_handle_t structure
callback	Pointer to the user callback function
userData	A user parameter passed to the callback function
dmaHandle	DMA handle pointer

10.4.4.2 status_t I2C_MasterTransferDMA (I2C_Type * *base*, i2c_master_dma_handle_t * *handle*, i2c_master_transfer_t * *xfer*)

Parameters

base	I2C peripheral base address
handle	A pointer to the i2c_master_dma_handle_t structure
xfer	A pointer to the transfer structure of the i2c_master_transfer_t

Return values

kStatus_Success	Sucessfully completes the data transmission.
kStatus_I2C_Busy	A previous transmission is still not finished.
kStatus_I2C_Timeout	A transfer error, waits for the signal timeout.
kStatus_I2C_Arbitration-Lost	A transfer error, arbitration lost.
kStataus_I2C_Nak	A transfer error, receives NAK during transfer.

10.4.4.3 status_t I2C_MasterTransferGetCountDMA (I2C_Type ∗ *base*, i2c_master_dma_handle_t ∗ *handle*, size_t ∗ *count*)

Parameters

base	I2C peripheral base address
handle	A pointer to the i2c_master_dma_handle_t structure
count	A number of bytes transferred so far by the non-blocking transaction.

10.4.4.4 void I2C_MasterTransferAbortDMA (I2C_Type ∗ *base*, i2c_master_dma_handle_t ∗ *handle*)

Parameters

base	I2C peripheral base address
handle	A pointer to the i2c_master_dma_handle_t structure.

10.5 I2C FreeRTOS Driver

10.5.1 Overview

I2C RTOS Operation

- status_t I2C_RTOS_Init (i2c_rtos_handle_t *handle, I2C_Type *base, const i2c_master_config_t *masterConfig, uint32_t srcClock_Hz)
  Initializes I2C.
- status_t I2C_RTOS_Deinit (i2c_rtos_handle_t *handle)
  Deinitializes the I2C.
- status_t I2C_RTOS_Transfer (i2c_rtos_handle_t *handle, i2c_master_transfer_t *transfer)
  Performs the I2C transfer.

10.5.2 Function Documentation

10.5.2.1 status_t I2C_RTOS_Init (i2c_rtos_handle_t * *handle*, I2C_Type * *base*, const i2c_master_config_t * *masterConfig*, uint32_t *srcClock_Hz*)

This function initializes the I2C module and the related RTOS context.

Parameters

handle	The RTOS I2C handle, the pointer to an allocated space for RTOS context.
base	The pointer base address of the I2C instance to initialize.
masterConfig	The configuration structure to set-up I2C in master mode.
srcClock_Hz	The frequency of an input clock of the I2C module.

Returns

status of the operation.

10.5.2.2 status_t I2C_RTOS_Deinit (i2c_rtos_handle_t * *handle*)

This function deinitializes the I2C module and the related RTOS context.

Parameters

handle	The RTOS I2C handle.

10.5.2.3 status_t I2C_RTOS_Transfer (i2c_rtos_handle_t * *handle,* i2c_master_transfer_t * *transfer*)

This function performs the I2C transfer according to the data given in the transfer structure.

Parameters

handle	The RTOS I2C handle.
transfer	A structure specifying the transfer parameters.

Returns

status of the operation.

Chapter 11
LLWU: Low-Leakage Wakeup Unit Driver

11.1 Overview

The MCUXpresso SDK provides a peripheral driver for the Low-Leakage Wakeup Unit (LLWU) module of MCUXpresso SDK devices. The LLWU module allows the user to select external pin sources and internal modules as a wake-up source from low-leakage power modes.

11.2 External wakeup pins configurations

Configures the external wakeup pins' working modes, gets, and clears the wake pin flags. External wakeup pins are accessed by the `pinIndex`, which is started from 1. Numbers of the external pins depend on the SoC configuration.

11.3 Internal wakeup modules configurations

Enables/disables the internal wakeup modules and gets the module flags. Internal modules are accessed by `moduleIndex`, which is started from 1. Numbers of external pins depend the on SoC configuration.

11.4 Digital pin filter for external wakeup pin configurations

Configures the digital pin filter of the external wakeup pins' working modes, gets, and clears the pin filter flags. Digital pin filters are accessed by the `filterIndex`, which is started from 1. Numbers of external pins depend on the SoC configuration.

Data Structures

- struct llwu_external_pin_filter_mode_t
  An external input pin filter control structure. More...

Enumerations

- enum llwu_external_pin_mode_t {
  kLLWU_ExternalPinDisable = 0U,
  kLLWU_ExternalPinRisingEdge = 1U,
  kLLWU_ExternalPinFallingEdge = 2U,
  kLLWU_ExternalPinAnyEdge = 3U }
  External input pin control modes.
- enum llwu_pin_filter_mode_t {
  kLLWU_PinFilterDisable = 0U,
  kLLWU_PinFilterRisingEdge = 1U,
  kLLWU_PinFilterFallingEdge = 2U,
  kLLWU_PinFilterAnyEdge = 3U }
  Digital filter control modes.

Driver version

- #define FSL_LLWU_DRIVER_VERSION (MAKE_VERSION(2, 0, 1))
  LLWU driver version 2.0.1.

Low-Leakage Wakeup Unit Control APIs

- void LLWU_SetExternalWakeupPinMode (LLWU_Type ∗base, uint32_t pinIndex, llwu_external-_pin_mode_t pinMode)
  Sets the external input pin source mode.
- bool LLWU_GetExternalWakeupPinFlag (LLWU_Type ∗base, uint32_t pinIndex)
  Gets the external wakeup source flag.
- void LLWU_ClearExternalWakeupPinFlag (LLWU_Type ∗base, uint32_t pinIndex)
  Clears the external wakeup source flag.
- void LLWU_SetPinFilterMode (LLWU_Type ∗base, uint32_t filterIndex, llwu_external_pin_filter-_mode_t filterMode)
  Sets the pin filter configuration.
- bool LLWU_GetPinFilterFlag (LLWU_Type ∗base, uint32_t filterIndex)
  Gets the pin filter configuration.
- void LLWU_ClearPinFilterFlag (LLWU_Type ∗base, uint32_t filterIndex)
  Clears the pin filter configuration.

11.5 Data Structure Documentation

11.5.1 struct llwu_external_pin_filter_mode_t

Data Fields

- uint32_t pinIndex
  A pin number.
- llwu_pin_filter_mode_t filterMode
  Filter mode.

11.6 Macro Definition Documentation

11.6.1 #define FSL_LLWU_DRIVER_VERSION (MAKE_VERSION(2, 0, 1))

11.7 Enumeration Type Documentation

11.7.1 enum llwu_external_pin_mode_t

Enumerator

kLLWU_ExternalPinDisable Pin disabled as a wakeup input.
kLLWU_ExternalPinRisingEdge Pin enabled with the rising edge detection.
kLLWU_ExternalPinFallingEdge Pin enabled with the falling edge detection.
kLLWU_ExternalPinAnyEdge Pin enabled with any change detection.

11.7.2 enum llwu_pin_filter_mode_t

Enumerator

kLLWU_PinFilterDisable Filter disabled.
kLLWU_PinFilterRisingEdge Filter positive edge detection.
kLLWU_PinFilterFallingEdge Filter negative edge detection.
kLLWU_PinFilterAnyEdge Filter any edge detection.

11.8 Function Documentation

11.8.1 void LLWU_SetExternalWakeupPinMode (LLWU_Type ∗ *base*, uint32_t *pinIndex*, llwu_external_pin_mode_t *pinMode*)

This function sets the external input pin source mode that is used as a wake up source.

Parameters

base	LLWU peripheral base address.
pinIndex	A pin index to be enabled as an external wakeup source starting from 1.
pinMode	A pin configuration mode defined in the llwu_external_pin_modes_t.

11.8.2 bool LLWU_GetExternalWakeupPinFlag (LLWU_Type ∗ *base*, uint32_t *pinIndex*)

This function checks the external pin flag to detect whether the MCU is woken up by the specific pin.

Parameters

base	LLWU peripheral base address.
pinIndex	A pin index, which starts from 1.

Returns

True if the specific pin is a wakeup source.

11.8.3 void LLWU_ClearExternalWakeupPinFlag (LLWU_Type ∗ *base*, uint32_t *pinIndex*)

This function clears the external wakeup source flag for a specific pin.

Parameters

base	LLWU peripheral base address.
pinIndex	A pin index, which starts from 1.

11.8.4 void LLWU_SetPinFilterMode (LLWU_Type ∗ *base*, uint32_t *filterIndex*, llwu_external_pin_filter_mode_t *filterMode*)

This function sets the pin filter configuration.

Parameters

base	LLWU peripheral base address.
filterIndex	A pin filter index used to enable/disable the digital filter, starting from 1.
filterMode	A filter mode configuration

11.8.5 bool LLWU_GetPinFilterFlag (LLWU_Type ∗ *base*, uint32_t *filterIndex*)

This function gets the pin filter flag.

Parameters

base	LLWU peripheral base address.
filterIndex	A pin filter index, which starts from 1.

Returns

True if the flag is a source of the existing low-leakage power mode.

11.8.6 void LLWU_ClearPinFilterFlag (LLWU_Type ∗ *base*, uint32_t *filterIndex*)

This function clears the pin filter flag.

Parameters

base	LLWU peripheral base address.
filterIndex	A pin filter index to clear the flag, starting from 1.

Chapter 12
LPTMR: Low-Power Timer

12.1 Overview

The MCUXpresso SDK provides a driver for the Low-Power Timer (LPTMR) of MCUXpresso SDK devices.

12.2 Function groups

The LPTMR driver supports operating the module as a time counter or as a pulse counter.

12.2.1 Initialization and deinitialization

The function LPTMR_Init() initializes the LPTMR with specified configurations. The function LPTMR_-GetDefaultConfig() gets the default configurations. The initialization function configures the LPTMR for a timer or a pulse counter mode mode. It also sets up the LPTMR's free running mode operation and a clock source.

The function LPTMR_DeInit() disables the LPTMR module and gates the module clock.

12.2.2 Timer period Operations

The function LPTMR_SetTimerPeriod() sets the timer period in units of count. Timers counts from 0 to the count value set here.

The function LPTMR_GetCurrentTimerCount() reads the current timer counting value. This function returns the real-time timer counting value ranging from 0 to a timer period.

The timer period operation function takes the count value in ticks. Call the utility macros provided in the fsl_common.h file to convert to microseconds or milliseconds.

12.2.3 Start and Stop timer operations

The function LPTMR_StartTimer() starts the timer counting. After calling this function, the timer counts up to the counter value set earlier by using the LPTMR_SetPeriod() function. Each time the timer reaches the count value and increments, it generates a trigger pulse and sets the timeout interrupt flag. An interrupt is also triggered if the timer interrupt is enabled.

The function LPTMR_StopTimer() stops the timer counting and resets the timer's counter register.

12.2.4 Status

Provides functions to get and clear the LPTMR status.

12.2.5 Interrupt

Provides functions to enable/disable LPTMR interrupts and get the currently enabled interrupts.

12.3 Typical use case

12.3.1 LPTMR tick example

Updates the LPTMR period and toggles an LED periodically.

```
int main(void)
{
    uint32_t currentCounter = 0U;
    lptmr_config_t lptmrConfig;

    LED_INIT();

    /* Board pin, clock, debug console initialization */
    BOARD_InitHardware();

    /* Configures the LPTMR */
    LPTMR_GetDefaultConfig(&lptmrConfig);

    /* Initializes the LPTMR */
    LPTMR_Init(LPTMR0, &lptmrConfig);

    /* Sets the timer period */
    LPTMR_SetTimerPeriod(LPTMR0, USEC_TO_COUNT(1000000U, LPTMR_SOURCE_CLOCK));

    /* Enables a timer interrupt */
    LPTMR_EnableInterrupts(LPTMR0,
      kLPTMR_TimerInterruptEnable);

    /* Enables the NVIC */
    EnableIRQ(LPTMR0_IRQn);

    PRINTF("Low Power Timer Example\r\n");

    /* Starts counting */
    LPTMR_StartTimer(LPTMR0);
    while (1)
    {
        if (currentCounter != lptmrCounter)
        {
            currentCounter = lptmrCounter;
            PRINTF("LPTMR interrupt No.%d \r\n", currentCounter);
        }
    }
}
```

Data Structures

- struct lptmr_config_t
  LPTMR config structure. More...

Enumerations

- enum lptmr_pin_select_t {
  kLPTMR_PinSelectInput_0 = 0x0U,
  kLPTMR_PinSelectInput_1 = 0x1U,
  kLPTMR_PinSelectInput_2 = 0x2U,
  kLPTMR_PinSelectInput_3 = 0x3U }
  LPTMR pin selection used in pulse counter mode.
- enum lptmr_pin_polarity_t {
  kLPTMR_PinPolarityActiveHigh = 0x0U,
  kLPTMR_PinPolarityActiveLow = 0x1U }
  LPTMR pin polarity used in pulse counter mode.
- enum lptmr_timer_mode_t {
  kLPTMR_TimerModeTimeCounter = 0x0U,
  kLPTMR_TimerModePulseCounter = 0x1U }
  LPTMR timer mode selection.
- enum lptmr_prescaler_glitch_value_t {
  kLPTMR_Prescale_Glitch_0 = 0x0U,
  kLPTMR_Prescale_Glitch_1 = 0x1U,
  kLPTMR_Prescale_Glitch_2 = 0x2U,
  kLPTMR_Prescale_Glitch_3 = 0x3U,
  kLPTMR_Prescale_Glitch_4 = 0x4U,
  kLPTMR_Prescale_Glitch_5 = 0x5U,
  kLPTMR_Prescale_Glitch_6 = 0x6U,
  kLPTMR_Prescale_Glitch_7 = 0x7U,
  kLPTMR_Prescale_Glitch_8 = 0x8U,
  kLPTMR_Prescale_Glitch_9 = 0x9U,
  kLPTMR_Prescale_Glitch_10 = 0xAU,
  kLPTMR_Prescale_Glitch_11 = 0xBU,
  kLPTMR_Prescale_Glitch_12 = 0xCU,
  kLPTMR_Prescale_Glitch_13 = 0xDU,
  kLPTMR_Prescale_Glitch_14 = 0xEU,
  kLPTMR_Prescale_Glitch_15 = 0xFU }
  LPTMR prescaler/glitch filter values.
- enum lptmr_prescaler_clock_select_t {
  kLPTMR_PrescalerClock_0 = 0x0U,
  kLPTMR_PrescalerClock_1 = 0x1U,
  kLPTMR_PrescalerClock_2 = 0x2U,
  kLPTMR_PrescalerClock_3 = 0x3U }
  LPTMR prescaler/glitch filter clock select.
- enum lptmr_interrupt_enable_t { kLPTMR_TimerInterruptEnable = LPTMR_CSR_TIE_MASK }
  List of the LPTMR interrupts.
- enum lptmr_status_flags_t { kLPTMR_TimerCompareFlag = LPTMR_CSR_TCF_MASK }
  List of the LPTMR status flags.

Driver version

- #define FSL_LPTMR_DRIVER_VERSION (MAKE_VERSION(2, 0, 1))

Version 2.0.1.

Initialization and deinitialization

- void LPTMR_Init (LPTMR_Type *base, const lptmr_config_t *config)
  Ungates the LPTMR clock and configures the peripheral for a basic operation.
- void LPTMR_Deinit (LPTMR_Type *base)
  Gates the LPTMR clock.
- void LPTMR_GetDefaultConfig (lptmr_config_t *config)
  Fills in the LPTMR configuration structure with default settings.

Interrupt Interface

- static void LPTMR_EnableInterrupts (LPTMR_Type *base, uint32_t mask)
  Enables the selected LPTMR interrupts.
- static void LPTMR_DisableInterrupts (LPTMR_Type *base, uint32_t mask)
  Disables the selected LPTMR interrupts.
- static uint32_t LPTMR_GetEnabledInterrupts (LPTMR_Type *base)
  Gets the enabled LPTMR interrupts.

Status Interface

- static uint32_t LPTMR_GetStatusFlags (LPTMR_Type *base)
  Gets the LPTMR status flags.
- static void LPTMR_ClearStatusFlags (LPTMR_Type *base, uint32_t mask)
  Clears the LPTMR status flags.

Read and write the timer period

- static void LPTMR_SetTimerPeriod (LPTMR_Type *base, uint32_t ticks)
  Sets the timer period in units of count.
- static uint32_t LPTMR_GetCurrentTimerCount (LPTMR_Type *base)
  Reads the current timer counting value.

Timer Start and Stop

- static void LPTMR_StartTimer (LPTMR_Type *base)
  Starts the timer.
- static void LPTMR_StopTimer (LPTMR_Type *base)
  Stops the timer.

12.4 Data Structure Documentation

12.4.1 struct lptmr_config_t

This structure holds the configuration settings for the LPTMR peripheral. To initialize this structure to reasonable defaults, call the LPTMR_GetDefaultConfig() function and pass a pointer to your configuration structure instance.

The configuration struct can be made constant so it resides in flash.

Data Fields

- lptmr_timer_mode_t timerMode
  Time counter mode or pulse counter mode.
- lptmr_pin_select_t pinSelect
  LPTMR pulse input pin select; used only in pulse counter mode.
- lptmr_pin_polarity_t pinPolarity
  LPTMR pulse input pin polarity; used only in pulse counter mode.
- bool enableFreeRunning
  True: enable free running, counter is reset on overflow False: counter is reset when the compare flag is set.
- bool bypassPrescaler
  True: bypass prescaler; false: use clock from prescaler.
- lptmr_prescaler_clock_select_t prescalerClockSource
  LPTMR clock source.
- lptmr_prescaler_glitch_value_t value
  Prescaler or glitch filter value.

12.5 Enumeration Type Documentation

12.5.1 enum lptmr_pin_select_t

Enumerator

kLPTMR_PinSelectInput_0 Pulse counter input 0 is selected.
kLPTMR_PinSelectInput_1 Pulse counter input 1 is selected.
kLPTMR_PinSelectInput_2 Pulse counter input 2 is selected.
kLPTMR_PinSelectInput_3 Pulse counter input 3 is selected.

12.5.2 enum lptmr_pin_polarity_t

Enumerator

kLPTMR_PinPolarityActiveHigh Pulse Counter input source is active-high.
kLPTMR_PinPolarityActiveLow Pulse Counter input source is active-low.

12.5.3 enum lptmr_timer_mode_t

Enumerator

kLPTMR_TimerModeTimeCounter Time Counter mode.
kLPTMR_TimerModePulseCounter Pulse Counter mode.

12.5.4 enum lptmr_prescaler_glitch_value_t

Enumerator

kLPTMR_Prescale_Glitch_0 Prescaler divide 2, glitch filter does not support this setting.
kLPTMR_Prescale_Glitch_1 Prescaler divide 4, glitch filter 2.
kLPTMR_Prescale_Glitch_2 Prescaler divide 8, glitch filter 4.
kLPTMR_Prescale_Glitch_3 Prescaler divide 16, glitch filter 8.
kLPTMR_Prescale_Glitch_4 Prescaler divide 32, glitch filter 16.
kLPTMR_Prescale_Glitch_5 Prescaler divide 64, glitch filter 32.
kLPTMR_Prescale_Glitch_6 Prescaler divide 128, glitch filter 64.
kLPTMR_Prescale_Glitch_7 Prescaler divide 256, glitch filter 128.
kLPTMR_Prescale_Glitch_8 Prescaler divide 512, glitch filter 256.
kLPTMR_Prescale_Glitch_9 Prescaler divide 1024, glitch filter 512.
kLPTMR_Prescale_Glitch_10 Prescaler divide 2048 glitch filter 1024.
kLPTMR_Prescale_Glitch_11 Prescaler divide 4096, glitch filter 2048.
kLPTMR_Prescale_Glitch_12 Prescaler divide 8192, glitch filter 4096.
kLPTMR_Prescale_Glitch_13 Prescaler divide 16384, glitch filter 8192.
kLPTMR_Prescale_Glitch_14 Prescaler divide 32768, glitch filter 16384.
kLPTMR_Prescale_Glitch_15 Prescaler divide 65536, glitch filter 32768.

12.5.5 enum lptmr_prescaler_clock_select_t

Note

Clock connections are SoC-specific

Enumerator

kLPTMR_PrescalerClock_0 Prescaler/glitch filter clock 0 selected.
kLPTMR_PrescalerClock_1 Prescaler/glitch filter clock 1 selected.
kLPTMR_PrescalerClock_2 Prescaler/glitch filter clock 2 selected.
kLPTMR_PrescalerClock_3 Prescaler/glitch filter clock 3 selected.

12.5.6 enum lptmr_interrupt_enable_t

Enumerator

kLPTMR_TimerInterruptEnable Timer interrupt enable.

12.5.7 enum lptmr_status_flags_t

Enumerator

kLPTMR_TimerCompareFlag Timer compare flag.

12.6 Function Documentation

12.6.1 void LPTMR_Init (LPTMR_Type * *base*, const lptmr_config_t * *config*)

Note

This API should be called at the beginning of the application using the LPTMR driver.

Parameters

base	LPTMR peripheral base address
config	A pointer to the LPTMR configuration structure.

12.6.2 void LPTMR_Deinit (LPTMR_Type * *base*)

Parameters

base	LPTMR peripheral base address

12.6.3 void LPTMR_GetDefaultConfig (lptmr_config_t * *config*)

The default values are as follows.

```
*    config->timerMode = kLPTMR_TimerModeTimeCounter;
*    config->pinSelect = kLPTMR_PinSelectInput_0;
*    config->pinPolarity = kLPTMR_PinPolarityActiveHigh;
*    config->enableFreeRunning = false;
*    config->bypassPrescaler = true;
*    config->prescalerClockSource = kLPTMR_PrescalerClock_1;
*    config->value = kLPTMR_Prescale_Glitch_0;
*
```

Parameters

config	A pointer to the LPTMR configuration structure.

12.6.4 static void LPTMR_EnableInterrupts (LPTMR_Type * *base*, uint32_t *mask*) [inline], [static]

Parameters

base	LPTMR peripheral base address
mask	The interrupts to enable. This is a logical OR of members of the enumeration lptmr-_interrupt_enable_t

12.6.5 static void LPTMR_DisableInterrupts (LPTMR_Type * *base*, uint32_t *mask*) [inline], [static]

Parameters

base	LPTMR peripheral base address
mask	The interrupts to disable. This is a logical OR of members of the enumeration lptmr-_interrupt_enable_t.

12.6.6 static uint32_t LPTMR_GetEnabledInterrupts (LPTMR_Type * *base*) [inline], [static]

Parameters

base	LPTMR peripheral base address

Returns

The enabled interrupts. This is the logical OR of members of the enumeration lptmr_interrupt_-enable_t

12.6.7 static uint32_t LPTMR_GetStatusFlags (LPTMR_Type * *base*) [inline], [static]

Parameters

base	LPTMR peripheral base address

Returns

The status flags. This is the logical OR of members of the enumeration lptmr_status_flags_t

12.6.8 static void LPTMR_ClearStatusFlags (LPTMR_Type * *base*, uint32_t *mask*) [inline], [static]

Parameters

base	LPTMR peripheral base address
mask	The status flags to clear. This is a logical OR of members of the enumeration lptmr_-status_flags_t.

12.6.9 static void LPTMR_SetTimerPeriod (LPTMR_Type * *base*, uint32_t *ticks*) [inline], [static]

Timers counts from 0 until it equals the count value set here. The count value is written to the CMR register.

Note

1. The TCF flag is set with the CNR equals the count provided here and then increments.
2. Call the utility macros provided in the fsl_common.h to convert to ticks.

Parameters

base	LPTMR peripheral base address
ticks	A timer period in units of ticks, which should be equal or greater than 1.

12.6.10 static uint32_t LPTMR_GetCurrentTimerCount (LPTMR_Type * *base*) [inline], [static]

This function returns the real-time timer counting value in a range from 0 to a timer period.

Note

Call the utility macros provided in the fsl_common.h to convert ticks to usec or msec.

Parameters

base	LPTMR peripheral base address

Returns

The current counter value in ticks

12.6.11 static void LPTMR_StartTimer (LPTMR_Type * *base*) [inline], [static]

After calling this function, the timer counts up to the CMR register value. Each time the timer reaches the CMR value and then increments, it generates a trigger pulse and sets the timeout interrupt flag. An interrupt is also triggered if the timer interrupt is enabled.

Parameters

base	LPTMR peripheral base address

12.6.12 static void LPTMR_StopTimer (LPTMR_Type * *base*) [inline], [static]

This function stops the timer and resets the timer's counter register.

Parameters

base	LPTMR peripheral base address

Chapter 13
LPUART: Low Power UART Driver

13.1 Overview

Modules

- LPUART DMA Driver
- LPUART Driver
- LPUART FreeRTOS Driver
- LPUART eDMA Driver

13.2 LPUART Driver

13.2.1 Overview

The MCUXpresso SDK provides a peripheral driver for the Low Power UART (LPUART) module of MCUXpresso SDK devices.

13.2.2 Typical use case

13.2.2.1 LPUART Operation

```
uint8_t ch;
LPUART_GetDefaultConfig(&user_config);
user_config.baudRate = 115200U;
config.enableTx = true;
config.enableRx = true;

LPUART_Init(LPUART1,&user_config,120000000U);

LPUART_WriteBlocking(LPUART1, txbuff, sizeof(txbuff) - 1);

while(1)
{
    LPUART_ReadBlocking(LPUART1, &ch, 1);
    LPUART_WriteBlocking(LPUART1, &ch, 1);
}
```

Data Structures

- struct lpuart_config_t
  LPUART configuration structure. More...
- struct lpuart_transfer_t
  LPUART transfer structure. More...
- struct lpuart_handle_t
  LPUART handle structure. More...

Typedefs

- typedef void(∗ lpuart_transfer_callback_t)(LPUART_Type ∗base, lpuart_handle_t ∗handle, status_t status, void ∗userData)
  LPUART transfer callback function.

Enumerations

- enum _lpuart_status {
kStatus_LPUART_TxBusy = MAKE_STATUS(kStatusGroup_LPUART, 0),
kStatus_LPUART_RxBusy = MAKE_STATUS(kStatusGroup_LPUART, 1),
kStatus_LPUART_TxIdle = MAKE_STATUS(kStatusGroup_LPUART, 2),
kStatus_LPUART_RxIdle = MAKE_STATUS(kStatusGroup_LPUART, 3),
kStatus_LPUART_TxWatermarkTooLarge = MAKE_STATUS(kStatusGroup_LPUART, 4),
kStatus_LPUART_RxWatermarkTooLarge = MAKE_STATUS(kStatusGroup_LPUART, 5),
kStatus_LPUART_FlagCannotClearManually = MAKE_STATUS(kStatusGroup_LPUART, 6),
kStatus_LPUART_Error = MAKE_STATUS(kStatusGroup_LPUART, 7),
kStatus_LPUART_RxRingBufferOverrun,
kStatus_LPUART_RxHardwareOverrun = MAKE_STATUS(kStatusGroup_LPUART, 9),
kStatus_LPUART_NoiseError = MAKE_STATUS(kStatusGroup_LPUART, 10),
kStatus_LPUART_FramingError = MAKE_STATUS(kStatusGroup_LPUART, 11),
kStatus_LPUART_ParityError = MAKE_STATUS(kStatusGroup_LPUART, 12),
kStatus_LPUART_BaudrateNotSupport }
Error codes for the LPUART driver.
- enum lpuart_parity_mode_t {
kLPUART_ParityDisabled = 0x0U,
kLPUART_ParityEven = 0x2U,
kLPUART_ParityOdd = 0x3U }
LPUART parity mode.
- enum lpuart_data_bits_t { kLPUART_EightDataBits = 0x0U }
LPUART data bits count.
- enum lpuart_stop_bit_count_t {
kLPUART_OneStopBit = 0U,
kLPUART_TwoStopBit = 1U }
LPUART stop bit count.
- enum _lpuart_interrupt_enable {
kLPUART_LinBreakInterruptEnable = (LPUART_BAUD_LBKDIE_MASK >> 8),
kLPUART_RxActiveEdgeInterruptEnable = (LPUART_BAUD_RXEDGIE_MASK >> 8),
kLPUART_TxDataRegEmptyInterruptEnable = (LPUART_CTRL_TIE_MASK),
kLPUART_TransmissionCompleteInterruptEnable = (LPUART_CTRL_TCIE_MASK),
kLPUART_RxDataRegFullInterruptEnable = (LPUART_CTRL_RIE_MASK),
kLPUART_IdleLineInterruptEnable = (LPUART_CTRL_ILIE_MASK),
kLPUART_RxOverrunInterruptEnable = (LPUART_CTRL_ORIE_MASK),
kLPUART_NoiseErrorInterruptEnable = (LPUART_CTRL_NEIE_MASK),
kLPUART_FramingErrorInterruptEnable = (LPUART_CTRL_FEIE_MASK),
kLPUART_ParityErrorInterruptEnable = (LPUART_CTRL_PEIE_MASK) }
LPUART interrupt configuration structure, default settings all disabled.
- enum _lpuart_flags {

kLPUART_TxDataRegEmptyFlag,
kLPUART_TransmissionCompleteFlag,
kLPUART_RxDataRegFullFlag,
kLPUART_IdleLineFlag = (LPUART_STAT_IDLE_MASK),
kLPUART_RxOverrunFlag = (LPUART_STAT_OR_MASK),
kLPUART_NoiseErrorFlag = (LPUART_STAT_NF_MASK),
kLPUART_FramingErrorFlag,
kLPUART_ParityErrorFlag = (LPUART_STAT_PF_MASK),
kLPUART_LinBreakFlag = (LPUART_STAT_LBKDIF_MASK),
kLPUART_RxActiveEdgeFlag,
kLPUART_RxActiveFlag,
kLPUART_DataMatch1Flag = LPUART_STAT_MA1F_MASK,
kLPUART_DataMatch2Flag = LPUART_STAT_MA2F_MASK,
kLPUART_NoiseErrorInRxDataRegFlag,
kLPUART_ParityErrorInRxDataRegFlag }
LPUART status flags.

Driver version

- #define FSL_LPUART_DRIVER_VERSION (MAKE_VERSION(2, 2, 3))
  LPUART driver version 2.2.3.

Initialization and deinitialization

- status_t LPUART_Init (LPUART_Type ∗base, const lpuart_config_t ∗config, uint32_t srcClock_-Hz)
  Initializes an LPUART instance with the user configuration structure and the peripheral clock.
- void LPUART_Deinit (LPUART_Type ∗base)
  Deinitializes a LPUART instance.
- void LPUART_GetDefaultConfig (lpuart_config_t ∗config)
  Gets the default configuration structure.
- status_t LPUART_SetBaudRate (LPUART_Type ∗base, uint32_t baudRate_Bps, uint32_t src-Clock_Hz)
  Sets the LPUART instance baudrate.

Status

- uint32_t LPUART_GetStatusFlags (LPUART_Type ∗base)
  Gets LPUART status flags.
- status_t LPUART_ClearStatusFlags (LPUART_Type ∗base, uint32_t mask)
  Clears status flags with a provided mask.

Interrupts

- void LPUART_EnableInterrupts (LPUART_Type ∗base, uint32_t mask)
  Enables LPUART interrupts according to a provided mask.
- void LPUART_DisableInterrupts (LPUART_Type ∗base, uint32_t mask)
  Disables LPUART interrupts according to a provided mask.
- uint32_t LPUART_GetEnabledInterrupts (LPUART_Type ∗base)
  Gets enabled LPUART interrupts.

Bus Operations

- static void LPUART_EnableTx (LPUART_Type ∗base, bool enable)
  Enables or disables the LPUART transmitter.
- static void LPUART_EnableRx (LPUART_Type ∗base, bool enable)
  Enables or disables the LPUART receiver.
- static void LPUART_WriteByte (LPUART_Type ∗base, uint8_t data)
  Writes to the transmitter register.
- static uint8_t LPUART_ReadByte (LPUART_Type ∗base)
  Reads the receiver register.
- void LPUART_WriteBlocking (LPUART_Type ∗base, const uint8_t ∗data, size_t length)
  Writes to the transmitter register using a blocking method.
- status_t LPUART_ReadBlocking (LPUART_Type ∗base, uint8_t ∗data, size_t length)
  Reads the receiver data register using a blocking method.

Transactional

- void LPUART_TransferCreateHandle (LPUART_Type ∗base, lpuart_handle_t ∗handle, lpuart_transfer_callback_t callback, void ∗userData)
  Initializes the LPUART handle.
- status_t LPUART_TransferSendNonBlocking (LPUART_Type ∗base, lpuart_handle_t ∗handle, lpuart_transfer_t ∗xfer)
  Transmits a buffer of data using the interrupt method.
- void LPUART_TransferStartRingBuffer (LPUART_Type ∗base, lpuart_handle_t ∗handle, uint8_t ∗ringBuffer, size_t ringBufferSize)
  Sets up the RX ring buffer.
- void LPUART_TransferStopRingBuffer (LPUART_Type ∗base, lpuart_handle_t ∗handle)
  Aborts the background transfer and uninstalls the ring buffer.
- void LPUART_TransferAbortSend (LPUART_Type ∗base, lpuart_handle_t ∗handle)
  Aborts the interrupt-driven data transmit.
- status_t LPUART_TransferGetSendCount (LPUART_Type ∗base, lpuart_handle_t ∗handle, uint32_t ∗count)
  Gets the number of bytes that have been written to the LPUART transmitter register.
- status_t LPUART_TransferReceiveNonBlocking (LPUART_Type ∗base, lpuart_handle_t ∗handle, lpuart_transfer_t ∗xfer, size_t ∗receivedBytes)
  Receives a buffer of data using the interrupt method.
- void LPUART_TransferAbortReceive (LPUART_Type ∗base, lpuart_handle_t ∗handle)
  Aborts the interrupt-driven data receiving.

- status_t LPUART_TransferGetReceiveCount (LPUART_Type *base, lpuart_handle_t *handle, uint32_t *count)
  Gets the number of bytes that have been received.
- void LPUART_TransferHandleIRQ (LPUART_Type *base, lpuart_handle_t *handle)
  LPUART IRQ handle function.
- void LPUART_TransferHandleErrorIRQ (LPUART_Type *base, lpuart_handle_t *handle)
  LPUART Error IRQ handle function.

13.2.3 Data Structure Documentation

13.2.3.1 struct lpuart_config_t

Data Fields

- uint32_t baudRate_Bps
  LPUART baud rate.
- lpuart_parity_mode_t parityMode
  Parity mode, disabled (default), even, odd.
- lpuart_data_bits_t dataBitsCount
  Data bits count, eight (default), seven.
- bool isMsb
  Data bits order, LSB (default), MSB.
- lpuart_stop_bit_count_t stopBitCount
  Number of stop bits, 1 stop bit (default) or 2 stop bits.
- bool enableTx
  Enable TX.
- bool enableRx
  Enable RX.

13.2.3.2 struct lpuart_transfer_t

Data Fields

- uint8_t * data
  The buffer of data to be transfer.
- size_t dataSize
  The byte count to be transfer.

13.2.3.2.0.26 Field Documentation

13.2.3.2.0.26.1 uint8_t* lpuart_transfer_t::data

13.2.3.2.0.26.2 size_t lpuart_transfer_t::dataSize

13.2.3.3 struct _lpuart_handle

Data Fields

- uint8_t *volatile txData
  Address of remaining data to send.
- volatile size_t txDataSize
  Size of the remaining data to send.
- size_t txDataSizeAll
  Size of the data to send out.
- uint8_t *volatile rxData
  Address of remaining data to receive.
- volatile size_t rxDataSize
  Size of the remaining data to receive.
- size_t rxDataSizeAll
  Size of the data to receive.
- uint8_t * rxRingBuffer
  Start address of the receiver ring buffer.
- size_t rxRingBufferSize
  Size of the ring buffer.
- volatile uint16_t rxRingBufferHead
  Index for the driver to store received data into ring buffer.
- volatile uint16_t rxRingBufferTail
  Index for the user to get data from the ring buffer.
- lpuart_transfer_callback_t callback
  Callback function.
- void * userData
  LPUART callback function parameter.
- volatile uint8_t txState
  TX transfer state.
- volatile uint8_t rxState
  RX transfer state.

13.2.3.3.0.27 Field Documentation

13.2.3.3.0.27.1 uint8_t∗ volatile lpuart_handle_t::txData

13.2.3.3.0.27.2 volatile size_t lpuart_handle_t::txDataSize

13.2.3.3.0.27.3 size_t lpuart_handle_t::txDataSizeAll

13.2.3.3.0.27.4 uint8_t∗ volatile lpuart_handle_t::rxData

13.2.3.3.0.27.5 volatile size_t lpuart_handle_t::rxDataSize

13.2.3.3.0.27.6 size_t lpuart_handle_t::rxDataSizeAll

13.2.3.3.0.27.7 uint8_t∗ lpuart_handle_t::rxRingBuffer

13.2.3.3.0.27.8 size_t lpuart_handle_t::rxRingBufferSize

13.2.3.3.0.27.9 volatile uint16_t lpuart_handle_t::rxRingBufferHead

13.2.3.3.0.27.10 volatile uint16_t lpuart_handle_t::rxRingBufferTail

13.2.3.3.0.27.11 lpuart_transfer_callback_t lpuart_handle_t::callback

13.2.3.3.0.27.12 void∗ lpuart_handle_t::userData

13.2.3.3.0.27.13 volatile uint8_t lpuart_handle_t::txState

13.2.3.3.0.27.14 volatile uint8_t lpuart_handle_t::rxState

13.2.4 Macro Definition Documentation

13.2.4.1 #define FSL_LPUART_DRIVER_VERSION (MAKE_VERSION(2, 2, 3))

13.2.5 Typedef Documentation

13.2.5.1 typedef void(∗ lpuart_transfer_callback_t)(LPUART_Type ∗base, lpuart_handle_t ∗handle, status_t status, void ∗userData)

13.2.6 Enumeration Type Documentation

13.2.6.1 enum _lpuart_status

Enumerator

kStatus_LPUART_TxBusy TX busy.
kStatus_LPUART_RxBusy RX busy.
kStatus_LPUART_TxIdle LPUART transmitter is idle.

kStatus_LPUART_RxIdle LPUART receiver is idle.
kStatus_LPUART_TxWatermarkTooLarge TX FIFO watermark too large.
kStatus_LPUART_RxWatermarkTooLarge RX FIFO watermark too large.
kStatus_LPUART_FlagCannotClearManually Some flag can't manually clear.
kStatus_LPUART_Error Error happens on LPUART.
kStatus_LPUART_RxRingBufferOverrun LPUART RX software ring buffer overrun.
kStatus_LPUART_RxHardwareOverrun LPUART RX receiver overrun.
kStatus_LPUART_NoiseError LPUART noise error.
kStatus_LPUART_FramingError LPUART framing error.
kStatus_LPUART_ParityError LPUART parity error.
kStatus_LPUART_BaudrateNotSupport Baudrate is not support in current clock source.

13.2.6.2 enum lpuart_parity_mode_t

Enumerator

kLPUART_ParityDisabled Parity disabled.
kLPUART_ParityEven Parity enabled, type even, bit setting: PE|PT = 10.
kLPUART_ParityOdd Parity enabled, type odd, bit setting: PE|PT = 11.

13.2.6.3 enum lpuart_data_bits_t

Enumerator

kLPUART_EightDataBits Eight data bit.

13.2.6.4 enum lpuart_stop_bit_count_t

Enumerator

kLPUART_OneStopBit One stop bit.
kLPUART_TwoStopBit Two stop bits.

13.2.6.5 enum _lpuart_interrupt_enable

This structure contains the settings for all LPUART interrupt configurations.

Enumerator

kLPUART_LinBreakInterruptEnable LIN break detect.
kLPUART_RxActiveEdgeInterruptEnable Receive Active Edge.
kLPUART_TxDataRegEmptyInterruptEnable Transmit data register empty.

kLPUART_TransmissionCompleteInterruptEnable Transmission complete.
kLPUART_RxDataRegFullInterruptEnable Receiver data register full.
kLPUART_IdleLineInterruptEnable Idle line.
kLPUART_RxOverrunInterruptEnable Receiver Overrun.
kLPUART_NoiseErrorInterruptEnable Noise error flag.
kLPUART_FramingErrorInterruptEnable Framing error flag.
kLPUART_ParityErrorInterruptEnable Parity error flag.

13.2.6.6 enum _lpuart_flags

This provides constants for the LPUART status flags for use in the LPUART functions.

Enumerator

kLPUART_TxDataRegEmptyFlag Transmit data register empty flag, sets when transmit buffer is empty.
kLPUART_TransmissionCompleteFlag Transmission complete flag, sets when transmission activity complete.
kLPUART_RxDataRegFullFlag Receive data register full flag, sets when the receive data buffer is full.
kLPUART_IdleLineFlag Idle line detect flag, sets when idle line detected.
kLPUART_RxOverrunFlag Receive Overrun, sets when new data is received before data is read from receive register.
kLPUART_NoiseErrorFlag Receive takes 3 samples of each received bit. If any of these samples differ, noise flag sets
kLPUART_FramingErrorFlag Frame error flag, sets if logic 0 was detected where stop bit expected.
kLPUART_ParityErrorFlag If parity enabled, sets upon parity error detection.
kLPUART_LinBreakFlag LIN break detect interrupt flag, sets when LIN break char detected and LIN circuit enabled.
kLPUART_RxActiveEdgeFlag Receive pin active edge interrupt flag, sets when active edge detected.
kLPUART_RxActiveFlag Receiver Active Flag (RAF), sets at beginning of valid start bit.
kLPUART_DataMatch1Flag The next character to be read from LPUART_DATA matches MA1.
kLPUART_DataMatch2Flag The next character to be read from LPUART_DATA matches MA2.
kLPUART_NoiseErrorInRxDataRegFlag NOISY bit, sets if noise detected in current data word.
kLPUART_ParityErrorInRxDataRegFlag PARITYE bit, sets if noise detected in current data word.

13.2.7 Function Documentation

13.2.7.1 status_t LPUART_Init (LPUART_Type ∗ *base*, const lpuart_config_t ∗ *config*, uint32_t *srcClock_Hz*)

This function configures the LPUART module with user-defined settings. Call the LPUART_GetDefault-Config() function to configure the configuration structure and get the default configuration. The example below shows how to use this API to configure the LPUART.

```
*  lpuart_config_t lpuartConfig;
*  lpuartConfig.baudRate_Bps = 115200U;
*  lpuartConfig.parityMode = kLPUART_ParityDisabled;
*  lpuartConfig.dataBitsCount = kLPUART_EightDataBits;
*  lpuartConfig.isMsb = false;
*  lpuartConfig.stopBitCount = kLPUART_OneStopBit;
*  lpuartConfig.txFifoWatermark = 0;
*  lpuartConfig.rxFifoWatermark = 1;
*  LPUART_Init(LPUART1, &lpuartConfig, 20000000U);
*
```

Parameters

base	LPUART peripheral base address.
config	Pointer to a user-defined configuration structure.
srcClock_Hz	LPUART clock source frequency in HZ.

Return values

kStatus_LPUART_-BaudrateNotSupport	Baudrate is not support in current clock source.
kStatus_Success	LPUART initialize succeed

13.2.7.2 void LPUART_Deinit (LPUART_Type ∗ *base*)

This function waits for transmit to complete, disables TX and RX, and disables the LPUART clock.

Parameters

base	LPUART peripheral base address.

13.2.7.3 void LPUART_GetDefaultConfig (lpuart_config_t ∗ *config*)

This function initializes the LPUART configuration structure to a default value. The default values are-: lpuartConfig->baudRate_Bps = 115200U; lpuartConfig->parityMode = kLPUART_ParityDisabled;

lpuartConfig->dataBitsCount = kLPUART_EightDataBits; lpuartConfig->isMsb = false; lpuartConfig->stopBitCount = kLPUART_OneStopBit; lpuartConfig->txFifoWatermark = 0; lpuartConfig->rxFifoWatermark = 1; lpuartConfig->enableTx = false; lpuartConfig->enableRx = false;

Parameters

config	Pointer to a configuration structure.

13.2.7.4 status_t LPUART_SetBaudRate (LPUART_Type * *base*, uint32_t *baudRate_Bps*, uint32_t *srcClock_Hz*)

This function configures the LPUART module baudrate. This function is used to update the LPUART module baudrate after the LPUART module is initialized by the LPUART_Init.

```
*  LPUART_SetBaudRate(LPUART1, 115200U, 20000000U);
*
```

Parameters

base	LPUART peripheral base address.
baudRate_Bps	LPUART baudrate to be set.
srcClock_Hz	LPUART clock source frequency in HZ.

Return values

kStatus_LPUART_-BaudrateNotSupport	Baudrate is not supported in the current clock source.
kStatus_Success	Set baudrate succeeded.

13.2.7.5 uint32_t LPUART_GetStatusFlags (LPUART_Type * *base*)

This function gets all LPUART status flags. The flags are returned as the logical OR value of the enumerators _lpuart_flags. To check for a specific status, compare the return value with enumerators in the _lpuart_flags. For example, to check whether the TX is empty:

```
*     if (kLPUART_TxDataRegEmptyFlag &
      LPUART_GetStatusFlags(LPUART1))
*     {
*         ...
*     }
*
```

Parameters

base	LPUART peripheral base address.

Returns

LPUART status flags which are ORed by the enumerators in the _lpuart_flags.

13.2.7.6 status_t LPUART_ClearStatusFlags (LPUART_Type ∗ *base*, uint32_t *mask*)

This function clears LPUART status flags with a provided mask. Automatically cleared flags can't be cleared by this function. Flags that can only cleared or set by hardware are: kLPUART_TxDataRegEmptyFlag, kLPUART_TransmissionCompleteFlag, kLPUART_RxDataRegFullFlag, kLPUART_RxActiveFlag, kLPUART_NoiseErrorInRxDataRegFlag, kLPUART_ParityErrorInRxDataRegFlag, kLPUART_TxFifoEmptyFlag,kLPUART_RxFifoEmptyFlag Note: This API should be called when the Tx/Rx is idle, otherwise it takes no effects.

Parameters

base	LPUART peripheral base address.
mask	the status flags to be cleared. The user can use the enumerators in the _lpuart_status_flag_t to do the OR operation and get the mask.

Returns

0 succeed, others failed.

Return values

kStatus_LPUART_FlagCannotClearManually	The flag can't be cleared by this function but it is cleared automatically by hardware.
kStatus_Success	Status in the mask are cleared.

13.2.7.7 void LPUART_EnableInterrupts (LPUART_Type ∗ *base*, uint32_t *mask*)

This function enables the LPUART interrupts according to a provided mask. The mask is a logical OR of enumeration members. See the _lpuart_interrupt_enable. This examples shows how to enable TX empty interrupt and RX full interrupt:

```
*     LPUART_EnableInterrupts(LPUART1,
      kLPUART_TxDataRegEmptyInterruptEnable |
      kLPUART_RxDataRegFullInterruptEnable);
*
```

Parameters

base	LPUART peripheral base address.
mask	The interrupts to enable. Logical OR of _uart_interrupt_enable.

13.2.7.8 void LPUART_DisableInterrupts (LPUART_Type * *base,* uint32_t *mask*)

This function disables the LPUART interrupts according to a provided mask. The mask is a logical OR of enumeration members. See _lpuart_interrupt_enable. This example shows how to disable the TX empty interrupt and RX full interrupt:

```
*     LPUART_DisableInterrupts(LPUART1,
      kLPUART_TxDataRegEmptyInterruptEnable |
      kLPUART_RxDataRegFullInterruptEnable);
*
```

Parameters

base	LPUART peripheral base address.
mask	The interrupts to disable. Logical OR of _lpuart_interrupt_enable.

13.2.7.9 uint32_t LPUART_GetEnabledInterrupts (LPUART_Type * *base*)

This function gets the enabled LPUART interrupts. The enabled interrupts are returned as the logical OR value of the enumerators _lpuart_interrupt_enable. To check a specific interrupt enable status, compare the return value with enumerators in _lpuart_interrupt_enable. For example, to check whether the TX empty interrupt is enabled:

```
*     uint32_t enabledInterrupts = LPUART_GetEnabledInterrupts(LPUART1);
*
*     if (kLPUART_TxDataRegEmptyInterruptEnable & enabledInterrupts)
*     {
*         ...
*     }
*
```

Parameters

base	LPUART peripheral base address.

Returns

LPUART interrupt flags which are logical OR of the enumerators in _lpuart_interrupt_enable.

13.2.7.10 static void LPUART_EnableTx (LPUART_Type * *base*, bool *enable*) `[inline]`, `[static]`

This function enables or disables the LPUART transmitter.

Parameters

base	LPUART peripheral base address.
enable	True to enable, false to disable.

13.2.7.11 static void LPUART_EnableRx (LPUART_Type * *base*, bool *enable*) [inline], [static]

This function enables or disables the LPUART receiver.

Parameters

base	LPUART peripheral base address.
enable	True to enable, false to disable.

13.2.7.12 static void LPUART_WriteByte (LPUART_Type * *base*, uint8_t *data*) [inline], [static]

This function writes data to the transmitter register directly. The upper layer must ensure that the TX register is empty or that the TX FIFO has room before calling this function.

Parameters

base	LPUART peripheral base address.
data	Data write to the TX register.

13.2.7.13 static uint8_t LPUART_ReadByte (LPUART_Type * *base*) [inline], [static]

This function reads data from the receiver register directly. The upper layer must ensure that the receiver register is full or that the RX FIFO has data before calling this function.

Parameters

base	LPUART peripheral base address.

Returns

Data read from data register.

13.2.7.14 void LPUART_WriteBlocking (LPUART_Type * *base*, const uint8_t * *data*, size_t *length*)

This function polls the transmitter register, waits for the register to be empty or for TX FIFO to have room, and writes data to the transmitter buffer.

Note

> This function does not check whether all data has been sent out to the bus. Before disabling the transmitter, check the kLPUART_TransmissionCompleteFlag to ensure that the transmit is finished.

Parameters

base	LPUART peripheral base address.
data	Start address of the data to write.
length	Size of the data to write.

13.2.7.15 status_t LPUART_ReadBlocking (LPUART_Type * *base*, uint8_t * *data*, size_t *length*)

This function polls the receiver register, waits for the receiver register full or receiver FIFO has data, and reads data from the TX register.

Parameters

base	LPUART peripheral base address.
data	Start address of the buffer to store the received data.
length	Size of the buffer.

Return values

kStatus_LPUART_Rx-HardwareOverrun	Receiver overrun happened while receiving data.
kStatus_LPUART_Noise-Error	Noise error happened while receiving data.

kStatus_LPUART_-FramingError	Framing error happened while receiving data.
kStatus_LPUART_Parity-Error	Parity error happened while receiving data.
kStatus_Success	Successfully received all data.

13.2.7.16 void LPUART_TransferCreateHandle (LPUART_Type ∗ *base*, lpuart_handle_t ∗ *handle*, lpuart_transfer_callback_t *callback*, void ∗ *userData*)

This function initializes the LPUART handle, which can be used for other LPUART transactional APIs. Usually, for a specified LPUART instance, call this API once to get the initialized handle.

The LPUART driver supports the "background" receiving, which means that user can set up an RX ring buffer optionally. Data received is stored into the ring buffer even when the user doesn't call the LPUART_TransferReceiveNonBlocking() API. If there is already data received in the ring buffer, the user can get the received data from the ring buffer directly. The ring buffer is disabled if passing NULL as `ringBuffer`.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.
callback	Callback function.
userData	User data.

13.2.7.17 status_t LPUART_TransferSendNonBlocking (LPUART_Type ∗ *base*, lpuart_handle_t ∗ *handle*, lpuart_transfer_t ∗ *xfer*)

This function send data using an interrupt method. This is a non-blocking function, which returns directly without waiting for all data written to the transmitter register. When all data is written to the TX register in the ISR, the LPUART driver calls the callback function and passes the kStatus_LPUART_TxIdle as status parameter.

Note

> The kStatus_LPUART_TxIdle is passed to the upper layer when all data are written to the TX register. However, there is no check to ensure that all the data sent out. Before disabling the T-X, check the kLPUART_TransmissionCompleteFlag to ensure that the transmit is finished.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.
xfer	LPUART transfer structure, see lpuart_transfer_t.

Return values

kStatus_Success	Successfully start the data transmission.
kStatus_LPUART_TxBusy	Previous transmission still not finished, data not all written to the TX register.
kStatus_InvalidArgument	Invalid argument.

13.2.7.18 void LPUART_TransferStartRingBuffer (LPUART_Type ∗ *base*, lpuart_handle_t ∗ *handle*, uint8_t ∗ *ringBuffer*, size_t *ringBufferSize*)

This function sets up the RX ring buffer to a specific UART handle.

When the RX ring buffer is used, data received is stored into the ring buffer even when the user doesn't call the UART_TransferReceiveNonBlocking() API. If there is already data received in the ring buffer, the user can get the received data from the ring buffer directly.

Note

> When using RX ring buffer, one byte is reserved for internal use. In other words, if `ringBufferSize` is 32, then only 31 bytes are used for saving data.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.
ringBuffer	Start address of ring buffer for background receiving. Pass NULL to disable the ring buffer.
ringBufferSize	size of the ring buffer.

13.2.7.19 void LPUART_TransferStopRingBuffer (LPUART_Type ∗ *base*, lpuart_handle_t ∗ *handle*)

This function aborts the background transfer and uninstalls the ring buffer.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.

13.2.7.20 void LPUART_TransferAbortSend (LPUART_Type ∗ *base*, lpuart_handle_t ∗ *handle*)

This function aborts the interrupt driven data sending. The user can get the remainBtyes to find out how many bytes are not sent out.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.

13.2.7.21 status_t LPUART_TransferGetSendCount (LPUART_Type ∗ *base*, lpuart_handle_t ∗ *handle*, uint32_t ∗ *count*)

This function gets the number of bytes that have been written to LPUART TX register by an interrupt method.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.
count	Send bytes count.

Return values

kStatus_NoTransferInProgress	No send in progress.
kStatus_InvalidArgument	Parameter is invalid.
kStatus_Success	Get successfully through the parameter `count`;

13.2.7.22 status_t LPUART_TransferReceiveNonBlocking (LPUART_Type ∗ *base*, lpuart_handle_t ∗ *handle*, lpuart_transfer_t ∗ *xfer*, size_t ∗ *receivedBytes*)

This function receives data using an interrupt method. This is a non-blocking function which returns without waiting to ensure that all data are received. If the RX ring buffer is used and not empty, the data in the ring buffer is copied and the parameter `receivedBytes` shows how many bytes are copied from the ring buffer. After copying, if the data in the ring buffer is not enough for read, the receive request is saved by the LPUART driver. When the new data arrives, the receive request is serviced first. When all data is received, the LPUART driver notifies the upper layer through a callback function and passes a status parameter kStatus_UART_RxIdle. For example, the upper layer needs 10 bytes but there are only 5 bytes in ring buffer. The 5 bytes are copied to xfer->data, which returns with the parameter `receivedBytes` set to 5. For the remaining 5 bytes, the newly arrived data is saved from xfer->data[5]. When 5 bytes are received, the LPUART driver notifies the upper layer. If the RX ring buffer is not enabled, this function enables the RX and RX interrupt to receive data to xfer->data. When all data is received, the upper layer is notified.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.
xfer	LPUART transfer structure, see #uart_transfer_t.
receivedBytes	Bytes received from the ring buffer directly.

Return values

kStatus_Success	Successfully queue the transfer into the transmit queue.
kStatus_LPUART_RxBusy	Previous receive request is not finished.
kStatus_InvalidArgument	Invalid argument.

13.2.7.23 void LPUART_TransferAbortReceive (LPUART_Type ∗ *base,* lpuart_handle_t ∗ *handle*)

This function aborts the interrupt-driven data receiving. The user can get the remainBytes to find out how many bytes not received yet.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.

13.2.7.24 status_t LPUART_TransferGetReceiveCount (LPUART_Type ∗ *base,* lpuart_handle_t ∗ *handle,* uint32_t ∗ *count*)

This function gets the number of bytes that have been received.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.
count	Receive bytes count.

Return values

kStatus_NoTransferInProgress	No receive in progress.
kStatus_InvalidArgument	Parameter is invalid.
kStatus_Success	Get successfully through the parameter `count`;

13.2.7.25 void LPUART_TransferHandleIRQ (LPUART_Type ∗ *base*, lpuart_handle_t ∗ *handle*)

This function handles the LPUART transmit and receive IRQ request.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.

13.2.7.26 void LPUART_TransferHandleErrorIRQ (LPUART_Type ∗ *base*, lpuart_handle_t ∗ *handle*)

This function handles the LPUART error IRQ request.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.

13.3 LPUART DMA Driver

13.3.1 Overview

Data Structures

- struct lpuart_dma_handle_t
  LPUART DMA handle. More...

Typedefs

- typedef void(∗ lpuart_dma_transfer_callback_t)(LPUART_Type ∗base, lpuart_dma_handle_t ∗handle, status_t status, void ∗userData)
  LPUART transfer callback function.

EDMA transactional

- void LPUART_TransferCreateHandleDMA (LPUART_Type ∗base, lpuart_dma_handle_t ∗handle, lpuart_dma_transfer_callback_t callback, void ∗userData, dma_handle_t ∗txDmaHandle, dma_handle_t ∗rxDmaHandle)
  Initializes the LPUART handle which is used in transactional functions.
- status_t LPUART_TransferSendDMA (LPUART_Type ∗base, lpuart_dma_handle_t ∗handle, lpuart_transfer_t ∗xfer)
  Sends data using DMA.
- status_t LPUART_TransferReceiveDMA (LPUART_Type ∗base, lpuart_dma_handle_t ∗handle, lpuart_transfer_t ∗xfer)
  Receives data using DMA.
- void LPUART_TransferAbortSendDMA (LPUART_Type ∗base, lpuart_dma_handle_t ∗handle)
  Aborts the sent data using DMA.
- void LPUART_TransferAbortReceiveDMA (LPUART_Type ∗base, lpuart_dma_handle_t ∗handle)
  Aborts the received data using DMA.
- status_t LPUART_TransferGetSendCountDMA (LPUART_Type ∗base, lpuart_dma_handle_t ∗handle, uint32_t ∗count)
  Gets the number of bytes written to the LPUART TX register.
- status_t LPUART_TransferGetReceiveCountDMA (LPUART_Type ∗base, lpuart_dma_handle_t ∗handle, uint32_t ∗count)
  Gets the number of received bytes.

13.3.2 Data Structure Documentation

13.3.2.1 struct _lpuart_dma_handle

Data Fields

- lpuart_dma_transfer_callback_t callback

Callback function.
- void ∗ userData
  LPUART callback function parameter.
- size_t rxDataSizeAll
  Size of the data to receive.
- size_t txDataSizeAll
  Size of the data to send out.
- dma_handle_t ∗ txDmaHandle
  The DMA TX channel used.
- dma_handle_t ∗ rxDmaHandle
  The DMA RX channel used.
- volatile uint8_t txState
  TX transfer state.
- volatile uint8_t rxState
  RX transfer state.

13.3.2.1.0.28 Field Documentation

13.3.2.1.0.28.1 lpuart_dma_transfer_callback_t lpuart_dma_handle_t::callback

13.3.2.1.0.28.2 void∗ lpuart_dma_handle_t::userData

13.3.2.1.0.28.3 size_t lpuart_dma_handle_t::rxDataSizeAll

13.3.2.1.0.28.4 size_t lpuart_dma_handle_t::txDataSizeAll

13.3.2.1.0.28.5 dma_handle_t∗ lpuart_dma_handle_t::txDmaHandle

13.3.2.1.0.28.6 dma_handle_t∗ lpuart_dma_handle_t::rxDmaHandle

13.3.2.1.0.28.7 volatile uint8_t lpuart_dma_handle_t::txState

13.3.3 Typedef Documentation

13.3.3.1 typedef void(∗ lpuart_dma_transfer_callback_t)(LPUART_Type ∗base, lpuart_dma_handle_t ∗handle, status_t status, void ∗userData)

13.3.4 Function Documentation

13.3.4.1 void LPUART_TransferCreateHandleDMA (LPUART_Type ∗ *base*, lpuart_dma_handle_t ∗ *handle*, lpuart_dma_transfer_callback_t *callback*, void ∗ *userData*, dma_handle_t ∗ *txDmaHandle*, dma_handle_t ∗ *rxDmaHandle*)

Parameters

base	LPUART peripheral base address.
handle	Pointer to lpuart_dma_handle_t structure.
callback	Callback function.
userData	User data.
txDmaHandle	User-requested DMA handle for TX DMA transfer.
rxDmaHandle	User-requested DMA handle for RX DMA transfer.

13.3.4.2 status_t LPUART_TransferSendDMA (LPUART_Type * *base*, lpuart_dma_handle_t * *handle*, lpuart_transfer_t * *xfer*)

This function sends data using DMA. This is a non-blocking function, which returns right away. When all data is sent, the send callback function is called.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.
xfer	LPUART DMA transfer structure. See lpuart_transfer_t.

Return values

kStatus_Success	if succeed, others failed.
kStatus_LPUART_TxBusy	Previous transfer on going.
kStatus_InvalidArgument	Invalid argument.

13.3.4.3 status_t LPUART_TransferReceiveDMA (LPUART_Type * *base*, lpuart_dma_handle_t * *handle*, lpuart_transfer_t * *xfer*)

This function receives data using DMA. This is a non-blocking function, which returns right away. When all data is received, the receive callback function is called.

Parameters

base	LPUART peripheral base address.
handle	Pointer to lpuart_dma_handle_t structure.
xfer	LPUART DMA transfer structure. See lpuart_transfer_t.

Return values

kStatus_Success	if succeed, others failed.
kStatus_LPUART_RxBusy	Previous transfer on going.
kStatus_InvalidArgument	Invalid argument.

13.3.4.4 void LPUART_TransferAbortSendDMA (LPUART_Type * *base*, lpuart_dma_handle_t * *handle*)

This function aborts send data using DMA.

Parameters

base	LPUART peripheral base address
handle	Pointer to lpuart_dma_handle_t structure

13.3.4.5 void LPUART_TransferAbortReceiveDMA (LPUART_Type * *base*, lpuart_dma_handle_t * *handle*)

This function aborts the received data using DMA.

Parameters

base	LPUART peripheral base address
handle	Pointer to lpuart_dma_handle_t structure

13.3.4.6 status_t LPUART_TransferGetSendCountDMA (LPUART_Type * *base*, lpuart_dma_handle_t * *handle*, uint32_t * *count*)

This function gets the number of bytes that have been written to LPUART TX register by DMA.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.
count	Send bytes count.

Return values

kStatus_NoTransferInProgress	No send in progress.
kStatus_InvalidArgument	Parameter is invalid.
kStatus_Success	Get successfully through the parameter `count`;

13.3.4.7 status_t LPUART_TransferGetReceiveCountDMA (LPUART_Type * *base*, lpuart_dma_handle_t * *handle*, uint32_t * *count*)

This function gets the number of received bytes.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.
count	Receive bytes count.

Return values

kStatus_NoTransferInProgress	No receive in progress.
kStatus_InvalidArgument	Parameter is invalid.
kStatus_Success	Get successfully through the parameter `count`;

13.4 LPUART eDMA Driver

13.4.1 Overview

Data Structures

- struct lpuart_edma_handle_t
  LPUART eDMA handle. More...

Typedefs

- typedef void(∗ lpuart_edma_transfer_callback_t)(LPUART_Type ∗base, lpuart_edma_handle_t ∗handle, status_t status, void ∗userData)
  LPUART transfer callback function.

eDMA transactional

- void LPUART_TransferCreateHandleEDMA (LPUART_Type ∗base, lpuart_edma_handle_t ∗handle, lpuart_edma_transfer_callback_t callback, void ∗userData, edma_handle_t ∗txEdmaHandle, edma_handle_t ∗rxEdmaHandle)
  Initializes the LPUART handle which is used in transactional functions.
- status_t LPUART_SendEDMA (LPUART_Type ∗base, lpuart_edma_handle_t ∗handle, lpuart_transfer_t ∗xfer)
  Sends data using eDMA.
- status_t LPUART_ReceiveEDMA (LPUART_Type ∗base, lpuart_edma_handle_t ∗handle, lpuart_transfer_t ∗xfer)
  Receives data using eDMA.
- void LPUART_TransferAbortSendEDMA (LPUART_Type ∗base, lpuart_edma_handle_t ∗handle)
  Aborts the sent data using eDMA.
- void LPUART_TransferAbortReceiveEDMA (LPUART_Type ∗base, lpuart_edma_handle_t ∗handle)
  Aborts the received data using eDMA.
- status_t LPUART_TransferGetSendCountEDMA (LPUART_Type ∗base, lpuart_edma_handle_t ∗handle, uint32_t ∗count)
  Gets the number of bytes written to the LPUART TX register.
- status_t LPUART_TransferGetReceiveCountEDMA (LPUART_Type ∗base, lpuart_edma_handle_t ∗handle, uint32_t ∗count)
  Gets the number of received bytes.

13.4.2 Data Structure Documentation

13.4.2.1 struct _lpuart_edma_handle

Data Fields

- lpuart_edma_transfer_callback_t callback
  Callback function.
- void ∗ userData
  LPUART callback function parameter.
- size_t rxDataSizeAll
  Size of the data to receive.
- size_t txDataSizeAll
  Size of the data to send out.
- edma_handle_t ∗ txEdmaHandle
  The eDMA TX channel used.
- edma_handle_t ∗ rxEdmaHandle
  The eDMA RX channel used.
- uint8_t nbytes
  eDMA minor byte transfer count initially configured.
- volatile uint8_t txState
  TX transfer state.
- volatile uint8_t rxState
  RX transfer state.

13.4.2.1.0.29 Field Documentation

13.4.2.1.0.29.1 lpuart_edma_transfer_callback_t lpuart_edma_handle_t::callback

13.4.2.1.0.29.2 void* lpuart_edma_handle_t::userData

13.4.2.1.0.29.3 size_t lpuart_edma_handle_t::rxDataSizeAll

13.4.2.1.0.29.4 size_t lpuart_edma_handle_t::txDataSizeAll

13.4.2.1.0.29.5 edma_handle_t* lpuart_edma_handle_t::txEdmaHandle

13.4.2.1.0.29.6 edma_handle_t* lpuart_edma_handle_t::rxEdmaHandle

13.4.2.1.0.29.7 uint8_t lpuart_edma_handle_t::nbytes

13.4.2.1.0.29.8 volatile uint8_t lpuart_edma_handle_t::txState

13.4.3 Typedef Documentation

13.4.3.1 typedef void(* lpuart_edma_transfer_callback_t)(LPUART_Type *base, lpuart_edma_handle_t *handle, status_t status, void *userData)

13.4.4 Function Documentation

13.4.4.1 void LPUART_TransferCreateHandleEDMA (LPUART_Type * *base*, lpuart_edma_handle_t * *handle*, lpuart_edma_transfer_callback_t *callback*, void * *userData*, edma_handle_t * *txEdmaHandle*, edma_handle_t * *rxEdmaHandle*)

Parameters

base	LPUART peripheral base address.
handle	Pointer to lpuart_edma_handle_t structure.
callback	Callback function.
userData	User data.
txEdmaHandle	User requested DMA handle for TX DMA transfer.
rxEdmaHandle	User requested DMA handle for RX DMA transfer.

13.4.4.2 status_t LPUART_SendEDMA (LPUART_Type ∗ *base*, lpuart_edma_handle_t ∗ *handle*, lpuart_transfer_t ∗ *xfer*)

This function sends data using eDMA. This is a non-blocking function, which returns right away. When all data is sent, the send callback function is called.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.
xfer	LPUART eDMA transfer structure. See lpuart_transfer_t.

Return values

kStatus_Success	if succeed, others failed.
kStatus_LPUART_TxBusy	Previous transfer on going.
kStatus_InvalidArgument	Invalid argument.

13.4.4.3 status_t LPUART_ReceiveEDMA (LPUART_Type ∗ *base*, lpuart_edma_handle_t ∗ *handle*, lpuart_transfer_t ∗ *xfer*)

This function receives data using eDMA. This is non-blocking function, which returns right away. When all data is received, the receive callback function is called.

Parameters

base	LPUART peripheral base address.
handle	Pointer to lpuart_edma_handle_t structure.
xfer	LPUART eDMA transfer structure, see lpuart_transfer_t.

Return values

kStatus_Success	if succeed, others fail.
kStatus_LPUART_Rx-Busy	Previous transfer ongoing.
kStatus_InvalidArgument	Invalid argument.

13.4.4.4 void LPUART_TransferAbortSendEDMA (LPUART_Type * *base*, lpuart_edma_handle_t * *handle*)

This function aborts the sent data using eDMA.

Parameters

base	LPUART peripheral base address.
handle	Pointer to lpuart_edma_handle_t structure.

13.4.4.5 void LPUART_TransferAbortReceiveEDMA (LPUART_Type * *base*, lpuart_edma_handle_t * *handle*)

This function aborts the received data using eDMA.

Parameters

base	LPUART peripheral base address.
handle	Pointer to lpuart_edma_handle_t structure.

13.4.4.6 status_t LPUART_TransferGetSendCountEDMA (LPUART_Type * *base*, lpuart_edma_handle_t * *handle*, uint32_t * *count*)

This function gets the number of bytes written to the LPUART TX register by DMA.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.
count	Send bytes count.

Return values

kStatus_NoTransferInProgress	No send in progress.
kStatus_InvalidArgument	Parameter is invalid.
kStatus_Success	Get successfully through the parameter `count`;

13.4.4.7 status_t LPUART_TransferGetReceiveCountEDMA (LPUART_Type * *base*, lpuart_edma_handle_t * *handle*, uint32_t * *count*)

This function gets the number of received bytes.

Parameters

base	LPUART peripheral base address.
handle	LPUART handle pointer.
count	Receive bytes count.

Return values

kStatus_NoTransferInProgress	No receive in progress.
kStatus_InvalidArgument	Parameter is invalid.
kStatus_Success	Get successfully through the parameter `count`;

13.5 LPUART FreeRTOS Driver

13.5.1 Overview

Data Structures

- struct lpuart_rtos_config_t
  LPUART RTOS configuration structure. More...

LPUART RTOS Operation

- int LPUART_RTOS_Init (lpuart_rtos_handle_t ∗handle, lpuart_handle_t ∗t_handle, const lpuart_rtos_config_t ∗cfg)
  Initializes an LPUART instance for operation in RTOS.
- int LPUART_RTOS_Deinit (lpuart_rtos_handle_t ∗handle)
  Deinitializes an LPUART instance for operation.

LPUART transactional Operation

- int LPUART_RTOS_Send (lpuart_rtos_handle_t ∗handle, const uint8_t ∗buffer, uint32_t length)
  Sends data in the background.
- int LPUART_RTOS_Receive (lpuart_rtos_handle_t ∗handle, uint8_t ∗buffer, uint32_t length, size_t ∗received)
  Receives data.

13.5.2 Data Structure Documentation

13.5.2.1 struct lpuart_rtos_config_t

Data Fields

- LPUART_Type ∗ base
  UART base address.
- uint32_t srcclk
  UART source clock in Hz.
- uint32_t baudrate
  Desired communication speed.
- lpuart_parity_mode_t parity
  Parity setting.
- lpuart_stop_bit_count_t stopbits
  Number of stop bits to use.
- uint8_t ∗ buffer
  Buffer for background reception.
- uint32_t buffer_size
  Size of buffer for background reception.

13.5.3 Function Documentation

13.5.3.1 int LPUART_RTOS_Init (lpuart_rtos_handle_t * *handle*, lpuart_handle_t * *t_handle*, const lpuart_rtos_config_t * *cfg*)

Parameters

handle	The RTOS LPUART handle, the pointer to an allocated space for RTOS context.
t_handle	The pointer to an allocated space to store the transactional layer internal state.
cfg	The pointer to the parameters required to configure the LPUART after initialization.

Returns

0 succeed, others failed

13.5.3.2 int LPUART_RTOS_Deinit (lpuart_rtos_handle_t ∗ *handle*)

This function deinitializes the LPUART module, sets all register value to the reset value, and releases the resources.

Parameters

handle	The RTOS LPUART handle.

13.5.3.3 int LPUART_RTOS_Send (lpuart_rtos_handle_t ∗ *handle,* const uint8_t ∗ *buffer,* uint32_t *length*)

This function sends data. It is an synchronous API. If the hardware buffer is full, the task is in the blocked state.

Parameters

handle	The RTOS LPUART handle.
buffer	The pointer to buffer to send.
length	The number of bytes to send.

13.5.3.4 int LPUART_RTOS_Receive (lpuart_rtos_handle_t ∗ *handle,* uint8_t ∗ *buffer,* uint32_t *length,* size_t ∗ *received*)

This function receives data from LPUART. It is an synchronous API. If any data is immediately available it is returned immediately and the number of bytes received.

Parameters

handle	The RTOS LPUART handle.
buffer	The pointer to buffer where to write received data.
length	The number of bytes to receive.
received	The pointer to a variable of size_t where the number of received data is filled.

Chapter 14
PMC: Power Management Controller

14.1 Overview

The MCUXpresso SDK provides a Peripheral driver for the Power Management Controller (PMC) module of MCUXpresso SDK devices. The PMC module contains internal voltage regulator, power on reset, low-voltage detect system, and high-voltage detect system.

Data Structures

- struct pmc_low_volt_detect_config_t
  Low-voltage Detect Configuration Structure. More...
- struct pmc_low_volt_warning_config_t
  Low-voltage Warning Configuration Structure. More...
- struct pmc_bandgap_buffer_config_t
  Bandgap Buffer configuration. More...

Enumerations

- enum pmc_low_volt_detect_volt_select_t {
  kPMC_LowVoltDetectLowTrip = 0U,
  kPMC_LowVoltDetectHighTrip = 1U }
  Low-voltage Detect Voltage Select.
- enum pmc_low_volt_warning_volt_select_t {
  kPMC_LowVoltWarningLowTrip = 0U,
  kPMC_LowVoltWarningMid1Trip = 1U,
  kPMC_LowVoltWarningMid2Trip = 2U,
  kPMC_LowVoltWarningHighTrip = 3U }
  Low-voltage Warning Voltage Select.

Driver version

- #define FSL_PMC_DRIVER_VERSION (MAKE_VERSION(2, 0, 0))
  PMC driver version.

Power Management Controller Control APIs

- void PMC_ConfigureLowVoltDetect (PMC_Type *base, const pmc_low_volt_detect_config_t *config)
  Configures the low-voltage detect setting.
- static bool PMC_GetLowVoltDetectFlag (PMC_Type *base)
  Gets the Low-voltage Detect Flag status.
- static void PMC_ClearLowVoltDetectFlag (PMC_Type *base)
  Acknowledges clearing the Low-voltage Detect flag.

- void PMC_ConfigureLowVoltWarning (PMC_Type ∗base, const pmc_low_volt_warning_config_t ∗config)
  Configures the low-voltage warning setting.
- static bool PMC_GetLowVoltWarningFlag (PMC_Type ∗base)
  Gets the Low-voltage Warning Flag status.
- static void PMC_ClearLowVoltWarningFlag (PMC_Type ∗base)
  Acknowledges the Low-voltage Warning flag.
- void PMC_ConfigureBandgapBuffer (PMC_Type ∗base, const pmc_bandgap_buffer_config_t ∗config)
  Configures the PMC bandgap.
- static bool PMC_GetPeriphIOIsolationFlag (PMC_Type ∗base)
  Gets the acknowledge Peripherals and I/O pads isolation flag.
- static void PMC_ClearPeriphIOIsolationFlag (PMC_Type ∗base)
  Acknowledges the isolation flag to Peripherals and I/O pads.
- static bool PMC_IsRegulatorInRunRegulation (PMC_Type ∗base)
  Gets the regulator regulation status.

14.2 Data Structure Documentation

14.2.1 struct pmc_low_volt_detect_config_t

Data Fields

- bool enableInt
  Enable interrupt when Low-voltage detect.
- bool enableReset
  Enable system reset when Low-voltage detect.
- pmc_low_volt_detect_volt_select_t voltSelect
  Low-voltage detect trip point voltage selection.

14.2.2 struct pmc_low_volt_warning_config_t

Data Fields

- bool enableInt
  Enable interrupt when low-voltage warning.
- pmc_low_volt_warning_volt_select_t voltSelect
  Low-voltage warning trip point voltage selection.

14.2.3 struct pmc_bandgap_buffer_config_t

Data Fields

- bool enable
  Enable bandgap buffer.
- bool enableInLowPowerMode

Enable bandgap buffer in low-power mode.

14.2.3.0.0.30 Field Documentation

14.2.3.0.0.30.1 bool pmc_bandgap_buffer_config_t::enable

14.2.3.0.0.30.2 bool pmc_bandgap_buffer_config_t::enableInLowPowerMode

14.3 Macro Definition Documentation

14.3.1 #define FSL_PMC_DRIVER_VERSION (MAKE_VERSION(2, 0, 0))

Version 2.0.0.

14.4 Enumeration Type Documentation

14.4.1 enum pmc_low_volt_detect_volt_select_t

Enumerator

kPMC_LowVoltDetectLowTrip Low-trip point selected (VLVD = VLVDL)
kPMC_LowVoltDetectHighTrip High-trip point selected (VLVD = VLVDH)

14.4.2 enum pmc_low_volt_warning_volt_select_t

Enumerator

kPMC_LowVoltWarningLowTrip Low-trip point selected (VLVW = VLVW1)
kPMC_LowVoltWarningMid1Trip Mid 1 trip point selected (VLVW = VLVW2)
kPMC_LowVoltWarningMid2Trip Mid 2 trip point selected (VLVW = VLVW3)
kPMC_LowVoltWarningHighTrip High-trip point selected (VLVW = VLVW4)

14.5 Function Documentation

14.5.1 void PMC_ConfigureLowVoltDetect (PMC_Type * *base*, const pmc_low_volt_detect_config_t * *config*)

This function configures the low-voltage detect setting, including the trip point voltage setting, enables or disables the interrupt, enables or disables the system reset.

Parameters

base	PMC peripheral base address.
config	Low-voltage detect configuration structure.

14.5.2 static bool PMC_GetLowVoltDetectFlag (PMC_Type * *base*) [inline], [static]

This function reads the current LVDF status. If it returns 1, a low-voltage event is detected.

Parameters

base	PMC peripheral base address.

Returns

Current low-voltage detect flag
- true: Low-voltage detected
- false: Low-voltage not detected

14.5.3 static void PMC_ClearLowVoltDetectFlag (PMC_Type * *base*) [inline], [static]

This function acknowledges the low-voltage detection errors (write 1 to clear LVDF).

Parameters

base	PMC peripheral base address.

14.5.4 void PMC_ConfigureLowVoltWarning (PMC_Type * *base*, const pmc_low_volt_warning_config_t * *config*)

This function configures the low-voltage warning setting, including the trip point voltage setting and enabling or disabling the interrupt.

Parameters

base	PMC peripheral base address.
config	Low-voltage warning configuration structure.

14.5.5 static bool PMC_GetLowVoltWarningFlag (PMC_Type * *base*) [inline], [static]

This function polls the current LVWF status. When 1 is returned, it indicates a low-voltage warning event. LVWF is set when V Supply transitions below the trip point or after reset and V Supply is already below the V LVW.

Parameters

base	PMC peripheral base address.

Returns

Current LVWF status
- true: Low-voltage Warning Flag is set.
- false: the Low-voltage Warning does not happen.

14.5.6 static void PMC_ClearLowVoltWarningFlag (PMC_Type * *base*) [inline], [static]

This function acknowledges the low voltage warning errors (write 1 to clear LVWF).

Parameters

base	PMC peripheral base address.

14.5.7 void PMC_ConfigureBandgapBuffer (PMC_Type * *base,* const pmc_bandgap_buffer_config_t * *config*)

This function configures the PMC bandgap, including the drive select and behavior in low-power mode.

Parameters

base	PMC peripheral base address.
config	Pointer to the configuration structure

14.5.8 static bool PMC_GetPeriphIOIsolationFlag (PMC_Type * *base*) [inline], [static]

This function reads the Acknowledge Isolation setting that indicates whether certain peripherals and the I/O pads are in a latched state as a result of having been in the VLLS mode.

Parameters

base	PMC peripheral base address.
base	Base address for current PMC instance.

Returns

ACK isolation 0 - Peripherals and I/O pads are in a normal run state. 1 - Certain peripherals and I/O pads are in an isolated and latched state.

14.5.9 static void PMC_ClearPeriphIOIsolationFlag (PMC_Type * *base*) [inline], [static]

This function clears the ACK Isolation flag. Writing one to this setting when it is set releases the I/O pads and certain peripherals to their normal run mode state.

Parameters

base	PMC peripheral base address.

14.5.10 static bool PMC_IsRegulatorInRunRegulation (PMC_Type * *base*) [inline], [static]

This function returns the regulator to run a regulation status. It provides the current status of the internal voltage regulator.

Parameters

base	PMC peripheral base address.
base	Base address for current PMC instance.

Returns

Regulation status 0 - Regulator is in a stop regulation or in transition to/from the regulation. 1 - Regulator is in a run regulation.

Chapter 15
PORT: Port Control and Interrupts

15.1 Overview

The MCUXpresso SDK provides a driver for the Port Control and Interrupts (PORT) module of MCUXpresso SDK devices.

15.2 Typical configuration use case

15.2.1 Input PORT configuration

```
/* Input pin PORT configuration */
port_pin_config_t config = {
    kPORT_PullUp,
    kPORT_FastSlewRate,
    kPORT_PassiveFilterDisable,
    kPORT_OpenDrainDisable,
    kPORT_LowDriveStrength,
    kPORT_MuxAsGpio,
    kPORT_UnLockRegister,
};
/*  Sets the configuration */
PORT_SetPinConfig(PORTA, 4, &config);
```

15.2.2 I2C PORT Configuration

```
/*  I2C pin PORTconfiguration */
port_pin_config_t config = {
    kPORT_PullUp,
    kPORT_FastSlewRate,
    kPORT_PassiveFilterDisable,
    kPORT_OpenDrainEnable,
    kPORT_LowDriveStrength,
    kPORT_MuxAlt5,
    kPORT_UnLockRegister,
};
PORT_SetPinConfig(PORTE,24u,&config);
PORT_SetPinConfig(PORTE,25u,&config);
```

Data Structures

- struct port_pin_config_t
  PORT pin configuration structure. More...

Enumerations

- enum _port_pull {
  kPORT_PullDisable = 0U,
  kPORT_PullDown = 2U,
  kPORT_PullUp = 3U }

Internal resistor pull feature selection.
- enum _port_slew_rate {
kPORT_FastSlewRate = 0U,
kPORT_SlowSlewRate = 1U }
  Slew rate selection.
- enum _port_passive_filter_enable {
kPORT_PassiveFilterDisable = 0U,
kPORT_PassiveFilterEnable = 1U }
  Passive filter feature enable/disable.
- enum _port_drive_strength {
kPORT_LowDriveStrength = 0U,
kPORT_HighDriveStrength = 1U }
  Configures the drive strength.
- enum port_mux_t {
kPORT_PinDisabledOrAnalog = 0U,
kPORT_MuxAsGpio = 1U,
kPORT_MuxAlt2 = 2U,
kPORT_MuxAlt3 = 3U,
kPORT_MuxAlt4 = 4U,
kPORT_MuxAlt5 = 5U,
kPORT_MuxAlt6 = 6U,
kPORT_MuxAlt7 = 7U,
kPORT_MuxAlt8 = 8U,
kPORT_MuxAlt9 = 9U,
kPORT_MuxAlt10 = 10U,
kPORT_MuxAlt11 = 11U,
kPORT_MuxAlt12 = 12U,
kPORT_MuxAlt13 = 13U,
kPORT_MuxAlt14 = 14U,
kPORT_MuxAlt15 = 15U }
  Pin mux selection.
- enum port_interrupt_t {
kPORT_InterruptOrDMADisabled = 0x0U,
kPORT_InterruptLogicZero = 0x8U,
kPORT_InterruptRisingEdge = 0x9U,
kPORT_InterruptFallingEdge = 0xAU,
kPORT_InterruptEitherEdge = 0xBU,
kPORT_InterruptLogicOne = 0xCU }
  Configures the interrupt generation condition.

Driver version

- #define FSL_PORT_DRIVER_VERSION (MAKE_VERSION(2, 0, 2))
  Version 2.0.2.

Configuration

- static void PORT_SetPinConfig (PORT_Type *base, uint32_t pin, const port_pin_config_t *config)
  Sets the port PCR register.
- static void PORT_SetMultiplePinsConfig (PORT_Type *base, uint32_t mask, const port_pin_config_t *config)
  Sets the port PCR register for multiple pins.
- static void PORT_SetPinMux (PORT_Type *base, uint32_t pin, port_mux_t mux)
  Configures the pin muxing.

Interrupt

- static void PORT_SetPinInterruptConfig (PORT_Type *base, uint32_t pin, port_interrupt_t config)
  Configures the port pin interrupt/DMA request.
- static uint32_t PORT_GetPinsInterruptFlags (PORT_Type *base)
  Reads the whole port status flag.
- static void PORT_ClearPinsInterruptFlags (PORT_Type *base, uint32_t mask)
  Clears the multiple pin interrupt status flag.

15.3 Data Structure Documentation

15.3.1 struct port_pin_config_t

Data Fields

- uint16_t pullSelect: 2
  No-pull/pull-down/pull-up select.
- uint16_t slewRate: 1
  Fast/slow slew rate Configure.
- uint16_t passiveFilterEnable: 1
  Passive filter enable/disable.
- uint16_t driveStrength: 1
  Fast/slow drive strength configure.
- uint16_t mux: 3
  Pin mux Configure.

15.4 Macro Definition Documentation

15.4.1 #define FSL_PORT_DRIVER_VERSION (MAKE_VERSION(2, 0, 2))

15.5 Enumeration Type Documentation

15.5.1 enum _port_pull

Enumerator

kPORT_PullDisable Internal pull-up/down resistor is disabled.
kPORT_PullDown Internal pull-down resistor is enabled.
kPORT_PullUp Internal pull-up resistor is enabled.

15.5.2 enum _port_slew_rate

Enumerator

kPORT_FastSlewRate Fast slew rate is configured.
kPORT_SlowSlewRate Slow slew rate is configured.

15.5.3 enum _port_passive_filter_enable

Enumerator

kPORT_PassiveFilterDisable Passive input filter is disabled.
kPORT_PassiveFilterEnable Passive input filter is enabled.

15.5.4 enum _port_drive_strength

Enumerator

kPORT_LowDriveStrength Low-drive strength is configured.
kPORT_HighDriveStrength High-drive strength is configured.

15.5.5 enum port_mux_t

Enumerator

kPORT_PinDisabledOrAnalog Corresponding pin is disabled, but is used as an analog pin.
kPORT_MuxAsGpio Corresponding pin is configured as GPIO.
kPORT_MuxAlt2 Chip-specific.
kPORT_MuxAlt3 Chip-specific.
kPORT_MuxAlt4 Chip-specific.
kPORT_MuxAlt5 Chip-specific.
kPORT_MuxAlt6 Chip-specific.
kPORT_MuxAlt7 Chip-specific.
kPORT_MuxAlt8 Chip-specific.
kPORT_MuxAlt9 Chip-specific.
kPORT_MuxAlt10 Chip-specific.
kPORT_MuxAlt11 Chip-specific.
kPORT_MuxAlt12 Chip-specific.
kPORT_MuxAlt13 Chip-specific.
kPORT_MuxAlt14 Chip-specific.
kPORT_MuxAlt15 Chip-specific.

15.5.6 enum port_interrupt_t

Enumerator

kPORT_InterruptOrDMADisabled Interrupt/DMA request is disabled.
kPORT_InterruptLogicZero Interrupt when logic zero.
kPORT_InterruptRisingEdge Interrupt on rising edge.
kPORT_InterruptFallingEdge Interrupt on falling edge.
kPORT_InterruptEitherEdge Interrupt on either edge.
kPORT_InterruptLogicOne Interrupt when logic one.

15.6 Function Documentation

15.6.1 static void PORT_SetPinConfig (PORT_Type * *base*, uint32_t *pin*, const port_pin_config_t * *config*) [inline], [static]

This is an example to define an input pin or output pin PCR configuration.

```
* // Define a digital input pin PCR configuration
* port_pin_config_t config = {
*      kPORT_PullUp,
*      kPORT_FastSlewRate,
*      kPORT_PassiveFilterDisable,
*      kPORT_OpenDrainDisable,
*      kPORT_LowDriveStrength,
*      kPORT_MuxAsGpio,
*      kPORT_UnLockRegister,
* };
*
```

Parameters

base	PORT peripheral base pointer.
pin	PORT pin number.
config	PORT PCR register configuration structure.

15.6.2 static void PORT_SetMultiplePinsConfig (PORT_Type * *base*, uint32_t *mask*, const port_pin_config_t * *config*) [inline], [static]

This is an example to define input pins or output pins PCR configuration.

```
* // Define a digital input pin PCR configuration
* port_pin_config_t config = {
*      kPORT_PullUp ,
*      kPORT_PullEnable,
*      kPORT_FastSlewRate,
*      kPORT_PassiveFilterDisable,
*      kPORT_OpenDrainDisable,
```

```
*       kPORT_LowDriveStrength,
*       kPORT_MuxAsGpio,
*       kPORT_UnlockRegister,
* };
*
```

Parameters

base	PORT peripheral base pointer.
mask	PORT pin number macro.
config	PORT PCR register configuration structure.

15.6.3 static void PORT_SetPinMux (PORT_Type ∗ *base*, uint32_t *pin*, port_mux_t *mux*) [inline], [static]

Parameters

base	PORT peripheral base pointer.
pin	PORT pin number.
mux	pin muxing slot selection. • kPORT_PinDisabledOrAnalog: Pin disabled or work in analog function. • kPORT_MuxAsGpio : Set as GPIO. • kPORT_MuxAlt2 : chip-specific. • kPORT_MuxAlt3 : chip-specific. • kPORT_MuxAlt4 : chip-specific. • kPORT_MuxAlt5 : chip-specific. • kPORT_MuxAlt6 : chip-specific. • kPORT_MuxAlt7 : chip-specific. : This function is NOT recommended to use together with the PORT_SetPinsConfig, because the PORT_SetPinsConfig need to configure the pin mux anyway (Otherwise the pin mux is reset to zero : kPORT_PinDisabledOrAnalog). This function is recommended to use to reset the pin mux

15.6.4 static void PORT_SetPinInterruptConfig (PORT_Type ∗ *base*, uint32_t *pin*, port_interrupt_t *config*) [inline], [static]

Parameters

base	PORT peripheral base pointer.
pin	PORT pin number.
config	PORT pin interrupt configuration. • kPORT_InterruptOrDMADisabled: Interrupt/DMA request disabled. • #kPORT_DMARisingEdge : DMA request on rising edge(if the DMA requests exit). • #kPORT_DMAFallingEdge: DMA request on falling edge(if the DMA requests exit). • #kPORT_DMAEitherEdge : DMA request on either edge(if the DMA requests exit). • #kPORT_FlagRisingEdge : Flag sets on rising edge(if the Flag states exit). • #kPORT_FlagFallingEdge : Flag sets on falling edge(if the Flag states exit). • #kPORT_FlagEitherEdge : Flag sets on either edge(if the Flag states exit). • kPORT_InterruptLogicZero : Interrupt when logic zero. • kPORT_InterruptRisingEdge : Interrupt on rising edge. • kPORT_InterruptFallingEdge: Interrupt on falling edge. • kPORT_InterruptEitherEdge : Interrupt on either edge. • kPORT_InterruptLogicOne : Interrupt when logic one. • #kPORT_ActiveHighTriggerOutputEnable : Enable active high-trigger output (if the trigger states exit). • #kPORT_ActiveLowTriggerOutputEnable : Enable active low-trigger output (if the trigger states exit).

15.6.5 static uint32_t PORT_GetPinsInterruptFlags (PORT_Type * *base*) [inline], [static]

If a pin is configured to generate the DMA request, the corresponding flag is cleared automatically at the completion of the requested DMA transfer. Otherwise, the flag remains set until a logic one is written to that flag. If configured for a level sensitive interrupt that remains asserted, the flag is set again immediately.

Parameters

base	PORT peripheral base pointer.

Returns

Current port interrupt status flags, for example, 0x00010001 means the pin 0 and 16 have the interrupt.

15.6.6 static void PORT_ClearPinsInterruptFlags (PORT_Type * *base*, uint32_t *mask*) [inline], [static]

Parameters

base	PORT peripheral base pointer.
mask	PORT pin number macro.

Chapter 16
RCM: Reset Control Module Driver

16.1 Overview

The MCUXpresso SDK provides a Peripheral driver for the Reset Control Module (RCM) module of MCUXpresso SDK devices.

Data Structures

- struct rcm_reset_pin_filter_config_t
  Reset pin filter configuration. More...

Enumerations

- enum rcm_reset_source_t {
  kRCM_SourceWakeup = RCM_SRS0_WAKEUP_MASK,
  kRCM_SourceLvd = RCM_SRS0_LVD_MASK,
  kRCM_SourceWdog = RCM_SRS0_WDOG_MASK,
  kRCM_SourcePin = RCM_SRS0_PIN_MASK,
  kRCM_SourcePor = RCM_SRS0_POR_MASK,
  kRCM_SourceLockup = RCM_SRS1_LOCKUP_MASK << 8U,
  kRCM_SourceSw = RCM_SRS1_SW_MASK << 8U,
  kRCM_SourceMdmap = RCM_SRS1_MDM_AP_MASK << 8U,
  kRCM_SourceSackerr = RCM_SRS1_SACKERR_MASK << 8U }
  System Reset Source Name definitions.
- enum rcm_run_wait_filter_mode_t {
  kRCM_FilterDisable = 0U,
  kRCM_FilterBusClock = 1U,
  kRCM_FilterLpoClock = 2U }
  Reset pin filter select in Run and Wait modes.
- enum rcm_boot_rom_config_t {
  kRCM_BootFlash = 0U,
  kRCM_BootRomCfg0 = 1U,
  kRCM_BootRomFopt = 2U,
  kRCM_BootRomBoth = 3U }
  Boot from ROM configuration.

Driver version

- #define FSL_RCM_DRIVER_VERSION (MAKE_VERSION(2, 0, 1))
  RCM driver version 2.0.1.

Reset Control Module APIs

- static uint32_t RCM_GetPreviousResetSources (RCM_Type *base)
  Gets the reset source status which caused a previous reset.
- static uint32_t RCM_GetStickyResetSources (RCM_Type *base)
  Gets the sticky reset source status.
- static void RCM_ClearStickyResetSources (RCM_Type *base, uint32_t sourceMasks)
  Clears the sticky reset source status.
- void RCM_ConfigureResetPinFilter (RCM_Type *base, const rcm_reset_pin_filter_config_t *config)
  Configures the reset pin filter.
- static rcm_boot_rom_config_t RCM_GetBootRomSource (RCM_Type *base)
  Gets the ROM boot source.
- static void RCM_ClearBootRomSource (RCM_Type *base)
  Clears the ROM boot source flag.
- void RCM_SetForceBootRomSource (RCM_Type *base, rcm_boot_rom_config_t config)
  Forces the boot from ROM.

16.2 Data Structure Documentation

16.2.1 struct rcm_reset_pin_filter_config_t

Data Fields

- bool enableFilterInStop
  Reset pin filter select in stop mode.
- rcm_run_wait_filter_mode_t filterInRunWait
  Reset pin filter in run/wait mode.
- uint8_t busClockFilterCount
  Reset pin bus clock filter width.

16.2.1.0.0.31 Field Documentation

16.2.1.0.0.31.1 bool rcm_reset_pin_filter_config_t::enableFilterInStop

16.2.1.0.0.31.2 rcm_run_wait_filter_mode_t rcm_reset_pin_filter_config_t::filterInRunWait

16.2.1.0.0.31.3 uint8_t rcm_reset_pin_filter_config_t::busClockFilterCount

16.3 Macro Definition Documentation

16.3.1 #define FSL_RCM_DRIVER_VERSION (MAKE_VERSION(2, 0, 1))

16.4 Enumeration Type Documentation

16.4.1 enum rcm_reset_source_t

Enumerator

kRCM_SourceWakeup Low-leakage wakeup reset.

kRCM_SourceLvd Low-voltage detect reset.
kRCM_SourceWdog Watchdog reset.
kRCM_SourcePin External pin reset.
kRCM_SourcePor Power on reset.
kRCM_SourceLockup Core lock up reset.
kRCM_SourceSw Software reset.
kRCM_SourceMdmap MDM-AP system reset.
kRCM_SourceSackerr Parameter could get all reset flags.

16.4.2 enum rcm_run_wait_filter_mode_t

Enumerator

kRCM_FilterDisable All filtering disabled.
kRCM_FilterBusClock Bus clock filter enabled.
kRCM_FilterLpoClock LPO clock filter enabled.

16.4.3 enum rcm_boot_rom_config_t

Enumerator

kRCM_BootFlash Boot from flash.
kRCM_BootRomCfg0 Boot from boot ROM due to BOOTCFG0.
kRCM_BootRomFopt Boot from boot ROM due to FOPT[7].
kRCM_BootRomBoth Boot from boot ROM due to both BOOTCFG0 and FOPT[7].

16.5 Function Documentation

16.5.1 static uint32_t RCM_GetPreviousResetSources (RCM_Type * *base*) [inline], [static]

This function gets the current reset source status. Use source masks defined in the rcm_reset_source_t to get the desired source status.

This is an example.

```
uint32_t resetStatus;

// To get all reset source statuses.
resetStatus = RCM_GetPreviousResetSources(RCM) & kRCM_SourceAll;

// To test whether the MCU is reset using Watchdog.
resetStatus = RCM_GetPreviousResetSources(RCM) &
      kRCM_SourceWdog;

// To test multiple reset sources.
resetStatus = RCM_GetPreviousResetSources(RCM) & (
      kRCM_SourceWdog | kRCM_SourcePin);
```

Parameters

base	RCM peripheral base address.

Returns

All reset source status bit map.

16.5.2 static uint32_t RCM_GetStickyResetSources (RCM_Type * *base*) [inline], [static]

This function gets the current reset source status that has not been cleared by software for a specific source.

This is an example.

```
uint32_t resetStatus;

// To get all reset source statuses.
resetStatus = RCM_GetStickyResetSources(RCM) & kRCM_SourceAll;

// To test whether the MCU is reset using Watchdog.
resetStatus = RCM_GetStickyResetSources(RCM) &
      kRCM_SourceWdog;

// To test multiple reset sources.
resetStatus = RCM_GetStickyResetSources(RCM) & (
      kRCM_SourceWdog | kRCM_SourcePin);
```

Parameters

base	RCM peripheral base address.

Returns

All reset source status bit map.

16.5.3 static void RCM_ClearStickyResetSources (RCM_Type * *base,* uint32_t *sourceMasks*) [inline], [static]

This function clears the sticky system reset flags indicated by source masks.

This is an example.

```
// Clears multiple reset sources.
RCM_ClearStickyResetSources(kRCM_SourceWdog |
      kRCM_SourcePin);
```

Parameters

base	RCM peripheral base address.
sourceMasks	reset source status bit map

16.5.4 void RCM_ConfigureResetPinFilter (RCM_Type * *base,* const rcm_reset_pin_filter_config_t * *config*)

This function sets the reset pin filter including the filter source, filter width, and so on.

Parameters

base	RCM peripheral base address.
config	Pointer to the configuration structure.

16.5.5 static rcm_boot_rom_config_t RCM_GetBootRomSource (RCM_Type * *base*) [inline], [static]

This function gets the ROM boot source during the last chip reset.

Parameters

base	RCM peripheral base address.

Returns

The ROM boot source.

16.5.6 static void RCM_ClearBootRomSource (RCM_Type * *base*) [inline], [static]

This function clears the ROM boot source flag.

Parameters

base	Register base address of RCM

16.5.7 void RCM_SetForceBootRomSource (RCM_Type * *base*, rcm_boot_rom_config_t *config*)

This function forces booting from ROM during all subsequent system resets.

Parameters

base	RCM peripheral base address.
config	Boot configuration.

Chapter 17
RTC: Real Time Clock

17.1 Overview

The MCUXpresso SDK provides a driver for the Real Time Clock (RTC) of MCUXpresso SDK devices.

17.2 Function groups

The RTC driver supports operating the module as a time counter.

17.2.1 Initialization and deinitialization

The function RTC_Init() initializes the RTC with specified configurations. The function RTC_GetDefault-Config() gets the default configurations.

The function RTC_Deinit() disables the RTC timer and disables the module clock.

17.2.2 Set & Get Datetime

The function RTC_SetDatetime() sets the timer period in seconds. Users pass in the details in date & time format by using the below data structure.

```
typedef struct _rtc_datetime
{
    uint16_t year;
    uint8_t month;
    uint8_t day;
    uint8_t hour;
    uint8_t minute;
    uint8_t second;
} rtc_datetime_t;
```

The function RTC_GetDatetime() reads the current timer value in seconds, converts it to date & time format and stores it into a datetime structure passed in by the user.

17.2.3 Set & Get Alarm

The function RTC_SetAlarm() sets the alarm time period in seconds. Users pass in the details in date & time format by using the datetime data structure.

The function RTC_GetAlarm() reads the alarm time in seconds, converts it to date & time format and stores it into a datetime structure passed in by the user.

17.2.4 Start & Stop timer

The function RTC_StartTimer() starts the RTC time counter.

The function RTC_StopTimer() stops the RTC time counter.

17.2.5 Status

Provides functions to get and clear the RTC status.

17.2.6 Interrupt

Provides functions to enable/disable RTC interrupts and get current enabled interrupts.

17.2.7 RTC Oscillator

Some SoC's allow control of the RTC oscillator through the RTC module.

The function RTC_SetOscCapLoad() allows the user to modify the capacitor load configuration of the RTC oscillator.

17.2.8 Monotonic Counter

Some SoC's have a 64-bit Monotonic counter available in the RTC module.

The function RTC_SetMonotonicCounter() writes a 64-bit to the counter.

The function RTC_GetMonotonicCounter() reads the monotonic counter and returns the 64-bit counter value to the user.

The function RTC_IncrementMonotonicCounter() increments the Monotonic Counter by one.

17.3 Typical use case

17.3.1 RTC tick example

Example to set the RTC current time and trigger an alarm.

```
int main(void)
{
    uint32_t sec;
    uint32_t currSeconds;
    rtc_datetime_t date;
    rtc_config_t rtcConfig;

    /* Board pin, clock, debug console init */
```

```
BOARD_InitHardware();
/* Init RTC */
RTC_GetDefaultConfig(&rtcConfig);
RTC_Init(RTC, &rtcConfig);
/* Select RTC clock source */
BOARD_SetRtcClockSource();

PRINTF("RTC example: set up time to wake up an alarm\r\n");

/* Set a start date time and start RT */
date.year = 2014U;
date.month = 12U;
date.day = 25U;
date.hour = 19U;
date.minute = 0;
date.second = 0;

/* RTC time counter has to be stopped before setting the date & time in the TSR register */
RTC_StopTimer(RTC);

/* Set RTC time to default */
RTC_SetDatetime(RTC, &date);

/* Enable RTC alarm interrupt */
RTC_EnableInterrupts(RTC, kRTC_AlarmInterruptEnable);

/* Enable at the NVIC */
EnableIRQ(RTC_IRQn);

/* Start the RTC time counter */
RTC_StartTimer(RTC);

/* This loop will set the RTC alarm */
while (1)
{
    busyWait = true;
    /* Get date time */
    RTC_GetDatetime(RTC, &date);

    /* print default time */
    PRINTF("Current datetime: %04hd-%02hd-%02hd %02hd:%02hd:%02hd\r\n", date.
  year, date.month, date.day, date.hour,
           date.minute, date.second);

    /* Get alarm time from the user */
    sec = 0;
    PRINTF("Input the number of second to wait for alarm \r\n");
    PRINTF("The second must be positive value\r\n");
    while (sec < 1)
    {
        SCANF("%d", &sec);
    }

    /* Read the RTC seconds register to get current time in seconds */
    currSeconds = RTC->TSR;

    /* Add alarm seconds to current time */
    currSeconds += sec;

    /* Set alarm time in seconds */
    RTC->TAR = currSeconds;

    /* Get alarm time */
    RTC_GetAlarm(RTC, &date);

    /* Print alarm time */
    PRINTF("Alarm will occur at: %04hd-%02hd-%02hd %02hd:%02hd:%02hd\r\n", date.
  year, date.month, date.day,
```

```
            date.hour, date.minute, date.second);

        /* Wait until alarm occurs */
        while (busyWait)
        {
        }

        PRINTF("\r\n Alarm occurs !!!! ");
    }
}
```

Data Structures

- struct rtc_datetime_t
  Structure is used to hold the date and time. More...
- struct rtc_config_t
  RTC config structure. More...

Enumerations

- enum rtc_interrupt_enable_t {
  kRTC_TimeInvalidInterruptEnable = RTC_IER_TIIE_MASK,
  kRTC_TimeOverflowInterruptEnable = RTC_IER_TOIE_MASK,
  kRTC_AlarmInterruptEnable = RTC_IER_TAIE_MASK,
  kRTC_SecondsInterruptEnable = RTC_IER_TSIE_MASK }
  List of RTC interrupts.
- enum rtc_status_flags_t {
  kRTC_TimeInvalidFlag = RTC_SR_TIF_MASK,
  kRTC_TimeOverflowFlag = RTC_SR_TOF_MASK,
  kRTC_AlarmFlag = RTC_SR_TAF_MASK }
  List of RTC flags.
- enum rtc_osc_cap_load_t {
  kRTC_Capacitor_2p = RTC_CR_SC2P_MASK,
  kRTC_Capacitor_4p = RTC_CR_SC4P_MASK,
  kRTC_Capacitor_8p = RTC_CR_SC8P_MASK,
  kRTC_Capacitor_16p = RTC_CR_SC16P_MASK }
  List of RTC Oscillator capacitor load settings.

Functions

- static void RTC_SetOscCapLoad (RTC_Type ∗base, uint32_t capLoad)
  This function sets the specified capacitor configuration for the RTC oscillator.
- static void RTC_Reset (RTC_Type ∗base)
  Performs a software reset on the RTC module.

Driver version

- #define FSL_RTC_DRIVER_VERSION (MAKE_VERSION(2, 0, 0))
  Version 2.0.0.

Initialization and deinitialization

- void RTC_Init (RTC_Type ∗base, const rtc_config_t ∗config)
  Ungates the RTC clock and configures the peripheral for basic operation.
- static void RTC_Deinit (RTC_Type ∗base)
  Stops the timer and gate the RTC clock.
- void RTC_GetDefaultConfig (rtc_config_t ∗config)
  Fills in the RTC config struct with the default settings.

Current Time & Alarm

- status_t RTC_SetDatetime (RTC_Type ∗base, const rtc_datetime_t ∗datetime)
  Sets the RTC date and time according to the given time structure.
- void RTC_GetDatetime (RTC_Type ∗base, rtc_datetime_t ∗datetime)
  Gets the RTC time and stores it in the given time structure.
- status_t RTC_SetAlarm (RTC_Type ∗base, const rtc_datetime_t ∗alarmTime)
  Sets the RTC alarm time.
- void RTC_GetAlarm (RTC_Type ∗base, rtc_datetime_t ∗datetime)
  Returns the RTC alarm time.

Interrupt Interface

- static void RTC_EnableInterrupts (RTC_Type ∗base, uint32_t mask)
  Enables the selected RTC interrupts.
- static void RTC_DisableInterrupts (RTC_Type ∗base, uint32_t mask)
  Disables the selected RTC interrupts.
- static uint32_t RTC_GetEnabledInterrupts (RTC_Type ∗base)
  Gets the enabled RTC interrupts.

Status Interface

- static uint32_t RTC_GetStatusFlags (RTC_Type ∗base)
  Gets the RTC status flags.
- void RTC_ClearStatusFlags (RTC_Type ∗base, uint32_t mask)
  Clears the RTC status flags.

Timer Start and Stop

- static void RTC_StartTimer (RTC_Type ∗base)
  Starts the RTC time counter.
- static void RTC_StopTimer (RTC_Type ∗base)
  Stops the RTC time counter.

17.4 Data Structure Documentation

17.4.1 struct rtc_datetime_t

Data Fields

- uint16_t year

Range from 1970 to 2099.
- uint8_t month
  Range from 1 to 12.
- uint8_t day
  Range from 1 to 31 (depending on month).
- uint8_t hour
  Range from 0 to 23.
- uint8_t minute
  Range from 0 to 59.
- uint8_t second
  Range from 0 to 59.

17.4.1.0.0.32 Field Documentation

17.4.1.0.0.32.1 uint16_t rtc_datetime_t::year

17.4.1.0.0.32.2 uint8_t rtc_datetime_t::month

17.4.1.0.0.32.3 uint8_t rtc_datetime_t::day

17.4.1.0.0.32.4 uint8_t rtc_datetime_t::hour

17.4.1.0.0.32.5 uint8_t rtc_datetime_t::minute

17.4.1.0.0.32.6 uint8_t rtc_datetime_t::second

17.4.2 struct rtc_config_t

This structure holds the configuration settings for the RTC peripheral. To initialize this structure to reasonable defaults, call the RTC_GetDefaultConfig() function and pass a pointer to your config structure instance.

The config struct can be made const so it resides in flash

Data Fields

- bool wakeupSelect
  true: Wakeup pin outputs the 32 KHz clock; false:Wakeup pin used to wakeup the chip
- bool updateMode
  true: Registers can be written even when locked under certain conditions, false: No writes allowed when registers are locked
- bool supervisorAccess
  true: Non-supervisor accesses are allowed; false: Non-supervisor accesses are not supported
- uint32_t compensationInterval
  Compensation interval that is written to the CIR field in RTC TCR Register.
- uint32_t compensationTime
  Compensation time that is written to the TCR field in RTC TCR Register.

17.5 Enumeration Type Documentation

17.5.1 enum rtc_interrupt_enable_t

Enumerator

kRTC_TimeInvalidInterruptEnable Time invalid interrupt.
kRTC_TimeOverflowInterruptEnable Time overflow interrupt.
kRTC_AlarmInterruptEnable Alarm interrupt.
kRTC_SecondsInterruptEnable Seconds interrupt.

17.5.2 enum rtc_status_flags_t

Enumerator

kRTC_TimeInvalidFlag Time invalid flag.
kRTC_TimeOverflowFlag Time overflow flag.
kRTC_AlarmFlag Alarm flag.

17.5.3 enum rtc_osc_cap_load_t

Enumerator

kRTC_Capacitor_2p 2 pF capacitor load
kRTC_Capacitor_4p 4 pF capacitor load
kRTC_Capacitor_8p 8 pF capacitor load
kRTC_Capacitor_16p 16 pF capacitor load

17.6 Function Documentation

17.6.1 void RTC_Init (RTC_Type ∗ *base*, const rtc_config_t ∗ *config*)

This function issues a software reset if the timer invalid flag is set.

Note

This API should be called at the beginning of the application using the RTC driver.

Parameters

base	RTC peripheral base address
config	Pointer to the user's RTC configuration structure.

17.6.2 static void RTC_Deinit (RTC_Type * *base*) [inline], [static]

Parameters

base	RTC peripheral base address

17.6.3 void RTC_GetDefaultConfig (rtc_config_t * *config*)

The default values are as follows.

```
*    config->wakeupSelect = false;
*    config->updateMode = false;
*    config->supervisorAccess = false;
*    config->compensationInterval = 0;
*    config->compensationTime = 0;
*
```

Parameters

config	Pointer to the user's RTC configuration structure.

17.6.4 status_t RTC_SetDatetime (RTC_Type * *base,* const rtc_datetime_t * *datetime*)

The RTC counter must be stopped prior to calling this function because writes to the RTC seconds register fail if the RTC counter is running.

Parameters

base	RTC peripheral base address

datetime	Pointer to the structure where the date and time details are stored.

Returns

kStatus_Success: Success in setting the time and starting the RTC kStatus_InvalidArgument: Error because the datetime format is incorrect

17.6.5 void RTC_GetDatetime (RTC_Type * *base,* rtc_datetime_t * *datetime*)

Parameters

base	RTC peripheral base address
datetime	Pointer to the structure where the date and time details are stored.

17.6.6 status_t RTC_SetAlarm (RTC_Type * *base,* const rtc_datetime_t * *alarmTime*)

The function checks whether the specified alarm time is greater than the present time. If not, the function does not set the alarm and returns an error.

Parameters

base	RTC peripheral base address
alarmTime	Pointer to the structure where the alarm time is stored.

Returns

kStatus_Success: success in setting the RTC alarm kStatus_InvalidArgument: Error because the alarm datetime format is incorrect kStatus_Fail: Error because the alarm time has already passed

17.6.7 void RTC_GetAlarm (RTC_Type * *base,* rtc_datetime_t * *datetime*)

Parameters

base	RTC peripheral base address
datetime	Pointer to the structure where the alarm date and time details are stored.

17.6.8 static void RTC_EnableInterrupts (RTC_Type * *base*, uint32_t *mask*) [inline], [static]

Parameters

base	RTC peripheral base address
mask	The interrupts to enable. This is a logical OR of members of the enumeration rtc_-interrupt_enable_t

17.6.9 static void RTC_DisableInterrupts (RTC_Type * *base*, uint32_t *mask*) [inline], [static]

Parameters

base	RTC peripheral base address
mask	The interrupts to enable. This is a logical OR of members of the enumeration rtc_-interrupt_enable_t

17.6.10 static uint32_t RTC_GetEnabledInterrupts (RTC_Type * *base*) [inline], [static]

Parameters

base	RTC peripheral base address

Returns

The enabled interrupts. This is the logical OR of members of the enumeration rtc_interrupt_enable_t

17.6.11 static uint32_t RTC_GetStatusFlags (RTC_Type * *base*) [inline], [static]

Parameters

base	RTC peripheral base address

Returns

The status flags. This is the logical OR of members of the enumeration rtc_status_flags_t

17.6.12 void RTC_ClearStatusFlags (RTC_Type * *base*, uint32_t *mask*)

Parameters

base	RTC peripheral base address
mask	The status flags to clear. This is a logical OR of members of the enumeration rtc_-status_flags_t

17.6.13 static void RTC_StartTimer (RTC_Type * *base*) [inline], [static]

After calling this function, the timer counter increments once a second provided SR[TOF] or SR[TIF] are not set.

Parameters

base	RTC peripheral base address

17.6.14 static void RTC_StopTimer (RTC_Type * *base*) [inline], [static]

RTC's seconds register can be written to only when the timer is stopped.

Parameters

base	RTC peripheral base address

17.6.15 static void RTC_SetOscCapLoad (RTC_Type * *base*, uint32_t *capLoad*) [inline], [static]

Parameters

base	RTC peripheral base address
capLoad	Oscillator loads to enable. This is a logical OR of members of the enumeration rtc_-osc_cap_load_t

17.6.16 static void RTC_Reset (RTC_Type * *base*) [inline], [static]

This resets all RTC registers except for the SWR bit and the RTC_WAR and RTC_RAR registers. The SWR bit is cleared by software explicitly clearing it.

Parameters

base	RTC peripheral base address

Chapter 18
SIM: System Integration Module Driver

18.1 Overview

The MCUXpresso SDK provides a peripheral driver for the System Integration Module (SIM) of MCU-Xpresso SDK devices.

Data Structures

- struct sim_uid_t
  Unique ID. More...

Enumerations

- enum _sim_flash_mode {
  kSIM_FlashDisableInWait = SIM_FCFG1_FLASHDOZE_MASK,
  kSIM_FlashDisable = SIM_FCFG1_FLASHDIS_MASK }
  Flash enable mode.

Functions

- void SIM_GetUniqueId (sim_uid_t ∗uid)
  Gets the unique identification register value.
- static void SIM_SetFlashMode (uint8_t mode)
  Sets the flash enable mode.

Driver version

- #define FSL_SIM_DRIVER_VERSION (MAKE_VERSION(2, 0, 0))
  Driver version 2.0.0.

18.2 Data Structure Documentation

18.2.1 struct sim_uid_t

Data Fields

- uint32_t MH
  UIDMH.
- uint32_t ML
  UIDML.
- uint32_t L
  UIDL.

18.2.1.0.0.33 Field Documentation

18.2.1.0.0.33.1 uint32_t sim_uid_t::MH

18.2.1.0.0.33.2 uint32_t sim_uid_t::ML

18.2.1.0.0.33.3 uint32_t sim_uid_t::L

18.3 Enumeration Type Documentation

18.3.1 enum _sim_flash_mode

Enumerator

kSIM_FlashDisableInWait Disable flash in wait mode.
kSIM_FlashDisable Disable flash in normal mode.

18.4 Function Documentation

18.4.1 void SIM_GetUniqueId (sim_uid_t * *uid*)

Parameters

uid	Pointer to the structure to save the UID value.

18.4.2 static void SIM_SetFlashMode (uint8_t *mode*) [inline], [static]

Parameters

mode	The mode to set; see _sim_flash_mode for mode details.

Chapter 19
SMC: System Mode Controller Driver

19.1 Overview

The MCUXpresso SDK provides a peripheral driver for the System Mode Controller (SMC) module of MCUXpresso SDK devices. The SMC module sequences the system in and out of all low-power stop and run modes.

API functions are provided to configure the system for working in a dedicated power mode. For different power modes, SMC_SetPowerModexxx() function accepts different parameters. System power mode state transitions are not available between power modes. For details about available transitions, see the power mode transitions section in the SoC reference manual.

19.2 Typical use case

19.2.1 Enter wait or stop modes

SMC driver provides APIs to set MCU to different wait modes and stop modes. Pre and post functions are used for setting the modes. The pre functions and post functions are used as follows.

1. Disable/enable the interrupt through PRIMASK. This is an example use case. The application sets the wakeup interrupt and calls SMC function SMC_SetPowerModeStop to set the MCU to STOP mode, but the wakeup interrupt happens so quickly that the ISR completes before the function SMC_SetPowerModeStop. As a result, the MCU enters the STOP mode and never is woken up by the interrupt. In this use case, the application first disables the interrupt through PRIMASK, sets the wakeup interrupt, and enters the STOP mode. After wakeup, enable the interrupt through PRIMASK. The MCU can still be woken up by disabling the interrupt through PRIMASK. The pre and post functions handle the PRIMASK.
2. Disable/enable the flash speculation. When entering stop modes, the flash speculation might be interrupted. As a result, pre functions disable the flash speculation and post functions enable it.

```
SMC_PreEnterStopModes();

/* Enable the wakeup interrupt here. */

SMC_SetPowerModeStop(SMC, kSMC_PartialStop);

SMC_PostExitStopModes();
```

Data Structures

- struct smc_power_mode_lls_config_t
    SMC Low-Leakage Stop power mode configuration. More...
- struct smc_power_mode_vlls_config_t
    SMC Very Low-Leakage Stop power mode configuration. More...

Enumerations

- enum smc_power_mode_protection_t {
  kSMC_AllowPowerModeVlls = SMC_PMPROT_AVLLS_MASK,
  kSMC_AllowPowerModeVlp = SMC_PMPROT_AVLP_MASK,
  kSMC_AllowPowerModeAll }
  Power Modes Protection.
- enum smc_power_state_t {
  kSMC_PowerStateRun = 0x01U << 0U,
  kSMC_PowerStateStop = 0x01U << 1U,
  kSMC_PowerStateVlpr = 0x01U << 2U,
  kSMC_PowerStateVlpw = 0x01U << 3U,
  kSMC_PowerStateVlps = 0x01U << 4U,
  kSMC_PowerStateVlls = 0x01U << 6U }
  Power Modes in PMSTAT.
- enum smc_run_mode_t {
  kSMC_RunNormal = 0U,
  kSMC_RunVlpr = 2U }
  Run mode definition.
- enum smc_stop_mode_t {
  kSMC_StopNormal = 0U,
  kSMC_StopVlps = 2U,
  kSMC_StopVlls = 4U }
  Stop mode definition.
- enum smc_stop_submode_t {
  kSMC_StopSub0 = 0U,
  kSMC_StopSub1 = 1U,
  kSMC_StopSub2 = 2U,
  kSMC_StopSub3 = 3U }
  VLLS/LLS stop sub mode definition.
- enum smc_partial_stop_option_t {
  kSMC_PartialStop = 0U,
  kSMC_PartialStop1 = 1U,
  kSMC_PartialStop2 = 2U }
  Partial STOP option.
- enum _smc_status { kStatus_SMC_StopAbort = MAKE_STATUS(kStatusGroup_POWER, 0) }
  SMC configuration status.

Driver version

- #define FSL_SMC_DRIVER_VERSION (MAKE_VERSION(2, 0, 3))
  SMC driver version 2.0.3.

System mode controller APIs

- static void SMC_SetPowerModeProtection (SMC_Type *base, uint8_t allowedModes)
  Configures all power mode protection settings.
- static smc_power_state_t SMC_GetPowerModeState (SMC_Type *base)

Gets the current power mode status.
- void SMC_PreEnterStopModes (void)
  Prepares to enter stop modes.
- void SMC_PostExitStopModes (void)
  Recovers after wake up from stop modes.
- static void SMC_PreEnterWaitModes (void)
  Prepares to enter wait modes.
- static void SMC_PostExitWaitModes (void)
  Recovers after wake up from stop modes.
- status_t SMC_SetPowerModeRun (SMC_Type *base)
  Configures the system to RUN power mode.
- status_t SMC_SetPowerModeWait (SMC_Type *base)
  Configures the system to WAIT power mode.
- status_t SMC_SetPowerModeStop (SMC_Type *base, smc_partial_stop_option_t option)
  Configures the system to Stop power mode.
- status_t SMC_SetPowerModeVlpr (SMC_Type *base)
  Configures the system to VLPR power mode.
- status_t SMC_SetPowerModeVlpw (SMC_Type *base)
  Configures the system to VLPW power mode.
- status_t SMC_SetPowerModeVlps (SMC_Type *base)
  Configures the system to VLPS power mode.
- status_t SMC_SetPowerModeVlls (SMC_Type *base, const smc_power_mode_vlls_config_t *config)
  Configures the system to VLLS power mode.

19.3 Data Structure Documentation

19.3.1 struct smc_power_mode_lls_config_t

Data Fields

- bool enableLpoClock
  Enable LPO clock in LLS mode.

19.3.2 struct smc_power_mode_vlls_config_t

Data Fields

- smc_stop_submode_t subMode
  Very Low-leakage Stop sub-mode.
- bool enablePorDetectInVlls0
  Enable Power on reset detect in VLLS mode.
- bool enableLpoClock
  Enable LPO clock in VLLS mode.

19.4 Macro Definition Documentation

19.4.1 #define FSL_SMC_DRIVER_VERSION (MAKE_VERSION(2, 0, 3))

19.5 Enumeration Type Documentation

19.5.1 enum smc_power_mode_protection_t

Enumerator

kSMC_AllowPowerModeVlls Allow Very-low-leakage Stop Mode.
kSMC_AllowPowerModeVlp Allow Very-Low-power Mode.
kSMC_AllowPowerModeAll Allow all power mode.

19.5.2 enum smc_power_state_t

Enumerator

kSMC_PowerStateRun 0000_0001 - Current power mode is RUN
kSMC_PowerStateStop 0000_0010 - Current power mode is STOP
kSMC_PowerStateVlpr 0000_0100 - Current power mode is VLPR
kSMC_PowerStateVlpw 0000_1000 - Current power mode is VLPW
kSMC_PowerStateVlps 0001_0000 - Current power mode is VLPS
kSMC_PowerStateVlls 0100_0000 - Current power mode is VLLS

19.5.3 enum smc_run_mode_t

Enumerator

kSMC_RunNormal Normal RUN mode.
kSMC_RunVlpr Very-low-power RUN mode.

19.5.4 enum smc_stop_mode_t

Enumerator

kSMC_StopNormal Normal STOP mode.
kSMC_StopVlps Very-low-power STOP mode.
kSMC_StopVlls Very-low-leakage Stop mode.

19.5.5 enum smc_stop_submode_t

Enumerator

kSMC_StopSub0 Stop submode 0, for VLLS0/LLS0.
kSMC_StopSub1 Stop submode 1, for VLLS1/LLS1.
kSMC_StopSub2 Stop submode 2, for VLLS2/LLS2.
kSMC_StopSub3 Stop submode 3, for VLLS3/LLS3.

19.5.6 enum smc_partial_stop_option_t

Enumerator

kSMC_PartialStop STOP - Normal Stop mode.
kSMC_PartialStop1 Partial Stop with both system and bus clocks disabled.
kSMC_PartialStop2 Partial Stop with system clock disabled and bus clock enabled.

19.5.7 enum _smc_status

Enumerator

kStatus_SMC_StopAbort Entering Stop mode is abort.

19.6 Function Documentation

19.6.1 static void SMC_SetPowerModeProtection (SMC_Type ∗ *base*, uint8_t *allowedModes*) [inline], [static]

This function configures the power mode protection settings for supported power modes in the specified chip family. The available power modes are defined in the smc_power_mode_protection_t. This should be done at an early system level initialization stage. See the reference manual for details. This register can only write once after the power reset.

The allowed modes are passed as bit map. For example, to allow LLS and VLLS, use SMC_SetPowerModeProtection(kSMC_AllowPowerModeVlls | kSMC_AllowPowerModeVlps). To allow all modes, use SMC_SetPowerModeProtection(kSMC_AllowPowerModeAll).

Parameters

base	SMC peripheral base address.
allowedModes	Bitmap of the allowed power modes.

19.6.2 static smc_power_state_t SMC_GetPowerModeState (SMC_Type * *base*) [inline], [static]

This function returns the current power mode status. After the application switches the power mode, it should always check the status to check whether it runs into the specified mode or not. The application should check this mode before switching to a different mode. The system requires that only certain modes can switch to other specific modes. See the reference manual for details and the smc_power_state_t for information about the power status.

Parameters

base	SMC peripheral base address.

Returns

Current power mode status.

19.6.3 void SMC_PreEnterStopModes (void)

This function should be called before entering STOP/VLPS/LLS/VLLS modes.

19.6.4 void SMC_PostExitStopModes (void)

This function should be called after wake up from STOP/VLPS/LLS/VLLS modes. It is used with SMC-_PreEnterStopModes.

19.6.5 static void SMC_PreEnterWaitModes (void) [inline], [static]

This function should be called before entering WAIT/VLPW modes.

19.6.6 static void SMC_PostExitWaitModes (void) [inline], [static]

This function should be called after wake up from WAIT/VLPW modes. It is used with SMC_PreEnter-WaitModes.

19.6.7 status_t SMC_SetPowerModeRun (SMC_Type * *base*)

Parameters

base	SMC peripheral base address.

Returns

SMC configuration error code.

19.6.8 status_t SMC_SetPowerModeWait (SMC_Type * *base*)

Parameters

base	SMC peripheral base address.

Returns

SMC configuration error code.

19.6.9 status_t SMC_SetPowerModeStop (SMC_Type * *base*, smc_partial_stop_option_t *option*)

Parameters

base	SMC peripheral base address.
option	Partial Stop mode option.

Returns

SMC configuration error code.

19.6.10 status_t SMC_SetPowerModeVlpr (SMC_Type * *base*)

Parameters

base	SMC peripheral base address.

Returns

SMC configuration error code.

19.6.11 status_t SMC_SetPowerModeVlpw (SMC_Type * *base*)

Parameters

base	SMC peripheral base address.

Returns

SMC configuration error code.

19.6.12 status_t SMC_SetPowerModeVlps (SMC_Type * *base*)

Parameters

base	SMC peripheral base address.

Returns

SMC configuration error code.

19.6.13 status_t SMC_SetPowerModeVlls (SMC_Type * *base*, const smc_power_mode_vlls_config_t * *config*)

Parameters

base	SMC peripheral base address.

config	The VLLS power mode configuration structure.

Returns

SMC configuration error code.

Chapter 20
SPI: Serial Peripheral Interface Driver

20.1 Overview

Modules

- SPI DMA Driver
- SPI Driver
- SPI FreeRTOS driver

20.2 SPI Driver

20.2.1 Overview

SPI driver includes functional APIs and transactional APIs.

Functional APIs are feature/property target low level APIs. Functional APIs can be used for SPI initialization/configuration/operation for optimization/customization purpose. Using the functional API requires the knowledge of the SPI peripheral and how to organize functional APIs to meet the application requirements. All functional API use the peripheral base address as the first parameter. SPI functional operation groups provide the functional API set.

Transactional APIs are transaction target high level APIs. Transactional APIs can be used to enable the peripheral and in the application if the code size and performance of transactional APIs satisfy the requirements. If the code size and performance are a critical requirement, see the transactional API implementation and write a custom code. All transactional APIs use the spi_handle_t as the first parameter. Initialize the handle by calling the SPI_MasterTransferCreateHandle() or SPI_SlaveTransferCreateHandle() API.

Transactional APIs support asynchronous transfer. This means that the functions SPI_MasterTransferNonBlocking() and SPI_SlaveTransferNonBlocking() set up the interrupt for data transfer. When the transfer completes, the upper layer is notified through a callback function with the kStatus_SPI_Idle status.

20.2.2 Typical use case

20.2.2.1 SPI master transfer using an interrupt method

```
#define BUFFER_LEN (64)
spi_master_handle_t spiHandle;
spi_master_config_t masterConfig;
spi_transfer_t xfer;
volatile bool isFinished = false;

const uint8_t sendData[BUFFER_LEN] = [......];
uint8_t receiveBuff[BUFFER_LEN];

void SPI_UserCallback(SPI_Type *base, spi_master_handle_t *handle, status_t status, void *userData)
{
    isFinished = true;
}

void main(void)
{
    //...

    SPI_MasterGetDefaultConfig(&masterConfig);

    SPI_MasterInit(SPI0, &masterConfig);
    SPI_MasterTransferCreateHandle(SPI0, &spiHandle, SPI_UserCallback, NULL);

    // Prepare to send.
    xfer.txData = sendData;
    xfer.rxData = receiveBuff;
    xfer.dataSize = BUFFER_LEN;

    // Send out.
    SPI_MasterTransferNonBlocking(SPI0, &spiHandle, &xfer);
```

```
    // Wait send finished.
    while (!isFinished)
    {
    }

    // ...
}
```

20.2.2.2 SPI Send/receive using a DMA method

```
#define BUFFER_LEN (64)
spi_dma_handle_t spiHandle;
dma_handle_t g_spiTxDmaHandle;
dma_handle_t g_spiRxDmaHandle;
spi_config_t masterConfig;
spi_transfer_t xfer;
volatile bool isFinished;
uint8_t sendData[BUFFER_LEN] = ...;
uint8_t receiveBuff[BUFFER_LEN];

void SPI_UserCallback(SPI_Type *base, spi_dma_handle_t *handle, status_t status, void *userData)
{
    isFinished = true;
}

void main(void)
{
    //...

    SPI_MasterGetDefaultConfig(&masterConfig);
    SPI_MasterInit(SPI0, &masterConfig);

    // Sets up the DMA.
    DMAMUX_Init(DMAMUX0);
    DMAMUX_SetSource(DMAMUX0, SPI_TX_DMA_CHANNEL, SPI_TX_DMA_REQUEST);
    DMAMUX_EnableChannel(DMAMUX0, SPI_TX_DMA_CHANNEL);
    DMAMUX_SetSource(DMAMUX0, SPI_RX_DMA_CHANNEL, SPI_RX_DMA_REQUEST);
    DMAMUX_EnableChannel(DMAMUX0, SPI_RX_DMA_CHANNEL);

    DMA_Init(DMA0);

    /* Creates the DMA handle. */
    DMA_CreateHandle(&g_spiTxDmaHandle, DMA0, SPI_TX_DMA_CHANNEL);
    DMA_CreateHandle(&g_spiRxDmaHandle, DMA0, SPI_RX_DMA_CHANNEL);

    SPI_MasterTransferCreateHandleDMA(SPI0, spiHandle, &g_spiTxDmaHandle,
      &g_spiRxDmaHandle, SPI_UserCallback, NULL);

    // Prepares to send.
    xfer.txData = sendData;
    xfer.rxData = receiveBuff;
    xfer.dataSize = BUFFER_LEN;

    // Sends out.
    SPI_MasterTransferDMA(SPI0, &spiHandle, &xfer);

    // Waits for send to complete.
    while (!isFinished)
    {
    }

    // ...
}
```

Data Structures

- struct spi_master_config_t
  SPI master user configure structure. More...
- struct spi_slave_config_t
  SPI slave user configure structure. More...
- struct spi_transfer_t
  SPI transfer structure. More...
- struct spi_master_handle_t
  SPI transfer handle structure. More...

Macros

- #define SPI_DUMMYDATA (0xFFU)
  SPI dummy transfer data, the data is sent while txBuff is NULL.

Typedefs

- typedef spi_master_handle_t spi_slave_handle_t
  Slave handle is the same with master handle.
- typedef void(∗ spi_master_callback_t)(SPI_Type ∗base, spi_master_handle_t ∗handle, status_t status, void ∗userData)
  SPI master callback for finished transmit.
- typedef void(∗ spi_slave_callback_t)(SPI_Type ∗base, spi_slave_handle_t ∗handle, status_t status, void ∗userData)
  SPI master callback for finished transmit.

Enumerations

- enum _spi_status {
  kStatus_SPI_Busy = MAKE_STATUS(kStatusGroup_SPI, 0),
  kStatus_SPI_Idle = MAKE_STATUS(kStatusGroup_SPI, 1),
  kStatus_SPI_Error = MAKE_STATUS(kStatusGroup_SPI, 2) }
  Return status for the SPI driver.
- enum spi_clock_polarity_t {
  kSPI_ClockPolarityActiveHigh = 0x0U,
  kSPI_ClockPolarityActiveLow }
  SPI clock polarity configuration.
- enum spi_clock_phase_t {
  kSPI_ClockPhaseFirstEdge = 0x0U,
  kSPI_ClockPhaseSecondEdge }
  SPI clock phase configuration.
- enum spi_shift_direction_t {
  kSPI_MsbFirst = 0x0U,
  kSPI_LsbFirst }

SPI data shifter direction options.
- enum spi_ss_output_mode_t {
kSPI_SlaveSelectAsGpio = 0x0U,
kSPI_SlaveSelectFaultInput = 0x2U,
kSPI_SlaveSelectAutomaticOutput = 0x3U }
SPI slave select output mode options.
- enum spi_pin_mode_t {
kSPI_PinModeNormal = 0x0U,
kSPI_PinModeInput = 0x1U,
kSPI_PinModeOutput = 0x3U }
SPI pin mode options.
- enum spi_data_bitcount_mode_t {
kSPI_8BitMode = 0x0U,
kSPI_16BitMode }
SPI data length mode options.
- enum _spi_interrupt_enable {
kSPI_RxFullAndModfInterruptEnable = 0x1U,
kSPI_TxEmptyInterruptEnable = 0x2U,
kSPI_MatchInterruptEnable = 0x4U }
SPI interrupt sources.
- enum _spi_flags {
kSPI_RxBufferFullFlag = SPI_S_SPRF_MASK,
kSPI_MatchFlag = SPI_S_SPMF_MASK,
kSPI_TxBufferEmptyFlag = SPI_S_SPTEF_MASK,
kSPI_ModeFaultFlag = SPI_S_MODF_MASK }
SPI status flags.

Driver version

- #define FSL_SPI_DRIVER_VERSION (MAKE_VERSION(2, 0, 3))
SPI driver version 2.0.3.

Initialization and deinitialization

- void SPI_MasterGetDefaultConfig (spi_master_config_t ∗config)
Sets the SPI master configuration structure to default values.
- void SPI_MasterInit (SPI_Type ∗base, const spi_master_config_t ∗config, uint32_t srcClock_Hz)
Initializes the SPI with master configuration.
- void SPI_SlaveGetDefaultConfig (spi_slave_config_t ∗config)
Sets the SPI slave configuration structure to default values.
- void SPI_SlaveInit (SPI_Type ∗base, const spi_slave_config_t ∗config)
Initializes the SPI with slave configuration.
- void SPI_Deinit (SPI_Type ∗base)
De-initializes the SPI.
- static void SPI_Enable (SPI_Type ∗base, bool enable)
Enables or disables the SPI.

Status

- uint32_t SPI_GetStatusFlags (SPI_Type *base)
  Gets the status flag.

Interrupts

- void SPI_EnableInterrupts (SPI_Type *base, uint32_t mask)
  Enables the interrupt for the SPI.
- void SPI_DisableInterrupts (SPI_Type *base, uint32_t mask)
  Disables the interrupt for the SPI.

DMA Control

- static uint32_t SPI_GetDataRegisterAddress (SPI_Type *base)
  Gets the SPI tx/rx data register address.

Bus Operations

- void SPI_MasterSetBaudRate (SPI_Type *base, uint32_t baudRate_Bps, uint32_t srcClock_Hz)
  Sets the baud rate for SPI transfer.
- static void SPI_SetMatchData (SPI_Type *base, uint32_t matchData)
  Sets the match data for SPI.
- void SPI_WriteBlocking (SPI_Type *base, uint8_t *buffer, size_t size)
  Sends a buffer of data bytes using a blocking method.
- void SPI_WriteData (SPI_Type *base, uint16_t data)
  Writes a data into the SPI data register.
- uint16_t SPI_ReadData (SPI_Type *base)
  Gets a data from the SPI data register.

Transactional

- void SPI_MasterTransferCreateHandle (SPI_Type *base, spi_master_handle_t *handle, spi_master_callback_t callback, void *userData)
  Initializes the SPI master handle.
- status_t SPI_MasterTransferBlocking (SPI_Type *base, spi_transfer_t *xfer)
  Transfers a block of data using a polling method.
- status_t SPI_MasterTransferNonBlocking (SPI_Type *base, spi_master_handle_t *handle, spi_transfer_t *xfer)
  Performs a non-blocking SPI interrupt transfer.
- status_t SPI_MasterTransferGetCount (SPI_Type *base, spi_master_handle_t *handle, size_t *count)
  Gets the bytes of the SPI interrupt transferred.
- void SPI_MasterTransferAbort (SPI_Type *base, spi_master_handle_t *handle)
  Aborts an SPI transfer using interrupt.

- void SPI_MasterTransferHandleIRQ (SPI_Type ∗base, spi_master_handle_t ∗handle)
  Interrupts the handler for the SPI.
- void SPI_SlaveTransferCreateHandle (SPI_Type ∗base, spi_slave_handle_t ∗handle, spi_slave_callback_t callback, void ∗userData)
  Initializes the SPI slave handle.
- static status_t SPI_SlaveTransferNonBlocking (SPI_Type ∗base, spi_slave_handle_t ∗handle, spi_transfer_t ∗xfer)
  Performs a non-blocking SPI slave interrupt transfer.
- static status_t SPI_SlaveTransferGetCount (SPI_Type ∗base, spi_slave_handle_t ∗handle, size_t ∗count)
  Gets the bytes of the SPI interrupt transferred.
- static void SPI_SlaveTransferAbort (SPI_Type ∗base, spi_slave_handle_t ∗handle)
  Aborts an SPI slave transfer using interrupt.
- void SPI_SlaveTransferHandleIRQ (SPI_Type ∗base, spi_slave_handle_t ∗handle)
  Interrupts a handler for the SPI slave.

20.2.3 Data Structure Documentation

20.2.3.1 struct spi_master_config_t

Data Fields

- bool enableMaster
  Enable SPI at initialization time.
- bool enableStopInWaitMode
  SPI stop in wait mode.
- spi_clock_polarity_t polarity
  Clock polarity.
- spi_clock_phase_t phase
  Clock phase.
- spi_shift_direction_t direction
  MSB or LSB.
- spi_ss_output_mode_t outputMode
  SS pin setting.
- spi_pin_mode_t pinMode
  SPI pin mode select.
- uint32_t baudRate_Bps
  Baud Rate for SPI in Hz.

20.2.3.2 struct spi_slave_config_t

Data Fields

- bool enableSlave
  Enable SPI at initialization time.
- bool enableStopInWaitMode
  SPI stop in wait mode.
- spi_clock_polarity_t polarity

Clock polarity.
- spi_clock_phase_t phase
  Clock phase.
- spi_shift_direction_t direction
  MSB or LSB.

20.2.3.3 struct spi_transfer_t

Data Fields

- uint8_t ∗ txData
  Send buffer.
- uint8_t ∗ rxData
  Receive buffer.
- size_t dataSize
  Transfer bytes.
- uint32_t flags
  SPI control flag, useless to SPI.

20.2.3.3.0.34 Field Documentation

20.2.3.3.0.34.1 uint32_t spi_transfer_t::flags

20.2.3.4 struct _spi_master_handle

Data Fields

- uint8_t ∗volatile txData
  Transfer buffer.
- uint8_t ∗volatile rxData
  Receive buffer.
- volatile size_t txRemainingBytes
  Send data remaining in bytes.
- volatile size_t rxRemainingBytes
  Receive data remaining in bytes.
- volatile uint32_t state
  SPI internal state.
- size_t transferSize
  Bytes to be transferred.
- uint8_t bytePerFrame
  SPI mode, 2bytes or 1byte in a frame.
- uint8_t watermark
  Watermark value for SPI transfer.
- spi_master_callback_t callback
  SPI callback.
- void ∗ userData
  Callback parameter.

20.2.4 Macro Definition Documentation

20.2.4.1 #define FSL_SPI_DRIVER_VERSION (MAKE_VERSION(2, 0, 3))

20.2.4.2 #define SPI_DUMMYDATA (0xFFU)

20.2.5 Enumeration Type Documentation

20.2.5.1 enum _spi_status

Enumerator

kStatus_SPI_Busy SPI bus is busy.
kStatus_SPI_Idle SPI is idle.
kStatus_SPI_Error SPI error.

20.2.5.2 enum spi_clock_polarity_t

Enumerator

kSPI_ClockPolarityActiveHigh Active-high SPI clock (idles low).
kSPI_ClockPolarityActiveLow Active-low SPI clock (idles high).

20.2.5.3 enum spi_clock_phase_t

Enumerator

kSPI_ClockPhaseFirstEdge First edge on SPSCK occurs at the middle of the first cycle of a data transfer.
kSPI_ClockPhaseSecondEdge First edge on SPSCK occurs at the start of the first cycle of a data transfer.

20.2.5.4 enum spi_shift_direction_t

Enumerator

kSPI_MsbFirst Data transfers start with most significant bit.
kSPI_LsbFirst Data transfers start with least significant bit.

20.2.5.5 enum spi_ss_output_mode_t

Enumerator

kSPI_SlaveSelectAsGpio Slave select pin configured as GPIO.
kSPI_SlaveSelectFaultInput Slave select pin configured for fault detection.
kSPI_SlaveSelectAutomaticOutput Slave select pin configured for automatic SPI output.

20.2.5.6 enum spi_pin_mode_t

Enumerator

kSPI_PinModeNormal Pins operate in normal, single-direction mode.
kSPI_PinModeInput Bidirectional mode. Master: MOSI pin is input; Slave: MISO pin is input.
kSPI_PinModeOutput Bidirectional mode. Master: MOSI pin is output; Slave: MISO pin is output.

20.2.5.7 enum spi_data_bitcount_mode_t

Enumerator

kSPI_8BitMode 8-bit data transmission mode
kSPI_16BitMode 16-bit data transmission mode

20.2.5.8 enum _spi_interrupt_enable

Enumerator

kSPI_RxFullAndModfInterruptEnable Receive buffer full (SPRF) and mode fault (MODF) interrupt.
kSPI_TxEmptyInterruptEnable Transmit buffer empty interrupt.
kSPI_MatchInterruptEnable Match interrupt.

20.2.5.9 enum _spi_flags

Enumerator

kSPI_RxBufferFullFlag Read buffer full flag.
kSPI_MatchFlag Match flag.
kSPI_TxBufferEmptyFlag Transmit buffer empty flag.
kSPI_ModeFaultFlag Mode fault flag.

20.2.6 Function Documentation

20.2.6.1 void SPI_MasterGetDefaultConfig (spi_master_config_t * *config*)

The purpose of this API is to get the configuration structure initialized for use in SPI_MasterInit(). User may use the initialized structure unchanged in SPI_MasterInit(), or modify some fields of the structure before calling SPI_MasterInit(). After calling this API, the master is ready to transfer. Example:

```
spi_master_config_t config;
SPI_MasterGetDefaultConfig(&config);
```

Parameters

config	pointer to master config structure

20.2.6.2 void SPI_MasterInit (SPI_Type * *base,* const spi_master_config_t * *config,* uint32_t *srcClock_Hz*)

The configuration structure can be filled by user from scratch, or be set with default values by SPI_Master-GetDefaultConfig(). After calling this API, the slave is ready to transfer. Example

```
spi_master_config_t config = {
.baudRate_Bps = 400000,
...
};
SPI_MasterInit(SPI0, &config);
```

Parameters

base	SPI base pointer
config	pointer to master configuration structure
srcClock_Hz	Source clock frequency.

20.2.6.3 void SPI_SlaveGetDefaultConfig (spi_slave_config_t * *config*)

The purpose of this API is to get the configuration structure initialized for use in SPI_SlaveInit(). Modify some fields of the structure before calling SPI_SlaveInit(). Example:

```
spi_slave_config_t config;
SPI_SlaveGetDefaultConfig(&config);
```

Parameters

config	pointer to slave configuration structure

20.2.6.4 void SPI_SlaveInit (SPI_Type * *base*, const spi_slave_config_t * *config*)

The configuration structure can be filled by user from scratch or be set with default values by SPI_Slave-GetDefaultConfig(). After calling this API, the slave is ready to transfer. Example

```
spi_slave_config_t config = {
.polarity = kSPIClockPolarity_ActiveHigh;
.phase = kSPIClockPhase_FirstEdge;
.direction = kSPIMsbFirst;
...
};
SPI_MasterInit(SPI0, &config);
```

Parameters

base	SPI base pointer
config	pointer to master configuration structure

20.2.6.5 void SPI_Deinit (SPI_Type * *base*)

Calling this API resets the SPI module, gates the SPI clock. The SPI module can't work unless calling the SPI_MasterInit/SPI_SlaveInit to initialize module.

Parameters

base	SPI base pointer

20.2.6.6 static void SPI_Enable (SPI_Type * *base*, bool *enable*) [inline], [static]

Parameters

base	SPI base pointer
enable	pass true to enable module, false to disable module

20.2.6.7 uint32_t SPI_GetStatusFlags (SPI_Type * *base*)

Parameters

base	SPI base pointer

Returns

SPI Status, use status flag to AND _spi_flags could get the related status.

20.2.6.8 void SPI_EnableInterrupts (SPI_Type * *base*, uint32_t *mask*)

Parameters

base	SPI base pointer
mask	SPI interrupt source. The parameter can be any combination of the following values: • kSPI_RxFullAndModfInterruptEnable • kSPI_TxEmptyInterruptEnable • kSPI_MatchInterruptEnable • kSPI_RxFifoNearFullInterruptEnable • kSPI_TxFifoNearEmptyInterruptEnable

20.2.6.9 void SPI_DisableInterrupts (SPI_Type * *base*, uint32_t *mask*)

Parameters

base	SPI base pointer
mask	SPI interrupt source. The parameter can be any combination of the following values: • kSPI_RxFullAndModfInterruptEnable • kSPI_TxEmptyInterruptEnable • kSPI_MatchInterruptEnable • kSPI_RxFifoNearFullInterruptEnable • kSPI_TxFifoNearEmptyInterruptEnable

20.2.6.10 static uint32_t SPI_GetDataRegisterAddress (SPI_Type * *base*) [inline], [static]

This API is used to provide a transfer address for the SPI DMA transfer configuration.

Parameters

base	SPI base pointer

Returns

data register address

20.2.6.11 void SPI_MasterSetBaudRate (SPI_Type * *base*, uint32_t *baudRate_Bps*, uint32_t *srcClock_Hz*)

This is only used in master.

Parameters

base	SPI base pointer
baudRate_Bps	baud rate needed in Hz.
srcClock_Hz	SPI source clock frequency in Hz.

20.2.6.12 static void SPI_SetMatchData (SPI_Type * *base*, uint32_t *matchData*) [inline], [static]

The match data is a hardware comparison value. When the value received in the SPI receive data buffer equals the hardware comparison value, the SPI Match Flag in the S register (S[SPMF]) sets. This can also generate an interrupt if the enable bit sets.

Parameters

base	SPI base pointer
matchData	Match data.

20.2.6.13 void SPI_WriteBlocking (SPI_Type * *base*, uint8_t * *buffer*, size_t *size*)

Note

This function blocks via polling until all bytes have been sent.

Parameters

base	SPI base pointer
buffer	The data bytes to send
size	The number of data bytes to send

20.2.6.14 void SPI_WriteData (SPI_Type ∗ *base*, uint16_t *data*)

Parameters

base	SPI base pointer
data	needs to be write.

20.2.6.15 uint16_t SPI_ReadData (SPI_Type ∗ *base*)

Parameters

base	SPI base pointer

Returns

Data in the register.

20.2.6.16 void SPI_MasterTransferCreateHandle (SPI_Type ∗ *base*, spi_master_handle_t ∗ *handle*, spi_master_callback_t *callback*, void ∗ *userData*)

This function initializes the SPI master handle which can be used for other SPI master transactional APIs. Usually, for a specified SPI instance, call this API once to get the initialized handle.

Parameters

base	SPI peripheral base address.
handle	SPI handle pointer.
callback	Callback function.

userData	User data.

20.2.6.17 status_t SPI_MasterTransferBlocking (SPI_Type ∗ *base*, spi_transfer_t ∗ *xfer*)

Parameters

base	SPI base pointer
xfer	pointer to spi_xfer_config_t structure

Return values

kStatus_Success	Successfully start a transfer.
kStatus_InvalidArgument	Input argument is invalid.

20.2.6.18 status_t SPI_MasterTransferNonBlocking (SPI_Type ∗ *base*, spi_master_handle_t ∗ *handle*, spi_transfer_t ∗ *xfer*)

Note

The API immediately returns after transfer initialization is finished. Call SPI_GetStatusIRQ() to get the transfer status.
If SPI transfer data frame size is 16 bits, the transfer size cannot be an odd number.

Parameters

base	SPI peripheral base address.
handle	pointer to spi_master_handle_t structure which stores the transfer state
xfer	pointer to spi_xfer_config_t structure

Return values

kStatus_Success	Successfully start a transfer.
kStatus_InvalidArgument	Input argument is invalid.
kStatus_SPI_Busy	SPI is not idle, is running another transfer.

20.2.6.19 status_t SPI_MasterTransferGetCount (SPI_Type ∗ *base*, spi_master_handle_t ∗ *handle*, size_t ∗ *count*)

Parameters

base	SPI peripheral base address.
handle	Pointer to SPI transfer handle, this should be a static variable.
count	Transferred bytes of SPI master.

Return values

kStatus_SPI_Success	Succeed get the transfer count.
kStatus_NoTransferIn-Progress	There is not a non-blocking transaction currently in progress.

20.2.6.20 void SPI_MasterTransferAbort (SPI_Type ∗ *base*, spi_master_handle_t ∗ *handle*)

Parameters

base	SPI peripheral base address.
handle	Pointer to SPI transfer handle, this should be a static variable.

20.2.6.21 void SPI_MasterTransferHandleIRQ (SPI_Type ∗ *base*, spi_master_handle_t ∗ *handle*)

Parameters

base	SPI peripheral base address.
handle	pointer to spi_master_handle_t structure which stores the transfer state.

20.2.6.22 void SPI_SlaveTransferCreateHandle (SPI_Type ∗ *base*, spi_slave_handle_t ∗ *handle*, spi_slave_callback_t *callback*, void ∗ *userData*)

This function initializes the SPI slave handle which can be used for other SPI slave transactional APIs. Usually, for a specified SPI instance, call this API once to get the initialized handle.

Parameters

base	SPI peripheral base address.
handle	SPI handle pointer.
callback	Callback function.
userData	User data.

20.2.6.23 static status_t SPI_SlaveTransferNonBlocking (SPI_Type * *base*, spi_slave_handle_t * *handle*, spi_transfer_t * *xfer*) [inline], [static]

Note

The API returns immediately after the transfer initialization is finished. Call SPI_GetStatusIRQ() to get the transfer status.
If SPI transfer data frame size is 16 bits, the transfer size cannot be an odd number.

Parameters

base	SPI peripheral base address.
handle	pointer to spi_master_handle_t structure which stores the transfer state
xfer	pointer to spi_xfer_config_t structure

Return values

kStatus_Success	Successfully start a transfer.
kStatus_InvalidArgument	Input argument is invalid.
kStatus_SPI_Busy	SPI is not idle, is running another transfer.

20.2.6.24 static status_t SPI_SlaveTransferGetCount (SPI_Type * *base*, spi_slave_handle_t * *handle*, size_t * *count*) [inline], [static]

Parameters

base	SPI peripheral base address.
handle	Pointer to SPI transfer handle, this should be a static variable.

count	Transferred bytes of SPI slave.

Return values

kStatus_SPI_Success	Succeed get the transfer count.
kStatus_NoTransferInProgress	There is not a non-blocking transaction currently in progress.

20.2.6.25 static void SPI_SlaveTransferAbort (SPI_Type * *base*, spi_slave_handle_t * *handle*) [inline], [static]

Parameters

base	SPI peripheral base address.
handle	Pointer to SPI transfer handle, this should be a static variable.

20.2.6.26 void SPI_SlaveTransferHandleIRQ (SPI_Type * *base*, spi_slave_handle_t * *handle*)

Parameters

base	SPI peripheral base address.
handle	pointer to spi_slave_handle_t structure which stores the transfer state

20.3 SPI DMA Driver

20.3.1 Overview

This section describes the programming interface of the SPI DMA driver.

Data Structures

- struct spi_dma_handle_t
  SPI DMA transfer handle, users should not touch the content of the handle. More...

Typedefs

- typedef void(∗ spi_dma_callback_t)(SPI_Type ∗base, spi_dma_handle_t ∗handle, status_t status, void ∗userData)
  SPI DMA callback called at the end of transfer.

DMA Transactional

- void SPI_MasterTransferCreateHandleDMA (SPI_Type ∗base, spi_dma_handle_t ∗handle, spi_dma_callback_t callback, void ∗userData, dma_handle_t ∗txHandle, dma_handle_t ∗rxHandle)
  Initialize the SPI master DMA handle.
- status_t SPI_MasterTransferDMA (SPI_Type ∗base, spi_dma_handle_t ∗handle, spi_transfer_t ∗xfer)
  Perform a non-blocking SPI transfer using DMA.
- void SPI_MasterTransferAbortDMA (SPI_Type ∗base, spi_dma_handle_t ∗handle)
  Abort a SPI transfer using DMA.
- status_t SPI_MasterTransferGetCountDMA (SPI_Type ∗base, spi_dma_handle_t ∗handle, size_t ∗count)
  Get the transferred bytes for SPI slave DMA.
- static void SPI_SlaveTransferCreateHandleDMA (SPI_Type ∗base, spi_dma_handle_t ∗handle, spi_dma_callback_t callback, void ∗userData, dma_handle_t ∗txHandle, dma_handle_t ∗rxHandle)
  Initialize the SPI slave DMA handle.
- static status_t SPI_SlaveTransferDMA (SPI_Type ∗base, spi_dma_handle_t ∗handle, spi_transfer_t ∗xfer)
  Perform a non-blocking SPI transfer using DMA.
- static void SPI_SlaveTransferAbortDMA (SPI_Type ∗base, spi_dma_handle_t ∗handle)
  Abort a SPI transfer using DMA.
- static status_t SPI_SlaveTransferGetCountDMA (SPI_Type ∗base, spi_dma_handle_t ∗handle, size_t ∗count)
  Get the transferred bytes for SPI slave DMA.

20.3.2 Data Structure Documentation

20.3.2.1 struct _spi_dma_handle

Data Fields

- bool txInProgress
  Send transfer finished.
- bool rxInProgress
  Receive transfer finished.
- dma_handle_t * txHandle
  DMA handler for SPI send.
- dma_handle_t * rxHandle
  DMA handler for SPI receive.
- uint8_t bytesPerFrame
  Bytes in a frame for SPI tranfer.
- spi_dma_callback_t callback
  Callback for SPI DMA transfer.
- void * userData
  User Data for SPI DMA callback.
- uint32_t state
  Internal state of SPI DMA transfer.
- size_t transferSize
  Bytes need to be transfer.

20.3.3 Typedef Documentation

20.3.3.1 typedef void(* spi_dma_callback_t)(SPI_Type *base, spi_dma_handle_t *handle, status_t status, void *userData)

20.3.4 Function Documentation

20.3.4.1 void SPI_MasterTransferCreateHandleDMA (SPI_Type * *base,* spi_dma_handle_t * *handle,* spi_dma_callback_t *callback,* void * *userData,* dma_handle_t * *txHandle,* dma_handle_t * *rxHandle*)

This function initializes the SPI master DMA handle which can be used for other SPI master transactional APIs. Usually, for a specified SPI instance, user need only call this API once to get the initialized handle.

Parameters

base	SPI peripheral base address.
handle	SPI handle pointer.
callback	User callback function called at the end of a transfer.
userData	User data for callback.
txHandle	DMA handle pointer for SPI Tx, the handle shall be static allocated by users.
rxHandle	DMA handle pointer for SPI Rx, the handle shall be static allocated by users.

20.3.4.2 status_t SPI_MasterTransferDMA (SPI_Type ∗ *base*, spi_dma_handle_t ∗ *handle*, spi_transfer_t ∗ *xfer*)

Note

This interface returned immediately after transfer initiates, users should call SPI_GetTransferStatus to poll the transfer status to check whether SPI transfer finished.

Parameters

base	SPI peripheral base address.
handle	SPI DMA handle pointer.
xfer	Pointer to dma transfer structure.

Return values

kStatus_Success	Successfully start a transfer.
kStatus_InvalidArgument	Input argument is invalid.
kStatus_SPI_Busy	SPI is not idle, is running another transfer.

20.3.4.3 void SPI_MasterTransferAbortDMA (SPI_Type ∗ *base*, spi_dma_handle_t ∗ *handle*)

Parameters

base	SPI peripheral base address.

handle	SPI DMA handle pointer.

20.3.4.4 status_t SPI_MasterTransferGetCountDMA (SPI_Type * *base,* spi_dma_handle_t * *handle,* size_t * *count*)

Parameters

base	SPI peripheral base address.
handle	SPI DMA handle pointer.
count	Transferred bytes.

Return values

kStatus_SPI_Success	Succeed get the transfer count.
kStatus_NoTransferInProgress	There is not a non-blocking transaction currently in progress.

20.3.4.5 static void SPI_SlaveTransferCreateHandleDMA (SPI_Type * *base,* spi_dma_handle_t * *handle,* spi_dma_callback_t *callback,* void * *userData,* dma_handle_t * *txHandle,* dma_handle_t * *rxHandle*) [inline], [static]

This function initializes the SPI slave DMA handle which can be used for other SPI master transactional APIs. Usually, for a specified SPI instance, user need only call this API once to get the initialized handle.

Parameters

base	SPI peripheral base address.
handle	SPI handle pointer.
callback	User callback function called at the end of a transfer.
userData	User data for callback.
txHandle	DMA handle pointer for SPI Tx, the handle shall be static allocated by users.
rxHandle	DMA handle pointer for SPI Rx, the handle shall be static allocated by users.

20.3.4.6 static status_t SPI_SlaveTransferDMA (SPI_Type * *base,* spi_dma_handle_t * *handle,* spi_transfer_t * *xfer*) [inline], [static]

Note

This interface returned immediately after transfer initiates, users should call SPI_GetTransferStatus to poll the transfer status to check whether SPI transfer finished.

Parameters

base	SPI peripheral base address.
handle	SPI DMA handle pointer.
xfer	Pointer to dma transfer structure.

Return values

kStatus_Success	Successfully start a transfer.
kStatus_InvalidArgument	Input argument is invalid.
kStatus_SPI_Busy	SPI is not idle, is running another transfer.

20.3.4.7 static void SPI_SlaveTransferAbortDMA (SPI_Type ∗ *base*, spi_dma_handle_t ∗ *handle*) [inline], [static]

Parameters

base	SPI peripheral base address.
handle	SPI DMA handle pointer.

20.3.4.8 static status_t SPI_SlaveTransferGetCountDMA (SPI_Type ∗ *base*, spi_dma_handle_t ∗ *handle*, size_t ∗ *count*) [inline], [static]

Parameters

base	SPI peripheral base address.
handle	SPI DMA handle pointer.
count	Transferred bytes.

Return values

kStatus_SPI_Success	Succeed get the transfer count.
kStatus_NoTransferIn-Progress	There is not a non-blocking transaction currently in progress.

20.4 SPI FreeRTOS driver

20.4.1 Overview

This section describes the programming interface of the SPI FreeRTOS driver.

SPI RTOS Operation

- status_t SPI_RTOS_Init (spi_rtos_handle_t *handle, SPI_Type *base, const spi_master_config_t *masterConfig, uint32_t srcClock_Hz)
  Initializes SPI.
- status_t SPI_RTOS_Deinit (spi_rtos_handle_t *handle)
  Deinitializes the SPI.
- status_t SPI_RTOS_Transfer (spi_rtos_handle_t *handle, spi_transfer_t *transfer)
  Performs SPI transfer.

20.4.2 Function Documentation

20.4.2.1 status_t SPI_RTOS_Init (spi_rtos_handle_t * *handle*, SPI_Type * *base*, const spi_master_config_t * *masterConfig*, uint32_t *srcClock_Hz*)

This function initializes the SPI module and related RTOS context.

Parameters

handle	The RTOS SPI handle, the pointer to an allocated space for RTOS context.
base	The pointer base address of the SPI instance to initialize.
masterConfig	Configuration structure to set-up SPI in master mode.
srcClock_Hz	Frequency of input clock of the SPI module.

Returns

status of the operation.

20.4.2.2 status_t SPI_RTOS_Deinit (spi_rtos_handle_t * *handle*)

This function deinitializes the SPI module and related RTOS context.

Parameters

handle	The RTOS SPI handle.

20.4.2.3 status_t SPI_RTOS_Transfer (spi_rtos_handle_t ∗ *handle*, spi_transfer_t ∗ *transfer*)

This function performs an SPI transfer according to data given in the transfer structure.

Parameters

handle	The RTOS SPI handle.
transfer	Structure specifying the transfer parameters.

Returns

status of the operation.

Chapter 21
TPM: Timer PWM Module

21.1 Overview

The MCUXpresso SDK provides a driver for the Timer PWM Module (TPM) of MCUXpresso SDK devices.

The TPM driver supports the generation of PWM signals, input capture, and output compare modes. On some SoCs, the driver supports the generation of combined PWM signals, dual-edge capture, and quadrature decoder modes. The driver also supports configuring each of the TPM fault inputs. The fault input is available only on some SoCs.

The function TPM_Init() initializes the TPM with a specified configurations. The function TPM_GetDefaultConfig() gets the default configurations. On some SoCs, the initialization function issues a software reset to reset the TPM internal logic. The initialization function configures the TPM's behavior when it receives a trigger input and its operation in doze and debug modes.

The function TPM_Deinit() disables the TPM counter and turns off the module clock.

The function TPM_SetupPwm() sets up TPM channels for the PWM output. The function can set up the PWM signal properties for multiple channels. Each channel has its own tpm_chnl_pwm_signal_param_t structure that is used to specify the output signals duty cycle and level-mode. However, the same PWM period and PWM mode is applied to all channels requesting a PWM output. The signal duty cycle is provided as a percentage of the PWM period. Its value should be between 0 and 100 where 0=inactive signal (0% duty cycle) and 100=always active signal (100% duty cycle). When generating a combined PWM signal, the channel number passed refers to a channel pair number, for example 0 refers to channel 0 and 1, 1 refers to channels 2 and 3.

The function TPM_UpdatePwmDutycycle() updates the PWM signal duty cycle of a particular TPM channel.

The function TPM_UpdateChnlEdgeLevelSelect() updates the level select bits of a particular TPM channel. This can be used to disable the PWM output when making changes to the PWM signal.

The function TPM_SetupInputCapture() sets up a TPM channel for input capture. The user can specify the capture edge.

The function TPM_SetupDualEdgeCapture() can be used to measure the pulse width of a signal. This is available only for certain SoCs. A channel pair is used during the capture with the input signal coming through a channel that can be configured. The user can specify the capture edge for each channel and any filter value to be used when processing the input signal.

The function TPM_SetupOutputCompare() sets up a TPM channel for output comparison. The user can specify the channel output on a successful comparison and a comparison value.

The function TPM_SetupQuadDecode() sets up TPM channels 0 and 1 for quad decode, which is available only for certain SoCs. The user can specify the quad decode mode, polarity, and filter properties for each input signal.

The function TPM_SetupFault() sets up the properties for each fault, which is available only for certain SoCs. The user can specify the fault polarity and whether to use a filter on a fault input. The overall fault filter value and fault control mode are set up during initialization.

Provides functions to get and clear the TPM status.

Provides functions to enable/disable TPM interrupts and get current enabled interrupts.

21.2 Typical use case

21.2.1 PWM output

Output the PWM signal on 2 TPM channels with different duty cycles. Periodically update the PWM signal duty cycle.

```
int main(void)
{
    bool brightnessUp = true; /* Indicates whether the LED is brighter or dimmer. */
    tpm_config_t tpmInfo;
    uint8_t updatedDutycycle = 0U;
    tpm_chnl_pwm_signal_param_t tpmParam[2];

    /* Configures the TPM parameters with frequency 24 kHZ. */
    tpmParam[0].chnlNumber = (tpm_chnl_t)BOARD_FIRST_TPM_CHANNEL;
    tpmParam[0].level = kTPM_LowTrue;
    tpmParam[0].dutyCyclePercent = 0U;

    tpmParam[1].chnlNumber = (tpm_chnl_t)BOARD_SECOND_TPM_CHANNEL;
    tpmParam[1].level = kTPM_LowTrue;
    tpmParam[1].dutyCyclePercent = 0U;

    /* Board pin, clock, and debug console initialization. */
    BOARD_InitHardware();

    TPM_GetDefaultConfig(&tpmInfo);
    /* Initializes the TPM module. */
    TPM_Init(BOARD_TPM_BASEADDR, &tpmInfo);

    TPM_SetupPwm(BOARD_TPM_BASEADDR, tpmParam, 2U,
      kTPM_EdgeAlignedPwm, 24000U, TPM_SOURCE_CLOCK);
    TPM_StartTimer(BOARD_TPM_BASEADDR, kTPM_SystemClock);
    while (1)
    {
        /* Delays to see the change of LED brightness. */
        delay();

        if (brightnessUp)
        {
            /* Increases a duty cycle until it reaches a limited value. */
            if (++updatedDutycycle == 100U)
            {
                brightnessUp = false;
            }
        }
        else
        {
            /* Decreases a duty cycle until it reaches a limited value. */
            if (--updatedDutycycle == 0U)
            {
                brightnessUp = true;
```

```
            }
        }
        /* Starts PWM mode with an updated duty cycle. */
        TPM_UpdatePwmDutycycle(BOARD_TPM_BASEADDR, (
      tpm_chnl_t)BOARD_FIRST_TPM_CHANNEL, kTPM_EdgeAlignedPwm,
                               updatedDutycycle);
        TPM_UpdatePwmDutycycle(BOARD_TPM_BASEADDR, (
      tpm_chnl_t)BOARD_SECOND_TPM_CHANNEL, kTPM_EdgeAlignedPwm,
                               updatedDutycycle);
    }
}
```

Data Structures

- struct tpm_chnl_pwm_signal_param_t
  Options to configure a TPM channel's PWM signal. More...
- struct tpm_config_t
  TPM config structure. More...

Enumerations

- enum tpm_chnl_t {
  kTPM_Chnl_0 = 0U,
  kTPM_Chnl_1,
  kTPM_Chnl_2,
  kTPM_Chnl_3,
  kTPM_Chnl_4,
  kTPM_Chnl_5,
  kTPM_Chnl_6,
  kTPM_Chnl_7 }
  List of TPM channels.
- enum tpm_pwm_mode_t {
  kTPM_EdgeAlignedPwm = 0U,
  kTPM_CenterAlignedPwm }
  TPM PWM operation modes.
- enum tpm_pwm_level_select_t {
  kTPM_NoPwmSignal = 0U,
  kTPM_LowTrue,
  kTPM_HighTrue }
  TPM PWM output pulse mode: high-true, low-true or no output.
- enum tpm_trigger_select_t
  Trigger options available.
- enum tpm_output_compare_mode_t {
  kTPM_NoOutputSignal = (1U << TPM_CnSC_MSA_SHIFT),
  kTPM_ToggleOnMatch = ((1U << TPM_CnSC_MSA_SHIFT) | (1U << TPM_CnSC_ELSA_S-HIFT)),
  kTPM_ClearOnMatch = ((1U << TPM_CnSC_MSA_SHIFT) | (2U << TPM_CnSC_ELSA_SH-IFT)),
  kTPM_SetOnMatch = ((1U << TPM_CnSC_MSA_SHIFT) | (3U << TPM_CnSC_ELSA_SHIF-T)),
  kTPM_HighPulseOutput = ((3U << TPM_CnSC_MSA_SHIFT) | (1U << TPM_CnSC_ELSA_-

SHIFT)),
kTPM_LowPulseOutput = ((3U << TPM_CnSC_MSA_SHIFT) | (2U << TPM_CnSC_ELSA_S-HIFT)) }
TPM output compare modes.
- enum tpm_input_capture_edge_t {
kTPM_RisingEdge = (1U << TPM_CnSC_ELSA_SHIFT),
kTPM_FallingEdge = (2U << TPM_CnSC_ELSA_SHIFT),
kTPM_RiseAndFallEdge = (3U << TPM_CnSC_ELSA_SHIFT) }
TPM input capture edge.
- enum tpm_clock_source_t {
kTPM_SystemClock = 1U,
kTPM_ExternalClock }
TPM clock source selection.
- enum tpm_clock_prescale_t {
kTPM_Prescale_Divide_1 = 0U,
kTPM_Prescale_Divide_2,
kTPM_Prescale_Divide_4,
kTPM_Prescale_Divide_8,
kTPM_Prescale_Divide_16,
kTPM_Prescale_Divide_32,
kTPM_Prescale_Divide_64,
kTPM_Prescale_Divide_128 }
TPM prescale value selection for the clock source.
- enum tpm_interrupt_enable_t {
kTPM_Chnl0InterruptEnable = (1U << 0),
kTPM_Chnl1InterruptEnable = (1U << 1),
kTPM_Chnl2InterruptEnable = (1U << 2),
kTPM_Chnl3InterruptEnable = (1U << 3),
kTPM_Chnl4InterruptEnable = (1U << 4),
kTPM_Chnl5InterruptEnable = (1U << 5),
kTPM_Chnl6InterruptEnable = (1U << 6),
kTPM_Chnl7InterruptEnable = (1U << 7),
kTPM_TimeOverflowInterruptEnable = (1U << 8) }
List of TPM interrupts.
- enum tpm_status_flags_t {
kTPM_Chnl0Flag = (1U << 0),
kTPM_Chnl1Flag = (1U << 1),
kTPM_Chnl2Flag = (1U << 2),
kTPM_Chnl3Flag = (1U << 3),
kTPM_Chnl4Flag = (1U << 4),
kTPM_Chnl5Flag = (1U << 5),
kTPM_Chnl6Flag = (1U << 6),
kTPM_Chnl7Flag = (1U << 7),
kTPM_TimeOverflowFlag = (1U << 8) }
List of TPM flags.

Driver version

- #define FSL_TPM_DRIVER_VERSION (MAKE_VERSION(2, 0, 2))
  Version 2.0.2.

Initialization and deinitialization

- void TPM_Init (TPM_Type ∗base, const tpm_config_t ∗config)
  Ungates the TPM clock and configures the peripheral for basic operation.
- void TPM_Deinit (TPM_Type ∗base)
  Stops the counter and gates the TPM clock.
- void TPM_GetDefaultConfig (tpm_config_t ∗config)
  Fill in the TPM config struct with the default settings.

Channel mode operations

- status_t TPM_SetupPwm (TPM_Type ∗base, const tpm_chnl_pwm_signal_param_t ∗chnlParams, uint8_t numOfChnls, tpm_pwm_mode_t mode, uint32_t pwmFreq_Hz, uint32_t srcClock_Hz)
  Configures the PWM signal parameters.
- void TPM_UpdatePwmDutycycle (TPM_Type ∗base, tpm_chnl_t chnlNumber, tpm_pwm_mode_t currentPwmMode, uint8_t dutyCyclePercent)
  Update the duty cycle of an active PWM signal.
- void TPM_UpdateChnlEdgeLevelSelect (TPM_Type ∗base, tpm_chnl_t chnlNumber, uint8_t level)
  Update the edge level selection for a channel.
- void TPM_SetupInputCapture (TPM_Type ∗base, tpm_chnl_t chnlNumber, tpm_input_capture_edge_t captureMode)
  Enables capturing an input signal on the channel using the function parameters.
- void TPM_SetupOutputCompare (TPM_Type ∗base, tpm_chnl_t chnlNumber, tpm_output_compare_mode_t compareMode, uint32_t compareValue)
  Configures the TPM to generate timed pulses.

Interrupt Interface

- void TPM_EnableInterrupts (TPM_Type ∗base, uint32_t mask)
  Enables the selected TPM interrupts.
- void TPM_DisableInterrupts (TPM_Type ∗base, uint32_t mask)
  Disables the selected TPM interrupts.
- uint32_t TPM_GetEnabledInterrupts (TPM_Type ∗base)
  Gets the enabled TPM interrupts.

Status Interface

- static uint32_t TPM_GetStatusFlags (TPM_Type ∗base)
  Gets the TPM status flags.
- static void TPM_ClearStatusFlags (TPM_Type ∗base, uint32_t mask)
  Clears the TPM status flags.

Read and write the timer period

- static void TPM_SetTimerPeriod (TPM_Type ∗base, uint32_t ticks)

Sets the timer period in units of ticks.
- static uint32_t TPM_GetCurrentTimerCount (TPM_Type ∗base)
  Reads the current timer counting value.

Timer Start and Stop

- static void TPM_StartTimer (TPM_Type ∗base, tpm_clock_source_t clockSource)
  Starts the TPM counter.
- static void TPM_StopTimer (TPM_Type ∗base)
  Stops the TPM counter.

21.3 Data Structure Documentation

21.3.1 struct tpm_chnl_pwm_signal_param_t

Data Fields

- tpm_chnl_t chnlNumber
  TPM channel to configure.
- tpm_pwm_level_select_t level
  PWM output active level select.
- uint8_t dutyCyclePercent
  PWM pulse width, value should be between 0 to 100 0=inactive signal(0% duty cycle)...

21.3.1.0.0.35 Field Documentation

21.3.1.0.0.35.1 tpm_chnl_t tpm_chnl_pwm_signal_param_t::chnlNumber

In combined mode (available in some SoC's, this represents the channel pair number

21.3.1.0.0.35.2 uint8_t tpm_chnl_pwm_signal_param_t::dutyCyclePercent

100=always active signal (100% duty cycle)

21.3.2 struct tpm_config_t

This structure holds the configuration settings for the TPM peripheral. To initialize this structure to reasonable defaults, call the TPM_GetDefaultConfig() function and pass a pointer to your config structure instance.

The config struct can be made const so it resides in flash

Data Fields

- tpm_clock_prescale_t prescale
  Select TPM clock prescale value.
- bool useGlobalTimeBase

true: Use of an external global time base is enabled; false: disabled
- tpm_trigger_select_t triggerSelect
  Input trigger to use for controlling the counter operation.
- bool enableDoze
  true: TPM counter is paused in doze mode; false: TPM counter continues in doze mode
- bool enableDebugMode
  true: TPM counter continues in debug mode; false: TPM counter is paused in debug mode
- bool enableReloadOnTrigger
  true: TPM counter is reloaded on trigger; false: TPM counter not reloaded
- bool enableStopOnOverflow
  true: TPM counter stops after overflow; false: TPM counter continues running after overflow
- bool enableStartOnTrigger
  true: TPM counter only starts when a trigger is detected; false: TPM counter starts immediately

21.4 Enumeration Type Documentation

21.4.1 enum tpm_chnl_t

Note

Actual number of available channels is SoC dependent

Enumerator

kTPM_Chnl_0 TPM channel number 0.
kTPM_Chnl_1 TPM channel number 1.
kTPM_Chnl_2 TPM channel number 2.
kTPM_Chnl_3 TPM channel number 3.
kTPM_Chnl_4 TPM channel number 4.
kTPM_Chnl_5 TPM channel number 5.
kTPM_Chnl_6 TPM channel number 6.
kTPM_Chnl_7 TPM channel number 7.

21.4.2 enum tpm_pwm_mode_t

Enumerator

kTPM_EdgeAlignedPwm Edge aligned PWM.
kTPM_CenterAlignedPwm Center aligned PWM.

21.4.3 enum tpm_pwm_level_select_t

Enumerator

kTPM_NoPwmSignal No PWM output on pin.

kTPM_LowTrue Low true pulses.
kTPM_HighTrue High true pulses.

21.4.4 enum tpm_trigger_select_t

This is used for both internal & external trigger sources (external option available in certain SoC's)

Note

The actual trigger options available is SoC-specific.

21.4.5 enum tpm_output_compare_mode_t

Enumerator

kTPM_NoOutputSignal No channel output when counter reaches CnV.
kTPM_ToggleOnMatch Toggle output.
kTPM_ClearOnMatch Clear output.
kTPM_SetOnMatch Set output.
kTPM_HighPulseOutput Pulse output high.
kTPM_LowPulseOutput Pulse output low.

21.4.6 enum tpm_input_capture_edge_t

Enumerator

kTPM_RisingEdge Capture on rising edge only.
kTPM_FallingEdge Capture on falling edge only.
kTPM_RiseAndFallEdge Capture on rising or falling edge.

21.4.7 enum tpm_clock_source_t

Enumerator

kTPM_SystemClock System clock.
kTPM_ExternalClock External clock.

21.4.8 enum tpm_clock_prescale_t

Enumerator

kTPM_Prescale_Divide_1 Divide by 1.
kTPM_Prescale_Divide_2 Divide by 2.
kTPM_Prescale_Divide_4 Divide by 4.
kTPM_Prescale_Divide_8 Divide by 8.
kTPM_Prescale_Divide_16 Divide by 16.
kTPM_Prescale_Divide_32 Divide by 32.
kTPM_Prescale_Divide_64 Divide by 64.
kTPM_Prescale_Divide_128 Divide by 128.

21.4.9 enum tpm_interrupt_enable_t

Enumerator

kTPM_Chnl0InterruptEnable Channel 0 interrupt.
kTPM_Chnl1InterruptEnable Channel 1 interrupt.
kTPM_Chnl2InterruptEnable Channel 2 interrupt.
kTPM_Chnl3InterruptEnable Channel 3 interrupt.
kTPM_Chnl4InterruptEnable Channel 4 interrupt.
kTPM_Chnl5InterruptEnable Channel 5 interrupt.
kTPM_Chnl6InterruptEnable Channel 6 interrupt.
kTPM_Chnl7InterruptEnable Channel 7 interrupt.
kTPM_TimeOverflowInterruptEnable Time overflow interrupt.

21.4.10 enum tpm_status_flags_t

Enumerator

kTPM_Chnl0Flag Channel 0 flag.
kTPM_Chnl1Flag Channel 1 flag.
kTPM_Chnl2Flag Channel 2 flag.
kTPM_Chnl3Flag Channel 3 flag.
kTPM_Chnl4Flag Channel 4 flag.
kTPM_Chnl5Flag Channel 5 flag.
kTPM_Chnl6Flag Channel 6 flag.
kTPM_Chnl7Flag Channel 7 flag.
kTPM_TimeOverflowFlag Time overflow flag.

21.5 Function Documentation

21.5.1 void TPM_Init (TPM_Type ∗ *base*, const tpm_config_t ∗ *config*)

Note

This API should be called at the beginning of the application using the TPM driver.

Parameters

base	TPM peripheral base address
config	Pointer to user's TPM config structure.

21.5.2 void TPM_Deinit (TPM_Type * *base*)

Parameters

base	TPM peripheral base address

21.5.3 void TPM_GetDefaultConfig (tpm_config_t * *config*)

The default values are:

```
*     config->prescale = kTPM_Prescale_Divide_1;
*     config->useGlobalTimeBase = false;
*     config->dozeEnable = false;
*     config->dbgMode = false;
*     config->enableReloadOnTrigger = false;
*     config->enableStopOnOverflow = false;
*     config->enableStartOnTrigger = false;
*#if FSL_FEATURE_TPM_HAS_PAUSE_COUNTER_ON_TRIGGER
*     config->enablePauseOnTrigger = false;
*#endif
*     config->triggerSelect = kTPM_Trigger_Select_0;
*#if FSL_FEATURE_TPM_HAS_EXTERNAL_TRIGGER_SELECTION
*     config->triggerSource = kTPM_TriggerSource_External;
*#endif
*
```

Parameters

config	Pointer to user's TPM config structure.

21.5.4 status_t TPM_SetupPwm (TPM_Type * *base,* const tpm_chnl_pwm_signal_param_t * *chnlParams,* uint8_t *numOfChnls,* tpm_pwm_mode_t *mode,* uint32_t *pwmFreq_Hz,* uint32_t *srcClock_Hz*)

User calls this function to configure the PWM signals period, mode, dutycycle and edge. Use this function to configure all the TPM channels that will be used to output a PWM signal

Parameters

base	TPM peripheral base address
chnlParams	Array of PWM channel parameters to configure the channel(s)
numOfChnls	Number of channels to configure, this should be the size of the array passed in
mode	PWM operation mode, options available in enumeration tpm_pwm_mode_t
pwmFreq_Hz	PWM signal frequency in Hz
srcClock_Hz	TPM counter clock in Hz

Returns

kStatus_Success if the PWM setup was successful, kStatus_Error on failure

21.5.5 void TPM_UpdatePwmDutycycle (TPM_Type ∗ *base*, tpm_chnl_t *chnlNumber*, tpm_pwm_mode_t *currentPwmMode*, uint8_t *dutyCyclePercent*)

Parameters

base	TPM peripheral base address
chnlNumber	The channel number. In combined mode, this represents the channel pair number
currentPwm-Mode	The current PWM mode set during PWM setup
dutyCycle-Percent	New PWM pulse width, value should be between 0 to 100 0=inactive signal(0% duty cycle)... 100=active signal (100% duty cycle)

21.5.6 void TPM_UpdateChnlEdgeLevelSelect (TPM_Type ∗ *base*, tpm_chnl_t *chnlNumber*, uint8_t *level*)

Parameters

base	TPM peripheral base address

chnlNumber	The channel number
level	The level to be set to the ELSnB:ELSnA field; valid values are 00, 01, 10, 11. See the appropriate SoC reference manual for details about this field.

21.5.7 void TPM_SetupInputCapture (TPM_Type * *base*, tpm_chnl_t *chnlNumber*, tpm_input_capture_edge_t *captureMode*)

When the edge specified in the captureMode argument occurs on the channel, the TPM counter is captured into the CnV register. The user has to read the CnV register separately to get this value.

Parameters

base	TPM peripheral base address
chnlNumber	The channel number
captureMode	Specifies which edge to capture

21.5.8 void TPM_SetupOutputCompare (TPM_Type * *base*, tpm_chnl_t *chnlNumber*, tpm_output_compare_mode_t *compareMode*, uint32_t *compareValue*)

When the TPM counter matches the value of compareVal argument (this is written into CnV reg), the channel output is changed based on what is specified in the compareMode argument.

Parameters

base	TPM peripheral base address
chnlNumber	The channel number
compareMode	Action to take on the channel output when the compare condition is met
compareValue	Value to be programmed in the CnV register.

21.5.9 void TPM_EnableInterrupts (TPM_Type * *base*, uint32_t *mask*)

Parameters

base	TPM peripheral base address
mask	The interrupts to enable. This is a logical OR of members of the enumeration tpm_-interrupt_enable_t

21.5.10 void TPM_DisableInterrupts (TPM_Type * *base*, uint32_t *mask*)

Parameters

base	TPM peripheral base address
mask	The interrupts to disable. This is a logical OR of members of the enumeration tpm_-interrupt_enable_t

21.5.11 uint32_t TPM_GetEnabledInterrupts (TPM_Type * *base*)

Parameters

base	TPM peripheral base address

Returns

The enabled interrupts. This is the logical OR of members of the enumeration tpm_interrupt_enable-_t

21.5.12 static uint32_t TPM_GetStatusFlags (TPM_Type * *base*) [inline], [static]

Parameters

base	TPM peripheral base address

Returns

The status flags. This is the logical OR of members of the enumeration tpm_status_flags_t

21.5.13 static void TPM_ClearStatusFlags (TPM_Type * *base*, uint32_t *mask*) [inline], [static]

Parameters

base	TPM peripheral base address
mask	The status flags to clear. This is a logical OR of members of the enumeration tpm_-status_flags_t

21.5.14 static void TPM_SetTimerPeriod (TPM_Type * *base*, uint32_t *ticks*) [inline], [static]

Timers counts from 0 until it equals the count value set here. The count value is written to the MOD register.

Note

1. This API allows the user to use the TPM module as a timer. Do not mix usage of this API with TPM's PWM setup API's.
2. Call the utility macros provided in the fsl_common.h to convert usec or msec to ticks.

Parameters

base	TPM peripheral base address
ticks	A timer period in units of ticks, which should be equal or greater than 1.

21.5.15 static uint32_t TPM_GetCurrentTimerCount (TPM_Type * *base*) [inline], [static]

This function returns the real-time timer counting value in a range from 0 to a timer period.

Note

Call the utility macros provided in the fsl_common.h to convert ticks to usec or msec.

Parameters

base	TPM peripheral base address

Returns

The current counter value in ticks

21.5.16 static void TPM_StartTimer (TPM_Type * *base,* tpm_clock_source_t *clockSource*) [inline], [static]

Parameters

base	TPM peripheral base address
clockSource	TPM clock source; once clock source is set the counter will start running

21.5.17 static void TPM_StopTimer (TPM_Type * *base*) [inline], [static]

Parameters

base	TPM peripheral base address

Chapter 22
VREF: Voltage Reference Driver

22.1 Overview

The MCUXpresso SDK provides a peripheral driver for the Crossbar Voltage Reference (VREF) block of MCUXpresso SDK devices.

The Voltage Reference(VREF) supplies an accurate 1.2 V voltage output that can be trimmed in 0.5 mV steps. VREF can be used in applications to provide a reference voltage to external devices and to internal analog peripherals, such as the ADC, DAC, or CMP. The voltage reference has operating modes that provide different levels of supply rejection and power consumption.

To configure the VREF driver, configure vref_config_t structure in one of two ways.

1. Use the VREF_GetDefaultConfig() function.
2. Set the parameter in the vref_config_t structure.

To initialize the VREF driver, call the VREF_Init() function and pass a pointer to the vref_config_t structure.

To de-initialize the VREF driver, call the VREF_Deinit() function.

22.2 Typical use case and example

This example shows how to generate a reference voltage by using the VREF module.

```
vref_config_t vrefUserConfig;
VREF_GetDefaultConfig(&vrefUserConfig); /* Gets a default configuration. */
VREF_Init(VREF, &vrefUserConfig);       /* Initializes and configures the VREF module */

/* Do something */

VREF_Deinit(VREF); /* De-initializes the VREF module */
```

Data Structures

- struct vref_config_t
  The description structure for the VREF module. More...

Enumerations

- enum vref_buffer_mode_t {
  kVREF_ModeBandgapOnly = 0U,
  kVREF_ModeHighPowerBuffer = 1U,
  kVREF_ModeLowPowerBuffer = 2U }
  VREF modes.

Driver version

- #define FSL_VREF_DRIVER_VERSION (MAKE_VERSION(2, 1, 0))
  Version 2.1.0.

VREF functional operation

- void VREF_Init (VREF_Type ∗base, const vref_config_t ∗config)
  Enables the clock gate and configures the VREF module according to the configuration structure.
- void VREF_Deinit (VREF_Type ∗base)
  Stops and disables the clock for the VREF module.
- void VREF_GetDefaultConfig (vref_config_t ∗config)
  Initializes the VREF configuration structure.
- void VREF_SetTrimVal (VREF_Type ∗base, uint8_t trimValue)
  Sets a TRIM value for the reference voltage.
- static uint8_t VREF_GetTrimVal (VREF_Type ∗base)
  Reads the value of the TRIM meaning output voltage.

22.3 Data Structure Documentation

22.3.1 struct vref_config_t

Data Fields

- vref_buffer_mode_t bufferMode
  Buffer mode selection.

22.4 Macro Definition Documentation

22.4.1 #define FSL_VREF_DRIVER_VERSION (MAKE_VERSION(2, 1, 0))

22.5 Enumeration Type Documentation

22.5.1 enum vref_buffer_mode_t

Enumerator

kVREF_ModeBandgapOnly Bandgap on only, for stabilization and startup.
kVREF_ModeHighPowerBuffer High-power buffer mode enabled.
kVREF_ModeLowPowerBuffer Low-power buffer mode enabled.

22.6 Function Documentation

22.6.1 void VREF_Init (VREF_Type ∗ *base*, const vref_config_t ∗ *config*)

This function must be called before calling all other VREF driver functions, read/write registers, and configurations with user-defined settings. The example below shows how to set up vref_config_t parameters and how to call the VREF_Init function by passing in these parameters. This is an example.

```
*   vref_config_t vrefConfig;
*   vrefConfig.bufferMode = kVREF_ModeHighPowerBuffer;
*   vrefConfig.enableExternalVoltRef = false;
*   vrefConfig.enableLowRef = false;
*   VREF_Init(VREF, &vrefConfig);
*
```

Parameters

base	VREF peripheral address.
config	Pointer to the configuration structure.

22.6.2 void VREF_Deinit (VREF_Type ∗ *base*)

This function should be called to shut down the module. This is an example.

```
*   vref_config_t vrefUserConfig;
*   VREF_Init(VREF);
*   VREF_GetDefaultConfig(&vrefUserConfig);
*   ...
*   VREF_Deinit(VREF);
*
```

Parameters

base	VREF peripheral address.

22.6.3 void VREF_GetDefaultConfig (vref_config_t ∗ *config*)

This function initializes the VREF configuration structure to default values. This is an example.

```
*   vrefConfig->bufferMode = kVREF_ModeHighPowerBuffer;
*   vrefConfig->enableExternalVoltRef = false;
*   vrefConfig->enableLowRef = false;
*
```

Parameters

config	Pointer to the initialization structure.

22.6.4 void VREF_SetTrimVal (VREF_Type ∗ *base,* uint8_t *trimValue*)

This function sets a TRIM value for the reference voltage. Note that the TRIM value maximum is 0x3F.

Parameters

base	VREF peripheral address.
trimValue	Value of the trim register to set the output reference voltage (maximum 0x3F (6-bit)).

22.6.5 static uint8_t VREF_GetTrimVal (VREF_Type * *base*) [inline], [static]

This function gets the TRIM value from the TRM register.

Parameters

base	VREF peripheral address.

Returns

Six-bit value of trim setting.

Chapter 23
Clock Driver

23.1 Overview

The MCUXpresso SDK provides APIs for MCUXpresso SDK devices' clock operation.

23.2 Get frequency

A centralized function CLOCK_GetFreq gets different clock type frequencies by passing a clock name. For example, pass a kCLOCK_CoreSysClk to get the core clock and pass a kCLOCK_BusClk to get the bus clock. Additionally, there are separate functions to get the frequency. For example, use CLOCK-_GetCoreSysClkFreq to get the core clock frequency and CLOCK_GetBusClkFreq to get the bus clock frequency. Using these functions reduces the image size.

23.3 External clock frequency

The external clocks EXTAL0/EXTAL1/EXTAL32 are decided by the board level design. The Clock driver uses variables g_xtal0Freq/g_xtal1Freq/g_xtal32Freq to save clock frequencies. Likewise, the APIs CLOCK_SetXtal0Freq, CLOCK_SetXtal1Freq, and CLOCK_SetXtal32Freq are used to set these variables.

The upper layer must set these values correctly. For example, after OSC0(SYSOSC) is initialized using CLOCK_InitOsc0 or CLOCK_InitSysOsc, the upper layer should call the CLOCK_SetXtal0Freq. Otherwise, the clock frequency get functions may not receive valid values. This is useful for multicore platforms where only one core calls CLOCK_InitOsc0 to initialize OSC0 and other cores call CLOCK_SetXtal0-Freq.

Modules

- Multipurpose Clock Generator Lite (MCGLITE)

Files

- file fsl_clock.h

Data Structures

- struct sim_clock_config_t
  SIM configuration structure for clock setting. More...
- struct oscer_config_t
  The OSC configuration for OSCERCLK. More...
- struct osc_config_t
  OSC Initialization Configuration Structure. More...
- struct mcglite_config_t
  MCG_Lite configure structure for mode change. More...

Macros

- #define FSL_SDK_DISABLE_DRIVER_CLOCK_CONTROL 0
  Configure whether driver controls clock.
- #define RTC_CLOCKS
  Clock ip name array for RTC.
- #define LPUART_CLOCKS
  Clock ip name array for LPUART.
- #define SPI_CLOCKS
  Clock ip name array for SPI.
- #define LPTMR_CLOCKS
  Clock ip name array for LPTMR.
- #define ADC16_CLOCKS
  Clock ip name array for ADC16.
- #define TPM_CLOCKS
  Clock ip name array for TPM.
- #define VREF_CLOCKS
  Clock ip name array for VREF.
- #define I2C_CLOCKS
  Clock ip name array for I2C.
- #define PORT_CLOCKS
  Clock ip name array for PORT.
- #define FTF_CLOCKS
  Clock ip name array for FTF.
- #define CMP_CLOCKS
  Clock ip name array for CMP.
- #define LPO_CLK_FREQ 1000U
  LPO clock frequency.
- #define SYS_CLK kCLOCK_CoreSysClk
  Peripherals clock source definition.

Enumerations

- enum clock_name_t {
  kCLOCK_CoreSysClk,
  kCLOCK_PlatClk,
  kCLOCK_BusClk,
  kCLOCK_FlashClk,
  kCLOCK_Er32kClk,
  kCLOCK_Osc0ErClk,
  kCLOCK_McgFixedFreqClk,
  kCLOCK_McgInternalRefClk,
  kCLOCK_McgFllClk,
  kCLOCK_McgPeriphClk,
  kCLOCK_McgIrc48MClk,
  kCLOCK_LpoClk }
  Clock name used to get clock frequency.
- enum clock_ip_name_t
  Clock gate name used for CLOCK_EnableClock/CLOCK_DisableClock.
- enum _osc_cap_load {

kOSC_Cap2P = OSC_CR_SC2P_MASK,
kOSC_Cap4P = OSC_CR_SC4P_MASK,
kOSC_Cap8P = OSC_CR_SC8P_MASK,
kOSC_Cap16P = OSC_CR_SC16P_MASK }
Oscillator capacitor load setting.
- enum _oscer_enable_mode {
kOSC_ErClkEnable = OSC_CR_ERCLKEN_MASK,
kOSC_ErClkEnableInStop = OSC_CR_EREFSTEN_MASK }
OSCERCLK enable mode.
- enum osc_mode_t {
kOSC_ModeExt = 0U,
kOSC_ModeOscLowPower = MCG_C2_EREFS0_MASK }
The OSC work mode.
- enum mcglite_clkout_src_t {
kMCGLITE_ClkSrcHirc,
kMCGLITE_ClkSrcLirc,
kMCGLITE_ClkSrcExt }
MCG_Lite clock source selection.
- enum mcglite_lirc_mode_t {
kMCGLITE_Lirc2M,
kMCGLITE_Lirc8M }
MCG_Lite LIRC select.
- enum mcglite_lirc_div_t {
kMCGLITE_LircDivBy1 = 0U,
kMCGLITE_LircDivBy2,
kMCGLITE_LircDivBy4,
kMCGLITE_LircDivBy8,
kMCGLITE_LircDivBy16,
kMCGLITE_LircDivBy32,
kMCGLITE_LircDivBy64,
kMCGLITE_LircDivBy128 }
MCG_Lite divider factor selection for clock source.
- enum mcglite_mode_t {
kMCGLITE_ModeHirc48M,
kMCGLITE_ModeLirc8M,
kMCGLITE_ModeLirc2M,
kMCGLITE_ModeExt,
kMCGLITE_ModeError }
MCG_Lite clock mode definitions.
- enum _mcglite_irclk_enable_mode {
kMCGLITE_IrclkEnable = MCG_C1_IRCLKEN_MASK,
kMCGLITE_IrclkEnableInStop = MCG_C1_IREFSTEN_MASK }
MCG internal reference clock (MCGIRCLK) enable mode definition.

Functions

- static void CLOCK_EnableClock (clock_ip_name_t name)

Enable the clock for specific IP.
- static void CLOCK_DisableClock (clock_ip_name_t name)
  Disable the clock for specific IP.
- static void CLOCK_SetEr32kClock (uint32_t src)
  Set ERCLK32K source.
- static void CLOCK_SetLpuart0Clock (uint32_t src)
  Set LPUART clock source.
- static void CLOCK_SetTpmClock (uint32_t src)
  Set TPM clock source.
- static void CLOCK_SetClkOutClock (uint32_t src)
  Set CLKOUT source.
- static void CLOCK_SetRtcClkOutClock (uint32_t src)
  Set RTC_CLKOUT source.
- static void CLOCK_SetOutDiv (uint32_t outdiv1, uint32_t outdiv4)
  System clock divider.
- uint32_t CLOCK_GetFreq (clock_name_t clockName)
  Gets the clock frequency for a specific clock name.
- uint32_t CLOCK_GetCoreSysClkFreq (void)
  Get the core clock or system clock frequency.
- uint32_t CLOCK_GetPlatClkFreq (void)
  Get the platform clock frequency.
- uint32_t CLOCK_GetBusClkFreq (void)
  Get the bus clock frequency.
- uint32_t CLOCK_GetFlashClkFreq (void)
  Get the flash clock frequency.
- uint32_t CLOCK_GetEr32kClkFreq (void)
  Get the external reference 32K clock frequency (ERCLK32K).
- uint32_t CLOCK_GetOsc0ErClkFreq (void)
  Get the OSC0 external reference clock frequency (OSC0ERCLK).
- void CLOCK_SetSimConfig (sim_clock_config_t const *config)
  Set the clock configure in SIM module.
- static void CLOCK_SetSimSafeDivs (void)
  Set the system clock dividers in SIM to safe value.

Variables

- uint32_t g_xtal0Freq
  External XTAL0 (OSC0) clock frequency.
- uint32_t g_xtal32Freq
  The external XTAL32/EXTAL32/RTC_CLKIN clock frequency.

Driver version

- #define FSL_CLOCK_DRIVER_VERSION (MAKE_VERSION(2, 1, 1))
  CLOCK driver version 2.1.1.

MCG_Lite clock frequency

- uint32_t CLOCK_GetOutClkFreq (void)
  Gets the MCG_Lite output clock (MCGOUTCLK) frequency.
- uint32_t CLOCK_GetInternalRefClkFreq (void)

Gets the MCG internal reference clock (MCGIRCLK) frequency.
- uint32_t CLOCK_GetPeriphClkFreq (void)
  Gets the current MCGPCLK frequency.

MCG_Lite mode.

- mcglite_mode_t CLOCK_GetMode (void)
  Gets the current MCG_Lite mode.
- status_t CLOCK_SetMcgliteConfig (mcglite_config_t const ∗targetConfig)
  Sets the MCG_Lite configuration.

OSC configuration

- static void OSC_SetExtRefClkConfig (OSC_Type ∗base, oscer_config_t const ∗config)
  Configures the OSC external reference clock (OSCERCLK).
- static void OSC_SetCapLoad (OSC_Type ∗base, uint8_t capLoad)
  Sets the capacitor load configuration for the oscillator.
- void CLOCK_InitOsc0 (osc_config_t const ∗config)
  Initializes the OSC0.
- void CLOCK_DeinitOsc0 (void)
  Deinitializes the OSC0.

External clock frequency

- static void CLOCK_SetXtal0Freq (uint32_t freq)
  Sets the XTAL0 frequency based on board settings.
- static void CLOCK_SetXtal32Freq (uint32_t freq)
  Sets the XTAL32/RTC_CLKIN frequency based on board settings.

23.4 Data Structure Documentation

23.4.1 struct sim_clock_config_t

Data Fields

- uint8_t er32kSrc
  ERCLK32K source selection.
- uint32_t clkdiv1
  SIM_CLKDIV1.

23.4.1.0.0.36 Field Documentation

23.4.1.0.0.36.1 uint8_t sim_clock_config_t::er32kSrc

23.4.1.0.0.36.2 uint32_t sim_clock_config_t::clkdiv1

23.4.2 struct oscer_config_t

Data Fields

- uint8_t enableMode
  OSCERCLK enable mode.

23.4.2.0.0.37 Field Documentation

23.4.2.0.0.37.1 uint8_t oscer_config_t::enableMode

OR'ed value of _oscer_enable_mode.

23.4.3 struct osc_config_t

Defines the configuration data structure to initialize the OSC. When porting to a new board, set the following members according to the board settings:

1. freq: The external frequency.
2. workMode: The OSC module mode.

Data Fields

- uint32_t freq
  External clock frequency.
- uint8_t capLoad
  Capacitor load setting.
- osc_mode_t workMode
  OSC work mode setting.
- oscer_config_t oscerConfig
  Configuration for OSCERCLK.

23.4.3.0.0.38 Field Documentation

23.4.3.0.0.38.1 uint32_t osc_config_t::freq

23.4.3.0.0.38.2 uint8_t osc_config_t::capLoad

23.4.3.0.0.38.3 osc_mode_t osc_config_t::workMode

23.4.3.0.0.38.4 oscer_config_t osc_config_t::oscerConfig

23.4.4 struct mcglite_config_t

Data Fields

- mcglite_clkout_src_t outSrc
  MCGOUT clock select.
- uint8_t irclkEnableMode
  MCGIRCLK enable mode, OR'ed value of _mcglite_irclk_enable_mode.
- mcglite_lirc_mode_t ircs
  MCG_C2[IRCS].
- mcglite_lirc_div_t fcrdiv
  MCG_SC[FCRDIV].
- mcglite_lirc_div_t lircDiv2
  MCG_MC[LIRC_DIV2].
- bool hircEnableInNotHircMode
  HIRC enable when not in HIRC mode.

23.4.4.0.0.39 Field Documentation

23.4.4.0.0.39.1 mcglite_clkout_src_t mcglite_config_t::outSrc

23.4.4.0.0.39.2 uint8_t mcglite_config_t::irclkEnableMode

23.4.4.0.0.39.3 mcglite_lirc_mode_t mcglite_config_t::ircs

23.4.4.0.0.39.4 mcglite_lirc_div_t mcglite_config_t::fcrdiv

23.4.4.0.0.39.5 mcglite_lirc_div_t mcglite_config_t::lircDiv2

23.4.4.0.0.39.6 bool mcglite_config_t::hircEnableInNotHircMode

23.5 Macro Definition Documentation

23.5.1 #define FSL_SDK_DISABLE_DRIVER_CLOCK_CONTROL 0

When set to 0, peripheral drivers will enable clock in initialize function and disable clock in de-initialize function. When set to 1, peripheral driver will not control the clock, application could contol the clock out of the driver.

Note

All drivers share this feature switcher. If it is set to 1, application should handle clock enable and disable for all drivers.

23.5.2 #define FSL_CLOCK_DRIVER_VERSION (MAKE_VERSION(2, 1, 1))

23.5.3 #define RTC_CLOCKS

Value:

```
{               \
        kCLOCK_Rtc0 \
    }
```

23.5.4 #define LPUART_CLOCKS

Value:

```
{                  \
        kCLOCK_Lpuart0 \
    }
```

23.5.5 #define SPI_CLOCKS

Value:

```
{               \
        kCLOCK_Spi0 \
    }
```

23.5.6 #define LPTMR_CLOCKS

Value:

```
{                 \
        kCLOCK_Lptmr0 \
    }
```

23.5.7 #define ADC16_CLOCKS

Value:

```
{                \
        kCLOCK_Adc0   \
    }
```

23.5.8 #define TPM_CLOCKS

Value:

```
{                            \
        kCLOCK_Tpm0, kCLOCK_Tpm1 \
    }
```

23.5.9 #define VREF_CLOCKS

Value:

```
{                \
        kCLOCK_Vref0 \
    }
```

23.5.10 #define I2C_CLOCKS

Value:

```
{               \
        kCLOCK_I2c0 \
    }
```

23.5.11 #define PORT_CLOCKS

Value:

```
{                              \
        kCLOCK_PortA, kCLOCK_PortB \
    }
```

23.5.12 #define FTF_CLOCKS

Value:

```
{              \
       kCLOCK_Ftf0 \
    }
```

23.5.13 #define CMP_CLOCKS

Value:

```
{              \
       kCLOCK_Cmp0 \
    }
```

23.5.14 #define SYS_CLK kCLOCK_CoreSysClk

23.6 Enumeration Type Documentation

23.6.1 enum clock_name_t

Enumerator

kCLOCK_CoreSysClk Core/system clock.
kCLOCK_PlatClk Platform clock.
kCLOCK_BusClk Bus clock.
kCLOCK_FlashClk Flash clock.
kCLOCK_Er32kClk External reference 32K clock (ERCLK32K)
kCLOCK_Osc0ErClk OSC0 external reference clock (OSC0ERCLK)
kCLOCK_McgFixedFreqClk MCG fixed frequency clock (MCGFFCLK)
kCLOCK_McgInternalRefClk MCG internal reference clock (MCGIRCLK)
kCLOCK_McgFllClk MCGFLLCLK.
kCLOCK_McgPeriphClk MCG peripheral clock (MCGPCLK)
kCLOCK_McgIrc48MClk MCG IRC48M clock.
kCLOCK_LpoClk LPO clock.

23.6.2 enum clock_ip_name_t

23.6.3 enum _osc_cap_load

Enumerator

kOSC_Cap2P 2 pF capacitor load

kOSC_Cap4P 4 pF capacitor load
kOSC_Cap8P 8 pF capacitor load
kOSC_Cap16P 16 pF capacitor load

23.6.4 enum _oscer_enable_mode

Enumerator

kOSC_ErClkEnable Enable.
kOSC_ErClkEnableInStop Enable in stop mode.

23.6.5 enum osc_mode_t

Enumerator

kOSC_ModeExt Use external clock.
kOSC_ModeOscLowPower Oscillator low power.

23.6.6 enum mcglite_clkout_src_t

Enumerator

kMCGLITE_ClkSrcHirc MCGOUTCLK source is HIRC.
kMCGLITE_ClkSrcLirc MCGOUTCLK source is LIRC.
kMCGLITE_ClkSrcExt MCGOUTCLK source is external clock source.

23.6.7 enum mcglite_lirc_mode_t

Enumerator

kMCGLITE_Lirc2M Slow internal reference(LIRC) 2 MHz clock selected.
kMCGLITE_Lirc8M Slow internal reference(LIRC) 8 MHz clock selected.

23.6.8 enum mcglite_lirc_div_t

Enumerator

kMCGLITE_LircDivBy1 Divider is 1.
kMCGLITE_LircDivBy2 Divider is 2.

kMCGLITE_LircDivBy4 Divider is 4.
kMCGLITE_LircDivBy8 Divider is 8.
kMCGLITE_LircDivBy16 Divider is 16.
kMCGLITE_LircDivBy32 Divider is 32.
kMCGLITE_LircDivBy64 Divider is 64.
kMCGLITE_LircDivBy128 Divider is 128.

23.6.9 enum mcglite_mode_t

Enumerator

kMCGLITE_ModeHirc48M Clock mode is HIRC 48 M.
kMCGLITE_ModeLirc8M Clock mode is LIRC 8 M.
kMCGLITE_ModeLirc2M Clock mode is LIRC 2 M.
kMCGLITE_ModeExt Clock mode is EXT.
kMCGLITE_ModeError Unknown mode.

23.6.10 enum _mcglite_irclk_enable_mode

Enumerator

kMCGLITE_IrclkEnable MCGIRCLK enable.
kMCGLITE_IrclkEnableInStop MCGIRCLK enable in stop mode.

23.7 Function Documentation

23.7.1 static void CLOCK_EnableClock (clock_ip_name_t *name*) [inline], [static]

Parameters

name	Which clock to enable, see clock_ip_name_t.

23.7.2 static void CLOCK_DisableClock (clock_ip_name_t *name*) [inline], [static]

Parameters

name	Which clock to disable, see clock_ip_name_t.

23.7.3 static void CLOCK_SetEr32kClock (uint32_t *src*) [inline], [static]

Parameters

src	The value to set ERCLK32K clock source.

23.7.4 static void CLOCK_SetLpuart0Clock (uint32_t *src*) [inline], [static]

Parameters

src	The value to set LPUART clock source.

23.7.5 static void CLOCK_SetTpmClock (uint32_t *src*) [inline], [static]

Parameters

src	The value to set TPM clock source.

23.7.6 static void CLOCK_SetClkOutClock (uint32_t *src*) [inline], [static]

Parameters

src	The value to set CLKOUT source.

23.7.7 static void CLOCK_SetRtcClkOutClock (uint32_t *src*) [inline], [static]

Parameters

src	The value to set RTC_CLKOUT source.

23.7.8 static void CLOCK_SetOutDiv (uint32_t *outdiv1*, uint32_t *outdiv4*) [inline], [static]

Set the SIM_CLKDIV1[OUTDIV1], SIM_CLKDIV1[OUTDIV4].

Parameters

outdiv1	Clock 1 output divider value.
outdiv4	Clock 4 output divider value.

23.7.9 uint32_t CLOCK_GetFreq (clock_name_t *clockName*)

This function checks the current clock configurations and then calculates the clock frequency for a specific clock name defined in clock_name_t. The MCG must be properly configured before using this function.

Parameters

clockName	Clock names defined in clock_name_t

Returns

Clock frequency value in Hertz

23.7.10 uint32_t CLOCK_GetCoreSysClkFreq (void)

Returns

Clock frequency in Hz.

23.7.11 uint32_t CLOCK_GetPlatClkFreq (void)

Returns

Clock frequency in Hz.

23.7.12 uint32_t CLOCK_GetBusClkFreq (void)

Returns

Clock frequency in Hz.

23.7.13 uint32_t CLOCK_GetFlashClkFreq (void)

Returns

Clock frequency in Hz.

23.7.14 uint32_t CLOCK_GetEr32kClkFreq (void)

Returns

Clock frequency in Hz.

23.7.15 uint32_t CLOCK_GetOsc0ErClkFreq (void)

Returns

Clock frequency in Hz.

23.7.16 void CLOCK_SetSimConfig (sim_clock_config_t const * *config*)

This function sets system layer clock settings in SIM module.

Parameters

config	Pointer to the configure structure.

23.7.17 static void CLOCK_SetSimSafeDivs (void) [inline], [static]

The system level clocks (core clock, bus clock, flexbus clock and flash clock) must be in allowed ranges. During MCG clock mode switch, the MCG output clock changes then the system level clocks may be out of range. This function could be used before MCG mode change, to make sure system level clocks are in allowed range.

Parameters

config	Pointer to the configure structure.

23.7.18 uint32_t CLOCK_GetOutClkFreq (void)

This function gets the MCG_Lite output clock frequency in Hz based on the current MCG_Lite register value.

Returns

The frequency of MCGOUTCLK.

23.7.19 uint32_t CLOCK_GetInternalRefClkFreq (void)

This function gets the MCG_Lite internal reference clock frequency in Hz based on the current MCG register value.

Returns

The frequency of MCGIRCLK.

23.7.20 uint32_t CLOCK_GetPeriphClkFreq (void)

This function gets the MCGPCLK frequency in Hz based on the current MCG_Lite register settings.

Returns

The frequency of MCGPCLK.

23.7.21 mcglite_mode_t CLOCK_GetMode (void)

This function checks the MCG_Lite registers and determines the current MCG_Lite mode.

Returns

The current MCG_Lite mode or error code.

23.7.22 status_t CLOCK_SetMcgliteConfig (mcglite_config_t const * *targetConfig*)

This function configures the MCG_Lite, includes the output clock source, MCGIRCLK settings, HIRC settings, and so on. See mcglite_config_t for details.

Parameters

targetConfig	Pointer to the target MCG_Lite mode configuration structure.

Returns

Error code.

23.7.23 static void OSC_SetExtRefClkConfig (OSC_Type * *base,* oscer_config_t const * *config*) [inline], [static]

This function configures the OSC external reference clock (OSCERCLK). This is an example to enable the OSCERCLK in normal mode and stop mode, and set the output divider to 1.

```
oscer_config_t config =
{
    .enableMode = kOSC_ErClkEnable |
      kOSC_ErClkEnableInStop,
    .erclkDiv   = 1U,
};

OSC_SetExtRefClkConfig(OSC, &config);
```

Parameters

base	OSC peripheral address.
config	Pointer to the configuration structure.

23.7.24 static void OSC_SetCapLoad (OSC_Type * *base,* uint8_t *capLoad*) [inline], [static]

This function sets the specified capacitor configuration for the oscillator. This should be done in the early system level initialization function call based on the system configuration.

Parameters

base	OSC peripheral address.

capLoad	OR'ed value for the capacitor load option.See _osc_cap_load.

Example:

```
// To enable only 2 pF and 8 pF capacitor load, please use like this.
OSC_SetCapLoad(OSC, kOSC_Cap2P | kOSC_Cap8P);
```

23.7.25 void CLOCK_InitOsc0 (osc_config_t const * *config*)

This function initializes the OSC0 according to the board configuration.

Parameters

config	Pointer to the OSC0 configuration structure.

23.7.26 void CLOCK_DeinitOsc0 (void)

This function deinitializes the OSC0.

23.7.27 static void CLOCK_SetXtal0Freq (uint32_t *freq*) [inline], [static]

Parameters

freq	The XTAL0/EXTAL0 input clock frequency in Hz.

23.7.28 static void CLOCK_SetXtal32Freq (uint32_t *freq*) [inline], [static]

Parameters

freq	The XTAL32/EXTAL32/RTC_CLKIN input clock frequency in Hz.

23.8 Variable Documentation

23.8.1 uint32_t g_xtal0Freq

The XTAL0/EXTAL0 (OSC0) clock frequency in Hz. When the clock is set up, use the function CLOCK_SetXtal0Freq to set the value in the clock driver. For example, if XTAL0 is 8 MHz:

```
* CLOCK_InitOsc0(...); // Set up the OSC0
* CLOCK_SetXtal0Freq(80000000); // Set the XTAL0 value to clock driver.
*
```

This is important for the multicore platforms where one core needs to set up the OSC0 using the CL-OCK_InitOsc0. All other cores need to call the CLOCK_SetXtal0Freq to get a valid clock frequency.

23.8.2 uint32_t g_xtal32Freq

The XTAL32/EXTAL32/RTC_CLKIN clock frequency in Hz. When the clock is set up, use the function CLOCK_SetXtal32Freq to set the value in the clock driver.

This is important for the multicore platforms where one core needs to set up the clock. All other cores need to call the CLOCK_SetXtal32Freq to get a valid clock frequency.

23.9 Multipurpose Clock Generator Lite (MCGLITE)

The MCUXpresso SDK provides a peripheral driver for the MCG_Lite module of MCUXpresso SDK devices.

23.9.1 Function description

The MCG_Lite driver provides three kinds of APIs:

1. APIs to get the MCG_Lite frequency.
2. APIs for MCG_Lite mode.
3. APIs for OSC setup.

23.9.1.1 MCG_Lite clock frequency

The CLOCK_GetOutClkFreq(), CLOCK_GetInternalRefClkFreq() and CLOCK_GetPeriphClkFreq() functions are used to get the frequency of MCGOUTCLK, MCGIRCLK, and MCGPCLK based on the current hardware setting.

23.9.1.2 MCG_Lite mode

The function CLOCK_GetMode() gets the current MCG_Lite mode.

The function CLOCK_SetMcgliteConfig() sets the MCG_Lite to a desired configuration. The MCG_Lite can't switch between the LIRC2M and LIRC8M. Instead, the function switches to the HIRC mode first and then switches to the target mode.

23.9.1.3 OSC configuration

To enable the OSC clock, the MCG_Lite is needed together with the OSC module. The function CLOCK-_InitOsc0() uses the MCG_Lite and the OSC to initialize the OSC. The OSC should be configured based on the board design.

Chapter 24
Secure Digital Card/Embedded MultiMedia Card (CARD)

24.1 Overview

The MCUXpresso SDK provides a driver to access the Secure Digital Card and Embedded MultiMedia Card based on the SDHC driver.

Function groups

This function group implements the SD card functional API.

This function group implements the MMC card functional API.

Typical use case

```
/* Initialize SDHC. */
sdhcConfig->cardDetectDat3 = false;
sdhcConfig->endianMode = kSDHC_EndianModeLittle;
sdhcConfig->dmaMode = kSDHC_DmaModeAdma2;
sdhcConfig->readWatermarkLevel = 0x80U;
sdhcConfig->writeWatermarkLevel = 0x80U;
SDHC_Init(BOARD_SDHC_BASEADDR, sdhcConfig);

/* Save host information. */
card->host.base = BOARD_SDHC_BASEADDR;
card->host.sourceClock_Hz = CLOCK_GetFreq(BOARD_SDHC_CLKSRC);
card->host.transfer = SDHC_TransferFunction;

/* Init card. */
if (SD_Init(card))
{
    PRINTF("\r\nSD card init failed.\r\n");
}

while (true)
{
    if (kStatus_Success != SD_WriteBlocks(card, g_dataWrite, DATA_BLOCK_START,
      DATA_BLOCK_COUNT))
    {
        PRINTF("Write multiple data blocks failed.\r\n");
    }
    if (kStatus_Success != SD_ReadBlocks(card, g_dataRead, DATA_BLOCK_START, DATA_BLOCK_COUNT)
      )
    {
        PRINTF("Read multiple data blocks failed.\r\n");
    }

    if (kStatus_Success != SD_EraseBlocks(card, DATA_BLOCK_START, DATA_BLOCK_COUNT))
    {
        PRINTF("Erase multiple data blocks failed.\r\n");
    }
}

SD_Deinit(card);


/* Initialize SDHC. */
```

```
sdhcConfig->cardDetectDat3 = false;
sdhcConfig->endianMode = kSDHC_EndianModeLittle;
sdhcConfig->dmaMode = kSDHC_DmaModeAdma2;
sdhcConfig->readWatermarkLevel = 0x80U;
sdhcConfig->writeWatermarkLevel = 0x80U;
SDHC_Init(BOARD_SDHC_BASEADDR, sdhcConfig);

/* Save host information. */
card->host.base = BOARD_SDHC_BASEADDR;
card->host.sourceClock_Hz = CLOCK_GetFreq(BOARD_SDHC_CLKSRC);
card->host.transfer = SDHC_TransferFunction;

/* Init card. */
if (MMC_Init(card))
{
    PRINTF("\n MMC card init failed \n");
}

while (true)
{
    if (kStatus_Success != MMC_WriteBlocks(card, g_dataWrite, DATA_BLOCK_START,
      DATA_BLOCK_COUNT))
    {
        PRINTF("Write multiple data blocks failed.\r\n");
    }
    if (kStatus_Success != MMC_ReadBlocks(card, g_dataRead, DATA_BLOCK_START,
      DATA_BLOCK_COUNT))
    {
        PRINTF("Read multiple data blocks failed.\r\n");
    }
}

MMC_Deinit(card);
```

Data Structures

- struct sd_card_t
  SD card state. More...
- struct sdio_card_t
  SDIO card state. More...
- struct mmc_card_t
  SD card state. More...
- struct mmc_boot_config_t
  MMC card boot configuration definition. More...

Macros

- #define FSL_SDMMC_DRIVER_VERSION (MAKE_VERSION(2U, 1U, 2U)) /*2.1.2*/
  Driver version.
- #define FSL_SDMMC_DEFAULT_BLOCK_SIZE (512U)
  Default block size.
- #define HOST_NOT_SUPPORT 0U
  use this define to indicate the host not support feature
- #define HOST_SUPPORT 1U
  use this define to indicate the host support feature

Enumerations

- enum _sdmmc_status {
kStatus_SDMMC_NotSupportYet = MAKE_STATUS(kStatusGroup_SDMMC, 0U),
kStatus_SDMMC_TransferFailed = MAKE_STATUS(kStatusGroup_SDMMC, 1U),
kStatus_SDMMC_SetCardBlockSizeFailed = MAKE_STATUS(kStatusGroup_SDMMC, 2U),
kStatus_SDMMC_HostNotSupport = MAKE_STATUS(kStatusGroup_SDMMC, 3U),
kStatus_SDMMC_CardNotSupport = MAKE_STATUS(kStatusGroup_SDMMC, 4U),
kStatus_SDMMC_AllSendCidFailed = MAKE_STATUS(kStatusGroup_SDMMC, 5U),
kStatus_SDMMC_SendRelativeAddressFailed = MAKE_STATUS(kStatusGroup_SDMMC, 6U),
kStatus_SDMMC_SendCsdFailed = MAKE_STATUS(kStatusGroup_SDMMC, 7U),
kStatus_SDMMC_SelectCardFailed = MAKE_STATUS(kStatusGroup_SDMMC, 8U),
kStatus_SDMMC_SendScrFailed = MAKE_STATUS(kStatusGroup_SDMMC, 9U),
kStatus_SDMMC_SetDataBusWidthFailed = MAKE_STATUS(kStatusGroup_SDMMC, 10U),
kStatus_SDMMC_GoIdleFailed = MAKE_STATUS(kStatusGroup_SDMMC, 11U),
kStatus_SDMMC_HandShakeOperationConditionFailed,
kStatus_SDMMC_SendApplicationCommandFailed,
kStatus_SDMMC_SwitchFailed = MAKE_STATUS(kStatusGroup_SDMMC, 14U),
kStatus_SDMMC_StopTransmissionFailed = MAKE_STATUS(kStatusGroup_SDMMC, 15U),
kStatus_SDMMC_WaitWriteCompleteFailed = MAKE_STATUS(kStatusGroup_SDMMC, 16U),
kStatus_SDMMC_SetBlockCountFailed = MAKE_STATUS(kStatusGroup_SDMMC, 17U),
kStatus_SDMMC_SetRelativeAddressFailed = MAKE_STATUS(kStatusGroup_SDMMC, 18U),
kStatus_SDMMC_SwitchBusTimingFailed = MAKE_STATUS(kStatusGroup_SDMMC, 19U),
kStatus_SDMMC_SendExtendedCsdFailed = MAKE_STATUS(kStatusGroup_SDMMC, 20U),
kStatus_SDMMC_ConfigureBootFailed = MAKE_STATUS(kStatusGroup_SDMMC, 21U),
kStatus_SDMMC_ConfigureExtendedCsdFailed = MAKE_STATUS(kStatusGroup_SDMMC, 22-U),
kStatus_SDMMC_EnableHighCapacityEraseFailed,
kStatus_SDMMC_SendTestPatternFailed = MAKE_STATUS(kStatusGroup_SDMMC, 24U),
kStatus_SDMMC_ReceiveTestPatternFailed = MAKE_STATUS(kStatusGroup_SDMMC, 25U),
kStatus_SDMMC_SDIO_ResponseError = MAKE_STATUS(kStatusGroup_SDMMC, 26U),
kStatus_SDMMC_SDIO_InvalidArgument,
kStatus_SDMMC_SDIO_SendOperationConditionFail,
kStatus_SDMMC_InvalidVoltage = MAKE_STATUS(kStatusGroup_SDMMC, 29U),
kStatus_SDMMC_SDIO_SwitchHighSpeedFail = MAKE_STATUS(kStatusGroup_SDMMC, 30-U),
kStatus_SDMMC_SDIO_ReadCISFail = MAKE_STATUS(kStatusGroup_SDMMC, 31U),
kStatus_SDMMC_SDIO_InvalidCard = MAKE_STATUS(kStatusGroup_SDMMC, 32U),
kStatus_SDMMC_TuningFail = MAKE_STATUS(kStatusGroup_SDMMC, 33U),
kStatus_SDMMC_SwitchVoltageFail = MAKE_STATUS(kStatusGroup_SDMMC, 34U),
kStatus_SDMMC_ReTuningRequest = MAKE_STATUS(kStatusGroup_SDMMC, 35U),
kStatus_SDMMC_SetDriverStrengthFail = MAKE_STATUS(kStatusGroup_SDMMC, 36U),
kStatus_SDMMC_SetPowerClassFail = MAKE_STATUS(kStatusGroup_SDMMC, 37U) }
SD/MMC card API's running status.
- enum _sd_card_flag {

kSD_SupportHighCapacityFlag = (1U << 1U),
kSD_Support4BitWidthFlag = (1U << 2U),
kSD_SupportSdhcFlag = (1U << 3U),
kSD_SupportSdxcFlag = (1U << 4U),
kSD_SupportVoltage180v = (1U << 5U),
kSD_SupportSetBlockCountCmd = (1U << 6U),
kSD_SupportSpeedClassControlCmd = (1U << 7U) }
SD card flags.
- enum _mmc_card_flag {
kMMC_SupportHighSpeed26MHZFlag = (1U << 0U),
kMMC_SupportHighSpeed52MHZFlag = (1U << 1U),
kMMC_SupportHighSpeedDDR52MHZ180V300VFlag = (1 << 2U),
kMMC_SupportHighSpeedDDR52MHZ120VFlag = (1 << 3U),
kMMC_SupportHS200200MHZ180VFlag = (1 << 4U),
kMMC_SupportHS200200MHZ120VFlag = (1 << 5U),
kMMC_SupportHS400DDR200MHZ180VFlag = (1 << 6U),
kMMC_SupportHS400DDR200MHZ120VFlag = (1 << 7U),
kMMC_SupportHighCapacityFlag = (1U << 8U),
kMMC_SupportAlternateBootFlag = (1U << 9U),
kMMC_SupportDDRBootFlag = (1U << 10U),
kMMC_SupportHighSpeedBootFlag = (1U << 11U),
kMMC_DataBusWidth4BitFlag = (1U << 12U),
kMMC_DataBusWidth8BitFlag = (1U << 13U),
kMMC_DataBusWidth1BitFlag = (1U << 14U) }
MMC card flags.
- enum card_operation_voltage_t {
kCARD_OperationVoltageNone = 0U,
kCARD_OperationVoltage330V = 1U,
kCARD_OperationVoltage300V = 2U,
kCARD_OperationVoltage180V = 3U }
card operation voltage
- enum _host_endian_mode {
kHOST_EndianModeBig = 0U,
kHOST_EndianModeHalfWordBig = 1U,
kHOST_EndianModeLittle = 2U }
host Endian mode corresponding to driver define

SDCARD Function

- status_t SD_Init (sd_card_t ∗card)
Initializes the card on a specific host controller.
- void SD_Deinit (sd_card_t ∗card)
Deinitializes the card.
- bool SD_CheckReadOnly (sd_card_t ∗card)
Checks whether the card is write-protected.
- status_t SD_ReadBlocks (sd_card_t ∗card, uint8_t ∗buffer, uint32_t startBlock, uint32_t blockCount)

Reads blocks from the specific card.
- status_t SD_WriteBlocks (sd_card_t *card, const uint8_t *buffer, uint32_t startBlock, uint32_t blockCount)
  Writes blocks of data to the specific card.
- status_t SD_EraseBlocks (sd_card_t *card, uint32_t startBlock, uint32_t blockCount)
  Erases blocks of the specific card.

MMCCARD Function

- status_t MMC_Init (mmc_card_t *card)
  Initializes the MMC card.
- void MMC_Deinit (mmc_card_t *card)
  Deinitializes the card.
- bool MMC_CheckReadOnly (mmc_card_t *card)
  Checks if the card is read-only.
- status_t MMC_ReadBlocks (mmc_card_t *card, uint8_t *buffer, uint32_t startBlock, uint32_-t blockCount)
  Reads data blocks from the card.
- status_t MMC_WriteBlocks (mmc_card_t *card, const uint8_t *buffer, uint32_t startBlock, uint32-_t blockCount)
  Writes data blocks to the card.
- status_t MMC_EraseGroups (mmc_card_t *card, uint32_t startGroup, uint32_t endGroup)
  Erases groups of the card.
- status_t MMC_SelectPartition (mmc_card_t *card, mmc_access_partition_t partitionNumber)
  Selects the partition to access.
- status_t MMC_SetBootConfig (mmc_card_t *card, const mmc_boot_config_t *config)
  Configures the boot activity of the card.
- status_t SDIO_CardInActive (sdio_card_t *card)
  set SDIO card to inactive state
- status_t SDIO_IO_Write_Direct (sdio_card_t *card, sdio_func_num_t func, uint32_t regAddr, uint8_t *data, bool raw)
  IO direct write transfer function.
- status_t SDIO_IO_Read_Direct (sdio_card_t *card, sdio_func_num_t func, uint32_t regAddr, uint8_t *data)
  IO direct read transfer function.
- status_t SDIO_IO_Write_Extended (sdio_card_t *card, sdio_func_num_t func, uint32_t regAddr, uint8_t *buffer, uint32_t count, uint32_t flags)
  IO extended write transfer function.
- status_t SDIO_IO_Read_Extended (sdio_card_t *card, sdio_func_num_t func, uint32_t regAddr, uint8_t *buffer, uint32_t count, uint32_t flags)
  IO extended read transfer function.
- status_t SDIO_GetCardCapability (sdio_card_t *card, sdio_func_num_t func)
  get SDIO card capability
- status_t SDIO_SetBlockSize (sdio_card_t *card, sdio_func_num_t func, uint32_t blockSize)
  set SDIO card block size
- status_t SDIO_CardReset (sdio_card_t *card)
  set SDIO card reset
- status_t SDIO_SetDataBusWidth (sdio_card_t *card, sdio_bus_width_t busWidth)
  set SDIO card data bus width
- status_t SDIO_SwitchToHighSpeed (sdio_card_t *card)

switch the card to high speed
- status_t SDIO_ReadCIS (sdio_card_t ∗card, sdio_func_num_t func, const uint32_t ∗tupleList, uint32_t tupleNum)
  read SDIO card CIS for each function
- status_t SDIO_Init (sdio_card_t ∗card)
  SDIO card init function.
- status_t SDIO_EnableIOInterrupt (sdio_card_t ∗card, sdio_func_num_t func, bool enable)
  enable IO interrupt
- status_t SDIO_EnableIO (sdio_card_t ∗card, sdio_func_num_t func, bool enable)
  enable IO and wait IO ready
- status_t SDIO_SelectIO (sdio_card_t ∗card, sdio_func_num_t func)
  select IO
- status_t SDIO_AbortIO (sdio_card_t ∗card, sdio_func_num_t func)
  Abort IO transfer.
- void SDIO_DeInit (sdio_card_t ∗card)
  SDIO card deinit.

adaptor function

- static status_t HOST_NotSupport (void ∗parameter)
  host not support function, this function is used for host not support feature
- status_t CardInsertDetect (HOST_TYPE ∗hostBase)
  Detect card insert, only need for SD cases.
- status_t HOST_Init (void ∗host)
  Init host controller.
- void HOST_Deinit (void ∗host)
  Deinit host controller.

24.2 Data Structure Documentation

24.2.1 struct sd_card_t

Define the card structure including the necessary fields to identify and describe the card.

Data Fields

- HOST_CONFIG host
  Host information.
- bool isHostReady
  use this flag to indicate if need host re-init or not
- uint32_t busClock_Hz
  SD bus clock frequency united in Hz.
- uint32_t relativeAddress
  Relative address of the card.
- uint32_t version
  Card version.
- uint32_t flags
  Flags in _sd_card_flag.
- uint32_t rawCid [4U]

Raw CID content.
- uint32_t rawCsd [4U]
  Raw CSD content.
- uint32_t rawScr [2U]
  Raw CSD content.
- uint32_t ocr
  Raw OCR content.
- sd_cid_t cid
  CID.
- sd_csd_t csd
  CSD.
- sd_scr_t scr
  SCR.
- uint32_t blockCount
  Card total block number.
- uint32_t blockSize
  Card block size.
- sd_timing_mode_t currentTiming
  current timing mode
- sd_driver_strength_t driverStrength
  driver strength
- sd_max_current_t maxCurrent
  card current limit
- card_operation_voltage_t operationVoltage
  card operation voltage

24.2.2 struct sdio_card_t

Define the card structure including the necessary fields to identify and describe the card.

Data Fields

- HOST_CONFIG host
  Host information.
- bool isHostReady
  use this flag to indicate if need host re-init or not
- bool memPresentFlag
  indicate if memory present
- uint32_t busClock_Hz
  SD bus clock frequency united in Hz.
- uint32_t relativeAddress
  Relative address of the card.
- uint8_t sdVersion
  SD version.
- uint8_t sdioVersion
  SDIO version.
- uint8_t cccrVersioin
  CCCR version.

- uint8_t ioTotalNumber
  total number of IO function
- uint32_t cccrflags
  Flags in _sd_card_flag.
- uint32_t io0blockSize
  record the io0 block size
- uint32_t ocr
  Raw OCR content, only 24bit avalible for SDIO card.
- uint32_t commonCISPointer
  point to common CIS
- sdio_fbr_t ioFBR [7U]
  FBR table.
- sdio_common_cis_t commonCIS
  CIS table.
- sdio_func_cis_t funcCIS [7U]
  function CIS table

24.2.3 struct mmc_card_t

Define the card structure including the necessary fields to identify and describe the card.

Data Fields

- HOST_CONFIG host
  Host information.
- bool isHostReady
  use this flag to indicate if need host re-init or not
- uint32_t busClock_Hz
  MMC bus clock united in Hz.
- uint32_t relativeAddress
  Relative address of the card.
- bool enablePreDefinedBlockCount
  Enable PRE-DEFINED block count when read/write.
- uint32_t flags
  Capability flag in _mmc_card_flag.
- uint32_t rawCid [4U]
  Raw CID content.
- uint32_t rawCsd [4U]
  Raw CSD content.
- uint32_t rawExtendedCsd [MMC_EXTENDED_CSD_BYTES/4U]
  Raw MMC Extended CSD content.
- uint32_t ocr
  Raw OCR content.
- mmc_cid_t cid
  CID.
- mmc_csd_t csd
  CSD.
- mmc_extended_csd_t extendedCsd

Extended CSD.
- uint32_t blockSize
  Card block size.
- uint32_t userPartitionBlocks
  Card total block number in user partition.
- uint32_t bootPartitionBlocks
  Boot partition size united as block size.
- uint32_t eraseGroupBlocks
  Erase group size united as block size.
- mmc_access_partition_t currentPartition
  Current access partition.
- mmc_voltage_window_t hostVoltageWindow
  Host voltage window.
- mmc_high_speed_timing_t currentTiming
  indicate the current host timing mode

24.2.4 struct mmc_boot_config_t

Data Fields

- bool enableBootAck
  Enable boot ACK.
- mmc_boot_partition_enable_t bootPartition
  Boot partition.
- bool retainBootBusWidth
  If retain boot bus width.
- mmc_data_bus_width_t bootDataBusWidth
  Boot data bus width.

24.3 Macro Definition Documentation

24.3.1 #define FSL_SDMMC_DRIVER_VERSION (MAKE_VERSION(2U, 1U, 2U)) /*2.1.2*/

24.4 Enumeration Type Documentation

24.4.1 enum _sdmmc_status

Enumerator

kStatus_SDMMC_NotSupportYet Haven't supported.
kStatus_SDMMC_TransferFailed Send command failed.
kStatus_SDMMC_SetCardBlockSizeFailed Set block size failed.
kStatus_SDMMC_HostNotSupport Host doesn't support.
kStatus_SDMMC_CardNotSupport Card doesn't support.
kStatus_SDMMC_AllSendCidFailed Send CID failed.
kStatus_SDMMC_SendRelativeAddressFailed Send relative address failed.

kStatus_SDMMC_SendCsdFailed Send CSD failed.
kStatus_SDMMC_SelectCardFailed Select card failed.
kStatus_SDMMC_SendScrFailed Send SCR failed.
kStatus_SDMMC_SetDataBusWidthFailed Set bus width failed.
kStatus_SDMMC_GoIdleFailed Go idle failed.
kStatus_SDMMC_HandShakeOperationConditionFailed Send Operation Condition failed.
kStatus_SDMMC_SendApplicationCommandFailed Send application command failed.
kStatus_SDMMC_SwitchFailed Switch command failed.
kStatus_SDMMC_StopTransmissionFailed Stop transmission failed.
kStatus_SDMMC_WaitWriteCompleteFailed Wait write complete failed.
kStatus_SDMMC_SetBlockCountFailed Set block count failed.
kStatus_SDMMC_SetRelativeAddressFailed Set relative address failed.
kStatus_SDMMC_SwitchBusTimingFailed Switch high speed failed.
kStatus_SDMMC_SendExtendedCsdFailed Send EXT_CSD failed.
kStatus_SDMMC_ConfigureBootFailed Configure boot failed.
kStatus_SDMMC_ConfigureExtendedCsdFailed Configure EXT_CSD failed.
kStatus_SDMMC_EnableHighCapacityEraseFailed Enable high capacity erase failed.
kStatus_SDMMC_SendTestPatternFailed Send test pattern failed.
kStatus_SDMMC_ReceiveTestPatternFailed Receive test pattern failed.
kStatus_SDMMC_SDIO_ResponseError sdio response error
kStatus_SDMMC_SDIO_InvalidArgument sdio invalid argument response error
kStatus_SDMMC_SDIO_SendOperationConditionFail sdio send operation condition fail
kStatus_SDMMC_InvalidVoltage invaild voltage
kStatus_SDMMC_SDIO_SwitchHighSpeedFail switch to high speed fail
kStatus_SDMMC_SDIO_ReadCISFail read CIS fail
kStatus_SDMMC_SDIO_InvalidCard invaild SDIO card
kStatus_SDMMC_TuningFail tuning fail
kStatus_SDMMC_SwitchVoltageFail switch voltage fail
kStatus_SDMMC_ReTuningRequest retuning request
kStatus_SDMMC_SetDriverStrengthFail set driver strength fail
kStatus_SDMMC_SetPowerClassFail set power class fail

24.4.2 enum _sd_card_flag

Enumerator

kSD_SupportHighCapacityFlag Support high capacity.
kSD_Support4BitWidthFlag Support 4-bit data width.
kSD_SupportSdhcFlag Card is SDHC.
kSD_SupportSdxcFlag Card is SDXC.
kSD_SupportVoltage180v card support 1.8v voltage
kSD_SupportSetBlockCountCmd card support cmd23 flag
kSD_SupportSpeedClassControlCmd card support speed class control flag

24.4.3 enum _mmc_card_flag

Enumerator

kMMC_SupportHighSpeed26MHZFlag Support high speed 26MHZ.
kMMC_SupportHighSpeed52MHZFlag Support high speed 52MHZ.
kMMC_SupportHighSpeedDDR52MHZ180V300VFlag ddr 52MHZ 1.8V or 3.0V
kMMC_SupportHighSpeedDDR52MHZ120VFlag DDR 52MHZ 1.2V.
kMMC_SupportHS200200MHZ180VFlag HS200 ,200MHZ,1.8V.
kMMC_SupportHS200200MHZ120VFlag HS200, 200MHZ, 1.2V.
kMMC_SupportHS400DDR200MHZ180VFlag HS400, DDR, 200MHZ,1.8V.
kMMC_SupportHS400DDR200MHZ120VFlag HS400, DDR, 200MHZ,1.2V.
kMMC_SupportHighCapacityFlag Support high capacity.
kMMC_SupportAlternateBootFlag Support alternate boot.
kMMC_SupportDDRBootFlag support DDR boot flag
kMMC_SupportHighSpeedBootFlag support high speed boot flag
kMMC_DataBusWidth4BitFlag current data bus is 4 bit mode
kMMC_DataBusWidth8BitFlag current data bus is 8 bit mode
kMMC_DataBusWidth1BitFlag current data bus is 1 bit mode

24.4.4 enum card_operation_voltage_t

Enumerator

kCARD_OperationVoltageNone indicate current voltage setting is not setting bu suser
kCARD_OperationVoltage330V card operation voltage around 3.3v
kCARD_OperationVoltage300V card operation voltage around 3.0v
kCARD_OperationVoltage180V card operation voltage around 31.8v

24.4.5 enum _host_endian_mode

Enumerator

kHOST_EndianModeBig Big endian mode.
kHOST_EndianModeHalfWordBig Half word big endian mode.
kHOST_EndianModeLittle Little endian mode.

24.5 Function Documentation

24.5.1 status_t SD_Init (sd_card_t ∗ *card*)

This function initializes the card on a specific host controller.

Parameters

card	Card descriptor.

Return values

kStatus_SDMMC_Go-IdleFailed	Go idle failed.
kStatus_SDMMC_Not-SupportYet	Card not support.
kStatus_SDMMC_Send-OperationCondition-Failed	Send operation condition failed.
kStatus_SDMMC_All-SendCidFailed	Send CID failed.
kStatus_SDMMC_Send-RelativeAddressFailed	Send relative address failed.
kStatus_SDMMC_Send-CsdFailed	Send CSD failed.
kStatus_SDMMC_Select-CardFailed	Send SELECT_CARD command failed.
kStatus_SDMMC_Send-ScrFailed	Send SCR failed.
kStatus_SDMMC_SetBus-WidthFailed	Set bus width failed.
kStatus_SDMMC_Switch-HighSpeedFailed	Switch high speed failed.
kStatus_SDMMC_Set-CardBlockSizeFailed	Set card block size failed.
kStatus_Success	Operate successfully.

24.5.2 void SD_Deinit (sd_card_t * *card*)

This function deinitializes the specific card.

Parameters

card	Card descriptor.

24.5.3 bool SD_CheckReadOnly (sd_card_t * *card*)

This function checks if the card is write-protected via the CSD register.

Parameters

card	The specific card.

Return values

true	Card is read only.
false	Card isn't read only.

24.5.4 status_t SD_ReadBlocks (sd_card_t * *card,* uint8_t * *buffer,* uint32_t *startBlock,* uint32_t *blockCount*)

This function reads blocks from the specific card with default block size defined by the SDHC_CARD_-DEFAULT_BLOCK_SIZE.

Parameters

card	Card descriptor.
buffer	The buffer to save the data read from card.
startBlock	The start block index.
blockCount	The number of blocks to read.

Return values

kStatus_InvalidArgument	Invalid argument.
kStatus_SDMMC_Card-NotSupport	Card not support.

kStatus_SDMMC_Not-SupportYet	Not support now.
kStatus_SDMMC_Wait-WriteCompleteFailed	Send status failed.
kStatus_SDMMC_-TransferFailed	Transfer failed.
kStatus_SDMMC_Stop-TransmissionFailed	Stop transmission failed.
kStatus_Success	Operate successfully.

24.5.5 status_t SD_WriteBlocks (sd_card_t * *card,* const uint8_t * *buffer,* uint32_t *startBlock,* uint32_t *blockCount*)

This function writes blocks to the specific card with default block size 512 bytes.

Parameters

card	Card descriptor.
buffer	The buffer holding the data to be written to the card.
startBlock	The start block index.
blockCount	The number of blocks to write.

Return values

kStatus_InvalidArgument	Invalid argument.
kStatus_SDMMC_Not-SupportYet	Not support now.
kStatus_SDMMC_Card-NotSupport	Card not support.
kStatus_SDMMC_Wait-WriteCompleteFailed	Send status failed.
kStatus_SDMMC_-TransferFailed	Transfer failed.

kStatus_SDMMC_Stop-TransmissionFailed	Stop transmission failed.
kStatus_Success	Operate successfully.

24.5.6 status_t SD_EraseBlocks (sd_card_t * *card*, uint32_t *startBlock*, uint32_t *blockCount*)

This function erases blocks of the specific card with default block size 512 bytes.

Parameters

card	Card descriptor.
startBlock	The start block index.
blockCount	The number of blocks to erase.

Return values

kStatus_InvalidArgument	Invalid argument.
kStatus_SDMMC_Wait-WriteCompleteFailed	Send status failed.
kStatus_SDMMC_-TransferFailed	Transfer failed.
kStatus_SDMMC_Wait-WriteCompleteFailed	Send status failed.
kStatus_Success	Operate successfully.

24.5.7 status_t MMC_Init (mmc_card_t * *card*)

Parameters

card	Card descriptor.

Return values

kStatus_SDMMC_GoIdleFailed	Go idle failed.
kStatus_SDMMC_SendOperationConditionFailed	Send operation condition failed.
kStatus_SDMMC_AllSendCidFailed	Send CID failed.
kStatus_SDMMC_SetRelativeAddressFailed	Set relative address failed.
kStatus_SDMMC_SendCsdFailed	Send CSD failed.
kStatus_SDMMC_CardNotSupport	Card not support.
kStatus_SDMMC_SelectCardFailed	Send SELECT_CARD command failed.
kStatus_SDMMC_SendExtendedCsdFailed	Send EXT_CSD failed.
kStatus_SDMMC_SetBusWidthFailed	Set bus width failed.
kStatus_SDMMC_SwitchHighSpeedFailed	Switch high speed failed.
kStatus_SDMMC_SetCardBlockSizeFailed	Set card block size failed.
kStatus_Success	Operate successfully.

24.5.8 void MMC_Deinit (mmc_card_t * *card*)

Parameters

card	Card descriptor.

24.5.9 bool MMC_CheckReadOnly (mmc_card_t * *card*)

Parameters

card	Card descriptor.

Return values

true	Card is read only.
false	Card isn't read only.

24.5.10 status_t MMC_ReadBlocks (mmc_card_t ∗ *card*, uint8_t ∗ *buffer*, uint32_t *startBlock*, uint32_t *blockCount*)

Parameters

card	Card descriptor.
buffer	The buffer to save data.
startBlock	The start block index.
blockCount	The number of blocks to read.

Return values

kStatus_InvalidArgument	Invalid argument.
kStatus_SDMMC_CardNotSupport	Card not support.
kStatus_SDMMC_SetBlockCountFailed	Set block count failed.
kStatus_SDMMC_TransferFailed	Transfer failed.
kStatus_SDMMC_StopTransmissionFailed	Stop transmission failed.
kStatus_Success	Operate successfully.

24.5.11 status_t MMC_WriteBlocks (mmc_card_t ∗ *card*, const uint8_t ∗ *buffer*, uint32_t *startBlock*, uint32_t *blockCount*)

Parameters

card	Card descriptor.
buffer	The buffer to save data blocks.
startBlock	Start block number to write.
blockCount	Block count.

Return values

kStatus_InvalidArgument	Invalid argument.
kStatus_SDMMC_NotSupportYet	Not support now.
kStatus_SDMMC_SetBlockCountFailed	Set block count failed.
kStatus_SDMMC_WaitWriteCompleteFailed	Send status failed.
kStatus_SDMMC_TransferFailed	Transfer failed.
kStatus_SDMMC_StopTransmissionFailed	Stop transmission failed.
kStatus_Success	Operate successfully.

24.5.12 status_t MMC_EraseGroups (mmc_card_t ∗ *card,* uint32_t *startGroup,* uint32_t *endGroup*)

Erase group is the smallest erase unit in MMC card. The erase range is [startGroup, endGroup].

Parameters

card	Card descriptor.
startGroup	Start group number.
endGroup	End group number.

Return values

kStatus_InvalidArgument	Invalid argument.
kStatus_SDMMC_Wait-WriteCompleteFailed	Send status failed.
kStatus_SDMMC_-TransferFailed	Transfer failed.
kStatus_Success	Operate successfully.

24.5.13 status_t MMC_SelectPartition (mmc_card_t ∗ *card,* mmc_access_partition_t *partitionNumber*)

Parameters

card	Card descriptor.
partition-Number	The partition number.

Return values

kStatus_SDMMC_-ConfigureExtendedCsd-Failed	Configure EXT_CSD failed.
kStatus_Success	Operate successfully.

24.5.14 status_t MMC_SetBootConfig (mmc_card_t ∗ *card,* const mmc_boot_config_t ∗ *config*)

Parameters

card	Card descriptor.
config	Boot configuration structure.

Return values

kStatus_SDMMC_NotSupportYet	Not support now.
kStatus_SDMMC_ConfigureExtendedCsdFailed	Configure EXT_CSD failed.
kStatus_SDMMC_ConfigureBootFailed	Configure boot failed.
kStatus_Success	Operate successfully.

24.5.15 status_t SDIO_CardInActive (sdio_card_t * *card*)

Parameters

card	Card descriptor.

Return values

kStatus_SDMMC_TransferFailed	
kStatus_Success	

24.5.16 status_t SDIO_IO_Write_Direct (sdio_card_t * *card,* sdio_func_num_t *func,* uint32_t *regAddr,* uint8_t * *data,* bool *raw*)

Parameters

card	Card descriptor.
function	IO numner
register	address
the	data pinter to write
raw	flag, indicate read after write or write only

Return values

kStatus_SDMMC_-TransferFailed	
kStatus_Success	

24.5.17 status_t SDIO_IO_Read_Direct (sdio_card_t * *card,* sdio_func_num_t *func,* uint32_t *regAddr,* uint8_t * *data*)

Parameters

card	Card descriptor.
function	IO number
register	address
data	pointer to read

Return values

kStatus_SDMMC_-TransferFailed	
kStatus_Success	

24.5.18 status_t SDIO_IO_Write_Extended (sdio_card_t * *card,* sdio_func_num_t *func,* uint32_t *regAddr,* uint8_t * *buffer,* uint32_t *count,* uint32_t *flags*)

Parameters

card	Card descriptor.
function	IO number
register	address
data	buffer to write
data	count
write	flags

Return values

kStatus_SDMMC_-TransferFailed	
kStatus_SDMMC_SDIO-_InvalidArgument	
kStatus_Success	

24.5.19 status_t SDIO_IO_Read_Extended (sdio_card_t * *card,* sdio_func_num_t *func,* uint32_t *regAddr,* uint8_t * *buffer,* uint32_t *count,* uint32_t *flags*)

Parameters

card	Card descriptor.
function	IO number
register	address
data	buffer to read
data	count
write	flags

Return values

kStatus_SDMMC_-TransferFailed	
kStatus_SDMMC_SDIO-_InvalidArgument	
kStatus_Success	

24.5.20 status_t SDIO_GetCardCapability (sdio_card_t * *card,* sdio_func_num_t *func*)

Parameters

card	Card descriptor.
function	IO number

Return values

kStatus_SDMMC_-TransferFailed	
kStatus_Success	

24.5.21 status_t SDIO_SetBlockSize (sdio_card_t * *card,* sdio_func_num_t *func,* uint32_t *blockSize*)

Parameters

card	Card descriptor.
function	io number
block	size

Return values

kStatus_SDMMC_Set-CardBlockSizeFailed	
kStatus_SDMMC_SDIO-_InvalidArgument	
kStatus_Success	

24.5.22 status_t SDIO_CardReset (sdio_card_t * *card*)

Parameters

card	Card descriptor.

Return values

kStatus_SDMMC_-TransferFailed	
kStatus_Success	

24.5.23 status_t SDIO_SetDataBusWidth (sdio_card_t * *card,* sdio_bus_width_t *busWidth*)

Parameters

card	Card descriptor.
data	bus width

Return values

kStatus_SDMMC_-TransferFailed	
kStatus_Success	

24.5.24 status_t SDIO_SwitchToHighSpeed (sdio_card_t * *card*)

Parameters

card	Card descriptor.

Return values

kStatus_SDMMC_-TransferFailed	
kStatus_SDMMC_SDIO-_SwitchHighSpeedFail	
kStatus_Success	

24.5.25 status_t SDIO_ReadCIS (sdio_card_t * *card,* sdio_func_num_t *func,* const uint32_t * *tupleList,* uint32_t *tupleNum*)

Parameters

card	Card descriptor.
function	io number
tuple	code list
tuple	code number

Return values

kStatus_SDMMC_SDIO-_ReadCISFail	
kStatus_SDMMC_-TransferFailed	
kStatus_Success	

24.5.26 status_t SDIO_Init (sdio_card_t * *card*)

Parameters

card	Card descriptor.

Return values

kStatus_SDMMC_Go-IdleFailed	
kStatus_SDMMC_Hand-ShakeOperation-ConditionFailed	
kStatus_SDMMC_SDIO-_InvalidCard	
kStatus_SDMMC_SDIO-_InvalidVoltage	
kStatus_SDMMC_Send-RelativeAddressFailed	

kStatus_SDMMC_Select-CardFailed	
kStatus_SDMMC_SDIO-_SwitchHighSpeedFail	
kStatus_SDMMC_SDIO-_ReadCISFail	
kStatus_SDMMC_-TransferFailed	
kStatus_Success	

24.5.27 status_t SDIO_EnableIOInterrupt (sdio_card_t * *card,* sdio_func_num_t *func,* bool *enable*)

Parameters

card	Card descriptor.
function	IO number
enable/disable	flag

Return values

kStatus_SDMMC_-TransferFailed	
kStatus_Success	

24.5.28 status_t SDIO_EnableIO (sdio_card_t * *card,* sdio_func_num_t *func,* bool *enable*)

Parameters

card	Card descriptor.
function	IO number

enable/disable	flag

Return values

kStatus_SDMMC_-TransferFailed	
kStatus_Success	

24.5.29 status_t SDIO_SelectIO (sdio_card_t * *card*, sdio_func_num_t *func*)

Parameters

card	Card descriptor.
function	IO number

Return values

kStatus_SDMMC_-TransferFailed	
kStatus_Success	

24.5.30 status_t SDIO_AbortIO (sdio_card_t * *card*, sdio_func_num_t *func*)

Parameters

card	Card descriptor.
function	IO number

Return values

kStatus_SDMMC_-TransferFailed	
kStatus_Success	

24.5.31 void SDIO_DeInit (sdio_card_t * *card*)

Parameters

card	Card descriptor.

24.5.32 static status_t HOST_NotSupport (void * *parameter*) [inline], [static]

Parameters

void	parameter ,used to avoid build warning

Return values

kStatus_Fail,host	do not suppport

24.5.33 status_t CardInsertDetect (HOST_TYPE * *hostBase*)

Parameters

hostBase	the pointer to host base address

Return values

kStatus_Success	detect card insert
kStatus_Fail	card insert event fail

24.5.34 status_t HOST_Init (void * *host*)

Parameters

host	the pointer to host structure in card structure.

Return values

kStatus_Success	host init success
kStatus_Fail	event fail

24.5.35 void HOST_Deinit (void * *host*)

Parameters

host	the pointer to host structure in card structure.

Chapter 25
SPI based Secure Digital Card (SDSPI)

25.1 Overview

The MCUXpresso SDK provides a driver to access the Secure Digital Card based on the SPI driver.

Function groups

This function group implements the SD card functional API in the SPI mode.

Typical use case

```
/* SPI_Init(). */

/* Register the SDSPI driver callback. */

/* Initializes card. */
if (kStatus_Success != SDSPI_Init(card))
{
    SDSPI_Deinit(card)
    return;
}

/* Read/Write card */
memset(g_testWriteBuffer, 0x17U, sizeof(g_testWriteBuffer));

while (true)
{
    memset(g_testReadBuffer, 0U, sizeof(g_testReadBuffer));

    SDSPI_WriteBlocks(card, g_testWriteBuffer, TEST_START_BLOCK, TEST_BLOCK_COUNT);

    SDSPI_ReadBlocks(card, g_testReadBuffer, TEST_START_BLOCK, TEST_BLOCK_COUNT);

    if (memcmp(g_testReadBuffer, g_testReadBuffer, sizeof(g_testWriteBuffer)))
    {
        break;
    }
}
```

Data Structures

- struct sdspi_command_t
    SDSPI command. More...
- struct sdspi_host_t
    SDSPI host state. More...
- struct sdspi_card_t
    SD Card Structure. More...

Enumerations

- enum _sdspi_status {
kStatus_SDSPI_SetFrequencyFailed = MAKE_STATUS(kStatusGroup_SDSPI, 0U),
kStatus_SDSPI_ExchangeFailed = MAKE_STATUS(kStatusGroup_SDSPI, 1U),
kStatus_SDSPI_WaitReadyFailed = MAKE_STATUS(kStatusGroup_SDSPI, 2U),
kStatus_SDSPI_ResponseError = MAKE_STATUS(kStatusGroup_SDSPI, 3U),
kStatus_SDSPI_WriteProtected = MAKE_STATUS(kStatusGroup_SDSPI, 4U),
kStatus_SDSPI_GoIdleFailed = MAKE_STATUS(kStatusGroup_SDSPI, 5U),
kStatus_SDSPI_SendCommandFailed = MAKE_STATUS(kStatusGroup_SDSPI, 6U),
kStatus_SDSPI_ReadFailed = MAKE_STATUS(kStatusGroup_SDSPI, 7U),
kStatus_SDSPI_WriteFailed = MAKE_STATUS(kStatusGroup_SDSPI, 8U),
kStatus_SDSPI_SendInterfaceConditionFailed,
kStatus_SDSPI_SendOperationConditionFailed,
kStatus_SDSPI_ReadOcrFailed = MAKE_STATUS(kStatusGroup_SDSPI, 11U),
kStatus_SDSPI_SetBlockSizeFailed = MAKE_STATUS(kStatusGroup_SDSPI, 12U),
kStatus_SDSPI_SendCsdFailed = MAKE_STATUS(kStatusGroup_SDSPI, 13U),
kStatus_SDSPI_SendCidFailed = MAKE_STATUS(kStatusGroup_SDSPI, 14U),
kStatus_SDSPI_StopTransmissionFailed = MAKE_STATUS(kStatusGroup_SDSPI, 15U),
kStatus_SDSPI_SendApplicationCommandFailed }
SDSPI API status.
- enum _sdspi_card_flag {
kSDSPI_SupportHighCapacityFlag = (1U << 0U),
kSDSPI_SupportSdhcFlag = (1U << 1U),
kSDSPI_SupportSdxcFlag = (1U << 2U),
kSDSPI_SupportSdscFlag = (1U << 3U) }
SDSPI card flag.
- enum sdspi_response_type_t {
kSDSPI_ResponseTypeR1 = 0U,
kSDSPI_ResponseTypeR1b = 1U,
kSDSPI_ResponseTypeR2 = 2U,
kSDSPI_ResponseTypeR3 = 3U,
kSDSPI_ResponseTypeR7 = 4U }
SDSPI response type.

SDSPI Function

- status_t SDSPI_Init (sdspi_card_t *card)
Initializes the card on a specific SPI instance.
- void SDSPI_Deinit (sdspi_card_t *card)
Deinitializes the card.
- bool SDSPI_CheckReadOnly (sdspi_card_t *card)
Checks whether the card is write-protected.
- status_t SDSPI_ReadBlocks (sdspi_card_t *card, uint8_t *buffer, uint32_t startBlock, uint32_t blockCount)
Reads blocks from the specific card.
- status_t SDSPI_WriteBlocks (sdspi_card_t *card, uint8_t *buffer, uint32_t startBlock, uint32_t blockCount)

Writes blocks of data to the specific card.

25.2 Data Structure Documentation

25.2.1 struct sdspi_command_t

Data Fields

- uint8_t index
  Command index.
- uint32_t argument
  Command argument.
- uint8_t responseType
  Response type.
- uint8_t response [5U]
  Response content.

25.2.2 struct sdspi_host_t

Data Fields

- uint32_t busBaudRate
  Bus baud rate.
- status_t(∗ setFrequency)(uint32_t frequency)
  Set frequency of SPI.
- status_t(∗ exchange)(uint8_t ∗in, uint8_t ∗out, uint32_t size)
  Exchange data over SPI.
- uint32_t(∗ getCurrentMilliseconds)(void)
  Get current time in milliseconds.

25.2.3 struct sdspi_card_t

Define the card structure including the necessary fields to identify and describe the card.

Data Fields

- sdspi_host_t ∗ host
  Host state information.
- uint32_t relativeAddress
  Relative address of the card.
- uint32_t flags
  Flags defined in _sdspi_card_flag.
- uint8_t rawCid [16U]
  Raw CID content.
- uint8_t rawCsd [16U]

Raw CSD content.

- uint8_t rawScr [8U]
  Raw SCR content.
- uint32_t ocr
  Raw OCR content.
- sd_cid_t cid
  CID.
- sd_csd_t csd
  CSD.
- sd_scr_t scr
  SCR.
- uint32_t blockCount
  Card total block number.
- uint32_t blockSize
  Card block size.

25.2.3.0.0.40 Field Documentation

25.2.3.0.0.40.1 uint32_t sdspi_card_t::flags

25.3 Enumeration Type Documentation

25.3.1 enum _sdspi_status

Enumerator

kStatus_SDSPI_SetFrequencyFailed Set frequency failed.
kStatus_SDSPI_ExchangeFailed Exchange data on SPI bus failed.
kStatus_SDSPI_WaitReadyFailed Wait card ready failed.
kStatus_SDSPI_ResponseError Response is error.
kStatus_SDSPI_WriteProtected Write protected.
kStatus_SDSPI_GoIdleFailed Go idle failed.
kStatus_SDSPI_SendCommandFailed Send command failed.
kStatus_SDSPI_ReadFailed Read data failed.
kStatus_SDSPI_WriteFailed Write data failed.
kStatus_SDSPI_SendInterfaceConditionFailed Send interface condition failed.
kStatus_SDSPI_SendOperationConditionFailed Send operation condition failed.
kStatus_SDSPI_ReadOcrFailed Read OCR failed.
kStatus_SDSPI_SetBlockSizeFailed Set block size failed.
kStatus_SDSPI_SendCsdFailed Send CSD failed.
kStatus_SDSPI_SendCidFailed Send CID failed.
kStatus_SDSPI_StopTransmissionFailed Stop transmission failed.
kStatus_SDSPI_SendApplicationCommandFailed Send application command failed.

25.3.2 enum _sdspi_card_flag

Enumerator

kSDSPI_SupportHighCapacityFlag Card is high capacity.
kSDSPI_SupportSdhcFlag Card is SDHC.
kSDSPI_SupportSdxcFlag Card is SDXC.
kSDSPI_SupportSdscFlag Card is SDSC.

25.3.3 enum sdspi_response_type_t

Enumerator

kSDSPI_ResponseTypeR1 Response 1.
kSDSPI_ResponseTypeR1b Response 1 with busy.
kSDSPI_ResponseTypeR2 Response 2.
kSDSPI_ResponseTypeR3 Response 3.
kSDSPI_ResponseTypeR7 Response 7.

25.4 Function Documentation

25.4.1 status_t SDSPI_Init (sdspi_card_t * *card*)

This function initializes the card on a specific SPI instance.

Parameters

card	Card descriptor

Return values

kStatus_SDSPI_SetFrequencyFailed	Set frequency failed.
kStatus_SDSPI_GoIdleFailed	Go idle failed.
kStatus_SDSPI_SendInterfaceConditionFailed	Send interface condition failed.

kStatus_SDSPI_Send-OperationCondition-Failed	Send operation condition failed.
kStatus_Timeout	Send command timeout.
kStatus_SDSPI_Not-SupportYet	Not support yet.
kStatus_SDSPI_ReadOcr-Failed	Read OCR failed.
kStatus_SDSPI_SetBlock-SizeFailed	Set block size failed.
kStatus_SDSPI_SendCsd-Failed	Send CSD failed.
kStatus_SDSPI_SendCid-Failed	Send CID failed.
kStatus_Success	Operate successfully.

25.4.2 void SDSPI_Deinit (sdspi_card_t * *card*)

This function deinitializes the specific card.

Parameters

card	Card descriptor

25.4.3 bool SDSPI_CheckReadOnly (sdspi_card_t * *card*)

This function checks if the card is write-protected via CSD register.

Parameters

card	Card descriptor.

Return values

true	Card is read only.
false	Card isn't read only.

25.4.4 status_t SDSPI_ReadBlocks (sdspi_card_t * *card,* uint8_t * *buffer,* uint32_t *startBlock,* uint32_t *blockCount*)

This function reads blocks from specific card.

Parameters

card	Card descriptor.
buffer	the buffer to hold the data read from card
startBlock	the start block index
blockCount	the number of blocks to read

Return values

kStatus_SDSPI_SendCommandFailed	Send command failed.
kStatus_SDSPI_ReadFailed	Read data failed.
kStatus_SDSPI_StopTransmissionFailed	Stop transmission failed.
kStatus_Success	Operate successfully.

25.4.5 status_t SDSPI_WriteBlocks (sdspi_card_t * *card,* uint8_t * *buffer,* uint32_t *startBlock,* uint32_t *blockCount*)

This function writes blocks to specific card

Parameters

card	Card descriptor.
buffer	the buffer holding the data to be written to the card

startBlock	the start block index
blockCount	the number of blocks to write

Return values

kStatus_SDSPI_Write-Protected	Card is write protected.
kStatus_SDSPI_Send-CommandFailed	Send command failed.
kStatus_SDSPI_-ResponseError	Response is error.
kStatus_SDSPI_Write-Failed	Write data failed.
kStatus_SDSPI_-ExchangeFailed	Exchange data over SPI failed.
kStatus_SDSPI_Wait-ReadyFailed	Wait card to be ready status failed.
kStatus_Success	Operate successfully.

Chapter 26
Debug Console

26.1 Overview

This chapter describes the programming interface of the debug console driver.

The debug console enables debug log messages to be output via the specified peripheral with frequency of the peripheral source clock and base address at the specified baud rate. Additionally, it provides input and output functions to scan and print formatted data.

26.2 Function groups

26.2.1 Initialization

To initialize the debug console, call the DbgConsole_Init() function with these parameters. This function automatically enables the module and the clock.

```
/*
 * @brief Initializes the the peripheral used to debug messages.
 *
 * @param baseAddr      Indicates which address of the peripheral is used to send debug messages.
 * @param baudRate      The desired baud rate in bits per second.
 * @param device        Low level device type for the debug console, can be one of:
 *                      @arg DEBUG_CONSOLE_DEVICE_TYPE_UART,
 *                      @arg DEBUG_CONSOLE_DEVICE_TYPE_LPUART,
 *                      @arg DEBUG_CONSOLE_DEVICE_TYPE_LPSCI,
 *                      @arg DEBUG_CONSOLE_DEVICE_TYPE_USBCDC.
 * @param clkSrcFreq    Frequency of peripheral source clock.
 *
 * @return              Whether initialization was successful or not.
 */
status_t DbgConsole_Init(uint32_t baseAddr, uint32_t baudRate, uint8_t device, uint32_t clkSrcFreq)
```

Selects the supported debug console hardware device type, such as

```
DEBUG_CONSOLE_DEVICE_TYPE_NONE
DEBUG_CONSOLE_DEVICE_TYPE_LPSCI
DEBUG_CONSOLE_DEVICE_TYPE_UART
DEBUG_CONSOLE_DEVICE_TYPE_LPUART
DEBUG_CONSOLE_DEVICE_TYPE_USBCDC
```

After the initialization is successful, stdout and stdin are connected to the selected peripheral. The debug console state is stored in the debug_console_state_t structure, such as shown here.

```
typedef struct DebugConsoleState
{
    uint8_t                     type;
    void*                       base;
    debug_console_ops_t         ops;
} debug_console_state_t;
```

This example shows how to call the DbgConsole_Init() given the user configuration structure.

```
uint32_t uartClkSrcFreq = CLOCK_GetFreq(BOARD_DEBUG_UART_CLKSRC);

DbgConsole_Init(BOARD_DEBUG_UART_BASEADDR, BOARD_DEBUG_UART_BAUDRATE, DEBUG_CONSOLE_DEVICE_TYPE_UART,
      uartClkSrcFreq);
```

26.2.2 Advanced Feature

The debug console provides input and output functions to scan and print formatted data.

- Support a format specifier for PRINTF following this prototype " %[flags][width][.precision][length]specifier", which is explained below

flags	Description
-	Left-justified within the given field width. Right-justified is the default.
+	Forces to precede the result with a plus or minus sign (+ or -) even for positive numbers. By default, only negative numbers are preceded with a - sign.
(space)	If no sign is written, a blank space is inserted before the value.
#	Used with o, x, or X specifiers the value is preceded with 0, 0x, or 0X respectively for values other than zero. Used with e, E and f, it forces the written output to contain a decimal point even if no digits would follow. By default, if no digits follow, no decimal point is written. Used with g or G the result is the same as with e or E but trailing zeros are not removed.
0	Left-pads the number with zeroes (0) instead of spaces, where padding is specified (see width sub-specifier).

Width	Description
(number)	A minimum number of characters to be printed. If the value to be printed is shorter than this number, the result is padded with blank spaces. The value is not truncated even if the result is larger.
*	The width is not specified in the format string, but as an additional integer value argument preceding the argument that has to be formatted.

.precision	Description
.number	For integer specifiers (d, i, o, u, x, X) precision specifies the minimum number of digits to be written. If the value to be written is shorter than this number, the result is padded with leading zeros. The value is not truncated even if the result is longer. A precision of 0 means that no character is written for the value 0. For e, E, and f specifiers this is the number of digits to be printed after the decimal point. For g and G specifiers This is the maximum number of significant digits to be printed. For s this is the maximum number of characters to be printed. By default, all characters are printed until the ending null character is encountered. For c type it has no effect. When no precision is specified, the default is 1. If the period is specified without an explicit value for precision, 0 is assumed.
.*	The precision is not specified in the format string, but as an additional integer value argument preceding the argument that has to be formatted.

length	Description
Do not support	

specifier	Description
d or i	Signed decimal integer
f	Decimal floating point
F	Decimal floating point capital letters
x	Unsigned hexadecimal integer
X	Unsigned hexadecimal integer capital letters
o	Signed octal
b	Binary value
p	Pointer address
u	Unsigned decimal integer
c	Character
s	String of characters
n	Nothing printed

- Support a format specifier for SCANF following this prototype " %[*][width][length]specifier", which is explained below

*	Description
An optional starting asterisk indicates that the data is to be read from the stream but ignored. In other words, it is not stored in the corresponding argument.	

width	Description
This specifies the maximum number of characters to be read in the current reading operation.	

length	Description
hh	The argument is interpreted as a signed character or unsigned character (only applies to integer specifiers: i, d, o, u, x, and X).
h	The argument is interpreted as a short integer or unsigned short integer (only applies to integer specifiers: i, d, o, u, x, and X).
l	The argument is interpreted as a long integer or unsigned long integer for integer specifiers (i, d, o, u, x, and X) and as a wide character or wide character string for specifiers c and s.
ll	The argument is interpreted as a long long integer or unsigned long long integer for integer specifiers (i, d, o, u, x, and X) and as a wide character or wide character string for specifiers c and s.
L	The argument is interpreted as a long double (only applies to floating point specifiers: e, E, f, g, and G).
j or z or t	Not supported

specifier	Qualifying Input	Type of argument
c	Single character: Reads the next character. If a width different from 1 is specified, the function reads width characters and stores them in the successive locations of the array passed as argument. No null character is appended at the end.	char *

specifier	Qualifying Input	Type of argument
i	Integer: : Number optionally preceded with a + or - sign	int *
d	Decimal integer: Number optionally preceded with a + or - sign	int *
a, A, e, E, f, F, g, G	Floating point: Decimal number containing a decimal point, optionally preceded by a + or - sign and optionally followed by the e or E character and a decimal number. Two examples of valid entries are -732.103 and 7.12e4	float *
o	Octal Integer:	int *
s	String of characters. This reads subsequent characters until a white space is found (white space characters are considered to be blank, newline, and tab).	char *
u	Unsigned decimal integer.	unsigned int *

The debug console has its own printf/scanf/putchar/getchar functions which are defined in the header file.

```
int DbgConsole_Printf(const char *fmt_s, ...);
int DbgConsole_Putchar(int ch);
int DbgConsole_Scanf(const char *fmt_ptr, ...);
int DbgConsole_Getchar(void);
```

This utility supports selecting toolchain's printf/scanf or the MCUXpresso SDK printf/scanf.

```
#if SDK_DEBUGCONSOLE    /* Select printf, scanf, putchar, getchar of SDK version. */
#define PRINTF                DbgConsole_Printf
#define SCANF                 DbgConsole_Scanf
#define PUTCHAR               DbgConsole_Putchar
#define GETCHAR               DbgConsole_Getchar
#else                   /* Select printf, scanf, putchar, getchar of toolchain. */
#define PRINTF                printf
#define SCANF                 scanf
#define PUTCHAR               putchar
#define GETCHAR               getchar
#endif /* SDK_DEBUGCONSOLE */
```

26.3 Typical use case

Some examples use the PUTCHAR & GETCHAR function

```
ch = GETCHAR();
PUTCHAR(ch);
```

Some examples use the PRINTF function

Statement prints the string format.

```
PRINTF("%s %s\r\n", "Hello", "world!");
```

Statement prints the hexadecimal format/

```
PRINTF("0x%02X hexadecimal number equivalents 255", 255);
```

Statement prints the decimal floating point and unsigned decimal.

```
PRINTF("Execution timer: %s\n\rTime: %u ticks %2.5f milliseconds\n\rDONE\n\r", "1 day", 86400, 86.4);
```

Some examples use the SCANF function

```
PRINTF("Enter a decimal number: ");
SCANF("%d", &i);
PRINTF("\r\nYou have entered %d.\r\n", i, i);
PRINTF("Enter a hexadecimal number: ");
SCANF("%x", &i);
PRINTF("\r\nYou have entered 0x%X (%d).\r\n", i, i);
```

Print out failure messages using KSDK __assert_func:

```
void __assert_func(const char *file, int line, const char *func, const char *failedExpr)
{
    PRINTF("ASSERT ERROR \" %s \": file \"%s\" Line \"%d\" function name \"%s\" \n", failedExpr, file ,
      line, func);
    for (;;)
    {}
}
```

Note:

To use 'printf' and 'scanf' for GNUC Base, add file **'fsl_sbrk.c'** in path: **..\{package}\devices\{subset}\utilities\fsl-_sbrk.c** to your project.

Modules

- Semihosting

26.4 Semihosting

Semihosting is a mechanism for ARM targets to communicate input/output requests from application code to a host computer running a debugger. This mechanism can be used, for example, to enable functions in the C library, such as printf() and scanf(), to use the screen and keyboard of the host rather than having a screen and keyboard on the target system.

26.4.1 Guide Semihosting for IAR

NOTE: After the setting both "printf" and "scanf" are available for debugging.

Step 1: Setting up the environment

1. To set debugger options, choose Project>Options. In the Debugger category, click the Setup tab.
2. Select Run to main and click OK. This ensures that the debug session starts by running the main function.
3. The project is now ready to be built.

Step 2: Building the project

1. Compile and link the project by choosing Project>Make or F7.
2. Alternatively, click the Make button on the tool bar. The Make command compiles and links those files that have been modified.

Step 3: Starting semihosting

1. Choose "Semihosting_IAR" project -> "Options" -> "Debugger" -> "J-Link/J-Trace".
2. Choose tab "J-Link/J-Trace" -> "Connection" tab -> "SWD".
3. Start the project by choosing Project>Download and Debug.
4. Choose View>Terminal I/O to display the output from the I/O operations.

26.4.2 Guide Semihosting for Keil µVision

NOTE: Keil supports Semihosting only for Cortex-M3/Cortex-M4 cores.

Step 1: Prepare code

Remove function fputc and fgetc is used to support KEIL in "fsl_debug_console.c" and add the following code to project.

```
#pragma import(__use_no_semihosting_swi)

volatile int ITM_RxBuffer = ITM_RXBUFFER_EMPTY;        /* used for Debug Input */
```

```
struct __FILE
{
    int handle;
};
FILE __stdout;
FILE __stdin;

int fputc(int ch, FILE *f)
{
    return (ITM_SendChar(ch));
}

int fgetc(FILE *f)
{ /* blocking */
    while (ITM_CheckChar() != 1)
        ;
    return (ITM_ReceiveChar());
}

int ferror(FILE *f)
{
    /* Your implementation of ferror */
    return EOF;
}

void _ttywrch(int ch)
{
    ITM_SendChar(ch);
}

void _sys_exit(int return_code)
{
label:
    goto label; /* endless loop */
}
```

Step 2: Setting up the environment

1. In menu bar, choose Project>Options for target or using Alt+F7 or click.
2. Select "Target" tab and not select "Use MicroLIB".
3. Select “Debug” tab, select “J-Link/J-Trace Cortex” and click “Setting button”.
4. Select “Debug” tab and choose Port:SW, then select "Trace" tab, choose "Enable" and click OK.

Step 3: Building the project

1. Compile and link the project by choosing Project>Build Target or using F7.

Step 4: Building the project

1. Choose “Debug” on menu bar or Ctrl F5.
2. In menu bar, choose "Serial Window" and click to "Debug (printf) Viewer".
3. Run line by line to see result in Console Window.

26.4.3 Guide Semihosting for KDS

NOTE: After the setting use "printf" for debugging.

Step 1: Setting up the environment

1. In menu bar, choose Project>Properties>C/C++ Build>Settings>Tool Settings.
2. Select “Libraries” on “Cross ARM C Linker” and delete “nosys”.
3. Select “Miscellaneous” on "Cross ARM C Linker”, add “-specs=rdimon.specs” to “Other link flages” and tick “Use newlib-nano”, and click OK.

Step 2: Building the project

1. In menu bar, choose Project>Build Project.

Step 3: Starting semihosting

1. In Debug configurations, choose "Startup" tab, tick “Enable semihosting and Telnet”. Press “Apply” and “Debug”.
2. After clicking Debug, the Window is displayed same as below. Run line by line to see the result in the Console Window.

26.4.4 Guide Semihosting for ATL

NOTE: J-Link has to be used to enable semihosting.

Step 1: Prepare code

Add the following code to the project.

```
int _write(int file, char *ptr, int len)
{
  /* Implement your write code here. This is used by puts and printf. */
  int i=0;
  for(i=0 ; i<len ; i++)
    ITM_SendChar((*ptr++));
  return len;
}
```

Step 2: Setting up the environment

1. In menu bar, choose Debug Configurations. In tab "Embedded C/C++ Aplication" choose "-Semihosting_ATL_xxx debug J-Link".
2. In tab "Debugger" set up as follows.
   - JTAG mode must be selected

- SWV tracing must be enabled
- Enter the Core Clock frequency, which is hardware board-specific.
- Enter the desired SWO Clock frequency. The latter depends on the JTAG Probe and must be a multiple of the Core Clock value.

3. Click "Apply" and "Debug".

Step 3: Starting semihosting

1. In the Views menu, expand the submenu SWV and open the docking view “SWV Console". 2. Open the SWV settings panel by clicking the "Configure Serial Wire Viewer" button in the SWV Console view toolbar. 3. Configure the data ports to be traced by enabling the ITM channel 0 check-box in the ITM stimulus ports group: Choose "EXETRC: Trace Exceptions" and In tab "ITM Stimulus Ports" choose "Enable Port" 0. Then click "OK".
2. It is recommended not to enable other SWV trace functionalities at the same time because this may over use the SWO pin causing packet loss due to a limited bandwidth (certain other SWV tracing capabilities can send a lot of data at very high-speed). Save the SWV configuration by clicking the OK button. The configuration is saved with other debug configurations and remains effective until changed.
3. Press the red Start/Stop Trace button to send the SWV configuration to the target board to enable SWV trace recoding. The board does not send any SWV packages until it is properly configured. The SWV Configuration must be present, if the configuration registers on the target board are reset. Also, tracing does not start until the target starts to execute.
4. Start the target execution again by pressing the green Resume Debug button.
5. The SWV console now shows the printf() output.

26.4.5 Guide Semihosting for ARMGCC

Step 1: Setting up the environment

1. Turn on "J-LINK GDB Server" -> Select suitable "Target device" -> "OK".
2. Turn on "PuTTY". Set up as follows.
   - "Host Name (or IP address)" : localhost
   - "Port" :2333
   - "Connection type" : Telet.
   - Click "Open".
3. Increase "Heap/Stack" for GCC to 0x2000:

Add to "CMakeLists.txt"

SET(CMAKE_EXE_LINKER_FLAGS_RELEASE "${CMAKE_EXE_LINKER_FLAGS_RELEASE} --defsym=__stack_size__=0x2000")

SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} --defsym=__stack_size__=0x2000")

SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} --

defsym=__heap_size__=0x2000")

SET(CMAKE_EXE_LINKER_FLAGS_RELEASE "${CMAKE_EXE_LINKER_FLAGS_RELEASE} --defsym=__heap_size__=0x2000")

Step 2: Building the project

1. Change "CMakeLists.txt":
   Change "SET(CMAKE_EXE_LINKER_FLAGS_RELEASE "${CMAKE_EXE_LINKER_FLAGS_RELEASE} –specs=nano.specs")"
   to "SET(CMAKE_EXE_LINKER_FLAGS_RELEASE "${CMAKE_EXE_LINKER_FLAGS_RELEASE} –specs=rdimon.specs")"
   Replace paragraph
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -fno-common")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -ffunction-sections")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -fdata-sections")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -ffreestanding")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -fno-builtin")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -mthumb")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -mapcs")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -Xlinker")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} --gc-sections")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -Xlinker")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -static")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -Xlinker")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -z")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} -Xlinker")
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBUG} muldefs")
   To
   SET(CMAKE_EXE_LINKER_FLAGS_DEBUG "${CMAKE_EXE_LINKER_FLAGS_DEBU-

G} --specs=rdimon.specs ")
Remove
target_link_libraries(semihosting_ARMGCC.elf debug nosys)
2. Run "build_debug.bat" to build project

Step 3: Starting semihosting

(a) Download the image and set as follows.

```
cd D:\mcu-sdk-2.0-origin\boards\twrk64f120m\driver_examples\semihosting\armgcc\debug
d:
C:\PROGRA~2\GNUTOO~1\4BD65~1.920\bin\arm-none-eabi-gdb.exe
target remote localhost:2331
monitor reset
monitor semihosting enable
monitor semihosting thumbSWI 0xAB
monitor semihosting IOClient 1
monitor flash device = MK64FN1M0xxx12
load semihosting_ARMGCC.elf
monitor reg pc = (0x00000004)
monitor reg sp = (0x00000000)
continue
```

(b) After the setting, press "enter". The PuTTY window now shows the printf() output.

Chapter 27
Notification Framework

27.1 Overview

This section describes the programming interface of the Notifier driver.

27.2 Notifier Overview

The Notifier provides a configuration dynamic change service. Based on this service, applications can switch between pre-defined configurations. The Notifier enables drivers and applications to register callback functions to this framework. Each time that the configuration is changed, drivers and applications receive a notification and change their settings. To simplify, the Notifier only supports the static callback registration. This means that, for applications, all callback functions are collected into a static table and passed to the Notifier.

These are the steps for the configuration transition.

1. Before configuration transition, the Notifier sends a "BEFORE" message to the callback table. When this message is received, IP drivers should check whether any current processes can be stopped and stop them. If the processes cannot be stopped, the callback function returns an error.
   The Notifier supports two types of transition policies, a graceful policy and a forceful policy. When the graceful policy is used, if some callbacks return an error while sending a "BEFORE" message, the configuration transition stops and the Notifier sends a "RECOVER" message to all drivers that have stopped. Then, these drivers can recover the previous status and continue to work. When the forceful policy is used, drivers are stopped forcefully.
2. After the "BEFORE" message is processed successfully, the system switches to the new configuration.
3. After the configuration changes, the Notifier sends an "AFTER" message to the callback table to notify drivers that the configuration transition is finished.

This example shows how to use the Notifier in the Power Manager application.

```
#include "fsl_notifier.h"

// Definition of the Power Manager callback.
status_t callback0(notifier_notification_block_t *notify, void *data)
{

    status_t ret = kStatus_Success;

    ...
    ...
    ...

    return ret;
}
// Definition of the Power Manager user function.
status_t APP_PowerModeSwitch(notifier_user_config_t *targetConfig, void *userData)
{
```

```
    ...
    ...
    ...
}
...
...
...
...
...
// Main function.
int main(void)
{
    // Define a notifier handle.
    notifier_handle_t powerModeHandle;

    // Callback configuration.
    user_callback_data_t callbackData0;

    notifier_callback_config_t callbackCfg0 = {callback0,
                kNOTIFIER_CallbackBeforeAfter,
                (void *)&callbackData0};

    notifier_callback_config_t callbacks[] = {callbackCfg0};

    // Power mode configurations.
    power_user_config_t vlprConfig;
    power_user_config_t stopConfig;

    notifier_user_config_t *powerConfigs[] = {&vlprConfig, &stopConfig};

    // Definition of a transition to and out the power modes.
    vlprConfig.mode = kAPP_PowerModeVlpr;
    vlprConfig.enableLowPowerWakeUpOnInterrupt = false;

    stopConfig = vlprConfig;
    stopConfig.mode = kAPP_PowerModeStop;

    // Create Notifier handle.
    NOTIFIER_CreateHandle(&powerModeHandle, powerConfigs, 2U, callbacks, 1U,
      APP_PowerModeSwitch, NULL);
    ...
    ...
    // Power mode switch.
    NOTIFIER_switchConfig(&powerModeHandle, targetConfigIndex,
      kNOTIFIER_PolicyAgreement);
}
```

Data Structures

- struct notifier_notification_block_t
  notification block passed to the registered callback function. More...
- struct notifier_callback_config_t
  Callback configuration structure. More...
- struct notifier_handle_t
  Notifier handle structure. More...

Typedefs

- typedef void notifier_user_config_t
  Notifier user configuration type.
- typedef status_t(∗ notifier_user_function_t)(notifier_user_config_t ∗targetConfig, void ∗userData)
  Notifier user function prototype Use this function to execute specific operations in configuration switch.

- typedef status_t(∗ notifier_callback_t)(notifier_notification_block_t ∗notify, void ∗data)
  Callback prototype.

Enumerations

- enum _notifier_status {
  kStatus_NOTIFIER_ErrorNotificationBefore,
  kStatus_NOTIFIER_ErrorNotificationAfter }
  Notifier error codes.
- enum notifier_policy_t {
  kNOTIFIER_PolicyAgreement,
  kNOTIFIER_PolicyForcible }
  Notifier policies.
- enum notifier_notification_type_t {
  kNOTIFIER_NotifyRecover = 0x00U,
  kNOTIFIER_NotifyBefore = 0x01U,
  kNOTIFIER_NotifyAfter = 0x02U }
  Notification type.
- enum notifier_callback_type_t {
  kNOTIFIER_CallbackBefore = 0x01U,
  kNOTIFIER_CallbackAfter = 0x02U,
  kNOTIFIER_CallbackBeforeAfter = 0x03U }
  The callback type, which indicates kinds of notification the callback handles.

Functions

- status_t NOTIFIER_CreateHandle (notifier_handle_t ∗notifierHandle, notifier_user_config_t ∗∗configs, uint8_t configsNumber, notifier_callback_config_t ∗callbacks, uint8_t callbacksNumber, notifier_user_function_t userFunction, void ∗userData)
  Creates a Notifier handle.
- status_t NOTIFIER_SwitchConfig (notifier_handle_t ∗notifierHandle, uint8_t configIndex, notifier_policy_t policy)
  Switches the configuration according to a pre-defined structure.
- uint8_t NOTIFIER_GetErrorCallbackIndex (notifier_handle_t ∗notifierHandle)
  This function returns the last failed notification callback.

27.3 Data Structure Documentation

27.3.1 struct notifier_notification_block_t

Data Fields

- notifier_user_config_t ∗ targetConfig
  Pointer to target configuration.
- notifier_policy_t policy
  Configure transition policy.
- notifier_notification_type_t notifyType
  Configure notification type.

27.3.1.0.0.41 Field Documentation

27.3.1.0.0.41.1 notifier_user_config_t* notifier_notification_block_t::targetConfig

27.3.1.0.0.41.2 notifier_policy_t notifier_notification_block_t::policy

27.3.1.0.0.41.3 notifier_notification_type_t notifier_notification_block_t::notifyType

27.3.2 struct notifier_callback_config_t

This structure holds the configuration of callbacks. Callbacks of this type are expected to be statically allocated. This structure contains the following application-defined data. callback - pointer to the callback function callbackType - specifies when the callback is called callbackData - pointer to the data passed to the callback.

Data Fields

- notifier_callback_t callback
  Pointer to the callback function.
- notifier_callback_type_t callbackType
  Callback type.
- void * callbackData
  Pointer to the data passed to the callback.

27.3.2.0.0.42 Field Documentation

27.3.2.0.0.42.1 notifier_callback_t notifier_callback_config_t::callback

27.3.2.0.0.42.2 notifier_callback_type_t notifier_callback_config_t::callbackType

27.3.2.0.0.42.3 void* notifier_callback_config_t::callbackData

27.3.3 struct notifier_handle_t

Notifier handle structure. Contains data necessary for the Notifier proper function. Stores references to registered configurations, callbacks, information about their numbers, user function, user data, and other internal data. NOTIFIER_CreateHandle() must be called to initialize this handle.

Data Fields

- notifier_user_config_t ** configsTable
  Pointer to configure table.
- uint8_t configsNumber
  Number of configurations.
- notifier_callback_config_t * callbacksTable
  Pointer to callback table.

- uint8_t callbacksNumber
  Maximum number of callback configurations.
- uint8_t errorCallbackIndex
  Index of callback returns error.
- uint8_t currentConfigIndex
  Index of current configuration.
- notifier_user_function_t userFunction
  User function.
- void ∗ userData
  User data passed to user function.

27.3.3.0.0.43 Field Documentation

27.3.3.0.0.43.1 notifier_user_config_t∗∗ notifier_handle_t::configsTable

27.3.3.0.0.43.2 uint8_t notifier_handle_t::configsNumber

27.3.3.0.0.43.3 notifier_callback_config_t∗ notifier_handle_t::callbacksTable

27.3.3.0.0.43.4 uint8_t notifier_handle_t::callbacksNumber

27.3.3.0.0.43.5 uint8_t notifier_handle_t::errorCallbackIndex

27.3.3.0.0.43.6 uint8_t notifier_handle_t::currentConfigIndex

27.3.3.0.0.43.7 notifier_user_function_t notifier_handle_t::userFunction

27.3.3.0.0.43.8 void∗ notifier_handle_t::userData

27.4 Typedef Documentation

27.4.1 typedef void notifier_user_config_t

Reference of the user defined configuration is stored in an array; the notifier switches between these configurations based on this array.

27.4.2 typedef status_t(∗ notifier_user_function_t)(notifier_user_config_t ∗targetConfig, void ∗userData)

Before and after this function execution, different notification is sent to registered callbacks. If this function returns any error code, NOTIFIER_SwitchConfig() exits.

Parameters

targetConfig	target Configuration.
userData	Refers to other specific data passed to user function.

Returns

An error code or kStatus_Success.

27.4.3 typedef status_t(∗ notifier_callback_t)(notifier_notification_block_t ∗notify, void ∗data)

Declaration of a callback. It is common for registered callbacks. Reference to function of this type is part of the notifier_callback_config_t callback configuration structure. Depending on callback type, function of this prototype is called (see NOTIFIER_SwitchConfig()) before configuration switch, after it or in both use cases to notify about the switch progress (see notifier_callback_type_t). When called, the type of the notification is passed as a parameter along with the reference to the target configuration structure (see notifier_notification_block_t) and any data passed during the callback registration. When notified before the configuration switch, depending on the configuration switch policy (see notifier_policy_t), the callback may deny the execution of the user function by returning an error code different than kStatus_Success (see NOTIFIER_SwitchConfig()).

Parameters

notify	Notification block.
data	Callback data. Refers to the data passed during callback registration. Intended to pass any driver or application data such as internal state information.

Returns

An error code or kStatus_Success.

27.5 Enumeration Type Documentation

27.5.1 enum _notifier_status

Used as return value of Notifier functions.

Enumerator

kStatus_NOTIFIER_ErrorNotificationBefore An error occurs during send "BEFORE" notification.

kStatus_NOTIFIER_ErrorNotificationAfter An error occurs during send "AFTER" notification.

27.5.2 enum notifier_policy_t

Defines whether the user function execution is forced or not. For kNOTIFIER_PolicyForcible, the user function is executed regardless of the callback results, while kNOTIFIER_PolicyAgreement policy is used to exit NOTIFIER_SwitchConfig() when any of the callbacks returns error code. See also NOTIFIER_-SwitchConfig() description.

Enumerator

kNOTIFIER_PolicyAgreement NOTIFIER_SwitchConfig() method is exited when any of the callbacks returns error code.
kNOTIFIER_PolicyForcible The user function is executed regardless of the results.

27.5.3 enum notifier_notification_type_t

Used to notify registered callbacks

Enumerator

kNOTIFIER_NotifyRecover Notify IP to recover to previous work state.
kNOTIFIER_NotifyBefore Notify IP that configuration setting is going to change.
kNOTIFIER_NotifyAfter Notify IP that configuration setting has been changed.

27.5.4 enum notifier_callback_type_t

Used in the callback configuration structure (notifier_callback_config_t) to specify when the registered callback is called during configuration switch initiated by the NOTIFIER_SwitchConfig(). Callback can be invoked in following situations.

- Before the configuration switch (Callback return value can affect NOTIFIER_SwitchConfig() execution. See the NOTIFIER_SwitchConfig() and notifier_policy_t documentation).
- After an unsuccessful attempt to switch configuration
- After a successful configuration switch

Enumerator

kNOTIFIER_CallbackBefore Callback handles BEFORE notification.
kNOTIFIER_CallbackAfter Callback handles AFTER notification.
kNOTIFIER_CallbackBeforeAfter Callback handles BEFORE and AFTER notification.

27.6 Function Documentation

27.6.1 status_t NOTIFIER_CreateHandle (notifier_handle_t * *notifierHandle,* notifier_user_config_t ** *configs,* uint8_t *configsNumber,* notifier_callback_config_t * *callbacks,* uint8_t *callbacksNumber,* notifier_user_function_t *userFunction,* void * *userData*)

Parameters

notifierHandle	A pointer to the notifier handle.
configs	A pointer to an array with references to all configurations which is handled by the Notifier.
configsNumber	Number of configurations. Size of the configuration array.
callbacks	A pointer to an array of callback configurations. If there are no callbacks to register during Notifier initialization, use NULL value.
callbacks-Number	Number of registered callbacks. Size of the callbacks array.
userFunction	User function.
userData	User data passed to user function.

Returns

An error Code or kStatus_Success.

27.6.2 status_t NOTIFIER_SwitchConfig (notifier_handle_t * *notifierHandle*, uint8_t *configIndex*, notifier_policy_t *policy*)

This function sets the system to the target configuration. Before transition, the Notifier sends notifications to all callbacks registered to the callback table. Callbacks are invoked in the following order: All registered callbacks are notified ordered by index in the callbacks array. The same order is used for before and after switch notifications. The notifications before the configuration switch can be used to obtain confirmation about the change from registered callbacks. If any registered callback denies the configuration change, further execution of this function depends on the notifier policy: the configuration change is either forced (kNOTIFIER_PolicyForcible) or exited (kNOTIFIER_PolicyAgreement). When configuration change is forced, the result of the before switch notifications are ignored. If an agreement is required, if any callback returns an error code, further notifications before switch notifications are cancelled and all already notified callbacks are re-invoked. The index of the callback which returned error code during pre-switch notifications is stored (any error codes during callbacks re-invocation are ignored) and NOTIFIER_GetErrorCallback() can be used to get it. Regardless of the policies, if any callback returns an error code, an error code indicating in which phase the error occurred is returned when NOTIFIER_SwitchConfig() exits.

Parameters

notifierHandle	pointer to notifier handle
configIndex	Index of the target configuration.
policy	Transaction policy, kNOTIFIER_PolicyAgreement or kNOTIFIER_PolicyForcible.

Returns

An error code or kStatus_Success.

27.6.3 uint8_t NOTIFIER_GetErrorCallbackIndex (notifier_handle_t * *notifierHandle*)

This function returns an index of the last callback that failed during the configuration switch while the last NOTIFIER_SwitchConfig() was called. If the last NOTIFIER_SwitchConfig() call ended successfully value equal to callbacks number is returned. The returned value represents an index in the array of static call-backs.

Parameters

notifierHandle	Pointer to the notifier handle

Returns

Callback Index of the last failed callback or value equal to callbacks count.

Chapter 28
Shell

28.1 Overview

This part describes the programming interface of the Shell middleware. Shell controls MCUs by commands via the specified communication peripheral based on the debug console driver.

28.2 Function groups

28.2.1 Initialization

To initialize the Shell middleware, call the SHELL_Init() function with these parameters. This function automatically enables the middleware.

```
void SHELL_Init(p_shell_context_t context, send_data_cb_t send_cb,
      recv_data_cb_t recv_cb, char *prompt);
```

Then, after the initialization was successful, call a command to control MCUs.

This example shows how to call the SHELL_Init() given the user configuration structure.

```
SHELL_Init(&user_context, SHELL_SendDataCallback, SHELL_ReceiveDataCallback, "SHELL>> ");
```

28.2.2 Advanced Feature

- Support to get a character from standard input devices.

  ```
  static uint8_t GetChar(p_shell_context_t context);
  ```

Commands	Description
Help	Lists all commands which are supported by Shell.
Exit	Exits the Shell program.
strCompare	Compares the two input strings.

Input character	Description
A	Gets the latest command in the history.
B	Gets the first command in the history.
C	Replaces one character at the right of the pointer.

Input character	Description
D	Replaces one character at the left of the pointer.
	Run AutoComplete function
	Run cmdProcess function
	Clears a command.

28.2.3 Shell Operation

```
SHELL_Init(&user_context, SHELL_SendDataCallback, SHELL_ReceiveDataCallback, "SHELL>> ");
SHELL_Main(&user_context);
```

Data Structures

- struct p_shell_context_t
  Data structure for Shell environment. More...
- struct shell_command_context_t
  User command data structure. More...
- struct shell_command_context_list_t
  Structure list command. More...

Macros

- #define SHELL_USE_HISTORY (0U)
  Macro to set on/off history feature.
- #define SHELL_SEARCH_IN_HIST (1U)
  Macro to set on/off history feature.
- #define SHELL_USE_FILE_STREAM (0U)
  Macro to select method stream.
- #define SHELL_AUTO_COMPLETE (1U)
  Macro to set on/off auto-complete feature.
- #define SHELL_BUFFER_SIZE (64U)
  Macro to set console buffer size.
- #define SHELL_MAX_ARGS (8U)
  Macro to set maximum arguments in command.
- #define SHELL_HIST_MAX (3U)
  Macro to set maximum count of history commands.
- #define SHELL_MAX_CMD (20U)
  Macro to set maximum count of commands.
- #define SHELL_OPTIONAL_PARAMS (0xFF)
  Macro to bypass arguments check.

Typedefs

- typedef void(∗ send_data_cb_t)(uint8_t ∗buf, uint32_t len)
  Shell user send data callback prototype.
- typedef void(∗ recv_data_cb_t)(uint8_t ∗buf, uint32_t len)

Shell user receiver data callback prototype.
- typedef int(∗ printf_data_t)(const char ∗format,...)
  Shell user printf data prototype.
- typedef int32_t(∗ cmd_function_t)(p_shell_context_t context, int32_t argc, char ∗∗argv)
  User command function prototype.

Enumerations

- enum fun_key_status_t {
  kSHELL_Normal = 0U,
  kSHELL_Special = 1U,
  kSHELL_Function = 2U }
  A type for the handle special key.

Shell functional operation

- void SHELL_Init (p_shell_context_t context, send_data_cb_t send_cb, recv_data_cb_t recv_cb, printf_data_t shell_printf, char ∗prompt)
  Enables the clock gate and configures the Shell module according to the configuration structure.
- int32_t SHELL_RegisterCommand (const shell_command_context_t ∗command_context)
  Shell register command.
- int32_t SHELL_Main (p_shell_context_t context)
  Main loop for Shell.

28.3 Data Structure Documentation

28.3.1 struct shell_context_struct

Data Fields

- char ∗ prompt
  Prompt string.
- enum _fun_key_status stat
  Special key status.
- char line [SHELL_BUFFER_SIZE]
  Consult buffer.
- uint8_t cmd_num
  Number of user commands.
- uint8_t l_pos
  Total line position.
- uint8_t c_pos
  Current line position.
- send_data_cb_t send_data_func
  Send data interface operation.
- recv_data_cb_t recv_data_func
  Receive data interface operation.
- uint16_t hist_current
  Current history command in hist buff.
- uint16_t hist_count

Total history command in hist buff.
- char hist_buf [SHELL_HIST_MAX][SHELL_BUFFER_SIZE]
  History buffer.
- bool exit
  Exit Flag.

28.3.2 struct shell_command_context_t

Data Fields

- const char ∗ pcCommand
  The command that is executed.
- char ∗ pcHelpString
  String that describes how to use the command.
- const cmd_function_t pFuncCallBack
  A pointer to the callback function that returns the output generated by the command.
- uint8_t cExpectedNumberOfParameters
  Commands expect a fixed number of parameters, which may be zero.

28.3.2.0.0.44 Field Documentation

28.3.2.0.0.44.1 const char∗ shell_command_context_t::pcCommand

For example "help". It must be all lower case.

28.3.2.0.0.44.2 char∗ shell_command_context_t::pcHelpString

It should start with the command itself, and end with "\r\n". For example "help: Returns a list of all the commands\r\n".

28.3.2.0.0.44.3 const cmd_function_t shell_command_context_t::pFuncCallBack

28.3.2.0.0.44.4 uint8_t shell_command_context_t::cExpectedNumberOfParameters

28.3.3 struct shell_command_context_list_t

Data Fields

- const shell_command_context_t ∗ CommandList [SHELL_MAX_CMD]
  The command table list.
- uint8_t numberOfCommandInList
  The total command in list.

28.4 Macro Definition Documentation

28.4.1 #define SHELL_USE_HISTORY (0U)

28.4.2 #define SHELL_SEARCH_IN_HIST (1U)

28.4.3 #define SHELL_USE_FILE_STREAM (0U)

28.4.4 #define SHELL_AUTO_COMPLETE (1U)

28.4.5 #define SHELL_BUFFER_SIZE (64U)

28.4.6 #define SHELL_MAX_ARGS (8U)

28.4.7 #define SHELL_HIST_MAX (3U)

28.4.8 #define SHELL_MAX_CMD (20U)

28.5 Typedef Documentation

28.5.1 typedef void(∗ send_data_cb_t)(uint8_t ∗buf, uint32_t len)

28.5.2 typedef void(∗ recv_data_cb_t)(uint8_t ∗buf, uint32_t len)

28.5.3 typedef int(∗ printf_data_t)(const char ∗format,...)

28.5.4 typedef int32_t(∗ cmd_function_t)(p_shell_context_t context, int32_t argc, char ∗∗argv)

28.6 Enumeration Type Documentation

28.6.1 enum fun_key_status_t

Enumerator

kSHELL_Normal Normal key.
kSHELL_Special Special key.
kSHELL_Function Function key.

28.7 Function Documentation

28.7.1 void SHELL_Init (p_shell_context_t *context*, send_data_cb_t *send_cb*, recv_data_cb_t *recv_cb*, printf_data_t *shell_printf*, char ∗ *prompt*)

This function must be called before calling all other Shell functions. Call operation the Shell commands with user-defined settings. The example below shows how to set up the middleware Shell and how to call the SHELL_Init function by passing in these parameters. This is an example.

```
*    shell_context_struct user_context;
*    SHELL_Init(&user_context, SendDataFunc, ReceiveDataFunc, "SHELL>> ");
*
```

Parameters

context	The pointer to the Shell environment and runtime states.
send_cb	The pointer to call back send data function.
recv_cb	The pointer to call back receive data function.
prompt	The string prompt of Shell

28.7.2 int32_t SHELL_RegisterCommand (const shell_command_context_t ∗ *command_context*)

Parameters

command_-context	The pointer to the command data structure.

Returns

-1 if error or 0 if success

28.7.3 int32_t SHELL_Main (p_shell_context_t *context*)

Main loop for Shell; After this function is called, Shell begins to initialize the basic variables and starts to work.

Parameters

context	The pointer to the Shell environment and runtime states.

Returns

This function does not return until Shell command exit was called.

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