
ARC labs handbook

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**CHAPTER
ONE**

OVERVIEW

1.1 Introduction

This is a handbook for ARC labs which is a part of ARC university courses. It's written to help students who attend the ARC university courses and anyone who is interested in DesignWare® ARC® processors to get started in DesignWare® ARC® processors processor development. It describes all the basic elements of ARC labs and how to finish the labs with step by step approach.

This book can be used as a Lab teaching material for ARC university courses at undergraduate or graduate level with majors in Computer Science, Computer Engineering, Electrical Engineering; or for professional engineers.

This handbook includes 12 labs currently (more labs will be added in the future), which can be classified into 3 levels:

- *Level 1: ARC basic*

The labs in this level cover the basic topics about DesignWare® ARC® processors, e.g., the installation of tools, hello world, interrupts, timers and so on.

- *Level 2: ARC advance*

The labs in this level cover the advanced topics about DesignWare® ARC® processors, e.g., RTOS, customized linkage, ARC DSP and so on.

- *Level 3: ARC exploration*

The labs in this level will cover some complex applications about DesignWare® ARC® processors, e.g., IoT application, embedded machine learning and so on.

Most of labs are based on the [embARC Open Software Platform \(OSP\)](#) which is an open software platform to facilitate the development of embedded systems based on DesignWare® ARC® processors.

It is designed to provide a unified platform for DesignWare® ARC® processors users by defining consistent and simple software interfaces to the processor and peripherals, together with ports of several well known FOSS embedded software stacks to DesignWare® ARC® processors.

For more details about embARC OSP, please refer its [online docs](#)

1.2 Supported Hardware Platform

At present, the following hardware platforms are supported in this handbook.

- [ARC EM Starter Kit](#)
- [ARC IoT Development Kit](#)

You can go to the above specific link to get the board's data sheet and user manual as a reference.

1.3 Reference

Here is reference for this hand book.

Item	Name
1	ARC EM Databook
2	MetaWare docs
3	ARC EM Starter Kit User Guide
4	ARC GNU docs

GETTING STARTED

Use this guide to get started with your ARC labs development.

2.1 Software Requirement

- **ARC Development Tools** Choose **MetaWare Toolkit** and/or **ARC GNU Toolchain** from the following list according to your requirement.
 - MetaWare Toolkit
 - * **Premium MetaWare Development Toolkit (2018.06)** The DesignWare ARC MetaWare Development Toolkit builds upon a 25-year legacy of industry-leading compiler and debugger products. It is a complete solution that contains all the components needed to support the development, debugging and tuning of embedded applications for the DesignWare ARC processors.
 - * **DesignWare ARC MetaWare Toolkit Lite (2018.06)** A demonstration/evaluation version of the MetaWare Development Toolkit is available for free from the Synopsys website. MetaWare Lite is a functioning demonstration of the MetaWare Development Toolkit, but has a number of restrictions, including a code-size limit of 32 Kilobytes and no runtime library sources. It is available for Microsoft Windows only.
 - ARC GNU Toolchain
 - * **Open Source ARC GNU IDE (2018.03)** The ARC GNU Toolchain offers all of the benefits of open source tools, including complete source code and a large install base. The ARC GNU IDE Installer consists of Eclipse IDE with **ARC GNU plugin for Eclipse**, **ARC GNU prebuilt toolchain** and **OpenOCD for ARC**
- **Digilent Adept Software** for Digilent JTAG-USB cable driver. All the supported boards are equipped with on board USB-JTAG debugger, so just one USB cable is required, no need for external debugger.
- **Tera Term** or **PUTTY** for serial terminal connection, 115200 baud, 8 bits data, 1 stop bit and no parity (115200-8-N-1) by default.

Note: If using embARC with GNU toolchain on Windows, install **Zadig** to replace FTDI driver with WinUSB driver. See **How to Use OpenOCD on Windows** for more information. If you want to switch back to Metaware toolchain, you should also switch back the usb-jtag driver from WinUSB to FTDI driver.

2.2 Install Software Tools

2.2.1 Install Metaware Toolkit

Here we will start install MetaWare Development Toolkit (2017.09).

1. Double click the **mw_dikit_arc_i_2017_09_win_install.exe**, it will show



2. Click next, choose I accept, continue to click next



3. Choose Typical installation, then click next



4. Set the install path (please use English letters only and no space), then click next until the installation is finished



5. Set the license file (SNPSLMD_LICENSE_FILE) for MetaWare Development Toolkit. It can be a real file containing license, also can be a license server
 - For Windows, go to Computer->property->Advanced->Environment Variables->System Variables->New to Set



- For Linux, please add SNPSLMD_LICENSE_FILE into your system variables
6. Test the MetaWare Development Toolkit and its license

Open cmd.exe in Windows and find the queens.c in the installation folder of MetaWare Development Toolkit, e.g., C:\ARC\MetaWare\arc\demos\queen.c. Type the following commands in cmd

```
# On Windows
cd C:\ARC\MetaWare\arc\demos
ccac queens.c
```

If you get the following message and no error, it means MetaWare Development Toolkit is successfully installed and license is ok.

```
MetaWare C Compiler N-2017.09 (build 005)           Serial 1-799999.  
(c) Copyright 1987-2017, Synopsys, Inc.  
MetaWare ARC Assembler N-2017.09 (build 005)  
(c) Copyright 1996-2017, Synopsys, Inc.  
MetaWare Linker (ELF/ARCompact) N-2017.09 (build 005)  
(c) Copyright 1995-2017, Synopsys, Inc.
```

2.2.2 Install ARC GNU Toolchain

Please go [here](https://github.com/foss-for-synopsys-dwc-arc-processors/toolchain/releases) (<https://github.com/foss-for-synopsys-dwc-arc-processors/toolchain/releases>) to get the latest version of ARC GNU toolchain.

To use and install ARC GNU toolchain, you can refer [this](http://embarc.org/toolchain/ide/index.html) (<http://embarc.org/toolchain/ide/index.html>), where has detailed instructions.

It's recommended to install ARC GNU toolchain in the path (windows: C:\\arc_gnu\\, linux: ~/arc_gnu/) and add arc_gnu/bin into \$PATH variable.

2.2.3 Install embARC OSP

The embARC OSP source code is hosted in a GitHub repository that supports cloning via git. There are scripts and such in this repo that you'll need to set up your development environment, and we'll be using Git to get this repo. If you don't have Git installed, see the beginning of the OS-specific instructions below for help.

We'll begin by using Git to clone the repository anonymously.

```
# On Windows  
cd %userprofile%  
# On Linux  
cd ~  
  
git clone https://github.com/foss-for-synopsys-dwc-arc-processors/embarc_osp.git  
→embarc_osp
```

You have successfully checked out a copy of the source code to your local machine.

2.3 Final Check

Check the following items and set development environment.

- Make sure the paths of the above required tools for the MetaWare toolkit and ARC GNU toolchain are added to the system variable **PATH** in your environment variables.
- We recommend users to install ARC GNU IDE to default location. Otherwise you need to make additional changes as below.
 - If running and debugging embARC applications using **arc-elf32-gdb** and **OpenOCD for ARC**, make sure 1) the path of **OpenOCD** is added to the **PATH** in your environment variables, and 2) modify **OPENOCD_SCRIPT_ROOT** variable in <embARC>/options/toolchain/toolchain_gnu.mk according to your **OpenOCD** root path.
 - If running GNU program with using the GNU toolchain on Linux, modify the **OpenOCD** configuration file as Linux format with LF line terminators. **dos2unix** can be used to convert it.

Note: Check the version of your toolchain. The embARC OSP software build system is purely makefile-based. **make/gmake** is provided in the MetaWare toolkit (gmake) and ARC GNU toolchain (make)

3.1 Overview

3.2 Labs

3.2.1 Level 1 Labs

How to use ARC IDE

MetaWare ToolKit

Purpose

- Learn the MetaWare IDE integration interface
- Familiar with the use of the MetaWare IDE interface and command line
- Familiar with the features and usage of the MetaWare Debugger debugger

Equipment

PC, MetaWare Development Toolkit, nSIM simulator, core_test source file in embAR OSP

Content

Create a C project using the Metaware IDE graphical interface, import the code CoreTest.c, configure compilation options to compile, and generate executable files.

Start the debugger of MetaWare IDE and enter debug mode. From the different angles of C language and assembly language, use the functions of setting breakpoint, single step execution, full speed execution, etc., combined with observing PC address, register status, global variable status and Profiling performance to analyze the debug target program.

Principles

Use the MetaWare IDE integrated development environment to create projects and load code. In the engineering unit, configure the compile option to compilation code, debug and analyze the compiled executable file.

Routine code CoreTest.c:

```
////////////////////////////////////////////////////////////////
// This small demo program finds the data point that is the
// minimal distance from x and y [here arbitrarily defined to be (4,5)]
//
// #define/undefine '_DEBUG' precompiler variable to obtain
// desired functionality. Including _DEBUG will bring in the
// I/O library to print results of the search.
//
// For purposes of simplicity, the data points used in the computations
// are hardcoded into the POINTX and POINTY constant values below
////////////////////////////////////////////////////////////////

#ifndef _DEBUG
#include "stdio.h"
#endif

#define POINTX {1, 2, 3, 4, 5, 6, 7, 8, 9, 10}
#define POINTY {2, 4, 6, 8, 10, 12, 14, 16, 18, 20}
#define POINTS 10

#define GetError(x, y, Px, Py) \
    ( (x-Px)*(x-Px) + (y-Py)*(y-Py) )

int main(int argc, char* argv[]) {
    int pPointX[] = POINTX;
    int pPointY[] = POINTY;

    int x, y;
    int index, error, minindex, minerror;

    x = 4;
    y = 5;

    minerror = GetError(x, y, pPointX[0], pPointY[0]);
    minindex = 0;

    for(index = 1; index < POINTS; index++) {
        error = GetError(x, y, pPointX[index], pPointY[index]);

        if (error < minerror) {
            minerror = error;
            minindex = index;
        }
    }

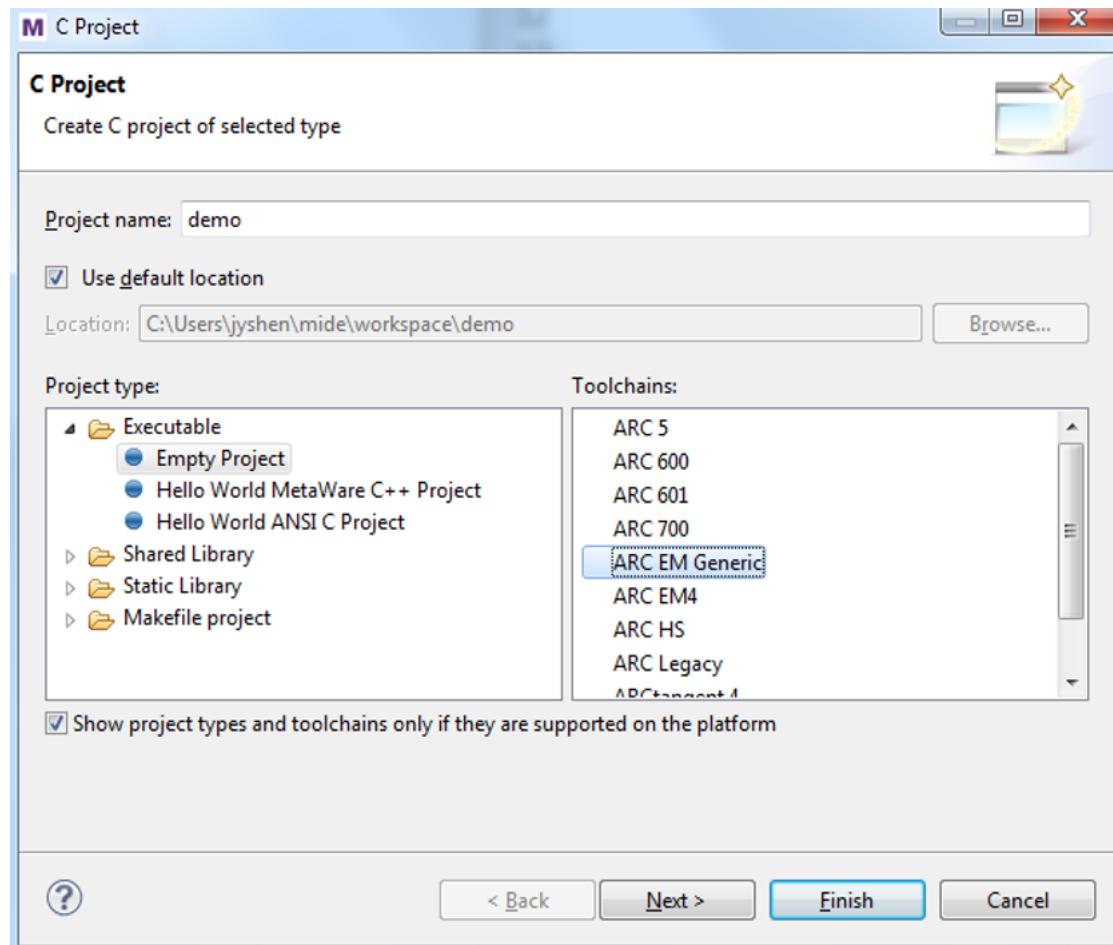
#ifdef _DEBUG
    printf("minindex = %d, minerror = %.2f.\n", minindex, minerror);
    printf("The point is (%d, %d).\n", pPointX[minindex], pPointY[minindex]);
    getchar();
#endif

    return 0;
}
```

Steps

Establishing a project

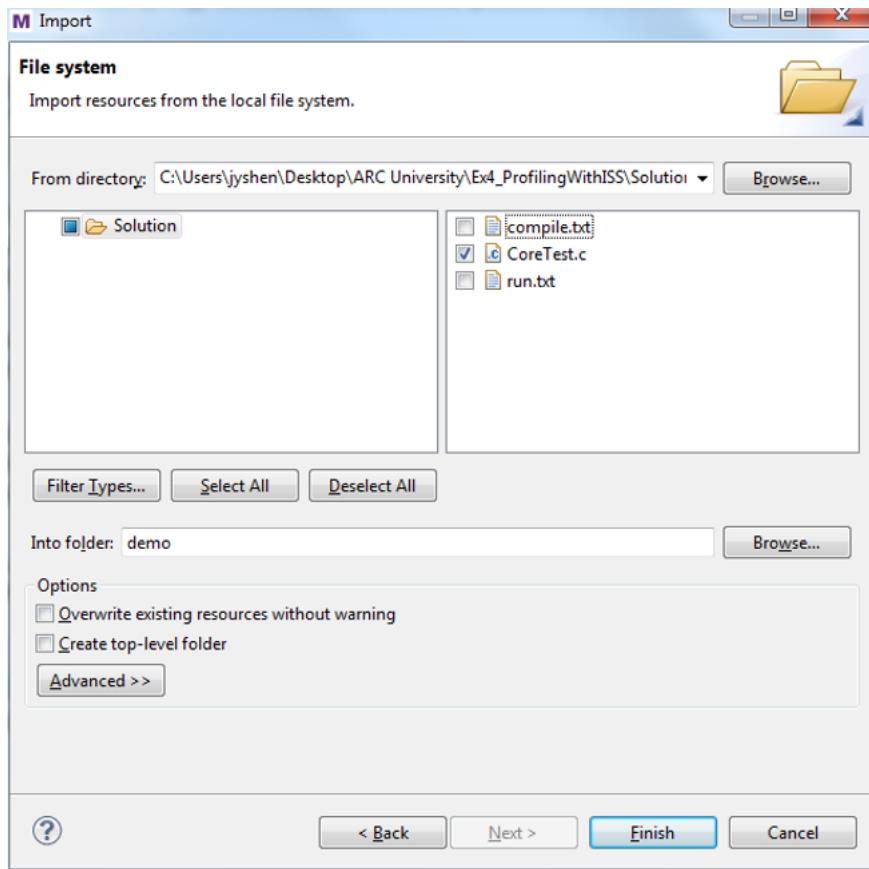
Open the MetaWare IDE, create an empty project called demo, and select the ARC EM series processor, as shown below (figure 1).



Import the code file CoreTest.c to the project demo.

In the Project Explorer on the left side of the MetaWare IDE main interface, click the icon  and select Import from the pop-up menu.

At this point, a dialog called Import appears, select the File System item in the General tab, and then click next. As shown in the figure below, add the file directory where the source code CoreTest.c is located. The dialog box will automatically display the name of the directory and the file name of the file contained in the directory. Select the file to be added, CoreTest.c, and click Finish to complete the entire import process(figure2).



After the import is complete, you can see the code file CoreTest.c you just added in the Project Explorer on the left side of the MetaWare IDE main interface.

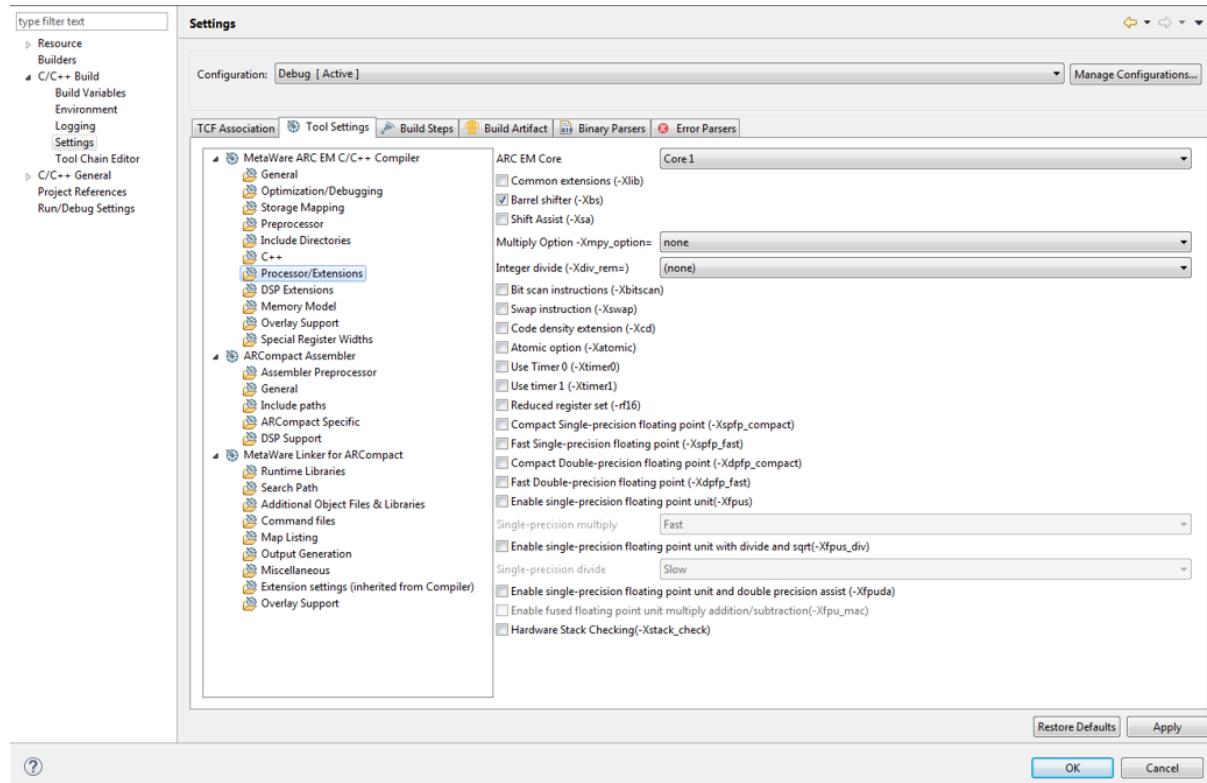
Set compilation options

Right click on the current project demo and select Properties in the popup tab. Click C/C++ Build, settings, Tool Settings to open the compile option settings page, as shown below(figure3).



In the current interface, select Optimization/Debugging to set the compiler optimization and debugging level. For example, set the optimization level to turn off optimization, and set the debugging level to load all debugging information

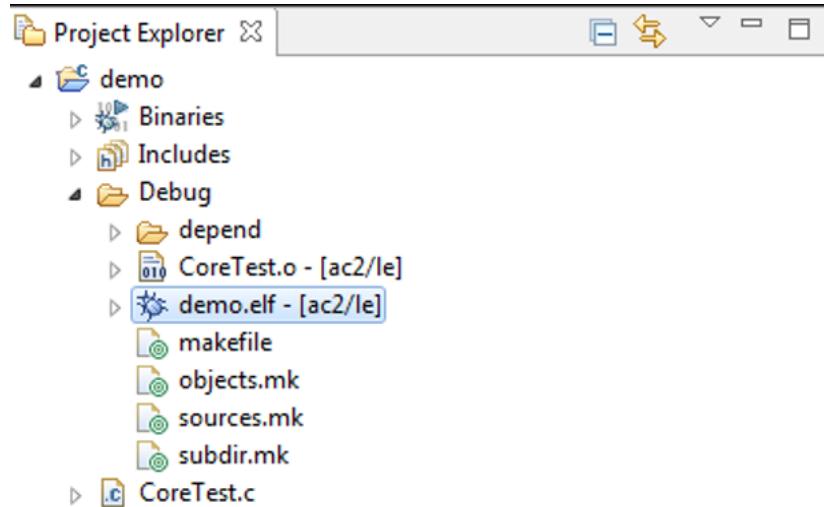
Select Processor/Extensions on the current interface to set the compile options corresponding to the target processor hardware properties, such as the version of the processor, whether to support extended instructions such as shift, multiplication, floating-point operations, etc., whether to include Timer0/1. As shown in the figure below, this setting indicates that the target processor supports normal extended instructions(figure4).



Finally select MetaWare ARC EM C/C++ and check the settings compile options in the All options column on the right. Then click OK to close the Properties dialog.

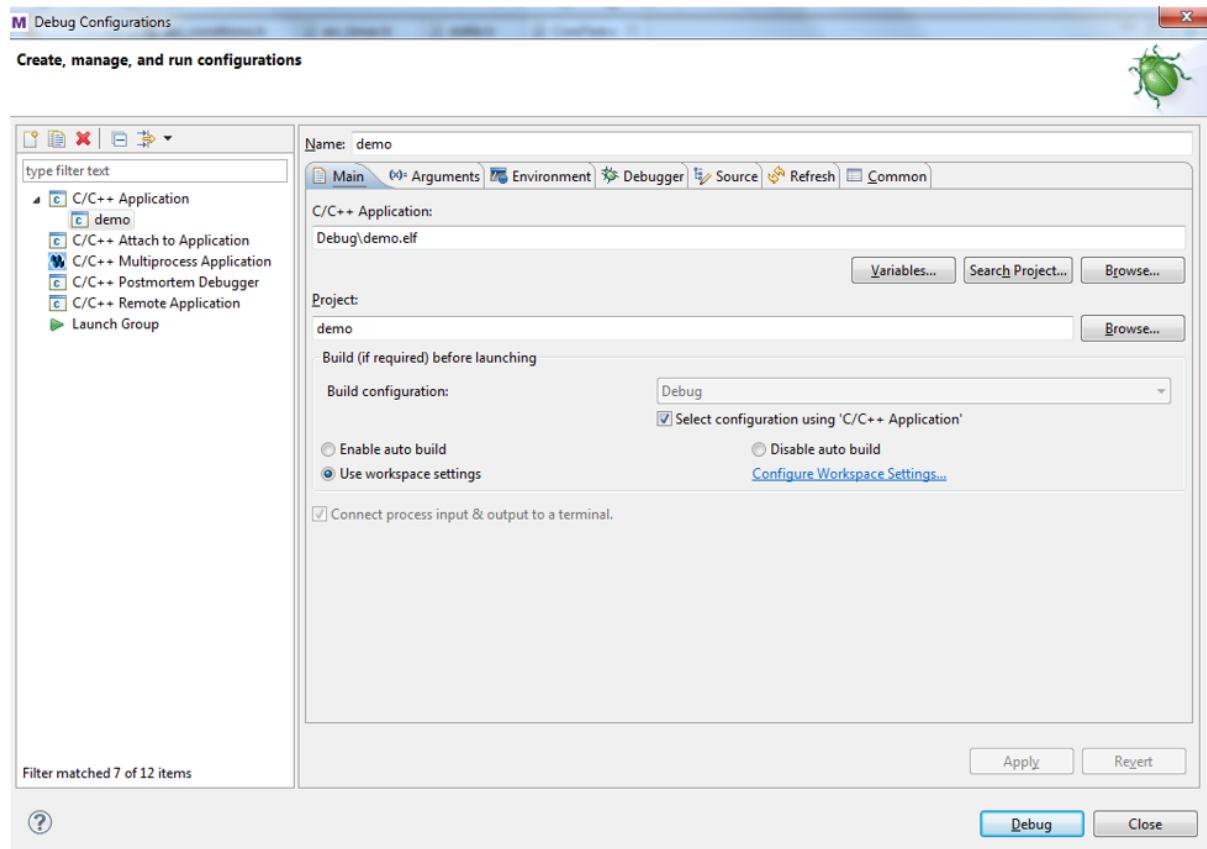
Compile project demo

Select Build Project from the Project drop-down menu in the MetaWare IDE main menu or click the icon  . In the middle of the MetaWare IDE main interface, select the Console tab to view the logs during compilation. When the message ‘Finished building target: demo.elf’ appears, the compilation is successful, and the compiled executable file demo.elf can be seen in the Project Explorer on the left side of the MetaWare IDE main interface, as shown in the following figure(figure5).



Set debug options

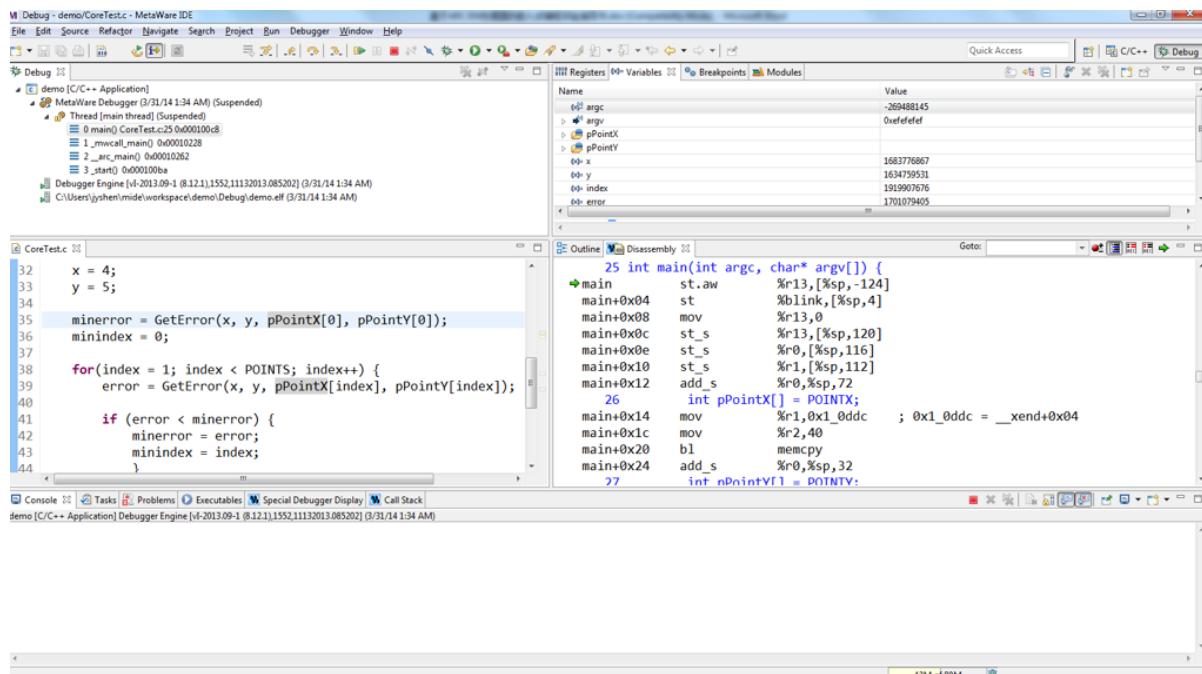
Select Debug Configurations from the Run drop-down menu in the MetaWare IDE main menu. Then double-click on C/C++ Application or right-click on New to get a dialog similar to the one below(figure6).



Click Debugger in the right tab, generally do not need to make any changes, finally check the contents of the bottom Debugger Options, click Debug to enter the debugging interface.

Debug executable file demo.elf

First, select the required debug window in the pull-down menu Debugger in the main menu of the debug interface, such as source code window, assembly code window, register window, global variable window, breakpoint window, function window, etc., as shown in the following figure(figure7).

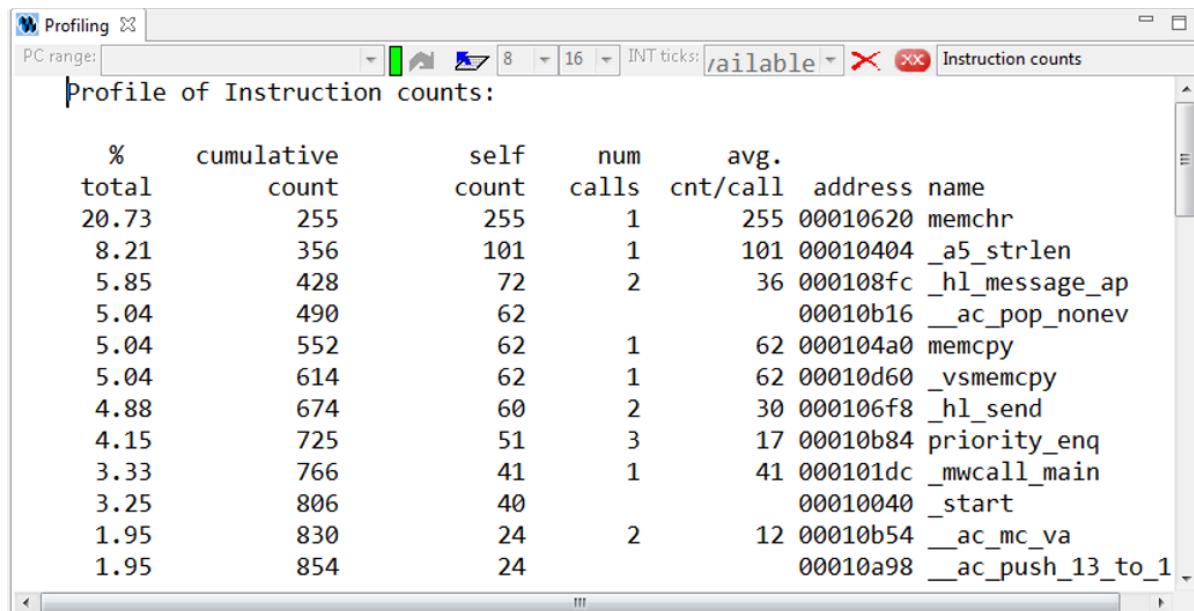


In the C code window, right-click the code line number on the left side of the window, select Toggle Breakpoint in the pop-up menu or double-click the line number to set a breakpoint on the current line. In the assembly code window, double-click a line of code to set a breakpoint on the current line.

Once the breakpoint is set, click the icon to run the program. After that, the program will run directly to the nearest breakpoint. At this point, you can observe the current program execution and the relevant status information of the processor through the various windows called in the previous step. If you want to know more about the details of program execution and the instruction behavior of the processor, you can use the following three execution commands | | to perform single-step debugging. The icon can choose to step through a C language statement or an assembly instruction to match the status information of each window. It can be very convenient for program debugging. If you want to end the current debugging process, click the icon . And if you want to return to the main MetaWare IDE page, click C/C++ in the upper right corner icon .

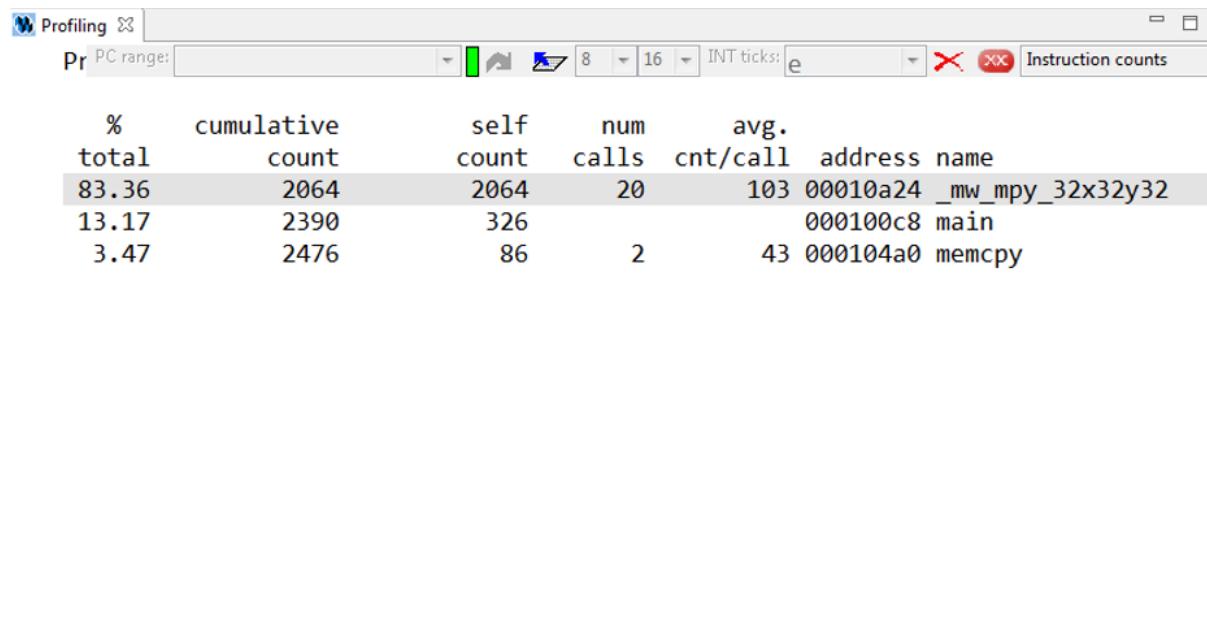
Code performance analysis using the debugger

Based on the previous project demo, open the Compile Options dialog in step 3 and set the Optimization Level to -O0 in the Optimization/Debugging column. Then click to recompile the project, then click to enter the debugging interface. Click Debugger in the main menu of the debugging interface, select Disassembly in the pop-up drop-down menu, open the disassembly code window, and you can see that the program is paused at the entrance of the main() function. In the same way, select Profiling in the Debugger drop-down menu, open the performance analysis window and click the icon in the window, as shown below(figure8).



The Profiling window displays the corresponding of the number of executed instructions of the program with each function under the current debug window. From left to right, the total number of executions of function instructions in the total number of executions of the entire program instruction, the total number of executions of the accumulated instructions, the total number of executions of the functions, the number of times the function is called, the number of including functions, the address of the function, and the name of the function. Through the relationship between the instruction information and the function in the Profiling window, it is very convenient to analyze the program efficiency and find the shortcoming of the program performance.

Let's take this project as an example to continue to introduce the use of the Profiling window. At this point, the program is paused at the entrance of the main() function and the Profiling window opens as shown above. The main() function is the main object of performance analysis optimization. At this time, the content displayed in the Profiling window is actually some function information initialized by the processor before the main() function is executed. Click the icon in the Profiling window to clear the current information. If you click the icon again, nothing will be displayed, And it indicate that the cleaning is successful. Then, set a breakpoint at the last statement of the main() function (either C statement or assembly statement), and click the icon in the toolbar above the debug interface to let the program execute to the breakpoint. Next, click on the icon in the Profiling window again, and only the information related to the main() function will be displayed, as shown below. Therefore, flexible setting of breakpoints, combined with the clear function, can perform performance analysis on the concerned blocks(figure9).



It can be seen that the multiplication library function `_mw_mpy_32x32y32` in the `main()` function is called 20 times, and a total of 2064 instructions are executed, while the `main()` function itself executes only 326 instructions, and the `memcpy` function executes 86 instructions. It can be seen that the implementation of the multiplication function of the program consumes a large number of instructions, and the large number of instructions means that the processor will spend a large number of computation cycles to perform multiplication operations. Therefore, multiplication is the shortcoming of current program performance. If you want to improve the performance of the program, you should first consider how you can use fewer instructions and implement multiplication more efficiently.

Exercises

How can I implement multiplication more efficiently with fewer instructions? Apply this method to the project demo of the fifth part, analyze it with the debugger's Profiling function, observe the total number of instructions consumed by the `main` function, and compare it with the previous Profiling result of Figure 8.

Note: The expand multiply instruction

How to use embARC OSP

Purpose

Equipment

Content

Principles

Steps

Exercises

ARC features: timer and auxiliary registers

Purpose

- To learn the timer resource of ARC EM processor
- To learn how to use the auxiliary registers to control the timer
- Read the count value of the timer, and implement a time clock by the timer

Equipment

PC, IoT DK, embARC OSP, example \Lab\timer in embARC OSP

Content

Read the auxiliary registers of ARC EM to get the version and other setting information of the timer resource. As all the EM processors have **Timer0**, we use the **Timer0** in this lab, and write the auxiliary registers to initialize, start and stop the timer. By reading the count value of the timer, we can calculate the execution time of a code block with the count value and the clock frequency.

Principles

Introduction of timer and auxiliary registers

The timers in ARC EM processor

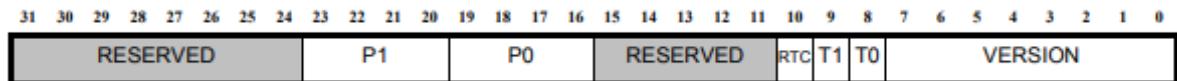
- Two 32-bits programmable timers **Timer0** and **Timer1**
- One 64-bits **RTC**(Real-Time Counter)

All the times are configurable, for example, there are four EM processor cores in **ARC EMSK1.1**, the configuration information are as follow.

Timer	EM4	EM4_16CR	EM4	EM4_16CR
HAS_TIMER0	1	1	1	1
HAS_TIMER1	1	0	1	0
RTC_OPTION	0	0	0	0

The auxiliary register Timer BCR stored the timer resource information of an EM processor core, the register address of **TIMER_BUILD** is *0x75*.

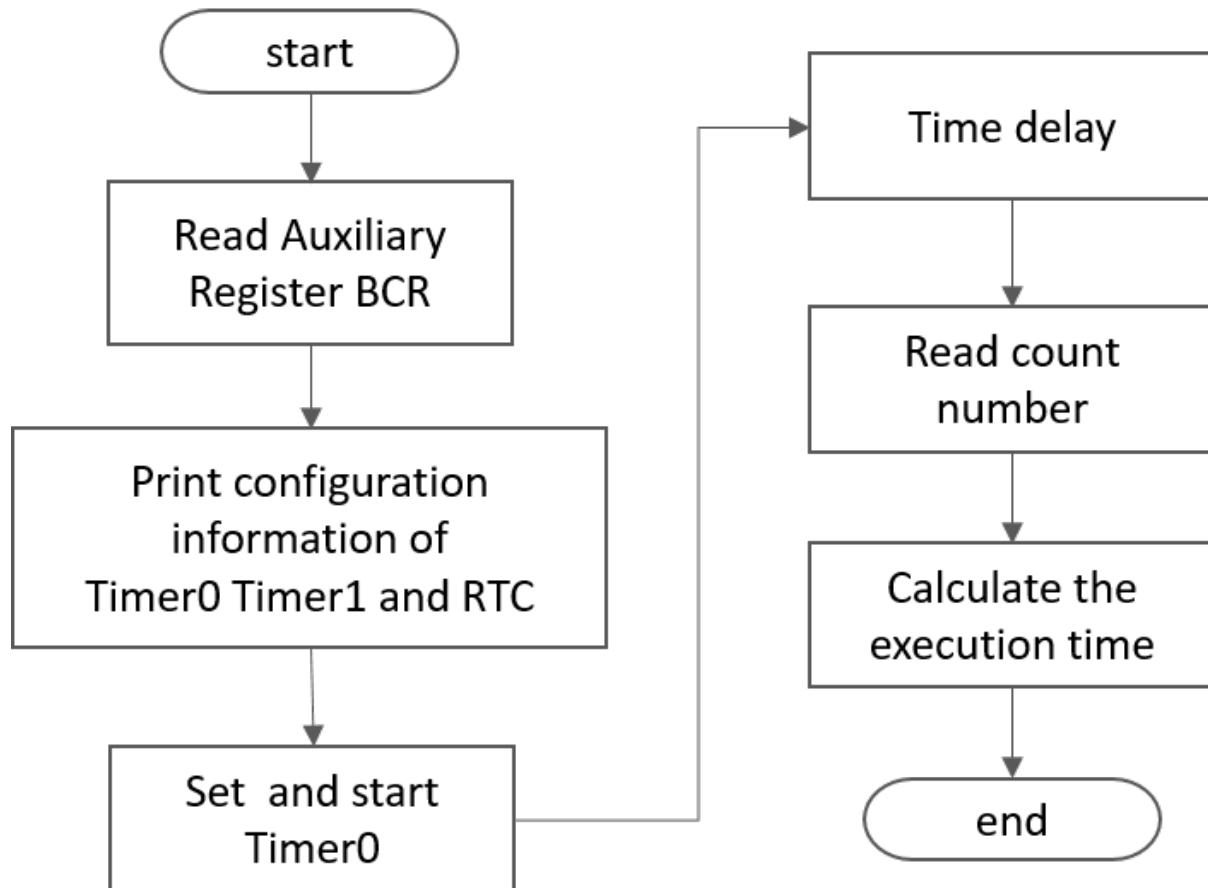
TIMER_BUILD



As we know the timer resources the EM processor configured, we can get the timer's configuration information and control the timers by writing and reading the auxiliary register of that timer. For example, there are the related auxiliary registers of the **Timer0**.

Auxiliary Register	Name	Permission	Description
0x21	COUNT0	RW	Processor timer 0 count value
0x22	CONTROL0	RW	Processor timer 0 control value
0x23	LIMIT0	RW	Processor timer 0 limit value

Program flow chart



Steps

Makefile configuration

There are two ways to do the configuration.

First, configured by compile command, for example:

```
make BOARD=iotdk BD_VER=10 CUR_CORE=arcem9d -j4 TOOLCHAIN=gnu run
```

Second, configured by modifying the makefile. At here, the compile command will be very simple, for example:

```
make -j4 run
```

Open the folder *embarc_osp\example\Lab\timer*, and open the *makefile*, here is the default configuration.

```
# Application name
APPL ?= lab_3_Timer_Interrupts

## 
## Current Board And Core
##
BOARD ?= iotdk
BD_VER ?= 10
CUR_CORE ?= arcem9d

## 
## Set toolchain
##
TOOLCHAIN ?= gnu

##
## root dir of embARC
##
EMBARC_ROOT = ../../..

MID_SEL = common

# application source dirs
APPL_CSRC_DIR = .
APPL_ASMSRC_DIR = .

# application include dirs
APPL_INC_DIR = .
```

- Reconfigure **BOARD** and **CUR_CORE**, in this lab, we use the launch board *iotdk*

```
## 
## Current Board And Core
##
BOARD ?= iotdk
BD_VER ?= 10
CUR_CORE ?= arcem9d
```

- Reconfigure **TOOLCHAIN**, select the toolchain *gnu* or *metaware* you used

```
## 
## Set toolchain
##
TOOLCHAIN ?= gnu
```

- Reconfigure **EMBARC_ROOT**, make sure the relative path between *embARC OSP* root folder and the *timer* folder is correct.

```
## 
## root dir of embARC
##
EMBARC_ROOT = ../../..
```

Main code

Read auxiliary register BCR_BUILD

We can use the function `_arc_aux_read` to read the auxiliary register for the timer resource information.

Read auxiliary register **TIMER_BUILD**. In the register **TIMER_BUILD** The lower 8 bits indicate the core version information, the bit 9 indicate the **Timer0**, the bit 10 indicate the **Timer1**, the bit 11 indicate the **RTC**. Here is the code:

```
uint32_t bcr = _arc_aux_read(AUX_BCR_TIMERS);
int timer0_flag=(bcr >> 8) & 1;
int timer1_flag=(bcr >> 9) & 1;
int RTC_flag=(bcr >> 10) & 1;
```

Read timer related auxiliary registers, for example, the **Timer0**. Here is the code:

```
EMBARC_PRINTF("Does this timer0 exist? YES\r\n");
/*Read auxiliary register configuration information*/
EMBARC_PRINTF("timer0's operating mode:0x%08x\r\n",_arc_aux_read(AUX_TIMER0_CTRL));
EMBARC_PRINTF("timer0's limit value :0x%08x\r\n",_arc_aux_read(AUX_TIMER0_LIMIT));
EMBARC_PRINTF("timer0's current cnt_number:0x%08x\r\n",_arc_aux_read(AUX_TIMER0_
CNT));
```

Stop-Set-Start the Timer0

We can use the function `_arc_aux_write` to write the auxiliary register.

To control the **Timer0** with the related auxiliary registers.

- **COUNT0**: write this register to set the initial value of the **Timer0**. It will increase from the set value at anytime you write this register.
- **CONTROL0**: write this register to update the control modes of the **Timer0**.
- **LIMIT0**: write this register to set the limit value of the **Timer0**, the limit value is the value after which an interrupt or a reset must be generated.

In this lab, we should stop timer before setting and starting it, the function `timer_stop` is already encapsulated in embARC OSP, you can use this function or directly write the register. And then set the timer work mode, enable interrupt or not and set the limit value. At last start the timer. Here is the code:

```
/* Stop it first since it might be enabled before */
_arc_aux_write(AUX_TIMER0_CTRL, 0);
_arc_aux_write(AUX_TIMER0_LIMIT,0);
_arc_aux_write(AUX_TIMER0_CNT, 0);
/* This is a example about timer0's timer function. */
uint32_t mode = TIMER_CTRL_NH; /*Timing without triggering interruption.*/
uint32_t val = MAX_COUNT;
_arc_aux_write(AUX_TIMER0_CNT, 0);
_arc_aux_write(AUX_TIMER0_LIMIT,val);
/* start the specific timer */
_arc_aux_write(AUX_TIMER0_CTRL,mode);
```

When the timer is running, we can read the count value of the timer, and calculate the execution time of a code block. Here is the code:

```
uint32_t start_cnt=_arc_aux_read(AUX_TIMER0_CNT);
/***
 * code block
 **/
```

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(continued from previous page)

```
uint32_t end_cnt=_arc_aux_read(AUX_TIMER0_CNT);  
uint32_t time=(end_cnt-start_cnt)/(BOARD_CPU_CLOCK/1000);
```

Compile and debug

- Compile and download

Open cmd under the folder *example\Lab\timer*, input the compile command as follow:

```
make -j4 run
```

Note: If your toolchain is metaware, you should use gmake. If you don't use core configuration specified in makefile, you need to pass all the make options to trigger make command

- Output

```
embARC Build Time: Aug 22 2018, 15:32:54
Compiler Version: Metaware, 4.2.1 Compatible Clang 4.0.1 (branches/release_40)
Does this timer0 exist? YES
timer0's operating mode:0x00000003
timer0's limit value :0x00023280
timer0's current cnt_number:0x0000c236
```

```
Does this timer1 exist? YES  
timer1's operating mode:0x00000000  
timer1's limit value :0x00000000  
timer1's current cnt number:0x00000000
```

Does this RTC timer exist? NO

The start_cnt number is:2
/***** TEST MODE START *****/

This is TEST CODE

This is TEST CODE

This is TEST CODE

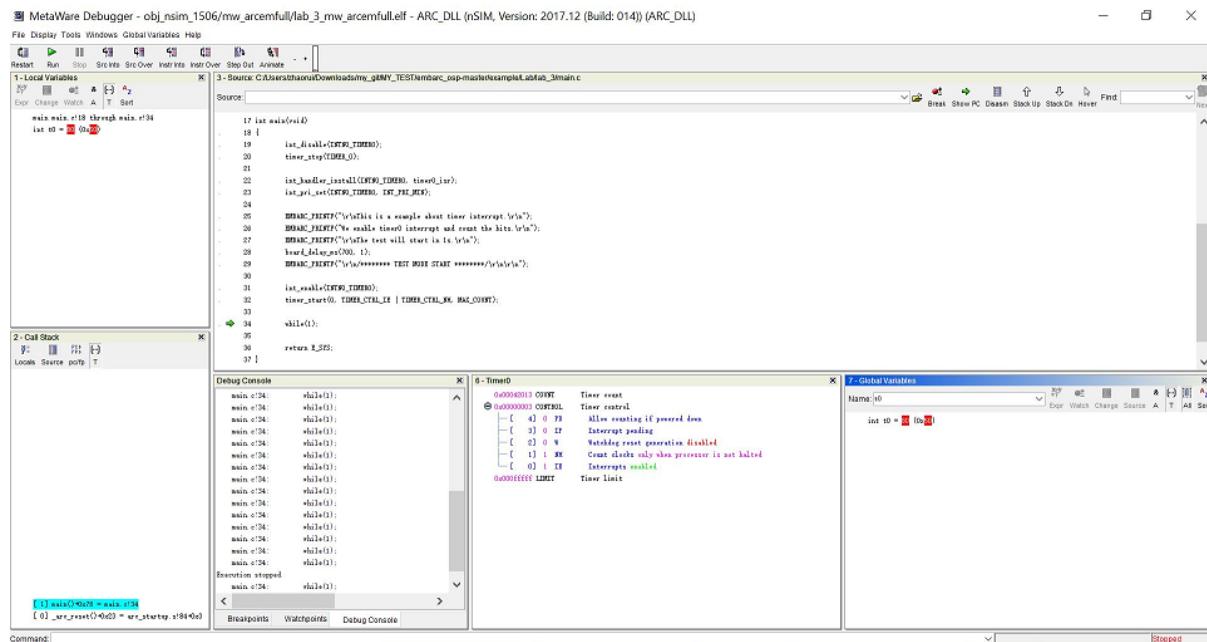
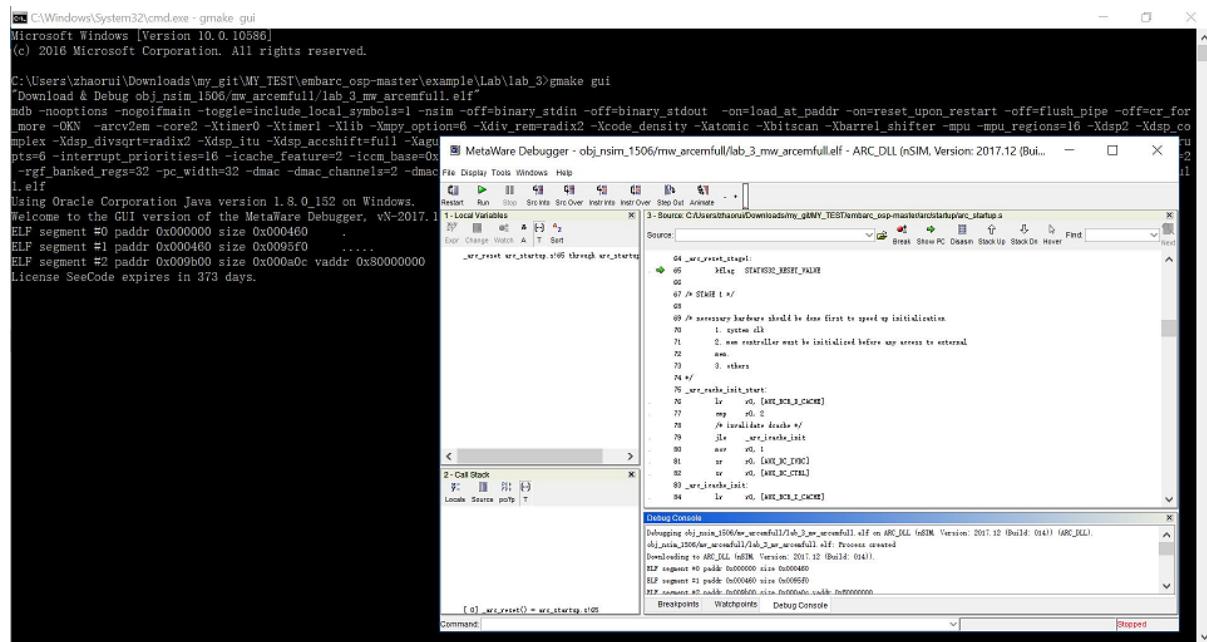
```
/***** TEST MODE END *****/  
The end_cnt number is:16785931  
The board cpu clock is:144000000
```

Total time of TEST CODE BLOCK operation:116

- Debug

Open cmd under the folder *example\Lab\timer*, input the command as follow:

```
make gui
```



The debug view will pop up automatically, we can watch the variables and registers.

Exercises

In the debug view, observe and understand the contents of the interrupt vector table.

Note: Click the Memory button in the debug view Debugger drop-down menu to see the contents of the memory in real time.

ARC features: interrupts

Purpose

- Introduce the interrupt module in the ARC embedded processor
- Demonstrate how to use the interrupt and timer APIs already defined in the embARC processor in the program

Equipment

PC, MetaWare toolchain/ARC GNU toolchain, nSIM simulator (to use GNU, you need to add nSIM to the environment variable first), interrupt source code

Content

This lab and lab 3 are both introductions to the internal characteristics of the embARC processor. Lab 3 introduces the timer. This lab aims to introduce the interrupt of embARC through examplelabinterrupt in the embARC OSP package. The two routines give you a preliminary understanding of the ARC interrupt resources.

Principles

The ARC EM processor uses vector interrupts to handle interrupt events. When the interrupt occurs, the processor stops the execution of the current program, and queries the corresponding interrupt vector in the predefined interrupt vector table according to the current interrupt type, that is, the entry address of the interrupt service program, and then jumps to the address to execute the interrupt service routine. After the execution is completed, return to the interrupted program and complete the response of the interrupt event.

In embARC OSP, we use the int_handler_install function to bind our interrupt function name to the interrupt vector of the corresponding interrupt, and then we can achieve the above functions.

Steps

Open and browse lab one

Go to the `embarc_osp\example\Lab\interrupt` directory, where there are two folders, `lab_4_1` and `lab_4_2`.

We first enter `lab_4_1`, which implements the precise timing function through the timer interrupt, which is the application of the interrupt comparison basis.

Open `main.c` and browse the entire program.

```
#include "embARC.h"
#include "embARC_debug.h"

#define COUNT (BOARD_CPU_CLOCK/1000)

volatile static int t0 = 0;
volatile static int second = 0;

/** arc timer 0 interrupt routine */
static void timer0_isr(void *ptr)
{
    timer_int_clear(TIMER_0);
    t0++;
}
```

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```
/** arc timer 0 interrupt delay */
void timer0_delay_ms(int ms)
{
    t0 = 0;
    while(t0<ms);
}

/** main entry for testing arc fiq interrupt */
int main(void)
{
    int_disable(INTNO_TIMER0);
    timer_stop(TIMER_0);

    int_handler_install(INTNO_TIMER0, timer0_isr);
    int_pri_set(INTNO_TIMER0, INT_PRI_MIN);

    EMBARC_PRINTF("\r\nThis is a example about timer interrupt.\r\n");
    EMBARC_PRINTF("\r\n***** TEST MODE START *****\r\n\r\n");

    int_enable(INTNO_TIMER0);
    timer_start(TIMER_0, TIMER_CTRL_IE | TIMER_CTRL_NH, COUNT);

    while(1)
    {
        timer0_delay_ms(1000);
        EMBARC_PRINTF("\r\n %ds.\r\n", second);
        second++;
    }
    return E_SYS;
}
```

Sub-module analysis lab one code

The code can be roughly divided into three parts: interrupt service function, main function, and delay function.

Let's analyze each one below:

- Interrupt service function:

```
static void timer0_isr(void *ptr)
{
    timer_int_clear(TIMER_0);
    t0++;
}
```

This code is a standard example of an interrupt service function, enters the service function, clears the interrupt flag bit, and then performs the processing that needs to be done in the interrupt service function. Other interrupt service functions can also be written using this template.

In this function, we incremented the count variable t0 by one.

- Main function

```
int main(void)
{
    int_disable(INTNO_TIMER0);
    timer_stop(TIMER_0);

    int_handler_install(INTNO_TIMER0, timer0_isr);
    int_pri_set(INTNO_TIMER0, INT_PRI_MIN);
```

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```

EMBARC_PRINTF ("\r\nThis is a example about timer interrupt.\r\n");
EMBARC_PRINTF ("\r\n***** TEST MODE START *****\r\n\r\n");

int_enable(INTNO_TIMER0);
timer_start(TIMER_0, TIMER_CTRL_IE | TIMER_CTRL_NH, COUNT);

while(1)
{
    timer0_delay_ms(1000);
    EMBARC_PRINTF ("\r\n %ds.\r\n", second);
    second++;
}
return E_SYS;
}

```

The EMBARC_PRINTF function in this code is only used to send information to the computer, which can be ignored during analysis.

This code is divided into two parts: initialization and looping.

In the initialization section, we configured the timer and timer interrupts.

Unlike Lab 3, this code uses the embARC OSP API to implement it. In fact, in essence, these two methods are the same. The API just encapsulates the read and write operations of the auxiliary registers for convenience.

First, in order to configure **Timer0** and its interrupts, we need to turn them off first. This work is done by the functions `int_disable` and `timer_stop`.

Then we configure the interrupt service function and priority for our interrupts. This work is done by the functions `int_handler_install` and `int_pri_set`.

Finally, after the interrupt configuration is complete, we need to enable the **Timer0** and interrupts that we previously turned off. This work is done by the functions `int_enable` and `timer_start`. The implementation of the `timer_start` function is basically the same as the reading and writing of the auxiliary registers in our lab_3. Interested students can view them in the file arc_timer.c. One point to note in this step is the configuration of `timer_limit` (the last parameter of `timer_start`). We need to configure the interrupt time to 1ms , so we need to do a simple calculation (the formula is the expression after COUNT).

In this example, the loop body only serves as an effect display. We call our own delay function in the loop body to print the time per second.

Note: Since nSIM is only simulated by computer, there may be time inaccuracy when using this function. Interested students can use the EMSK to program the program in the development board. In this case, the time will be much higher than that in nSIM.

- Delay function

```

static void timer0_isr(void *ptr)
{
t0 = 0;
while(t0<ms);
}

```

This code is very simple and the idea is clear. When we enter the function, we clear the global variable `t0`. Since we have set the interrupt interval to 1ms in the above `timer_start`, we can think that every time `t0` is incremented, the time has passed 1ms.

Then, we wait through the `while(t0<ms)` sentence, so that we can get the full ms delay with higher precision.

Lab one Labal phenomenon

After the lab one program is successfully downloaded, the serial output is as follows:

```
embARC Build Time: Mar 16 2018, 09:58:46
Compiler Version: Metaware, 4.2.1 Compatible Clang 4.0.1

This is an example about timer interrupt
*****TEST MODE START*****
0s

1s

2s

3s

4s

5s

...
```

Open and browse the lab two

We then enter lab_4_2, which mainly shows the working state of priority and interrupt nesting.

Open main.c and browse through the entire program.

```
#include "embARC.h"
#include "embARC_debug.h"

#define MAX_COUNT 0xfffffff

volatile static uint8_t timer_flag = 0;
volatile static uint8_t hits = 0;

volatile static uint8_t nesting_flag = 1;

/** arc timer 0 interrupt routine */
static void timer0_isr(void *ptr)
{
    timer_int_clear(TIMER_0);

    timer_flag = 0;

    board_delay_ms(10, 1);

    if(timer_flag)
    {
        EMBARC_PRINTF("Interrupt nesting!\r\n");
    }
    else
    {
        EMBARC_PRINTF("Interrupt\r\n");
    }

    hits++;
}

/** arc timer 1 interrupt routine */
```

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```

static void timer1_isr(void *ptr)
{
    timer_int_clear(TIMER_1);

    timer_flag = 1;
}

/** main entry for testing arc fiq interrupt */
int main(void)
{
    timer_stop(TIMER_0);
    timer_stop(TIMER_1);

    int_disable(INTNO_TIMER0);
    int_disable(INTNO_TIMER1);

    int_handler_install(INTNO_TIMER0, timer0_isr);
    int_pri_set(INTNO_TIMER0, INT_PRI_MAX);

    int_handler_install(INTNO_TIMER1, timer1_isr);
    int_pri_set(INTNO_TIMER1, INT_PRI_MIN);

    EMBARC_PRINTF("\r\nThe test will start in 1s.\r\n");
    EMBARC_PRINTF("\r\n***** TEST MODE START *****\r\n\r\n");

    int_enable(INTNO_TIMER0);
    int_enable(INTNO_TIMER1);

    timer_start(TIMER_0, TIMER_CTRL_IE | TIMER_CTRL_NH, MAX_COUNT);
    timer_start(TIMER_1, TIMER_CTRL_IE | TIMER_CTRL_NH, MAX_COUNT/100);

    while(1)
    {
        if((hits >= 5)&&(nesting_flag == 1))
        {
            timer_stop(TIMER_0);
            timer_stop(TIMER_1);

            int_disable(INTNO_TIMER0);
            int_disable(INTNO_TIMER1);

            int_pri_set(INTNO_TIMER0, INT_PRI_MIN);
            int_pri_set(INTNO_TIMER1, INT_PRI_MAX);

            nesting_flag = 0;

            int_enable(INTNO_TIMER0);
            int_enable(INTNO_TIMER1);

            timer_start(TIMER_0, TIMER_CTRL_IE | TIMER_CTRL_NH, MAX_COUNT);
            timer_start(TIMER_1, TIMER_CTRL_IE | TIMER_CTRL_NH, MAX_COUNT/
            ↪100);
        }
        else if((hits >= 10)&&(nesting_flag == 0))
        {
            timer_stop(TIMER_0);
            timer_stop(TIMER_1);

            int_disable(INTNO_TIMER0);
            int_disable(INTNO_TIMER1);
        }
    }
}

```

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```

int_pri_set(INTNO_TIMER0, INT_PRI_MAX);
int_pri_set(INTNO_TIMER1, INT_PRI_MIN);

hits = 0;
nesting_flag = 1;

int_enable(INTNO_TIMER0);
int_enable(INTNO_TIMER1);

timer_start(TIMER_0, TIMER_CTRL_IE | TIMER_CTRL_NH, MAX_COUNT);
timer_start(TIMER_1, TIMER_CTRL_IE | TIMER_CTRL_NH, MAX_COUNT/
↪100);
}

return E_SYS;
}

```

Sub-module analysis lab two code

Lab two seems complicated, but it is very simple. The code for Lab two only needs to be divided into two parts: the interrupt service function and the main function.

- Interrupt service function

```

static void timer0_isr(void *ptr)
{
    timer_int_clear(TIMER_0);

    timer_flag = 0;

    board_delay_ms(10, 1);

    if(timer_flag)
    {
        EMBARC_PRINTF("Interrupt nesting!\r\n");
    }
    else
    {
        EMBARC_PRINTF("Interrupt\r\n");
    }

    hits++;
}

static void timer1_isr(void *ptr)
{
    timer_int_clear(TIMER_1);

    timer_flag = 1;
}

```

First, in order to analyze the code, we first ignore the extraneous parts (such as EMBARC_PRINTF, delay and hits in if).

In this case, we can find that for the interrupt service function timer0_isr, it is impossible to have the timer_flag of 1 only when it is itself. The only way to do this is to have another higher priority interrupt between timer_flag=0 and if statement set it.

Following this line of thought, let's look at timer1_isr again, and sure enough.

Regarding EMBARC_PRINTF, it is used to indicate the status.

Regarding the delay, its role is to lengthen this period of time, making nesting more likely.

Regarding hits, it will be mentioned in the main function module.

- main function

```
int main(void)
{
    timer_stop(TIMER_0);
    timer_stop(TIMER_1);

    int_disable(INTNO_TIMER0);
    int_disable(INTNO_TIMER1);

    int_handler_install(INTNO_TIMER0, timer0_isr);
    int_pri_set(INTNO_TIMER0, INT_PRI_MAX);

    int_handler_install(INTNO_TIMER1, timer1_isr);
    int_pri_set(INTNO_TIMER1, INT_PRI_MIN);

    EMBARC_PRINTF("\r\nThe test will start in 1s.\r\n");
    EMBARC_PRINTF("\r\n***** TEST MODE START *****\r\n\r\n");

    int_enable(INTNO_TIMER0);
    int_enable(INTNO_TIMER1);

    timer_start(TIMER_0, TIMER_CTRL_IE | TIMER_CTRL_NH, MAX_COUNT);
    timer_start(TIMER_1, TIMER_CTRL_IE | TIMER_CTRL_NH, MAX_COUNT/100);

    while(1)
    {
        if((hits >= 5)&&(nesting_flag == 1))
        {
            timer_stop(TIMER_0);
            timer_stop(TIMER_1);

            int_disable(INTNO_TIMER0);
            int_disable(INTNO_TIMER1);

            int_pri_set(INTNO_TIMER0, INT_PRI_MIN);
            int_pri_set(INTNO_TIMER1, INT_PRI_MAX);

            nesting_flag = 0;

            int_enable(INTNO_TIMER0);
            int_enable(INTNO_TIMER1);

            timer_start(TIMER_0, TIMER_CTRL_IE | TIMER_CTRL_NH, MAX_COUNT);
            timer_start(TIMER_1, TIMER_CTRL_IE | TIMER_CTRL_NH, MAX_COUNT/
→100);
        }
        else if((hits >= 10)&&(nesting_flag == 0))
        {
            timer_stop(TIMER_0);
            timer_stop(TIMER_1);

            int_disable(INTNO_TIMER0);
            int_disable(INTNO_TIMER1);

            int_pri_set(INTNO_TIMER0, INT_PRI_MAX);
            int_pri_set(INTNO_TIMER1, INT_PRI_MIN);

            hits = 0;
        }
    }
}
```

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```

nesting_flag = 1;

int_enable(INTNO_TIMER0);
int_enable(INTNO_TIMER1);

timer_start(TIMER_0, TIMER_CTRL_IE | TIMER_CTRL_NH, MAX_COUNT);
timer_start(TIMER_1, TIMER_CTRL_IE | TIMER_CTRL_NH, MAX_COUNT/
↪100);
}
return E_SYS;
}

```

The main function looks very long, but in fact there is a considerable part of it that is repetitive (we can also build a small function to make the code look more concise).

In the first lab, we have already discussed the configuration of the timer and the creation of the interrupt, we will not repeat them here.

The main function is simple: when the interrupt of timer0 occurs 5 times, change the priority relationship of the two interrupts. The hits mentioned earlier are count variables to assist in the above functions.

Lab two Labal phenomenon

The labal phenomenon of Lab two is shown in the figure.

“Interrupt nesting!” indicates that interrupt nesting has occurred, and “Interrupt” indicates that it has not occurred.

For a better understanding, let’s go back and look at the priority settings in the main function.

It is easy to see that when the timer0 interrupt priority is low (INT_PRI_MAX is low priority, this setting is contrary to most people’s intuition), the timer1 interrupt can be embedded therein; when the timer0 interrupt priority is high, the timer1 interrupt cannot be embedded.

To summarize, high-priority interrupts can interrupt low-priority interrupts, and low-priority interrupts can be embedded by high-priority interrupts. The Main function can be understood as the lowest priority interrupt.

```

embARC Build Time: Mar 16 2018, 09:58:46
Compiler Version: Metaware, 4.2.1 Compatible Clang 4.0.1

This test will start in 1s.

/******TEST MODE START*****/

Interrupt nesting!
Interrupt nesting!
Interrupt nesting!
Interrupt nesting!
Interrupt nesting!
Interrupt
Interrupt
Interrupt
Interrupt
Interrupt
Interrupt nesting!
Interrupt nesting!
Interrupt nesting!
Interrupt nesting!
Interrupt nesting!
Interrupt nesting!
Interrupt
Interrupt
Interrupt

```

Exercises

Try using an interrupt other than a timer to write a small program. (For example, use the GPIO interrupt to implement the button lighting)

How to use ARC board

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A simple bootloader

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3.2.2 Level 2 Labs

A WiFi temperature monitor

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A BLE Lamp

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Chapter 3. Labs

Steps

- Learn how to use the linker

Equipment

PC, MetaWare Development Toolkit, nsim simulator, example \labs\lab8_linker in ARC labs

Content

Customizing your program with **compiler pragmas**. At first, using “pragma code” to specify a new name of section in which the code of function reside. Then mapping this code section into specified memory location with linker. Finally, checking the location of this code section after build process.

Principles

By default, compiler-generated code is placed in the *.text* section. The default code section name can be overridden by using the *code pragma*. After compile process, the linker will automatically map all input sections from object files to output sections in executable files. If you want to customize the mapping, you can change the default linker mapping by invoking a linker command file.

Steps

Create a project and overriding code section name

Open the MetaWare IDE, create an empty C project called lab_linker and select ARC EM series processor. Then import the main.c and link.cmd files under \labs\lab8_linker directory into the project.

Open main.c file in MetaWare IDE, using “pragma code” to change the section in which function `modify` reside from *.text* to a new name “*modify_seg*”.

```
#pragma Code ("modify_seg")
void modify(int list[], int size) {
    int out, in, temp;

    for(out=0; out<size; out++)
        for(in=out+1; in<size; in++)
            if(list[out] > list[in]) {
                temp = list[in];
                list[in] = list[out];
                list[out] = temp;
            }
}
#pragma Code ()
```

Pragma code has two forms that must be used in pairs to bracket the affected function definitions:

```
#pragma code(Section_name)
/* ----- Affected function definitions go here ---- */
#pragma code() /* No parameters here */
```

`Section_name` is a constant string expression that denotes the name of the section

Note: About detailed usage of the compiler pragmas, please refer to the document “MetaWare C/C++ Programmer’s Guide for the ccac Compiler”

Edit the linker command file

Open the link.cmd file, there are two parts, one is for memory blocks location, the other is for sections mapping. Add one new block named “MyBlock” in MEMORY, the start address is 0x00002000, and the size is 32KB. Then add one new GROUP in SECTIONS, and mapping section “modify_seg” into MyBlock.

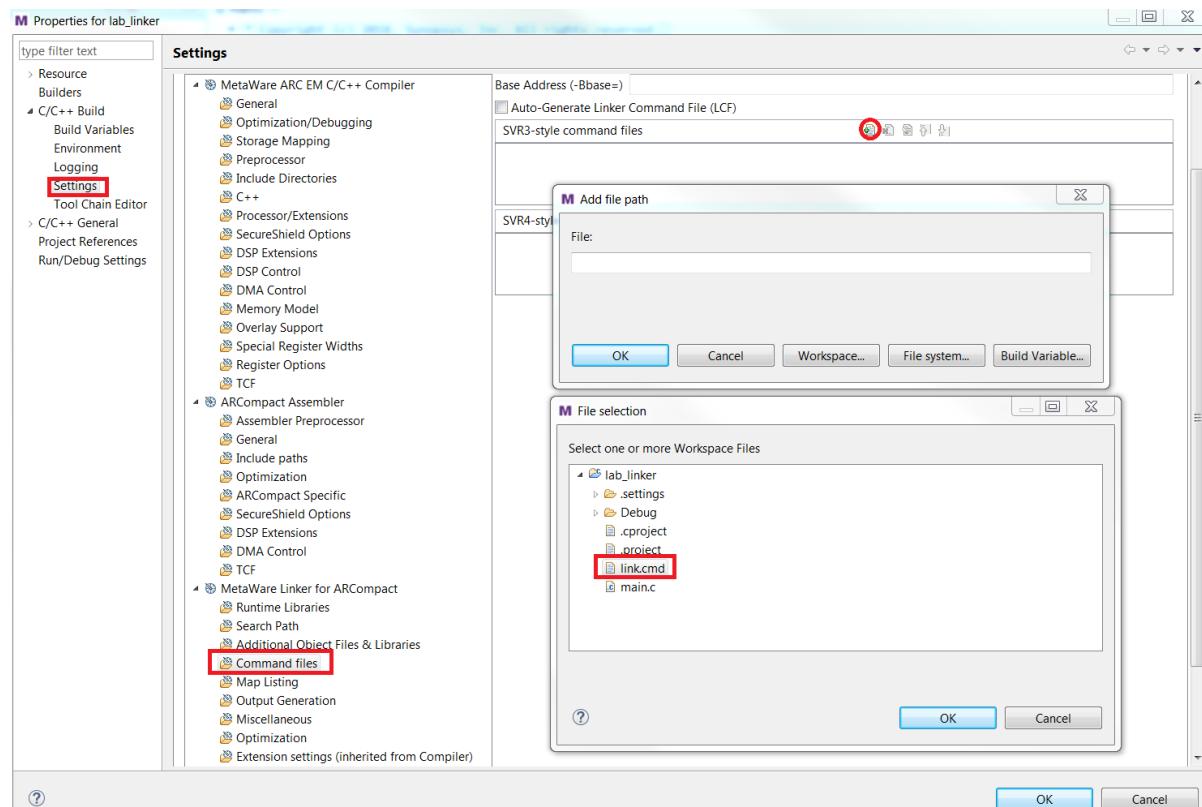
```
MEMORY {
    // Note: overlap of code and data spaces is not recommended since it makes
    //        Address validity checking impossible with the debugger and simulator
    MyBlock: ORIGIN = 0x00002000, LENGTH = 32K
    MEMORY_BLOCK1: ORIGIN = 0x0010000, LENGTH = 64K
    MEMORY_BLOCK2: ORIGIN = 0x0020000, LENGTH = 128K
}

SECTIONS {
    GROUP: {
        modify_seg: {}
    }>MyBlock
....
```

Note: About format and syntax of the linker command file, please refer to the document “MetaWare ELF Linker and Utilities User’s Guide”

Add the linker command file into the project

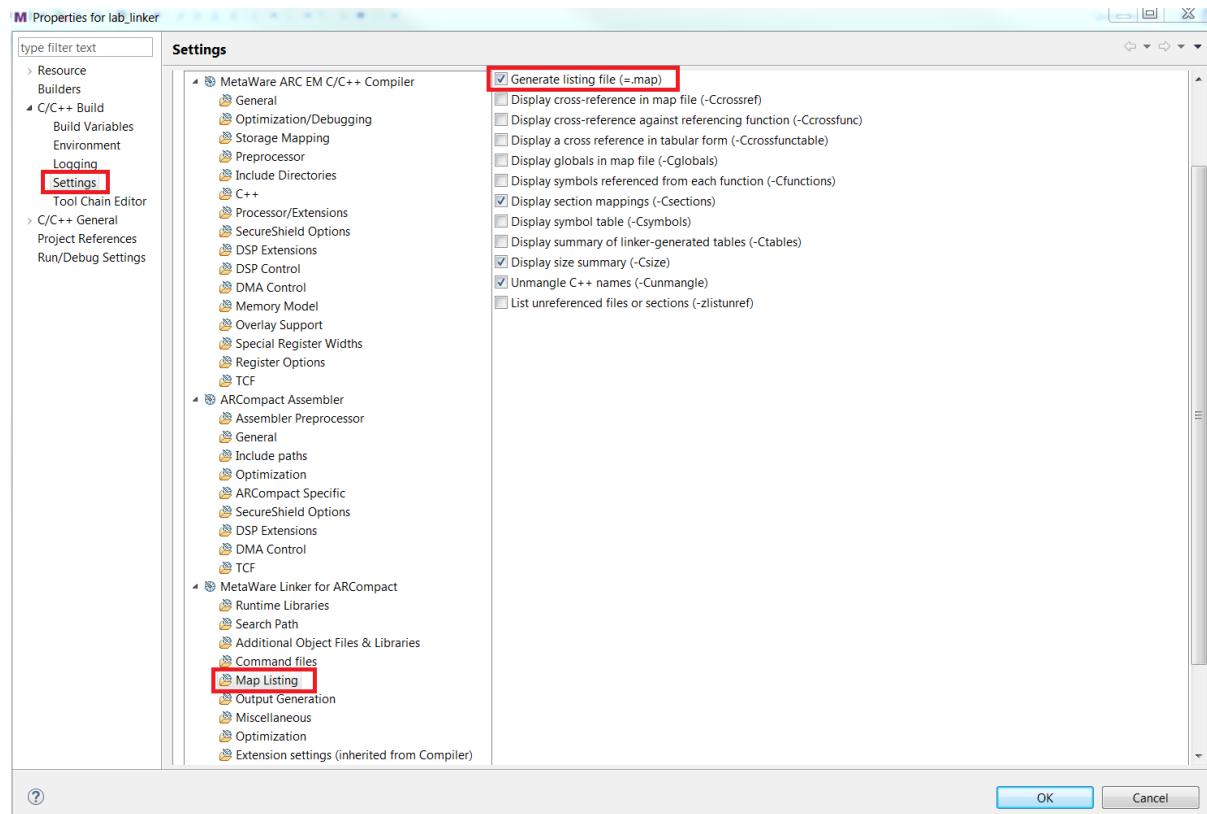
Right click the current project lab_linker and select Properties in the popup tab. Click C/C++ build >> settings >> Tool Settings to open the linker option settings page.



In the current page, select Command files to add linker.cmd file into this project.

Check the result

In linker option settings page, select Map listing to check Generate listing file(=.map)



Build the lab_linker project, then open the lab_linker.map file under Debug directory.

SECTION SUMMARY

OUTPUT/ INPUT	TYPE SECTION	START ADDRESS	END ADDRESS	LENGTH
modity_seg				
.text	text	00002000	00002039	0000003a
.fini	text	00010000	00010005	00000006
.init	text	00010008	0001000d	00000006
.text	text	00010010	0001013d	0000012e
.vectors	text	00010140	0001017f	00000040
.sdata	bss	00020000	0001ffff	00000000
.data	data	00020000	0002001f	00000020
.stack	bss	00020020	0003001f	00010000

In this file, search SECTIONS SUMMARY, then you can check the size and location of *modify_seg* section, it resides in *MyBlock*, same as you set in the linker cmd file.

Exercises

Try to check the memory mapping info of *modify_seg* section by using elfdump tool.

How to use FreeRTOS

Purpose

- Learn how to implement tasks in FreeRTOS operating system
- Learn how to register tasks in FreeRTOS
- Get familiar with inter-task communication of FreeRTOS

Equipment

PC, IoT DK, embARC OSP, example \Lab\FreeRTOS in embARC OSP

Content

This lab utilizes FreeRTOS v9.0.0, and will create 3 tasks based on embARC_osp. You should apply inter-task communicate methods such as semaphore and message queue in order to get running LEDs result. We should go through basic functions of FreeRTOS first.

Principles

Background

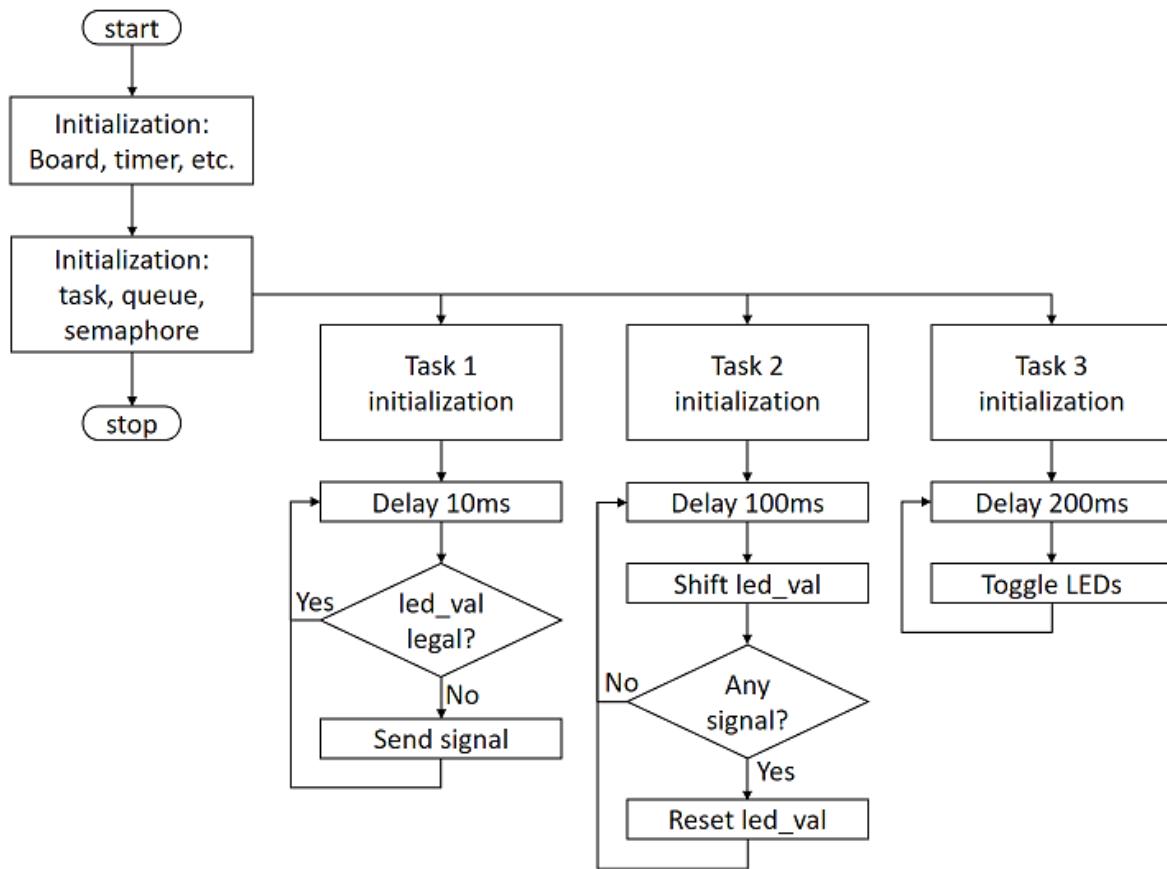
A Real Time Operating System (RTOS) is an operating system intended to serve real-time applications that process data in limited time as it comes in. Being within time bound and highly reliable are two important characters of RTOS.

As resources becoming abundant for modern micro processors, the cost to run RTOS is become increasingly neglectable. RTOS also provides event-driven mode for better utilization of CPU with efficiency. Among RTOSs for micro processors, FreeRTOS stands out as a free for use, opensourced RTOS with complete documents. These are the reasons of why we choose to learn FreeRTOS in this lab.

Design

This lab implements a running LED light with 3 tasks on FreeRTOS. Despite using 3 tasks is an overkill for a running LED, but it's beneficial for the understanding of FreeRTOS itself and inter-task communication as well.

The flow chat of the program is shown below:



Realization

The code of system is shown below, including various Initialization and task time delay.

```

#include "embARC.h"
#include "embARC_debug.h"
#include <stdlib.h>

static void task1(void *par);
static void task2(void *par);
static void task3(void *par);

#define TSK_PRIOR_1          (configMAX_PRIORITIES-1)
#define TSK_PRIOR_2          (configMAX_PRIORITIES-2)
#define TSK_PRIOR_3          (configMAX_PRIORITIES-3)

// Semaphores
static SemaphoreHandle_t sem1_id;

// Queues
static QueueHandle_t dtql1_id;

// Task IDs
static TaskHandle_t task1_handle = NULL;
static TaskHandle_t task2_handle = NULL;
static TaskHandle_t task3_handle = NULL;

int main(void)
{

```

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```

vTaskSuspendAll();

    // Create Tasks
    if (xTaskCreate(task1, "task1", 128, (void *)1, TSK_PRIOR_1, &task1_
→handle) != pdPASS) {
        /*!< FreeRTOS xTaskCreate() API function */
        EMBARC_PRINTF("Create task1 Failed\r\n");
        return -1;
    } else {
        EMBARC_PRINTF("Create task1 Successfully\r\n");
    }

    if (xTaskCreate(task2, "task2", 128, (void *)2, TSK_PRIOR_2, &task2_
→handle) != pdPASS) {
        /*!< FreeRTOS xTaskCreate() API function */
        EMBARC_PRINTF("Create task2 Failed\r\n");
        return -1;
    } else {
        EMBARC_PRINTF("Create task2 Successfully\r\n");
    }

    if (xTaskCreate(task3, "task3", 128, (void *)3, TSK_PRIOR_3, &task3_
→handle) != pdPASS) {
        /*!< FreeRTOS xTaskCreate() API function */
        EMBARC_PRINTF("Create task3 Failed\r\n");
        return -1;
    } else {
        EMBARC_PRINTF("Create task3 Successfully\r\n");
    }

    // Create Semaphores
sem1_id = xSemaphoreCreateBinary();
xSemaphoreGive(sem1_id);

    // Create Queues
dtq1_id = xQueueCreate(8, sizeof(uint32_t));

xTaskResumeAll();
vTaskSuspend(NULL);

    return 0;
}

static void task1(void *par)
{
    uint32_t led_val = 0;

    static portTickType xLastWakeTime;
    const portTickType xFrequency = pdMS_TO_TICKS(10);

    // Use current time to init xLastWakeTime, mind the difference with
→vTaskDelay()
    xLastWakeTime = xTaskGetTickCount();

    while (1) {
        /* call Freertos system function for 10ms delay */
        vTaskDelayUntil(&xLastWakeTime, xFrequency);

        #####Insert code here#####
    }
}

```

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```

static void task2(void *par)
{
    uint32_t led_val = 0x0001;

    static portTickType xLastWakeTime;
    const portTickType xFrequency = pdMS_TO_TICKS(100);

    // Use current time to init xLastWakeTime, mind the difference with
    →vTaskDelay()
    xLastWakeTime = xTaskGetTickCount();

    while (1) {
        /* call Freertos system function for 100ms delay */
        vTaskDelayUntil( &xLastWakeTime, xFrequency );

        //####Insert code here####
    }
}

static void task3(void *par)
{
    uint32_t led_val = 0;

    static portTickType xLastWakeTime;
    const portTickType xFrequency = pdMS_TO_TICKS(200);

    // Use current time to init xLastWakeTime, mind the difference with
    →vTaskDelay()
    xLastWakeTime = xTaskGetTickCount();

    while (1) {
        /* call Freertos system function for 100ms delay */
        vTaskDelayUntil( &xLastWakeTime, xFrequency );

        //####Insert code here####
    }
}

```

Steps

Build and run the incompletely completed code

the code is at ‘embarc_osp\example\Lab\lab_9’, use an uart terminal console and run the code, you will see a message from program like the one shown below:

```

embARC Build Time: Mar 9 2018, 17:57:50
Compiler Version: Metaware, 4.2.1 Compatible Clang 4.0.1 (branches/release_40)
Create task1 Successfully
Create task2 Successfully
Create task3 Successfully

```

This message implies that three tasks are working correctly.

Implement task 3

It is required for task 3 to retrieve new value from the queue and assign the value to led_val. The LED controls are already implemented in previous labs, so the only new function to learn is xQueueReceive(). This is a FreeRTOS

API to pop and read an item from queue. Please take reference from FreeRTOS documents and complete the code for this task. (An example is in ‘complete’ folder)

Implement task 1

It is required for task 1 to check if value from queue is legal. If not, a reset signal is needed to be sent.

Two new functions might be helpful for this task: xSemaphoreGive() for release a signal and xQueuePeek() for read item but not pop from a queue. Please take reference from FreeRTOS documents and complete the code for this task. (An example is in ‘complete’ folder)

Do notice the difference between xQueueReceive() and xQueuePeek().

Implement task 2

There are two different works for task 2 to complete: to shift led_val and queue it, and to reset both led_val and queue when illegal led_val is detected.

Three functions can be helpful: xQueueSend(), xSemaphoreTake(), xQueueReset(). Please take reference from FreeRTOS documents and complete the code for this task. (An example is in ‘complete’ folder)

Build and run the completed code

BUild the completed program and debug it to fulfill all requirements. (8-digit running LEDs are used in example code)

Exercises

The problem of philosophers having meal:

Five philosophers sitting at a round dining table. Suppose they are either thinking or eating, but they can't do these two things at same time. So each time when they are having food, they stop thinking and vice versa. There are five forks on the table for eating noddle, each fork is placed between two adjacent philosophers It's hard to eat noddle with one fork, so all philosophers need two forks in order to eat.

Please write a program with proper console output to simulate this process.

3.2.3 Level 3 Labs

AWS IoT Smarthome

Purpose

- Show the smart home solution based on ARC and AWS IoT Cloud
- Learn how to use the AWS IoT Cloud
- Learn how to use the EMSK Board peripheral modules and on-board resources

Equipment

Required Hardware

- [DesignWare ARC EM Starter Kit(EMSK)]

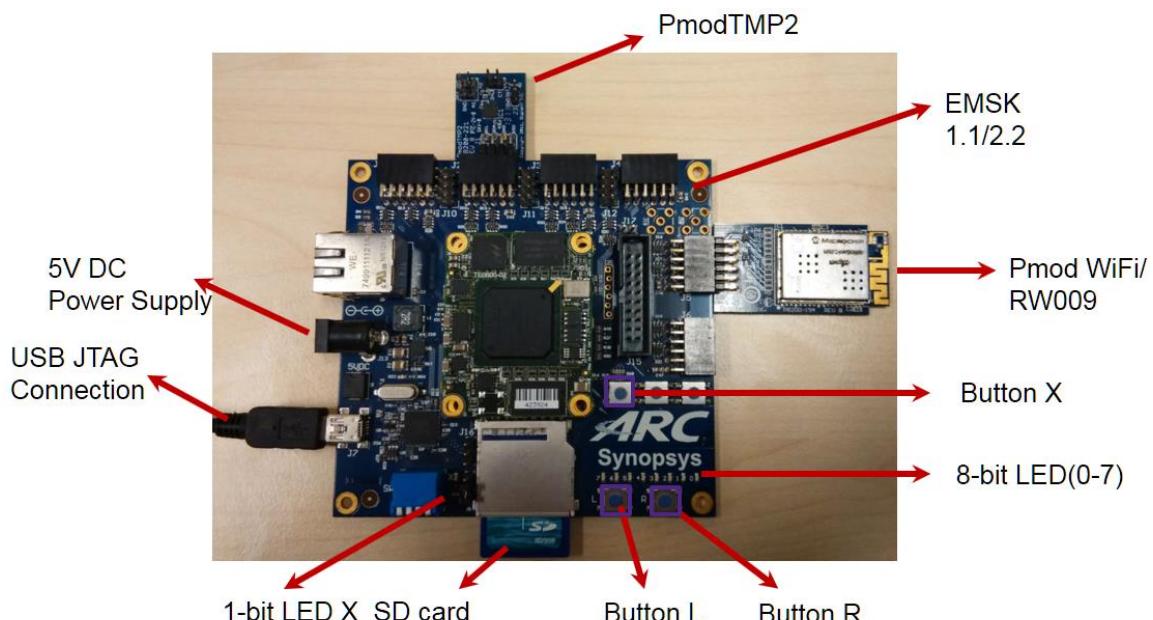
- [Digilent PMOD WiFi(MRF24WG0MA)]
- [Digilent PMOD TMP2]
- SD Card
- WiFi Hotspot(SSID:embARC, Password:**qazwsxedc**, WPA/WPA2 encrypted)

Required Software

- Metaware or ARC GNU Toolset
- Serial port terminal, such as putty, tera-term or minicom

Hardware Connection(EMSK Board)

- Connect PMOD WiFi to J5, connect PMOD TMP2 to J2.

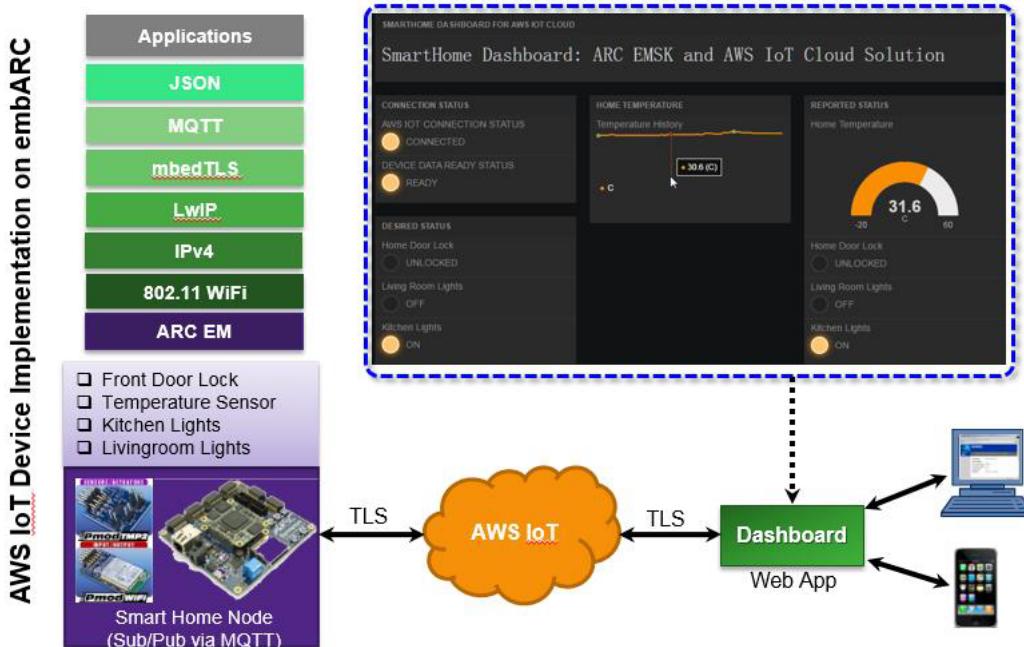


- Required hardware: EMSK 1.1/2.2, PmodTMP2, PmodWiFi, SDCard
- USB UART can be connected to PC for interoperation using NT-Shell.
 - Configure your hardware with proper core configuration.
 - The hardware resources are allocated as following table.

Hardware Resources	Represent
BUTTON R	Livingroom Lights Control
LED 0-1	Livingroom Lights Status(On or Off)
BUTTON L	Kitchen Lights Control
LED 2-3	Kitchen Lights Status(On or Off)
BUTTON X	Front Door Lock Control
LED 4-5	Front Door Lock Status(On or Off)
LED 7	WiFi connection status(On for connected, Off for not)
LED X	Node working status(toggling in 2s period if working well)
PMOD TMP2	Temperature Sensor
PMOD WiFi	Provide WiFi Connection

Content

This article provides instructions on how to establish connection between the EMSK and Amazon Web Services Internet of Things (AWS IoT) cloud in a simulated smart home application. AWS IoT is a managed cloud platform that lets connected devices securely interact with cloud applications and other devices. It supports Message Queue Telemetry Transport (MQTT) and provides authentication and end-to-end encryption.



This application is designed to show how to connect only 1 EMSK and AWS IoT Cloud using embARC. The connection between EMSK and AWS IoT Cloud is secured by TLS.

Principles

This application demonstrates the smart home solution based on EMSK by establishing the connection between EMSK Board and AWS IoT Cloud. The AWS IoT Device C SDK for the embedded platform has been optimized and transplanted for embARC.

In the application, the EMSK Board peripheral modules and onboard resources are used to simulate the objects which is controlled and monitored in smart home, the AWS IoT Cloud is used as the Cloud host and control platform which communicate with the EMSK Board through the MQTT protocol, and a special HTML5 Web APP is designed, which provide a dash board to monitor and control smart home nodes.

Steps

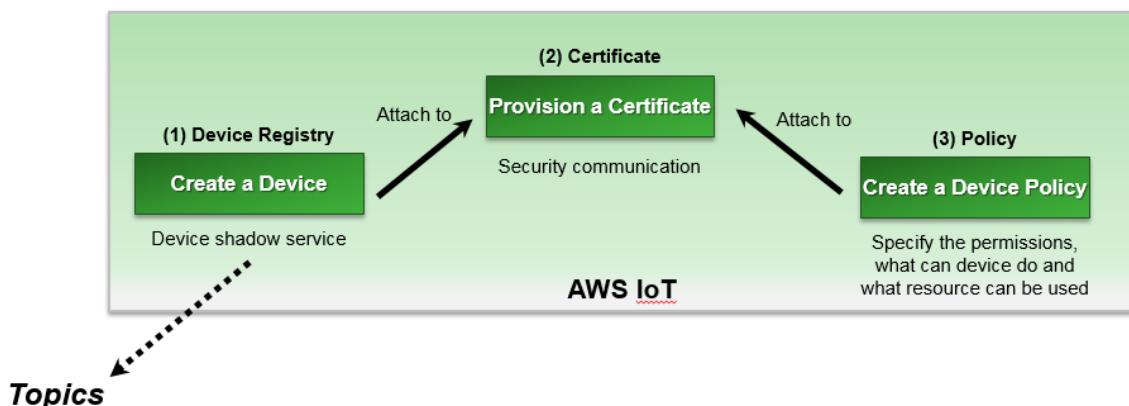
Creating and setting smart home node

1. Create an AWS account in [\[here\]](#). Amazon offers various account levels, including a free tier for AWS IoT.
2. Log into AWS console and choose AWS IoT.
 AWS IoT
Connect Devices to the Cloud
3. Choose an appropriate IoT server in the top right corner of the AWS IoT console page.

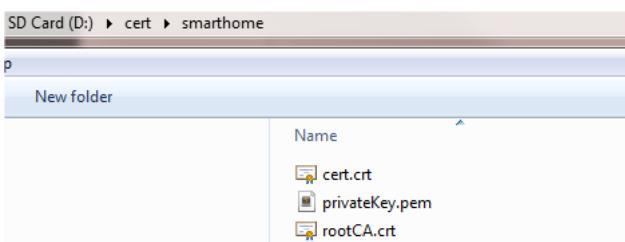
US East (N. Virginia)
 US West (N. California)
 US West (Oregon)
 EU (Ireland)
 EU (Frankfurt)
 Asia Pacific (Tokyo)
 Asia Pacific (Seoul)
 Asia Pacific (Singapore)
 Asia Pacific (Sydney)
 South America (São Paulo)

4. Create your smart home node in the thing registry and generate X.509 certificate for the node. Create an AWS IoT policy. Then attach your smart home node and policy to the X.509 certificate.

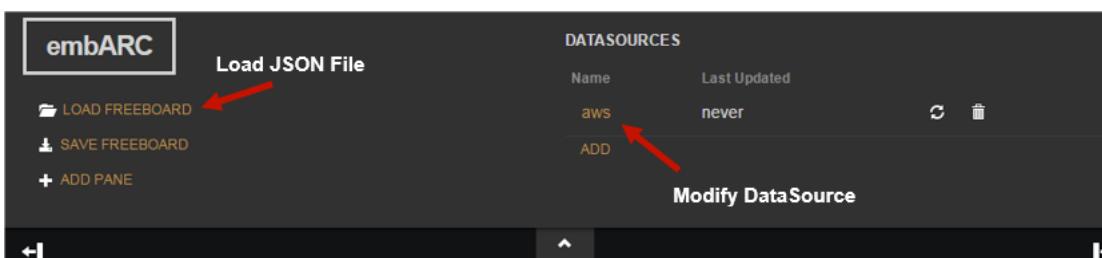
Note: for more details [Using a Smart Home Iot Application with EMSK]



5. Download the root CA certificate from [\[here\]](#). Rename it rootCA.crt. Copy the certificate files cert.crt, privateKey.pem and rootCA.crt to folder `cert\smarthome`. Insert the SD card to your PC, and copy the certificate folder cert to the SD Card root.



6. Open the [\[Web App\]](#) in a web browser and load the configuration file `dashboard-smarthomesinglething.json` obtained from `embARC\example\freertos\iot\aws\smarthome_demo`. The dashboard can be loaded automatically.



7. Click “ADD” to go to DATASOURCE page and fill up the forms.

1. TYPE: Choose AWS IoT.
2. NAME: Name is aws.

DATA SOURCE

Receive data from an MQTT server.

TYPE: AWS IoT

NAME: aws

AWS IOT ENDPOINT: input_your_own_endpoint
Your AWS account-specific AWS IoT endpoint. You can use the AWS IoT CLI describe-endpoint command to find this endpoint

REGION: input_your_own_region
The AWS region of your AWS account

CLIENT ID:

ACCESS KEY: input_your_own_accesskey
Access Key of AWS IAM

SECRET KEY: input_your_own_secretKey
Secret Key of AWS IAM

THINGS: Thing
SmartHome X

ADD
AWS IoT Thing Name of the Shadow this device is associated with

SAVE CANCEL

3. AWS IOT ENDPOINT: Go to AWS IoT console and click your smart home node “SmartHome”. Copy the content XXXXXXXXXXXXXXXXX.iot.us-east-1.amazonaws.com in REST API endpoint to AWS IOT ENDPOINT.

AWS IoT

Resources | MQTT Client | Tutorial | Settings | 0 notifications

AWS IOT ENDPOINT

+ Create a resource

Resources

Filter by resource names or by resource type (below)

Select all Actions ▾

All 1/1 things 0/0 rules
0/0 CAs 1/1 certificates
0/0 policies

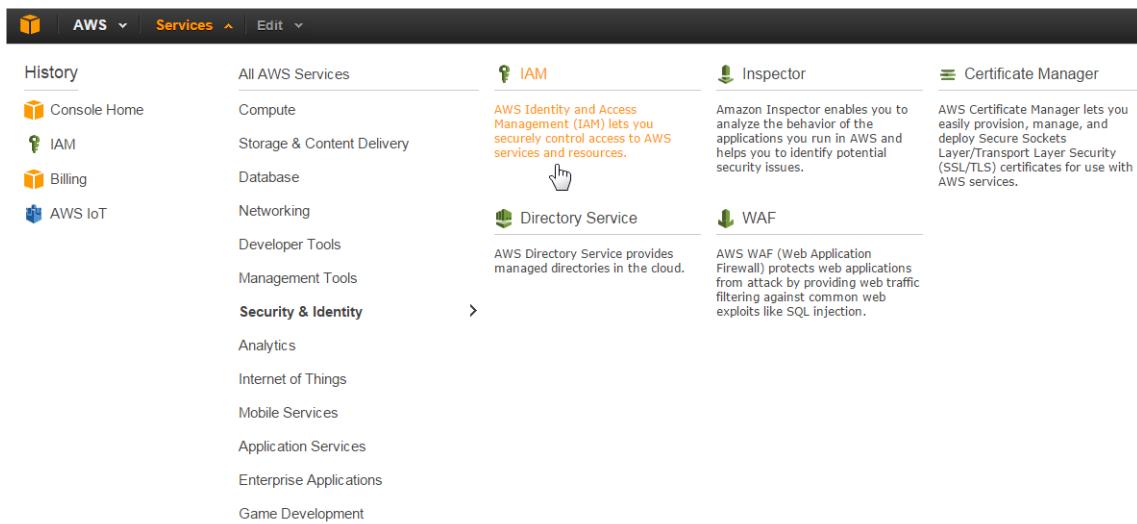
First Previous 1 Next Last

Smart Home 9ce7e d7884 fhh ACTIV E

Name: SmartHome
REST API endpoint: https://XXXXXXXXXXXXXX.iot.us-east-1.amazonaws.com/things/SmartHome/shadow
MQTT topic: Saws/things/SmartHome/shadow/update
Last update: No state
Attributes: None
Linked certificates: None

4. REGION: Copy the AWS region of your smart home node in REST API endpoint to REGION. For example, <https://XXXXXXXXXXXXXX.iot.us-east1.amazonaws.com/things/SmartHome/shadow>. REGION is us-east-1.
5. CLIENT ID: Leave it blank as default.

6. ACCESS KEY and SECRET KEY: Go to AWS Services page and click “IAM”.

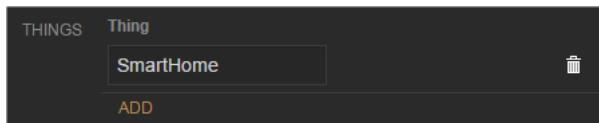


Go to User page and click “Create New Users”. Enter User Names “AWSIoTUser”. Then download user security credentials, Access Key ID and Secret Access Key. Copy Access Key ID to ACCESS KEY and Secret Access Key to SECRET KEY.



Go to User page and click “AWSIoTUser”. Click “Attach Policy” to attach “AWSIoTDataAccess” to “AWSIoTUser”.

7. THINGS: AWS IoT thing name “SmartHome”.



8. Click “Save” to finish the setting.

Building and running AWS IoT smart home example

1. The AWS IoT thing SDK for C has been ported to embARC. Check the above steps in order for your IoT application to work smoothly. Go to `embARC\example\freetos\iot\aws\smarthome_demo`. Modify `aws_iot_config.h` to match your AWS IoT configuration. The macro `AWS_IOT_MQTT_HOST` can be copied from the REST API endpoint in AWS IoT console. For example, <https://XXXXXXXXXXXXXX.iot.us-east-1.amazonaws.com/things/SmartHome/shadow>. `AWS_IOT_MQTT_HOST` should be `XXXXXXXXXXXXXX.iot.us-east-1.amazonaws.com`.

```
// Get from console
// =====
#define AWS_IOT_MQTT_HOST      "xxxxxxxxxxxxxx.iot.us-east-1.amazonaws.com" //< Cus-
#define AWS_IOT_MQTT_PORT       8883 //< default port for MQTT/S
#define AWS_IOT_CLIENT_ID        "csdk-SH" //< MQTT client ID should be unique for ev-
#define AWS_IOT_THING_NAME       "SmartHome" //< Thing Name of the Shadow this device
#define AWS_IOT_ROOT_CA_FILENAME "rootCA.crt" //< Root CA file name
#define AWS_IOT_CERTIFICATE_FILENAME "cert.crt" //< device signed certificate file name
#define AWS_IOT_PRIVATE_KEY_FILENAME "privateKey.pem" //< Device private key filename
// =====
```

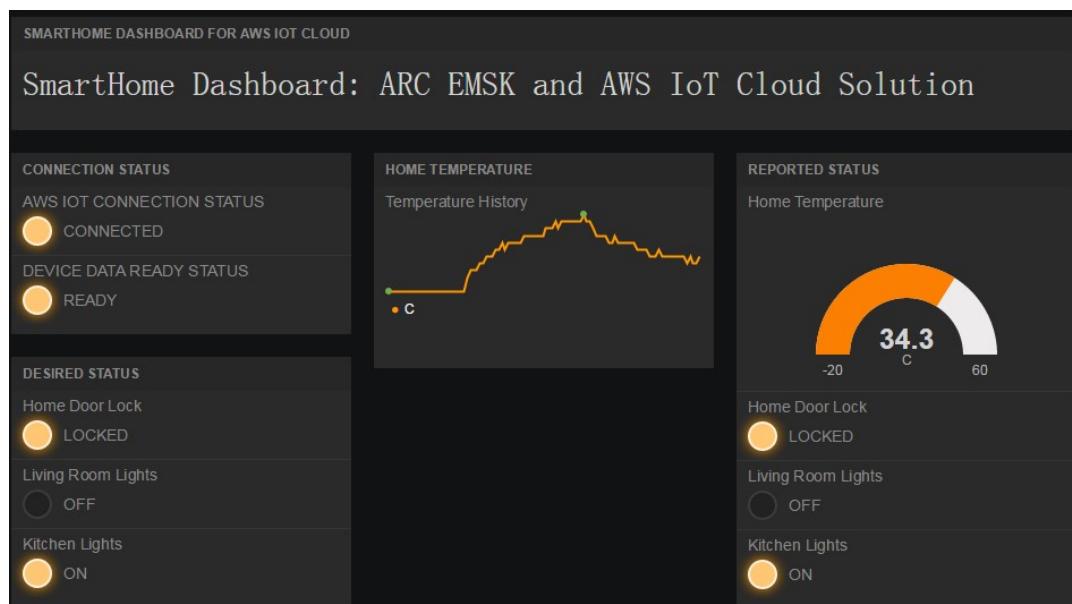
2. Use USB cable to connect the EMSK board. Set the baud rate of the terminal emulator to 115200.
3. Insert the SD Card into the EMSK board SD Card slot. Run the AWS IoT application using JTAG. Go to *embARC\example\freertos\iot\aws\smarthome_demo* in command line, input the compile command as follow:

```
make TOOLCHAIN=gnu BD_VER=22 CUR_CORE=arcem7d run
```

4. FreeRTOS-based runtime environment can be loaded automatically. Wait for WiFi initialization and connection establishment(30 seconds or less) until the “WiFi connected” message is shown in the terminal emulator. “Network is ok” will be shown after the certificate files cert.crt, privateKey.pem and rootCA.crt are validated. The information in “reported”: {} is the state of the EMSK-based smart home node. “Updated Accepted !!” means the connection works between the smart home node and AWS IoT cloud.

```
Shadow Init
Shadow Connect
FrontDoor is open
turn off Kitchenlights
Turn off LivingRoomLights
Update shadow: {"state": {"reported": {"temperature": 29.6, "DoorLocked": false,
"KitchenLights": false, "LivingRoomLights": false}}, "clientToken": "csdk-SH-0"}
*****
Delta - Frontdoor state changed to 1
FrontDoor is locked
Delta - KitchenLights light state changed to 1
Turn on Kitchenlights
Update Accepted !
Update Shadow: {"state": {"reported": {"temperature": 29.6, "DoorLocked": true,
"KitchenLights": true, "LivingRoomLights": false}}, "clientToken": "csdk-SH-1"}
*****
Update Accepted !
Update Shadow: {"state": {"reported": {"temperature": 29.6, "DoorLocked": true,
"KitchenLights": true, "LivingRoomLights": false}}, "clientToken": "csdk-SH-2"}
*****
```

4. Interact using EMSK and Dashboard. You can press the button L/R/X to see the led changes on board and also on dashboard web app. You can also click the lights of DESIRED STATUS pane on the dashboard app, and see the led changes on board and dashboard web app.



Exercises

This application is designed to show how to connect only 1 EMSK and AWS IoT Cloud using embARC. Try to do the Multi Node AWS IoT Smarthome Demo.

Note: Related demo codes you can find [\[here\]](#)

**CHAPTER
FOUR**

APPENDIX

**CHAPTER
FIVE**

INDICES AND TABLES

- genindex
- search