Interrupt Controller

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Input/Output system management

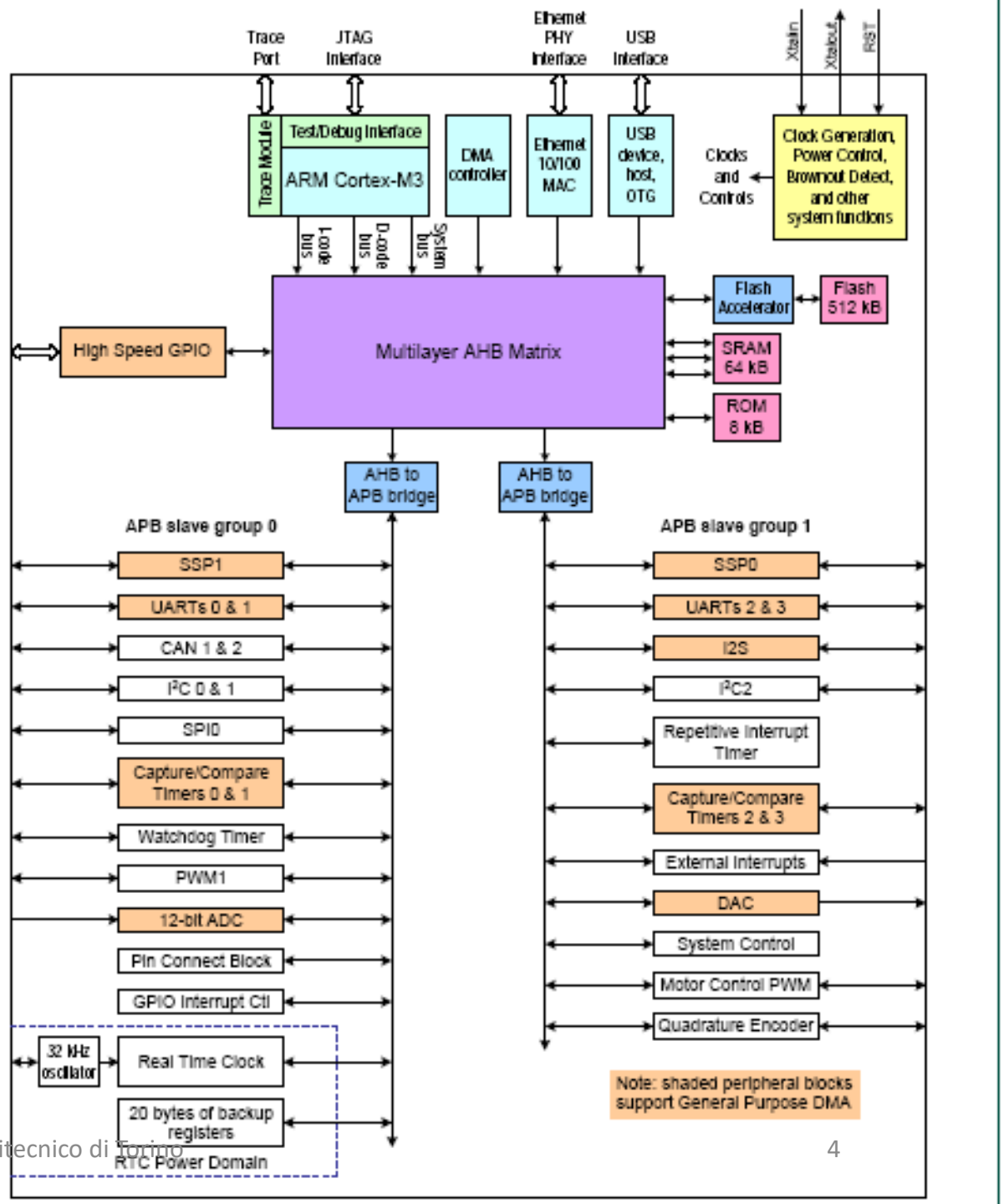
- The main function of a Input/Output (I/O) system is to exchange information with the external world.
- An I/O system needs to be controlled by the CPU which has to incercept service requests
  - For example if a new data is received by a peripheral core
- There are 2 main methods used to manage service requests:
  - Polling
  - Interrupt.

System event categories

- Respond to infrequent but important events
  - Alarm conditions like low battery power (i.e., NMI)
  - Error conditions (i.e., USAGE FAULT)
- I/O synchronization
  - Trigger interrupt when signal on a port changes
- Periodic interrupts
  - Generated by the timer at a regular rate
  - Systick timer can generate interrupt when it hits zero
  - Reload value + frequency determine interrupt rate
- Data acquisition samples ADC

Block diagram NXP LPC1768

- I/O system composed of several peripheral cores
  - Serial ports – UARTS
  - 12-bit ADC / DAC
  - GPIO
  - Timers
  - Other communication protocols like
    - I2C
    - SPI/SSP



Polling

- Polling is the process where the computer or controlling device frequently interrogates an external device to check for its current state
  - Checking status registers (best practice)
  - Checking data registers.
- The polling is often implemented as a software cycle
  - Performing a predefined sequence of checks at a regular pace
  - A scheduling can be defined to access peripheral cores more or less frequently
- If the polled core needs to be handled, the CPU moves from the polling loop to the handler of the specific event.
- Main characteristics
  - The most of the time is spent in the software cycle (disadvantage – power inefficient)
  - Easy to implement (advantage)
  - High latency in the managing cycle (disadvantage – low performance)
  - Difficult management of nested requests (disadvantage – very low performance).

Interrupt

- Peripheral devices are directly interacting with the CPU,
  - CPU may perform different tasks having low level priority,
  - Idle mode can be entered,
  - The system wakes up as soon as a peripheral core is requesting a service
- When a request is received, the CPU needs to recognize the source of request in order to execute the proper handler
- Current architectures implement a Vectored Interrupt management method
  - Based on the Interrupt Vector Table (IVT)
  - The CPU collaborates with an external device called Interrupt Controller

System setup for interrupt mode

- Things you must do when programming a system to use interrupts
- BOOT TIME
  - Initialize data structures
    - Counters, pointers
    - Eventually specify a process variable that may interrupt (i.e., semaphores)
  - Configure Interrupt Controller
    - Enable interrupt sources
    - Set priority of every source

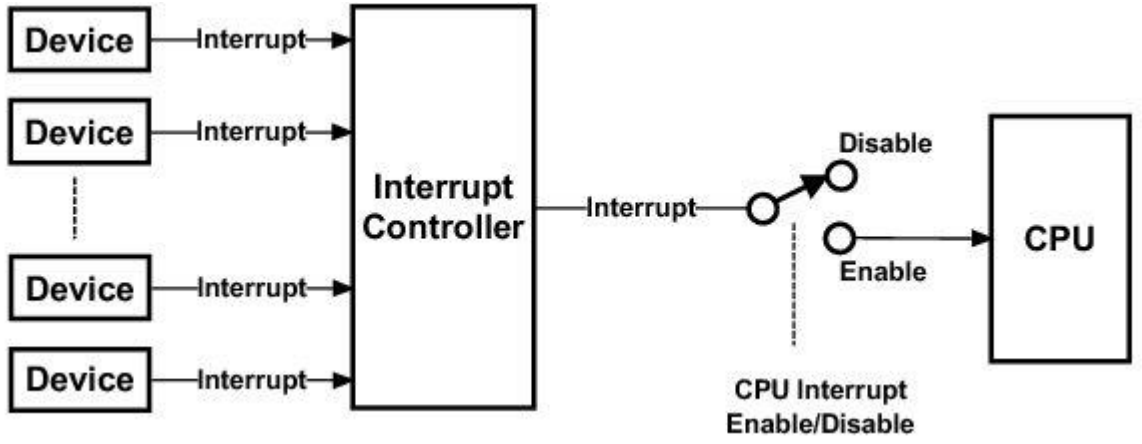
System setup for interrupt mode (II)

- Things you must do in every interrupt service routine
- RUNTIME
  - Acknowledge
    - Clear the flags that indicate the interrupt is active
    - Can be done in different parts of the interrupt service routine
  - Maintain contents of R4-R8,R10-R11 (ABI AAPCS)
  - Communicate via shared global variables.

May be important for nesting interruptions

Interrupt controller

- In computing, an interrupt controller is a device that is used to combine several sources of interrupt into one or more CPU lines, while allowing priority levels to be assigned to its interrupt outputs
- Manages interrupt signals received from devices by combining multiple interrupts into a single interrupt output.

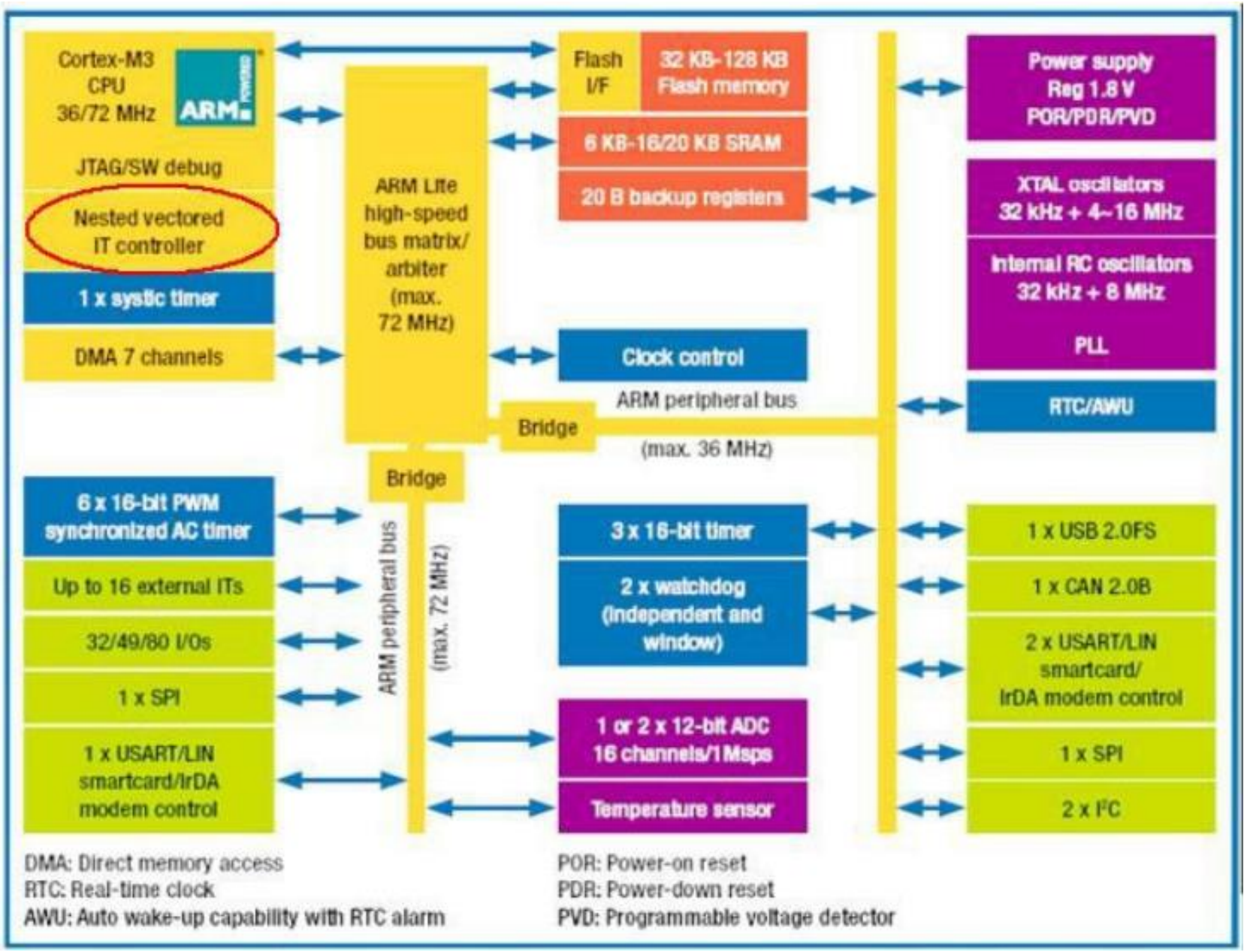


Nested Vectored Interrupt Controller (NVIC) (UM pg. 78)

- The Nested Vectored Interrupt Controller (NVIC) is an integral part of the Cortex-M3.
- The tight coupling to the CPU allows for low interrupt latency and efficient processing of late arriving interrupts
- It manages 35 possible external interrupt.

Table 52. Interrupt Set-Enable Register 0 register (ISER0 - 0xE000 E100)

Bit	Name	Function
0	ISE_WDT	Watchdog Timer Interrupt Enable. Write: writing 0 has no effect, writing 1 enables the interrupt. Read: 0 indicates that the interrupt is disabled, 1 indicates that the interrupt is enabled.
1	ISE_TIMER0	Timer 0 Interrupt Enable. See functional description for bit 0.
2	ISE_TIMER1	Timer 1. Interrupt Enable. See functional description for bit 0.
3	ISE_TIMER2	Timer 2 Interrupt Enable. See functional description for bit 0.
4	ISE_TIMER3	Timer 3 Interrupt Enable. See functional description for bit 0.
5	ISE_UART0	UART0 Interrupt Enable. See functional description for bit 0.
6	ISE_UART1	UART1 Interrupt Enable. See functional description for bit 0.
7	ISE_UART2	UART2 Interrupt Enable. See functional description for bit 0.
8	ISE_UART3	UART3 Interrupt Enable. See functional description for bit 0.
9	ISE_PWM	PWM1 Interrupt Enable. See functional description for bit 0.
10	ISE_I2C0	I^2C0 Interrupt Enable. See functional description for bit 0.
11	ISE_I2C1	I^2C1 Interrupt Enable. See functional description for bit 0.
12	ISE_I2C2	I^2C2 Interrupt Enable. See functional description for bit 0.
13	ISE_SPI	SPI Interrupt Enable. See functional description for bit 0.
14	ISE_SSP0	SSP0 Interrupt Enable. See functional description for bit 0.
15	ISE_SSP1	SSP1 Interrupt Enable. See functional description for bit 0.
16	ISE_PLL0	PLL0 (Main PLL) Interrupt Enable. See functional description for bit 0.
17	ISE_RTC	Real Time Clock (RTC) Interrupt Enable. See functional description for bit 0.
18	ISE_EINT0	External Interrupt 0 Interrupt Enable. See functional description for bit 0.
19	ISE_EINT1	External Interrupt 1 Interrupt Enable. See functional description for bit 0.
20	ISE_EINT2	External Interrupt 2 Interrupt Enable. See functional description for bit 0.
21	ISE_EINT3	External Interrupt 3 Interrupt Enable. See functional description for bit 0.
22	ISE_ADC	ADC Interrupt Enable. See functional description for bit 0.
23	ISE_BOD	BOD Interrupt Enable. See functional description for bit 0.
24	ISE_USB	USB Interrupt Enable. See functional description for bit 0.
25	ISE_CAN	CAN Interrupt Enable. See functional description for bit 0.
26	ISE_DMA	GPDMA Interrupt Enable. See functional description for bit 0.
27	ISE_I2S	I^2S Interrupt Enable. See functional description for bit 0.
28	ISE_ENET	Ethernet Interrupt Enable. See functional description for bit 0.
29	ISE_RIT	Repetitive Interrupt Timer Interrupt Enable. See functional description for bit 0.
30	ISE_MCPWM	Motor Control PWM Interrupt Enable. See functional description for bit 0.
31	ISE_QEI	Quadrature Encoder Interface Interrupt Enable. See functional description for bit 0.


Cortex-M3
CPU
36/72 MHz
JTAG/SW debug
Nested vectored
IT controller
1 x systic timer
DMA 7 channels
ARM Lite
high-speed
bus matrix/
arbiter
(max.
72 MHz)
Flash
I/F
32 KB-128 KB
Flash memory
6 KB-16/20 KB SRAM
20 B backup registers
Clock control
ARM peripheral bus
Bridge
(max. 36 MHz)
Bridge
ARM peripheral bus
(max. 72 MHz)
6 x 16-bit PWM
synchronized AC timer
Up to 16 external ITs
32/49/80 I/Os
1 x SPI
1 x USART/LIN
smartcard/IrDA
modem control
3 x 16-bit timer
2 x watchdog
(independent and
window)
1 or 2 x 12-bit ADC
16 channels/1 Msps
Temperature sensor
Power supply
Reg 1.8 V
POR/PDR/PVD
XTAL oscillators
32 kHz + 4~16 MHz
Internal RC oscillators
32 kHz + 8 MHz
PLL
RTC/AWU
1 x USB 2.0FS
1 x CAN 2.0B
2 x USART/LIN
smartcard/
IrDA modem control
1 x SPI
2 x I²C
DMA: Direct memory access
RTC: Real-time clock
AWU: Auto wake-up capability with RTC alarm
POR: Power-on reset
PDR: Power-down reset
PVD: Programmable voltage detector

Library functions in core_cm3.h

```
935 /** \brief  Enable External Interrupt
936
937     This function enables a device specific interupt in the NVIC interrupt controller.
938     The interrupt number cannot be a negative value.
939
940     \param [in]      IRQn  Number of the external interrupt to enable
941  */
942 static __INLINE void NVIC_EnableIRQ(IRQn_Type IRQn)
943 {
944   NVIC->ISER[((uint32_t)(IRQn) >> 5)] = (1 << ((uint32_t)(IRQn) & 0x1F)); /* enable interrupt */
945 }
946
```

```
1015 /** \brief  Set Interrupt Priority
1016
1017     This function sets the priority for the specified interrupt. The interrupt
1018     number can be positive to specify an external (device specific)
1019     interrupt, or negative to specify an internal (core) interrupt.
1020
1021     Note: The priority cannot be set for every core interrupt.
1022
1023     \param [in]      IRQn  Number of the interrupt for set priority
1024     \param [in]  priority  Priority to set
1025  */
1026 static __INLINE void NVIC_SetPriority(IRQn_Type IRQn, uint32_t priority)
1027 {
1028   if(IRQn < 0) {
1029     SCB->SHP[((uint32_t)(IRQn) & 0xF)-4] = ((priority << (8 - __NVIC_PRIO_BITS)) & 0xff); } /* set Priority for Cortex-M  System I
1030   else {
1031     NVIC->IP[(uint32_t)(IRQn)] = ((priority << (8 - __NVIC_PRIO_BITS)) & 0xff);    }        /* set Priority for device specific In
1032 }
```

NVIC Constant and addresses

- core_cm3.h

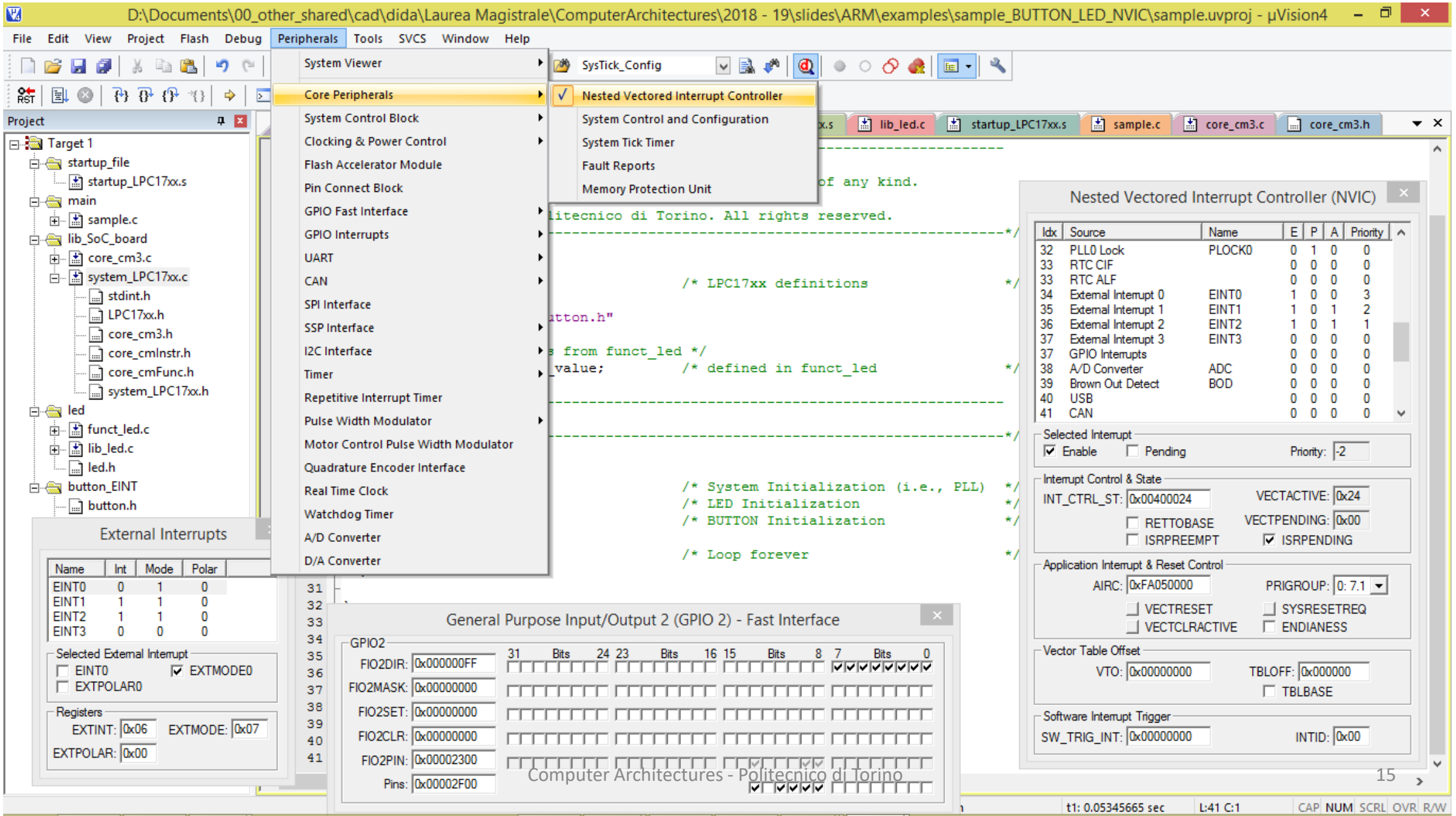
```
832 /* Memory mapping of Cortex-M3 Hardware */
833 #define SCS_BASE            (0xE000E000)                          /*!< System Control Space Base Address */
834 #define ITM_BASE            (0xE0000000)                          /*!< ITM Base Address                  */
835 #define CoreDebug_BASE      (0xE000EDF0)                          /*!< Core Debug Base Address           */
836 #define SysTick_BASE        (SCS_BASE +  0x0010)                  /*!< SysTick Base Address              */
837 #define NVIC_BASE           (SCS_BASE +  0x0100)                  /*!< NVIC Base Address                 */
838 #define SCB_BASE            (SCS_BASE +  0x0D00)                  /*!< System Control Block Base Address */
839
840 #define InterruptType       ((InterruptType_Type *) SCS_BASE)     /*!< Interrupt Type Register           */
841 #define SCB                 ((SCB_Type *)           SCB_BASE)     /*!< SCB configuration struct          */
842 #define SysTick             ((SysTick_Type *)       SysTick_BASE) /*!< SysTick configuration struct      */
843 #define NVIC                ((NVIC_Type *)          NVIC_BASE)    /*!< NVIC configuration struct         */
844 #define ITM                 ((ITM_Type *)           ITM_BASE)     /*!< ITM configuration struct          */
845 #define CoreDebug           ((CoreDebug_Type *)     CoreDebug_BASE) /*!< Core Debug configuration struct */
846
```

NVIC Constant and addresses

- core_cm3.h

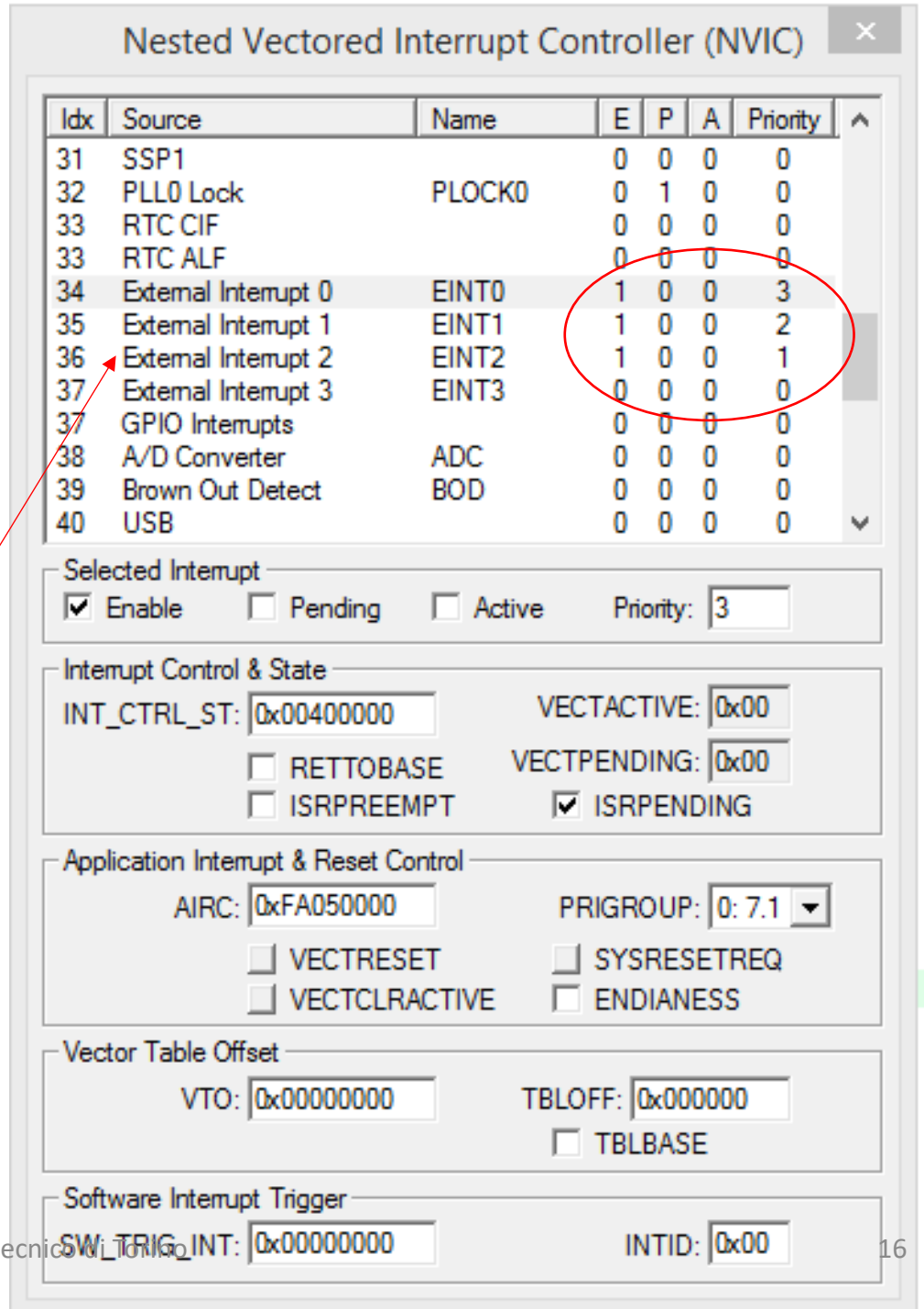
```
214 /** \brief  Structure type to access the Nested Vectored Interrupt Controller (NVIC).
215  */
216 typedef struct
217 {
218   __IO uint32_t ISER[8];                 /*!< Offset: 0x000 (R/W)  Interrupt Set Enable Register           */
219        uint32_t RESERVED0[24];
220   __IO uint32_t ICER[8];                 /*!< Offset: 0x080 (R/W)  Interrupt Clear Enable Register         */
221        uint32_t RSERVED1[24];
222   __IO uint32_t ISPR[8];                 /*!< Offset: 0x100 (R/W)  Interrupt Set Pending Register          */
223        uint32_t RESERVED2[24];
224   __IO uint32_t ICPR[8];                 /*!< Offset: 0x180 (R/W)  Interrupt Clear Pending Register        */
225        uint32_t RESERVED3[24];
226   __IO uint32_t IABR[8];                 /*!< Offset: 0x200 (R/W)  Interrupt Active bit Register           */
227        uint32_t RESERVED4[56];
228   __IO uint8_t  IP[240];                 /*!< Offset: 0x300 (R/W)  Interrupt Priority Register (8Bit wide) */
229        uint32_t RESERVED5[644];
230   __O  uint32_t STIR;                    /*!< Offset: 0xE00 ( /W)  Software Trigger Interrupt Register     */
231 }  NVIC_Type;
```

Experiment priority and nested interruptions



BOOT

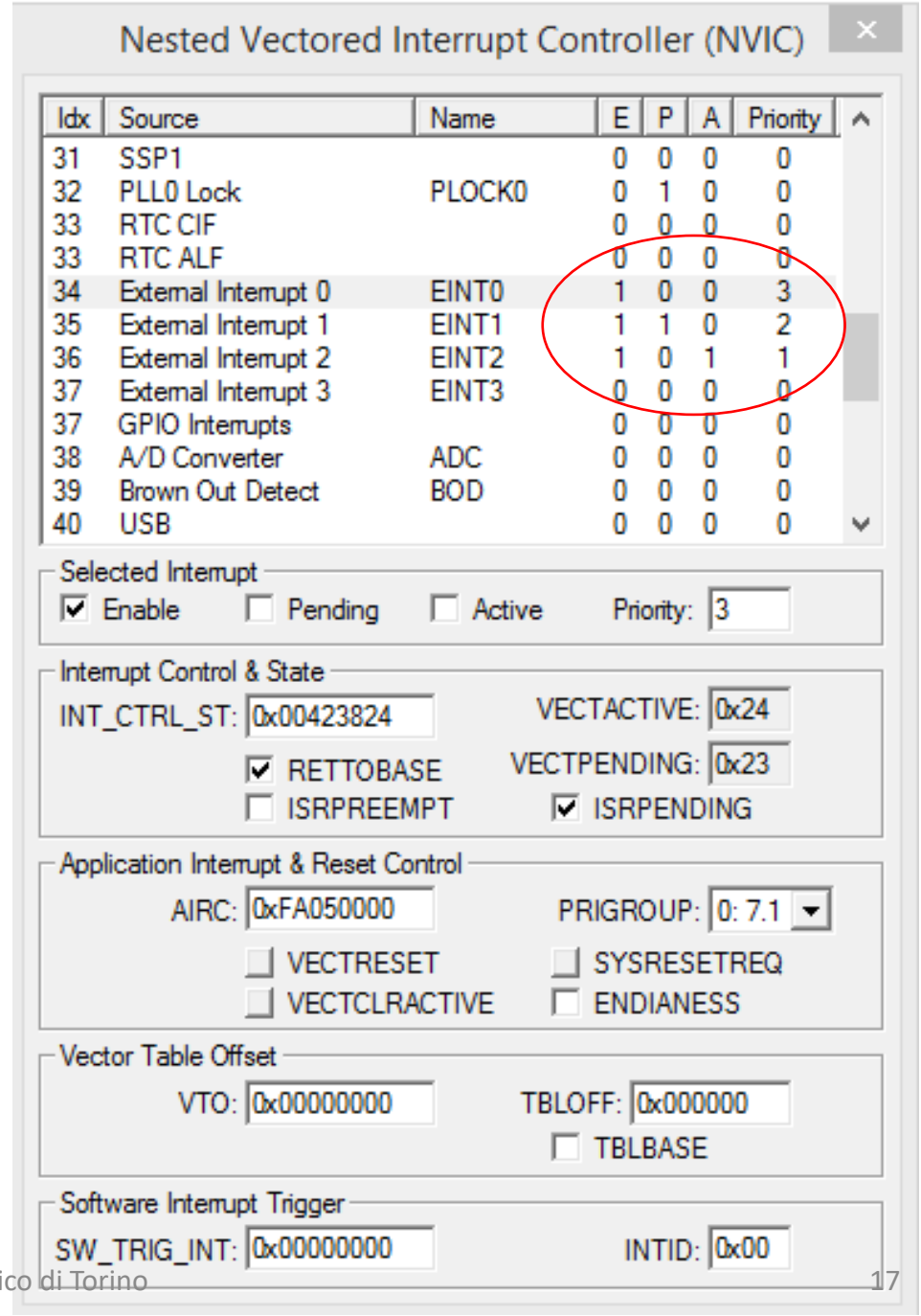
```
 8  void BUTTON_init(void) {
 9
10    LPC_PINCON->PINSEL4    |= (1 << 20);
11    LPC_GPIO2->FIODIR      &= ~(1 << 10);
12
13    LPC_PINCON->PINSEL4    |= (1 << 22);
14    LPC_GPIO2->FIODIR      &= ~(1 << 11);
15
16    LPC_PINCON->PINSEL4    |= (1 << 24);
17    LPC_GPIO2->FIODIR      &= ~(1 << 12);
18
19    LPC_SC->EXTMODE = 0x7;
20
21    NVIC_EnableIRQ(EINT2_IRQn);
22    NVIC_SetPriority(EINT2_IRQn, 1);
23    NVIC_EnableIRQ(EINT1_IRQn);
24    NVIC_SetPriority(EINT1_IRQn, 2);
25    NVIC_EnableIRQ(EINT0_IRQn);
26    NVIC_SetPriority(EINT0_IRQn, 3);
27  }
28
```



RUNTIME (1)

- CASE 1)
  1. The EINT2 interrupt is taken and being served
  2. The EINT1 interrupt (with lower priority) is taken
  3. EINT1 is pending and will be served only when EINT2 is fully handled

```
6  void EINT0_IRQHandler (void)
7  {
8    LED_On(0);
9    LPC_SC->EXTINT &= (1 << 0);     /* clear pending interrupt         */
10 }
11
12
13 void EINT1_IRQHandler (void)
14 {
15   LED_On(1);
16   LPC_SC->EXTINT &= (1 << 1);     /* clear pending interrupt         */
17 }
18
19 void EINT2_IRQHandler (void)
20 {
21   LED_Off(0);
22   LED_Off(1);
23   LPC_SC->EXTINT &= (1 << 2);     /* clear pending interrupt         */
24 }
25
```



RUNTIME (2)

- CASE 2)
  1. The EINT1 interrupt is taken and being served
  2. The EINT2 interrupt (with higher priority) is taken
  3. EINT1 is suspended and completed only when EINT2 is handled

```
6  void EINT0_IRQHandler (void)
7  {
8    LED_On(0);
9    LPC_SC->EXTINT &= (1 << 0);     /* clear pending interrupt        */
10 }
11
12
13 void EINT1_IRQHandler (void)
14 {
15   LED_On(1);
16   LPC_SC->EXTINT &= (1 << 1);     /* clear pending interrupt        */
17 }
18
19 void EINT2_IRQHandler (void)
20 {
21   LED_Off(0);
22   LED_Off(1);
23   LPC_SC->EXTINT &= (1 << 2);     /* clear pending interrupt        */
24 }
25
```