

August 21 (Monday)

Organizational Meeting.

1. The "GreenSheet" is posted on the github

Note: Bring your Laptop Computer to the Class.

<https://github.com/hualili/CMPE244>

Course and Contact Information

Instructor:	Harry Li, Ph.D. Professor, Computer Engineering Dept., San Jose State University
Office Location:	Engineering Building 267A
Telephone:	(408) 924-4060 (650) 400-1116
Email:	hua.li@sjtu.edu
Class Days/Time:	Mondays and Wednesdays, 4:30 pm – 5:45 pm, August 21, 2023
Office Hours:	Mondays and Wednesdays, 3:00 pm – 4:00 pm
Classroom:	Engineering Building Room 295
Prerequisites:	CMPE 180A and CMPE 180D, classified standing, computer science majors or Artificial Intelligence or Computer Engineering or Software Engineering majors only.

2. Emphasis on Posix O.S. Linux OpenSource O.S. & Device Drivers Programming and Development. Scalability & Vertical Solution.

Course Description

Experiments dealing with advanced embedded software programming concepts, interfacing techniques, hardware organization, and software development using embedded systems. Individual projects.

3. Course Format: In-Person.

Hands-on Class. Prototype System

Optional. NVIDIA Jetson Nano. GPU (128)

4 GB Version CPU JetPack

Option 2. Broadcom Piex3B+, Piex4.

Option 3. RISC-V FPGA Dev. Board + FreeRTOS

Selection Decision in 1 week

Option 4. NXP LPC11G24 or

LPC1768, RTOS. NXP

Dev. Forum.

has limited Processing Power.

May Not Meet the Need for Our Project

4. Textbook & References

Set I: Datasheets(s), CPU Datasheet, Developer Guide; Set II: NVIDIA Developer Forum. Set III: PPTs, Sample Code, Handouts in the Class GitHub.

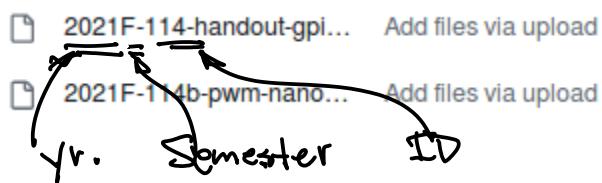
Course Materials

Instructor's teaching materials and online resources.

1. Professor's git: <https://github.com/hualili/CMPE244>
2. Jetson NANO Jetpack download <https://developer.nvidia.com/embedded/downloads>

Other Equipment / Material

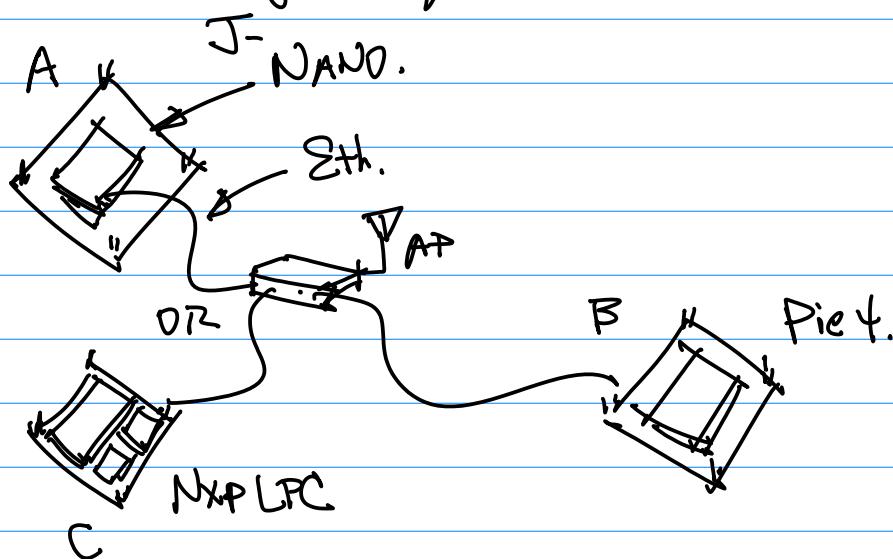
1. Hardware Equipment: You may choose any one of the following options. For detailed selection information, I will cover it in the introduction session of the class. Option 1. Nvidia Jetson NANO Board with minimum 2 GB RAM; or Option 2. Pi 3B+, or Pi 4; Option 3: Nvidia Jetson Tx2 developer kit; or Option 4: LPC1769 CPU Module: https://www.mouser.com/NXP-Semiconductors/Embedded-Solutions/Engineering-Tools/Embedded-Processor-Development-Kits/Development-Boards-Kits-ARM/_/N-cxd2t2P=1z0jm4m&Keyword=LPC1769&FS=True&gclid=Cj0KCQjwqKuKBhCRAIIsACf4XuHyN8WfqtQ24WGgt0MdKd6n-k17c-YNz-r1hTcPt0ErdZN62jrM0mgaAtXZEALw_wcB or Option 5: Samsung ARM11 developer platform.
2. Linux Host Machine (Ubuntu 18.04).



Naming Convention:

A & B
A & C

Note: Regarding the Selection of
A Target Platform:



5. Grading Policy

Project Assignment (Two Projects)	
Phased	
Assignments and projects:	15% (pts) for the assigned projects.
Midterm Exam:	30%
Final Exam:	30%
Total:	40%
	100%

August 23rd (Wed)

Introduction

Note: Rm268

Ref:

Datasheets.



bcm



lpc



nvda



sam

Broadcom

Pi e

Linux O.S.

NXP

LPC1769

RTOS

IP Stack

Micro Web Server

Jetson

NAND.

JetPack O.S.

Linux (Ubuntu)

+ Additional
Packages.

Samsung

ARM11

2021F-107-lpc-cpu-
UM10360.pdf

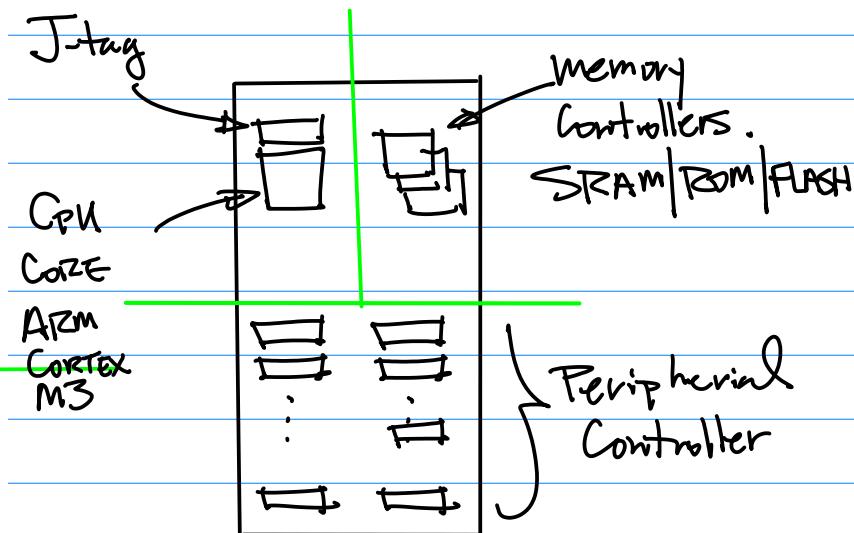
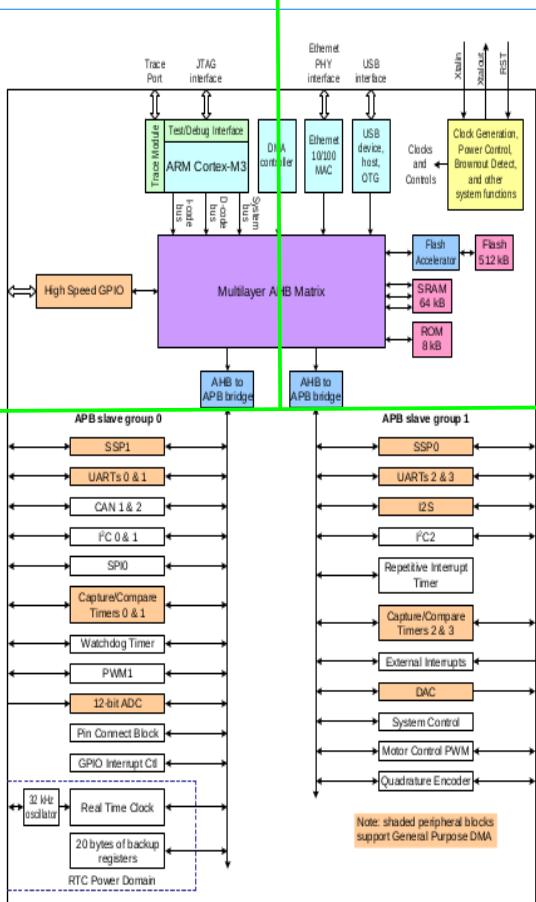
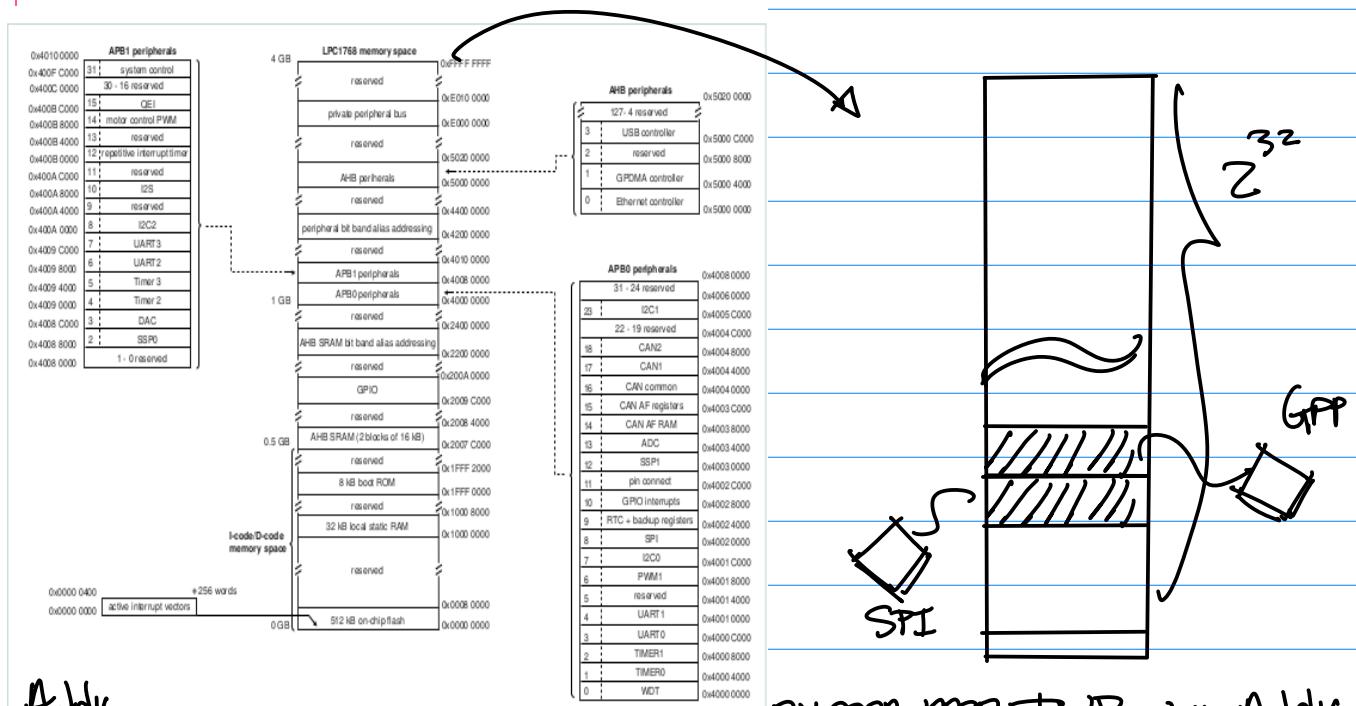


Fig. 1

Note: The CPU Block Diagram for LPC1769 is a Sample for the Rest of the target platforms.

e.g. Pic34 ; Sam's ARM 11 ;
NVIDIA Jetson NANO

Note 2 :



Addrs.

$$Z^{32} = Z^0 \cdot Z^1 \cdot Z^2 \cdot Z^3$$

1024 : 1 4
1K : 1
1Meg. : 1
1G. : 1

4 G Addressess.

Example: "B", Sam's CPU
ARM11

Fig. 2

0X0000-0000 PWR-up Addr.

Datasheets.

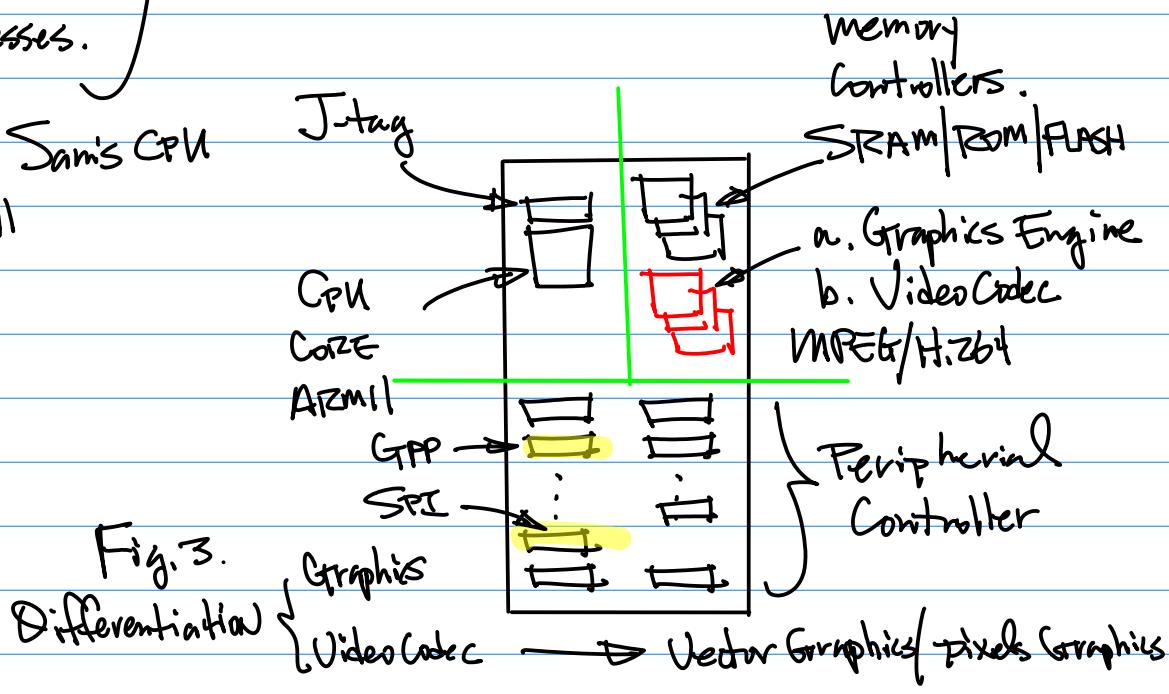
2021F-105-#0-cpu-arm11-
2018S-29-CPU_S3C6410X.
pdfLocate the page with the top level
Description of the CPU Architecture

Fig. 3.

Differentiation

Graphics
Video Codec

→ Vector Graphics/Pixels Graphics

Example: Connection to (Embedded) Software Architecture

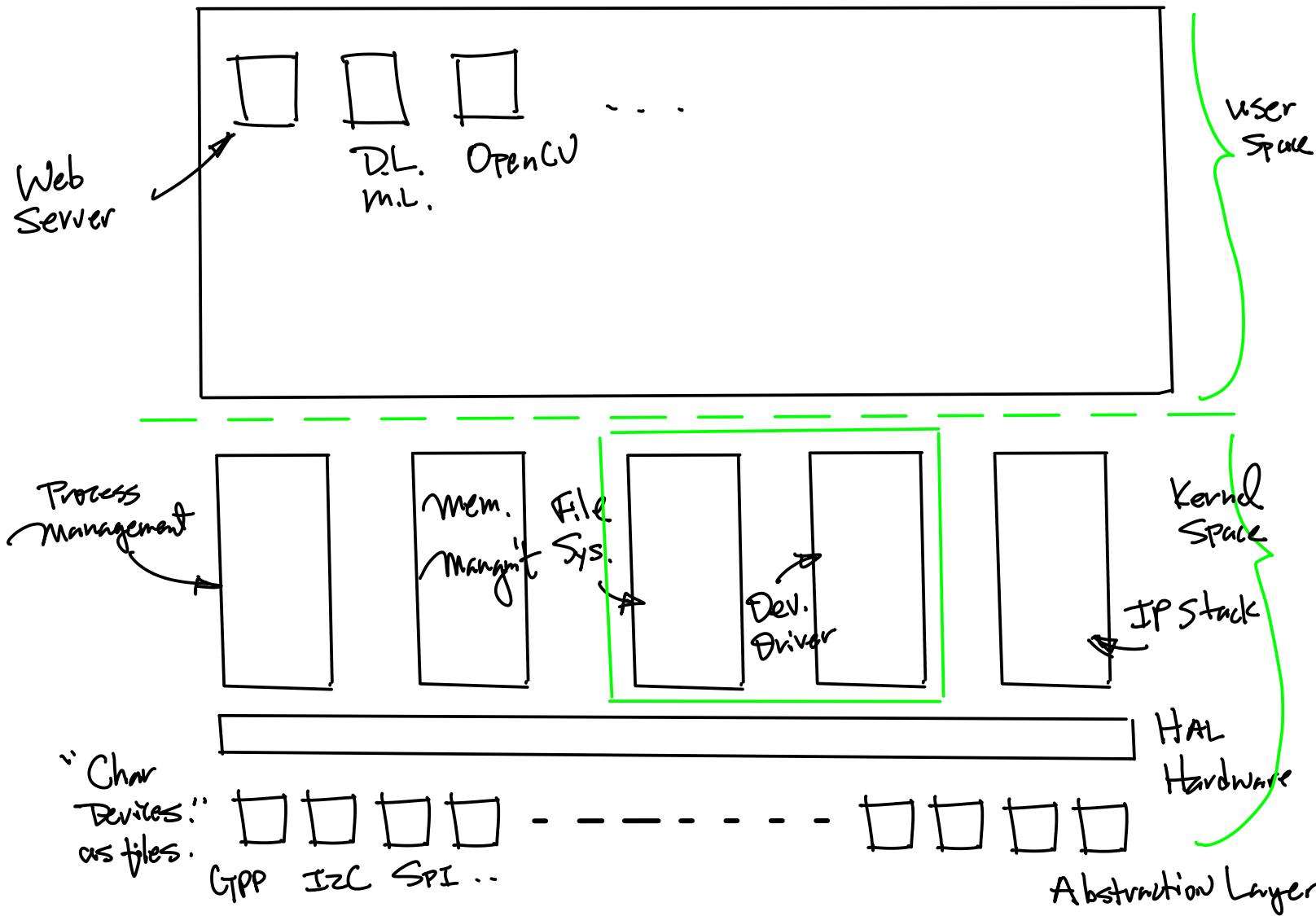


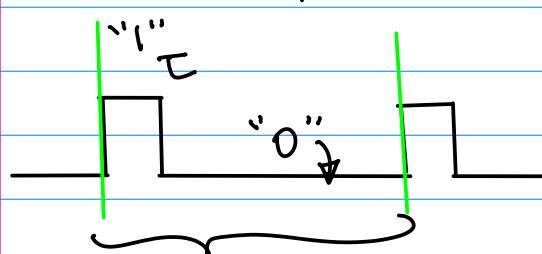
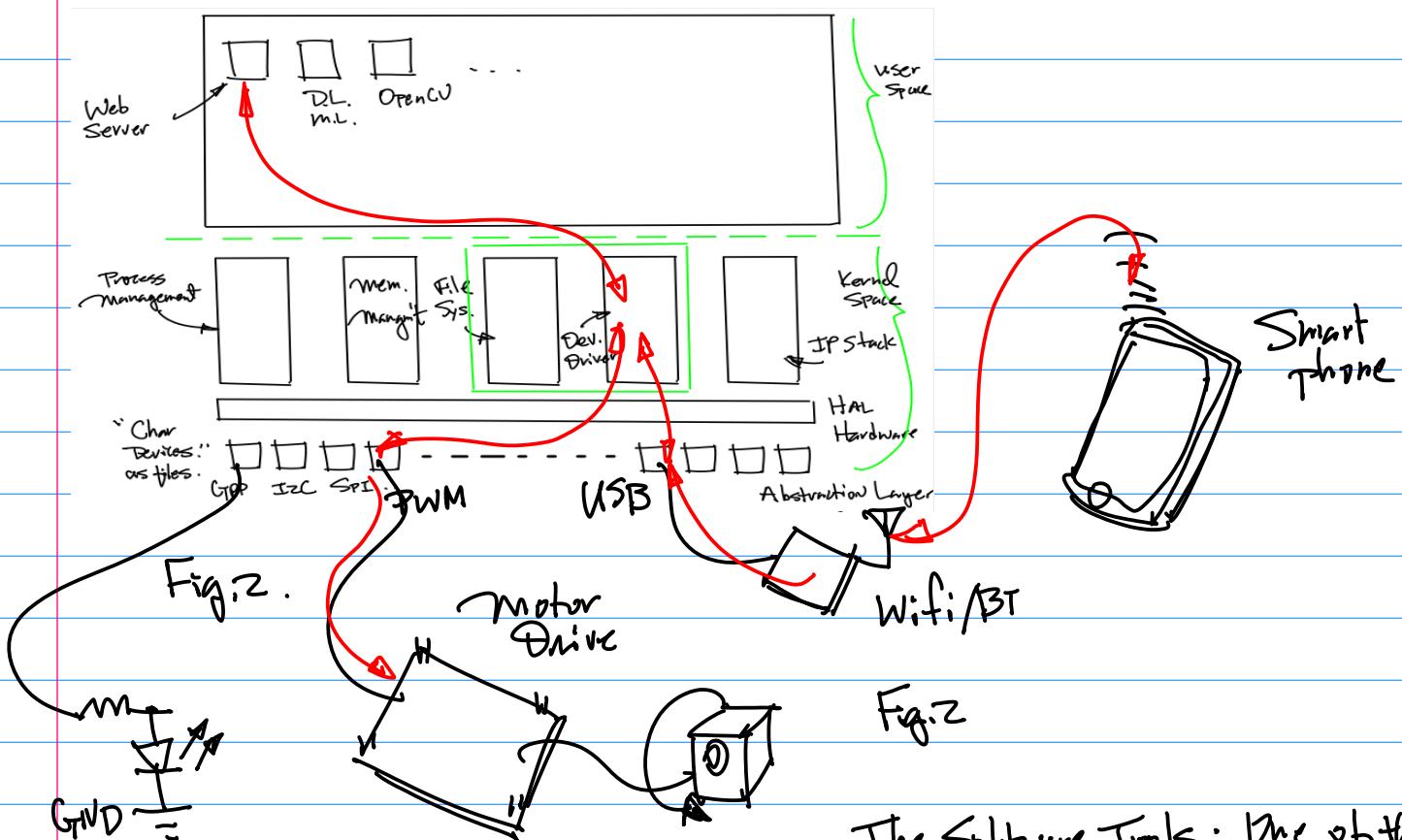
Fig.1.

Note: Data Size for 1080P
Image OR 720P

August 28 (Monday)
Note: 1^o Brief Description D.V.
the Scope of Semester-Long
Project.

- Embedded Software; Kernel D.S.
- Device Driver → APPS for iPhone/Android phone
- 2^o CANVAS is up.
- Honesty pledge
- 3^o Target platform → Minor upgrade to Enable RTC by Adding On-Board Battery

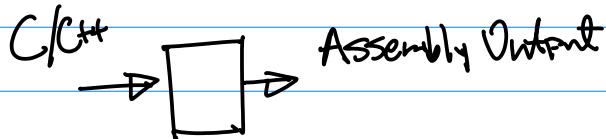
Example: Continuation of the Introduction/Embedded Software Architecture.



T One Period

$$\left\{ \begin{array}{l} \text{Duty Cycle} = \frac{T}{f_{\text{PWM}}} \dots (1) \\ f_{\text{PWM}} \dots (2) \end{array} \right.$$

The Software Tools: One of them is open source gcc, or g++ Compiler.



Porting. → Match to the Core (ISA: Instruction Set Architecture)
Device Drivers Customization.

✓ Peripheral Controller
A Set of Special Purpose Registers.

Most Likely this SPR has
the paddr in the Block.

Identify A peripheral controller, GPP

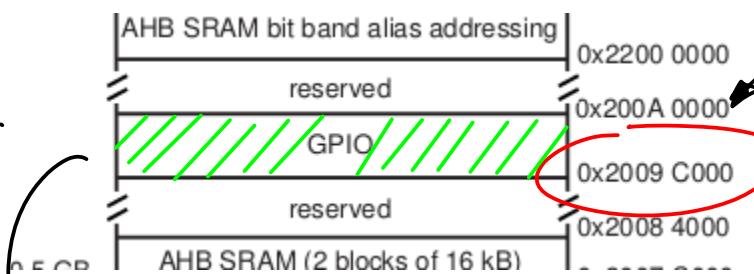
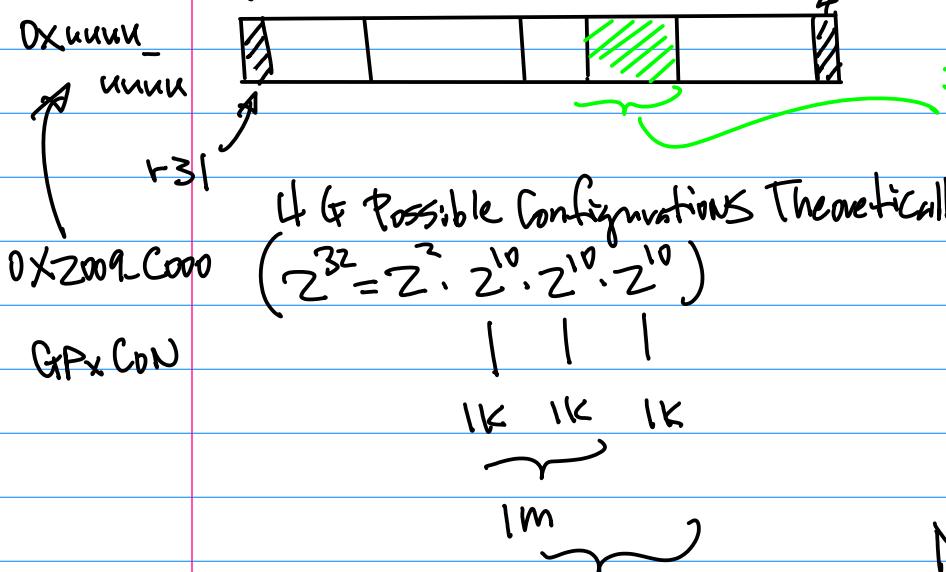


Fig. 3.

→ Memory is dedicated for
SPR's (Special Purpose Registers)

Control & Configuration Register



It has its unique address. (at the multiple of 4).

Write 32 bits unsigned Data as Init & Config pattern to Select the GPP & the pin as output.

Next. Naming Convention.

Guideline : RISC → UC Berkeley David Patterson
Stanford, John Hennessy

August 30 (Wed)

Note: 1^o CANVAS is up.

Honesty Pledge to Be Signed
And Submit on CANVAS
By this Friday 11:59 pm.

2^o Please Bring the target platform to the Class. Next Wednesday.

3^o (Written Requirements) ^{in 2 weeks}

Bring up your target platform
By Downloading Kernel OS.

Image to A micro-SD Card,
then boot the System.

then Screen Capture with your personal identifier, Submit it on CANVAS.

4^o Create A ChatGPT Account, Python interface to ChatGPT (3.5) API.

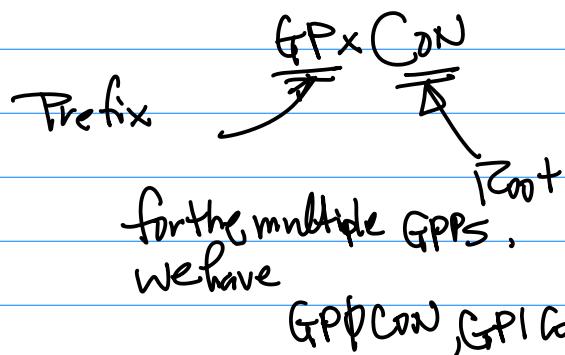
Example: Continued.

Naming Convention of the Control & Configuration Register.

By John Hennessy . Golden Rules

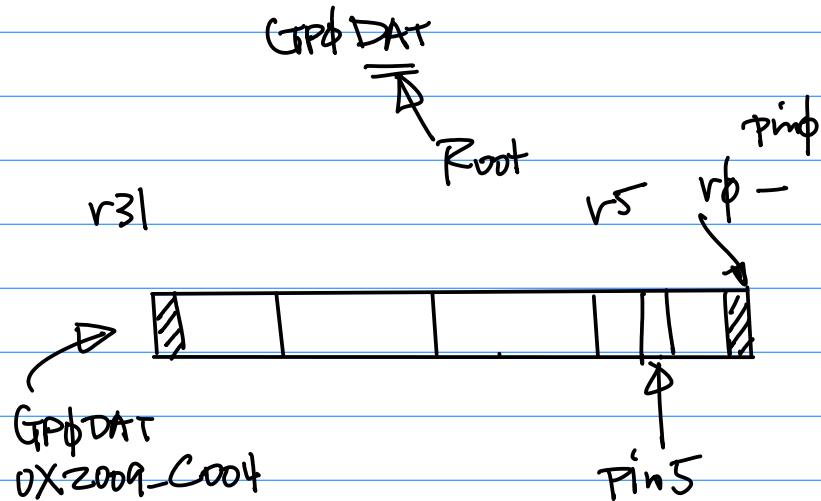
Uniformity, "3+3"
Regularity,
Orthogonality Naming Convention

Prefix + Root
3 letters 3 letters.



Suppose we want to use GP0 pin 5 as an output to turn on/off LED.

Design 2nd SPR.



place "1" @ R5 to Output logical high.
"0" ..
Low.

#define GP0CON
GP0DAT

Porting Porting
gcc/g++ → ARM → CORTEX

Porting ↓
Board

Sept 6 (Wed).

Note: 1° Target Board
Inspection:

Purpose: J41 Connector

RTC Battery 2021F-114~
Ref: on the github.

2021F-114-gpio-nano-v2-h1-2021-10-20.pdf

Harry Li, Ph.D.

NVIDIA Jetson Nano J41 Header Pinout

<https://www.jetsonhacks.com/nvidia-jetson-nano-j41-header-pinout/>

Note: I2C and UART pins are connected to hardware and should not be reassigned. By default, all other pins (except power) are assigned as GPIO. Pins labeled with other functions are recommended functions if using a different device tree.

GPIO	Name	Pin	Pin	Name	Sysfs GPIO
	3.3 VDC Power	1	2	5.0 VDC Power	
	I2C_2_SDA I2C Bus 1	3	4	5.0 VDC Power	
	I2C_2_SCL I2C Bus 1	5	6	GND	
gpio216	AUDIO_MCLK	7	8	UART_2_TX /dev/ttyTHS1	
	GND	9	10	UART_2_RX /dev/ttyTHS2	
gpio50	UART_2_RTS	11	12	I2S_4_SCLK	gpio79
gpio14	SPI_2_SCK	13	14	GND	
gpio194	LCD_TE	15	16	SPI_2_CS1	gpio232
	3.3 VDC Power	17	18	SPI_2_CS0	gpio15
gpio16	SPI_1_MOSI	19	20	GND	
gpio17	SPI_1_MISO	21	22	SPI_2_MISO	gpio13
gpio18	SPI_1_SCK	23	24	SPI_1_CS0	gpio19
	GND	25	26	SPI_1_CS1	gpio20

Diagram showing the pinout for the NVIDIA Jetson Nano J41 Header. The diagram is divided into two main sections: Top (left) and Bottom (right). The Top section shows pins 25 through 39, while the Bottom section shows pins 1 through 24. Various pins are color-coded and grouped by function:

- Power:** GND (Grey), 3.3 VDC Power (Orange), 5.0 VDC Power (Red).
- I2C:** I2C_1_SDA (Pink), I2C_1_SCL (Pink), I2C_2_SDA (Purple), I2C_2_SCL (Purple).
- UART:** UART_2_RTS (Blue), UART_2_RX (Blue), UART_2_TX (Blue).
- SPI:** SPI_2_SCK (Green), SPI_2_CS1 (Green), SPI_2_CS0 (Green), SPI_1_MOSI (Orange), SPI_1_MISO (Blue), SPI_1_SCK (Blue), SPI_1_CS0 (Blue), SPI_1_CS1 (Blue).
- Other:** LCD_TE (Green), GND (Grey), CAM_AF_EN (Green), GPIO_PZ0 (Green), GPIO_PE6 (Green), I2S_4_LRCK (Blue), SPI_2_MOSI (Blue), I2S_4_SDIN (Blue), I2S_4_SDOUT (Blue).

Pin 25 is highlighted with a red box at the bottom left of the diagram. Pin 6 is highlighted with a red box in the middle of the top section. Pin 12 is highlighted with a red box in the middle of the bottom section.

Note: 1° Power Pins

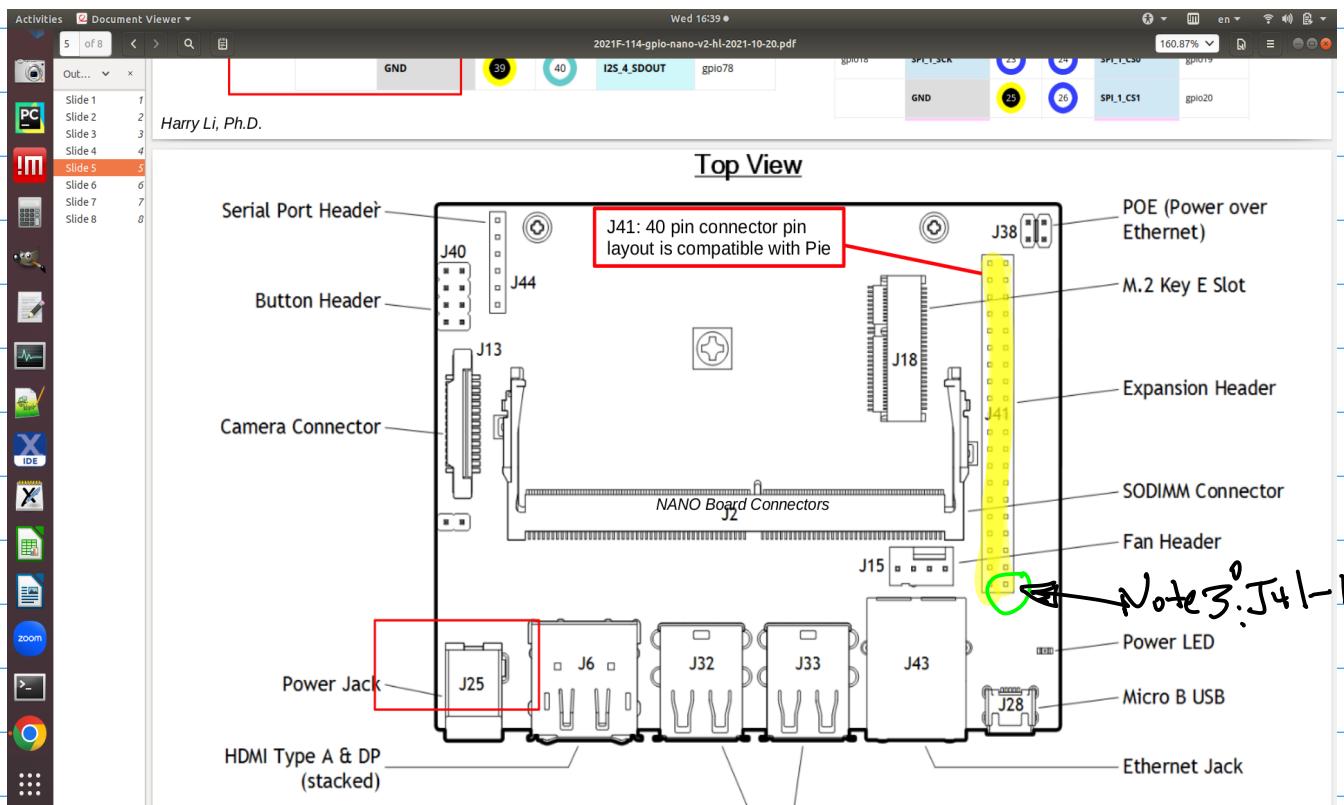
{ GND : b19/25/39
Vout: 3.3VDC/5VDC
Pin 1, Pin 2, 4.
Vin: J25 (5A or higher
@ 5VDC)

Note 2° GPIO

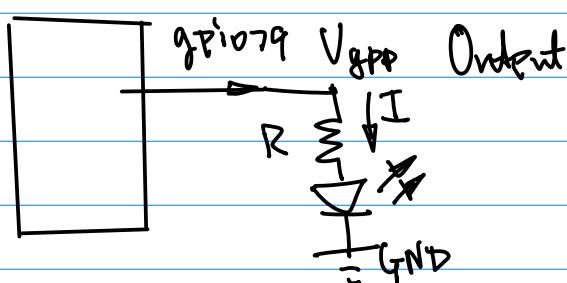
J41-Pins
J41-12
J41-40

CPU Functionality

gpio79
gpio78



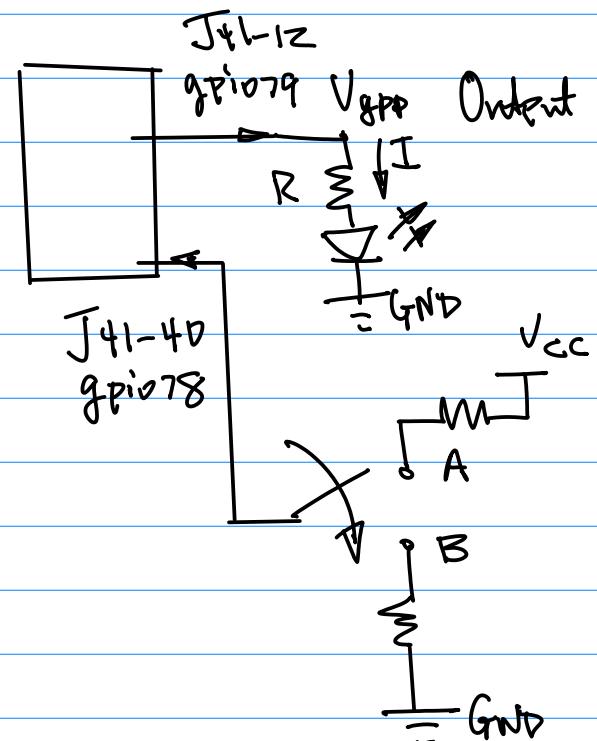
Note 4^o: GPIO Input/Output Testing Ckt
Build the following Testing Ckt.



Let $I = 4 \text{ mA}$, $V_{\text{LED}} \approx 1.8 \text{ V}$

$$V_{\text{DDP.H}} = IR + V_{\text{LED}} \dots (1)$$

w/o Resistor With Proper Selected LED.

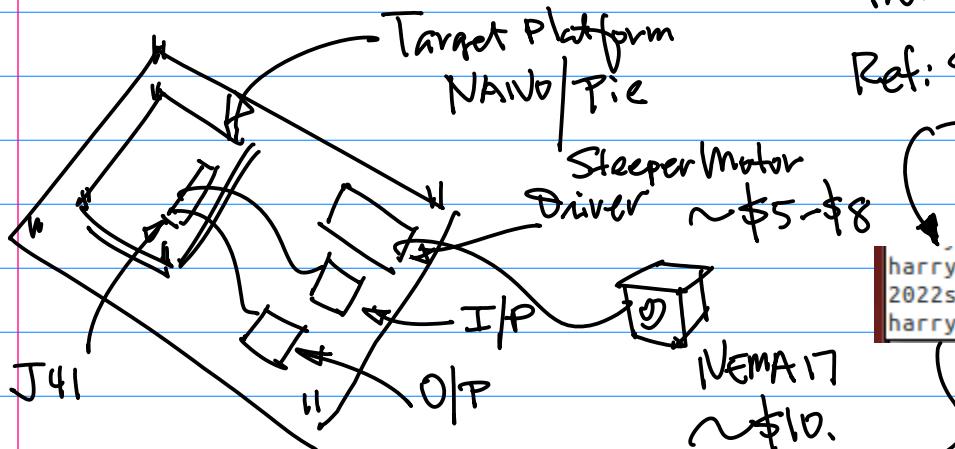


GPIO J41 Pins	CPU Functionality	Note
J41-12	gpio79	Output
J41-40	gpio78	Input

User Space Code
Kernel Space Code

Take a Reference Design
from Arm11, Samsung CPU.

Ref: Sample code has been
Posted on the github.



```
harry@harry-laptop:/opt/FriendlyARM/min
2022s-104d-userSpace-gpio.c led led.c
harry@harry-laptop:/opt/FriendlyARM/min
```

CMPE242-Embedded-Systems- / 2022S / 2022S-104d-userSpace-gpio.c

hualili Add files via upload

Code	Blame	37 lines (30 loc) · 642 Bytes	Code 55% faster with Git
------	-------	-------------------------------	--------------------------

```

1 #include <stdio.h>
2 #include <stdlib.h>
3 #include <unistd.h>
4 #include <sys/ioctl.h>
5 #include <sys/types.h>
6 #include <sys/stat.h>
7 #include <fcntl.h>
```

Note: Form 2 person Team for
A Semester Long Project.

Sharp: Hardware Layer
(Sensors/Actuators)
↓
"Security"
Device Driver/Kernel Space
↓
Process Management

↓
Web Server

↓
Smartphone APPs.

ChatGPT 3.5 API + Python Interface

Example: Sample Code for GPIO Device
Driver

Sept. 11 (Monday)

Notel: Homework Due in 1½ weeks.

To Be Posted on Line today;

a. Bring up the target, Screen
Capture with Personal Identifier.

b. GPIO Testing (Python + Hardware
Circuit). (1) Input Testing (KT).

Output Testing (KT). (2) Coding:

Python.

Note 2: B.o.M. (Bill of Material)

for the class/Project

a. Motor (Stepper Motor, NEMA.

17



Nema17
Stepper Motor
\$8.99
Amazon.com

(2) BLDC
Brushless DC
motor

c. Smartphone (iPhone

OR Android phone

Swift Mac OS. as Development
platform.

Ubuntu Linux.
18.04.

NVIDIA JetPack (OS.)

Note:

With GPIO Testing

Ckt.

(Work-In-
progress)

Target
Board

NVIDIA Jetson Nano Bread Board/

OR Wine Wrapping
Board.



350W Brushed
Electric Motor



10 Inch Hub
Motor 1000w, ...



48V 500W
Wheel Motor ...

b. Motor Drive Unit.



EASON
Stepper Motor
\$9.69
Amazon.com



SparkFun
Electronics ...
\$12.09
DigiKey



WWZMDiB
A4988 Stepper
\$7.99
Amazon.com



Pololu
Corporation
\$8.49
DigiKey



[STEPPERONLINE](#)
[CNC Stepper Motor](#)
[Driver 1.0-4.2A](#)
20-50VDC 1/128

Example: Continuation on Linux D.D.

on ARM-11 (Samsung). Note! userSpace Code Samples, Kernel Space code

```
linux
harry@harry-laptop:/opt/FriendlyARM/mini6410$ cd linux/
harry@harry-laptop:/opt/FriendlyARM/mini6410/linux$ ls
arm-qte-4.7.0      examples          u-boot-mini6410
arm-qt-extended-4.4.3  linux-2.6.38    x86-qte-4.6.1
arm-qtopia          rootfs_qtopia_qt4  x86-qt-extended-4.4.3
busybox-1.17.2     rootfs_qtopia_qt4-s x86-qtopia
harry@harry-laptop:/opt/FriendlyARM/mini6410/linux$
```

Ref. Sample code on github.

```
harry@harry-laptop:/opt/FriendlyARM/mini6410/linux/examples/leds$ ls
2022s-104d-userSpace-gpio.c  led  led.c  led.c~  Makefile  Makefile~
harry@harry-laptop:/opt/FriendlyARM/mini6410/linux/examples/leds$
```

```
22
23      fd = open("/dev/leds0", 0);
24  if (fd < 0) {
25      fd = open("/dev/leds", 0);
26  }
27  if (fd < 0) {
28      perror("open device leds");
29      exit(1);
30  }
31
32      ioctl(fd, on, led_no);
33  close(fd);
34 }
```

Note1: "Char" Device. Open the Device just like a file.

Kernel (OS. Image)
path to the Device.
The Device Driver can be either integrated as the whole kernel image or module (installed/removed)

Note2 for passing control parameter(s) to the Device for Control Action.

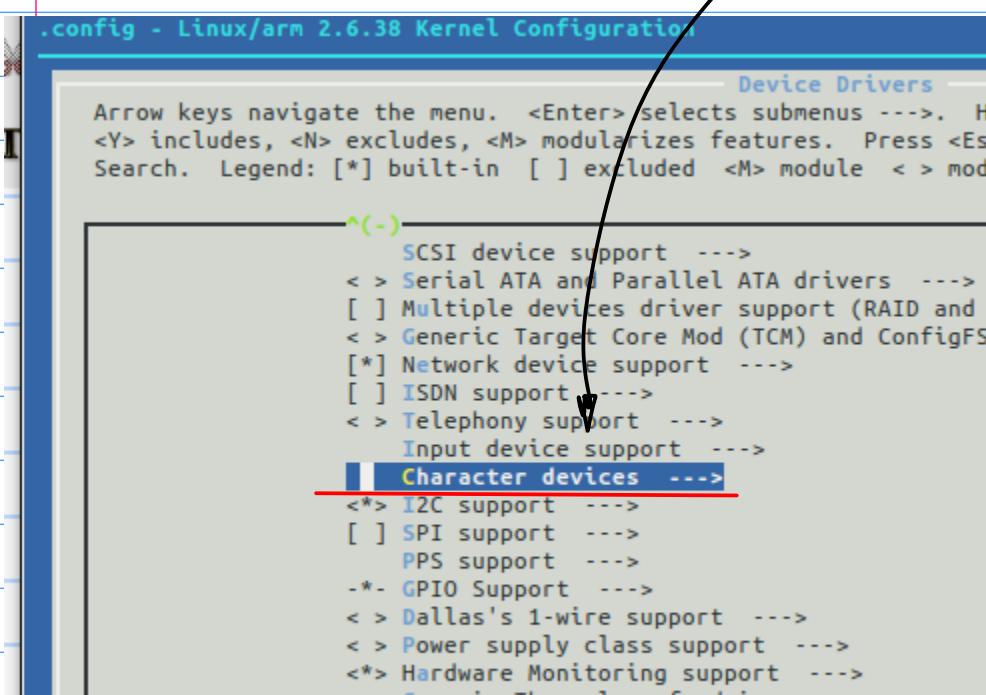
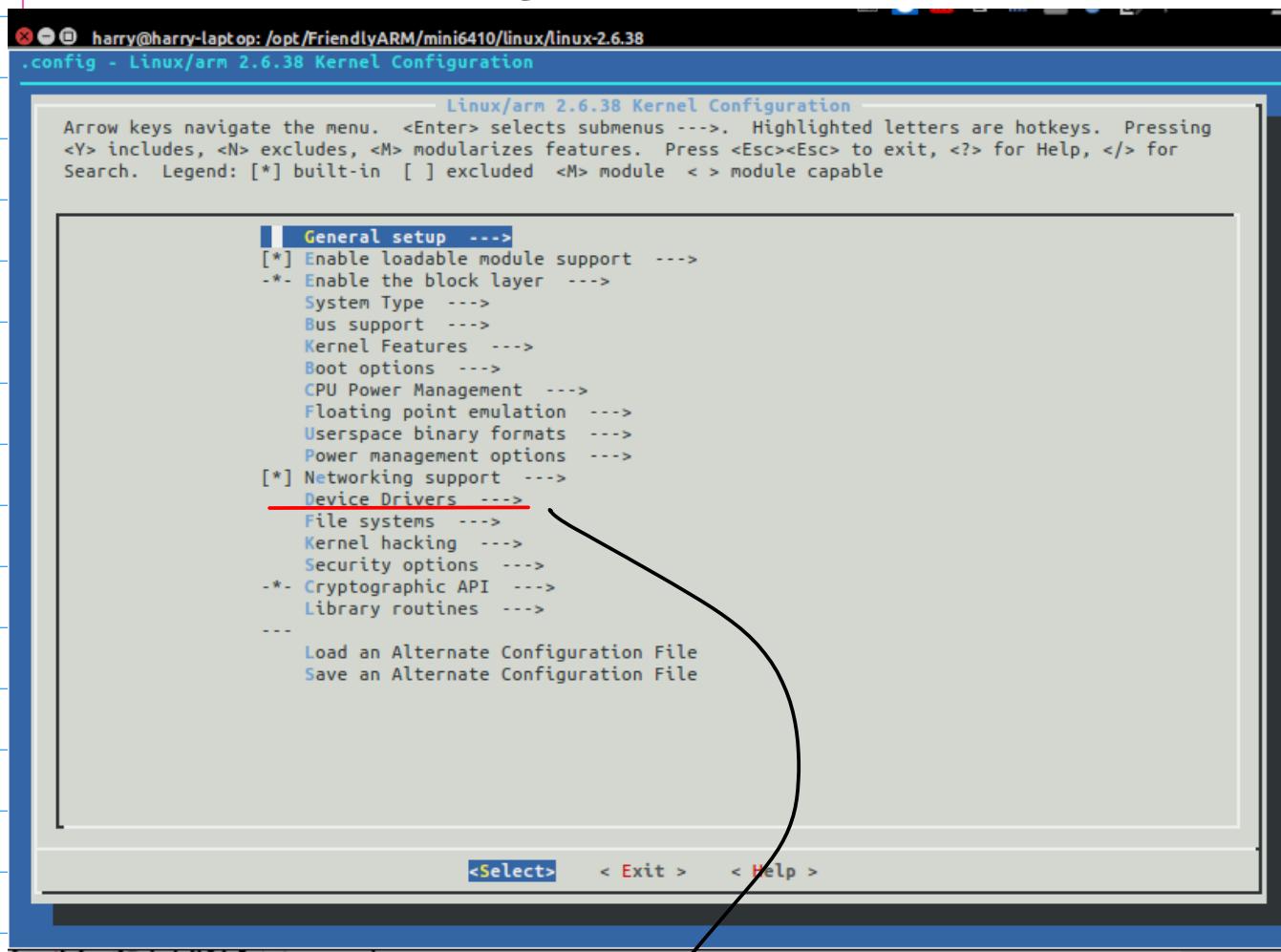
Note3. Close it, when done!

Build

Kernel image using

"menuconfig" → NVDA, Broadcom, Smart phones
Embedded

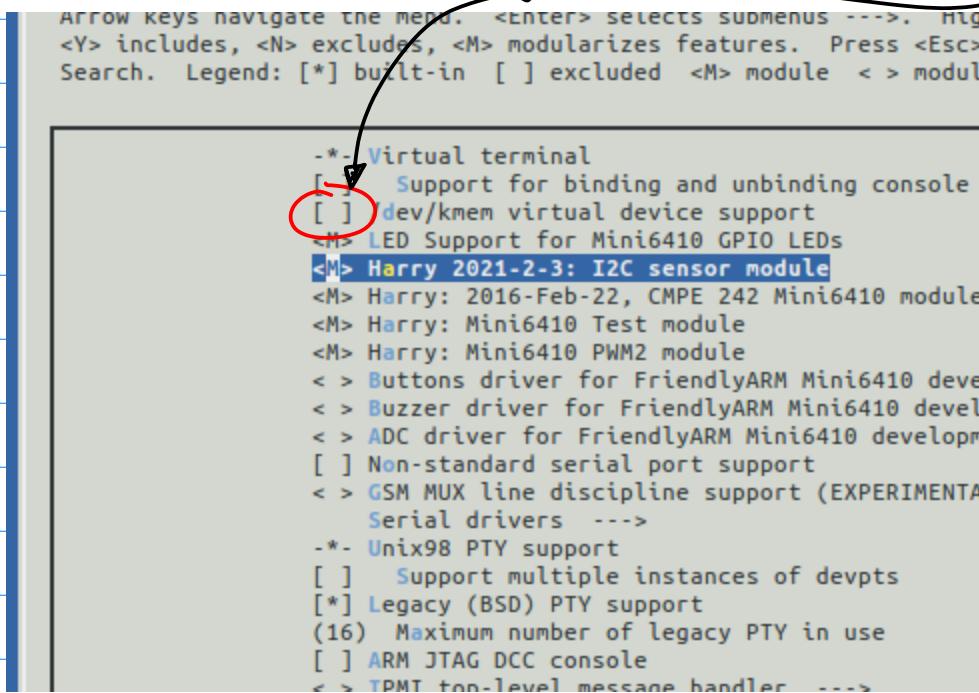
Android.



Note 4. menutools controls how the Kernel Image is built.
 Here, the "Char" Device Driver can be Selected/Deselected.
 b. Use "Space Bar" to toggle between 3 options.

```
Arrow keys navigate the menu. <Enter> selects submenus ---. Hig
<Y> includes, <N> excludes, <M> modularizes features. Press <Esc>
Search. Legend: [*] built-in [ ] excluded <M> module < > modul

```



(Non | M | *)
↓
Module
Integrated Kernel Image

Note 5. Folder for the "Char" D.D., The "gpio" (leds) Device Driver

2023-10-4
CMPE242

```
harry@harry-laptop:/opt/FriendlyARM/mini6410/linux/linux-2.6.38/drivers$ cd char
harry@harry-laptop:/opt/FriendlyARM/mini6410/linux/linux-2.6.38/drivers/char$ ls
20-2021S-9-mini6410_pwmHarry.c  ip2          misc.c      rtc.c
2q                           ipmi         misc.o      scc.i
agg                          isicom.c    mmtimer.c  scx2i
amiserial.c                  istallion.c modules.builtin ser_i
apm-emulation.c              Kconfig     modules.order moxa.c
applicom.c                   lp.c        moxa.h      moxa.h
applicom.h                   Makefile   mspec.c      mspec.c
bfin_jtag_comm.c             Makefile-backup  mwave       mxser.c
bfin-otp.c                   mbcs.c     mxser.h      mxser.h
briq_panel.c                mbcs.h      nozomi.c    nsc_gpio.c
bsr.c                        mem.c       nvram.c      nwbutton.c
built-in.o                   mem.o       nwbutton.h   nwflash.c
cd1865.h                     mini6410_adc.c  pc8736x_gpio.c
cyclades.c                  mini6410_adc.mod.c  pcmcia
digi1.h                      mini6410_adc.o   ppdev.c
digiFep1.h                  mini6410_buttons.c  ps3flash.c
digiPCI.h                   mini6410_buttons.o  ramoops.c
ds1302.c                     mini6410_hello_module.c random.c
ds1620.c                     mini6410_hello_module.o  random.o
dsp56k.c                     mini6410_hello_module.mod.c
dtlk.c                       mini6410_hello_module.mod.o
efirtc.c                     mini6410_hello_module.o
epca.c                       mini6410_leds.c
epcaconfig.h                 mini6410_leds.ko
```

Example: Kernel Space

Device Driver Code Requirements: Code Spec.

Note1:
 Connect the Code to the CPU
 Datasheet
 ↓
 Debug

```

66 static int __init dev_init(void)
67 {
68     int ret;
69
70     {
71         unsigned tmp;
72         tmp = readl(S3C64XX_GPECON);
73         tmp = (tmp & ~(0xffffU<<16))|(0x1111U<<16);
74         writel(tmp, S3C64XX_GPECON);
75
76         tmp = readl(S3C64XX_GPEDAT);
77         tmp |= (0xF << 4);
78         writel(tmp, S3C64XX_GPEDAT);
79     }
80
81     ret = misc_register(&misc);
82
83     printk (DEVICE_NAME"\nHarry: PGE initialized\n");
84 }
```

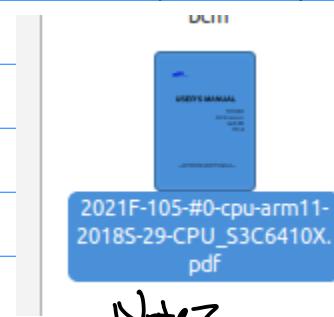
Note2. Read long 32bit

Naming: ID — Peripheral Control
 (Manufacturer Part) GPP



Memory map.

Ref: CPU Datasheet.



Note2.

TP320.

a) GPE Con

6410X_UM

10.5.5 PORT E CONTROL REGISTERS

There are five control registers including GPECON, GPEDAT, GPEPUD, GPECONS, and GPEPUDS in the Port E Control Registers.

Register	Address	R/W	Description	Reset Value
GPECON	0x7F008080	R/W	Port E Configuration Register	0x00
GPEDAT	0x7F008084	R/W	Port E Data Register	Undefined
GPEPUD	0x7F008088	R/W	Port E Pull-up/down Register	0x00000155
GPECONS	0x7F00808C	R/W	Port E Sleep mode Configuration Register	0x0
GPEPUDS	0x7F008090	R/W	Port E Sleep mode Pull-up/down Register	0x0

C. GPEDAT.

d. Two Addition types:

↓
 GPEPUD
 ↓
 GPECONS
 GPEPUDS

Power Control

GPDCON	Bit	Description		Initial State
GPE0	[3:0]	0000 = Input 0010 = PCM SCLK[1] 0100 = AC97 BITCLK 0110 = Reserved	0001 = Output 0011 = I2S CLK[1] 0101 = Reserved 0111 = Reserved	0000
GPE1	[7:4]	0000 = Input 0010 = PCM EXTCLK[1] 0100 = AC97 RESETn 0110 = Reserved	0001 = Output 0011 = I2S CDCLK[1] 0101 = Reserved 0111 = Reserved	0000

Note 3. From the D.D. Code, GPE1 is utilized for the I/O function

$$GPECON[7:4] = 0001$$

5
GPIO
pins

GPDCON	Bit	Description		Initial State
GPE0	[3:0]	0000 = Input 0010 = PCM SCLK[1] 0100 = AC97 BITCLK 0110 = Reserved	0001 = Output 0011 = I2S CLK[1] 0101 = Reserved 0111 = Reserved	0000
GPE1	[7:4]	0000 = Input 0010 = PCM EXTCLK[1] 0100 = AC97 RESETn 0110 = Reserved	0001 = Output 0011 = I2S CDCLK[1] 0101 = Reserved 0111 = Reserved	0000
GPE2	[11:8]	0000 = Input 0010 = PCM FSYNC[1] 0100 = AC97 SYNC 0110 = Reserved	0001 = Output 0011 = I2S LRCLK[1] 0101 = Reserved 0111 = Reserved	0000
GPE3	[15:12]	0000 = Input 0010 = PCM SIN[1] 0100 = AC97 SDI 0110 = Reserved	0001 = Output 0011 = I2S DI[1] 0101 = Reserved 0111 = Reserved	0000
GPE4	[19:16]	0000 = Input 0010 = PCM SOUT[1] 0100 = AC97 SDO 0110 = Reserved	0001 = Output 0011 = I2S DO[1] 0101 = Reserved 0111 = Reserved	0000

How To

Question: Make GPE1 as an output pin,
But keep the rest unchanged?

Sept. 18 (Monday)

Note: 1^o Homework Posted on the
CANVAS.

2^o Homework, Due Sept. 27
(Wed), PWM Testing.

① Enable PWM Device
Driver via Driver mapping
utility By NVIDIA

② Test PWM Output By
Changing f_{PWM} from 2 kHz
to 50 Hz; By changing
Duty Cycle from 5% to 90%.

Then, Observe its Output

Note: Output with 2222 npn Transistor
to drive a LED. (see the
details in the Class PPT on
github). (U.S.)

Note: Prepare the Source Distribution
Download, to build Kernel
Image from the distribution.
(1 ~ 1½ week).

Note: Ref. on Smartphone Apps.
Android APPs Development.

Note: Device Driver Sample Code

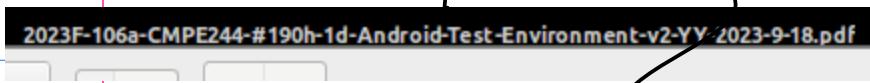
- 2023F-104-gpio-command-line-2023...
- 2023F-105a-2022s-104d-userSpace...
- 2023F-105b-mini6410_leds.mod.c
- 2023F-106a-CMPE244-#190h-1d-A...

README.md

Update README.md

APPS .

Note: Install Android Studio
ON your Laptop .



Install Android Studio on Ubuntu 18.04 (9/15-8/3/2023)

1. Check Java version

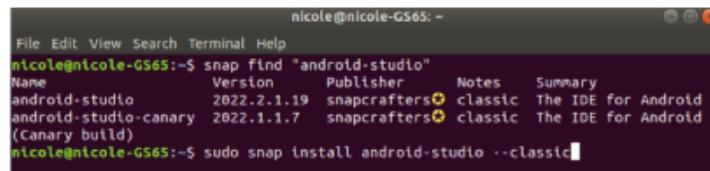
```
nicole@nicole-GS65:~$ java --version
openjdk 11.0.19 2023-04-18
OpenJDK Runtime Environment (build 11.0.19+7-post-Ubuntu-0ubuntu118.04.1)
OpenJDK 64-Bit Server VM (build 11.0.19+7-post-Ubuntu-0ubuntu118.04.1, mixed mode, sharing)
nicole@nicole-GS65:~$
```

3. Once installed, double click the icon to start the studio

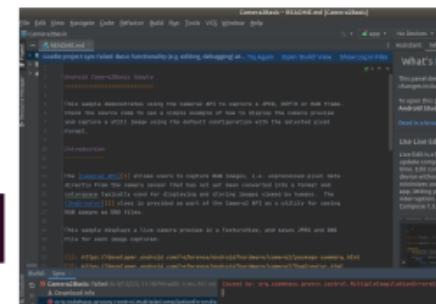


2. Install Android Studio using snap

```
$ snap find "android-studio"
$ sudo snap install android-studio --classic
```



```
(base) harry@harrys-gpu-laptop:~$ sudo snap install android-studio --classic
[sudo] password for harry:
android-studio 2022.3.1.18 from Snapcrafters● installed
```



Note: Team Project (1) Formation of
The Team ; (2) Selection of Smart phone
for the APP. (3) Stepper motor
Drive Board and Stepper motor.

Example: GPIO & PWM .

2023F-104

GPIO Command Line

<https://jetsonhacks.com/2019/06/07/jetson-nano-gpio/>

```
# Map GPIO Pin
# gpio79 is pin 12 on the Jetson Nano
$ echo 79 > /sys/class/gpio/export
# Set Direction
$ echo out > /sys/class/gpio/gpio79/direction
# Bit Bangin'!
$ echo 1 > /sys/class/gpio/gpio79/value
$ echo 0 > /sys/class/gpio/gpio79/value
# Unmap GPIO Pin
$ echo 79 > /sys/class/gpio/unexport
# Query Status
$ cat /sys/kernel/debug/gpio
```

PWM

2021F-114b - ~

Note: Establish Remote Access to your target, e.g. Laptop to Access your target Board.

→ Next Monday, Show+Tell in class

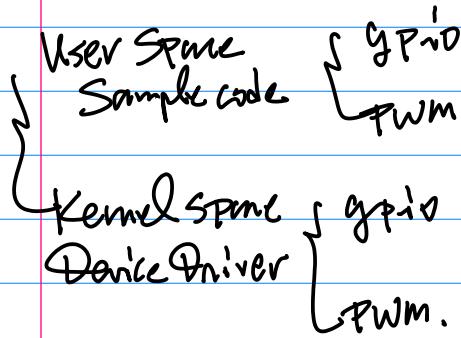
Sept 25 (Monday).

Note: 1^o Updated github Sample code.

(1) 2023F-107.

Booting Jetson Nano without HDMI Connection.

(2) 2023F-105a to 2023F-105f.



Target Board Connection

Requirements.

a. The Demo/Show+Tell in Class is required, Also

Midterm Exam, and Final Exam are Based on Analyzing & Executing your Implementation Code on the target platform;

b. Bring gpio Homework with the target Board to the Classroom

Wednesday for Quick Inspection,

Show+Tell; (Sept. 27, Wednesday).

Note: HDMI Monitor is optional, To Be Able to Boot your System is the requirement.

Consider the github Sample code.

Ref: -105a, User Space program.

for GPIO.
 open()
 ioctl()
 close()

-105b & c

```

1 #include <mach/gpio-bank-k.h>
2
3 #define DEVICE_NAME "leds0"
4
5 static long sbc2440_leds_ioctl(struct file *filp, unsigned
6                                long arg)
7 {
8     switch(cmd) {
9         case 0:
10            unsigned tmp;
11
12            make
13            memory
14            for the Kernel
15            Driver
16            Configuration.
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18            make
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1167           for the Kernel
1168           Driver
1169           Configuration.
1170
1171           make
1172           memory
1173           for the Kernel
1174           Driver
1175           Configuration.
1176
1177           make
1178           memory
1179           for the Kernel
1180           Driver
1181           Configuration.
1182
1183           make
1184           memory
1185           for the Kernel
1186           Driver
1187           Configuration.
1188
1189           make
1190           memory
1191           for the Kernel
1192           Driver
1193           Configuration.
1194
1195           make
1196           memory
1197           for the Kernel
1198           Driver
1199           Configuration.
1199
1200           make
1201           memory
1202           for the Kernel
1203           Driver
1204           Configuration.
1205
1206           make
1207           memory
1208           for the Kernel
1209           Driver
1210           Configuration.
1211
1212           make
1213           memory
1214           for the Kernel
1215           Driver
1216           Configuration.
1217
1218           make
1219           memory
1220           for the Kernel
1221           Driver
1222           Configuration.
1223
1224           make
1225           memory
1226           for the Kernel
1227           Driver
1228           Configuration.
1229
1230           make
1231           memory
1232           for the Kernel
1233           Driver
1234           Configuration.
1235
1236           make
1237           memory
1238           for the Kernel
1239           Driver
1240           Configuration.
1241
1242           make
1243           memory
1244           for the Kernel
1245           Driver
1246           Configuration.
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1251           Driver
1252           Configuration.
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1254           make
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1256           for the Kernel
1257           Driver
1258           Configuration.
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1262           for the Kernel
1263           Driver
1264           Configuration.
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1266           make
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1293           Driver
1294           Configuration.
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1297           memory
1298           for the Kernel
1299           Driver
1300           Configuration.
1300
1301           make
1302           memory
1303           for the Kernel
1304           Driver
1305           Configuration.
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1307           make
1308           memory
1309           for the Kernel
1310           Driver
1311           Configuration.
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1313           make
1314           memory
1315           for the Kernel
1316           Driver
1317           Configuration.
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1319           make
1320           memory
1321           for the Kernel
1322           Driver
1323           Configuration.
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1326           memory
1327           for the Kernel
1328           Driver
1329           Configuration.
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1333           Driver
1334           Configuration.
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1337           memory
1338           for the Kernel
1339           Driver
1340           Configuration.
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1344           for the Kernel
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1348           make
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1350           for the Kernel
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1356           for the Kernel
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1375           Driver
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1381           Driver
1382           Configuration.
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1384           make
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1386           for the Kernel
1387           Driver
1388           Configuration.
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1390           make
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1392           for the Kernel
1393           Driver
1394           Configuration.
1395
1396           make
1397           memory
1398           for the Kernel
1399           Driver
1400           Configuration.
1400
1401           make
1402           memory
1403           for the Kernel
1404           Driver
1405           Configuration.
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1407           make
1408           memory
1409           for the Kernel
1410           Driver
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1415           for the Kernel
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1423           Configuration.
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1427           for the Kernel
1428           Driver
1429           Configuration.
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1430           make
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1432           for the Kernel
1433           Driver
1434           Configuration.
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1436           make
1437           memory
1438           for the Kernel
1439           Driver
1440           Configuration.
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1442           make
1443           memory
1444           for the Kernel
1445           Driver
1446           Configuration.
1447
1448           make
1449           memory
1450           for the Kernel
1451           Driver
1452           Configuration.
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1456           for the Kernel
1457           Driver
1458           Configuration.
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1462           for the Kernel
1463           Driver
1464           Configuration.
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1466           make
1467           memory
1468           for the Kernel
1469           Driver
1470           Configuration.
1471
1472           make
1473           memory
1474           for the Kernel
1475           Driver
1476           Configuration.
1477
1478           make
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1480           for the Kernel
1481           Driver
1482           Configuration.
1483
1484           make
1485           memory
1486           for the Kernel
1487           Driver
1488           Configuration.
1489
1490           make
1491           memory
1492           for the Kernel
1493           Driver
1494           Configuration.
1495
1496           make
1497           memory
1498           for the Kernel
1499           Driver
1500           Configuration.
1500
1501           make
1502           memory
1503           for the Kernel
1504           Driver
1505           Configuration.
1506
1507           make
1508           memory
1509           for the Kernel
1510           Driver
1511           Configuration.
1512
1513           make
1514           memory
1515           for the Kernel
1516           Driver
1517           Configuration.
1518
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1520           memory
1521           for the Kernel
1522           Driver
1523           Configuration.
1524
1525           make
1526           memory
1527           for the Kernel
1528           Driver
1529           Configuration.
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1530           make
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1532           for the Kernel
1533           Driver
1534           Configuration.
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1536           make
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1538           for the Kernel
1539           Driver
1540           Configuration.
1541
1542           make
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1544           for the Kernel
1545           Driver
1546           Configuration.
1547
1548           make
1549           memory
1550           for the Kernel
1551           Driver
1552           Configuration.
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1554           make
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1556           for the Kernel
1557           Driver
1558           Configuration.
1559
1560           make
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1563           Driver
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1566           make
1567           memory
1568           for the Kernel
1569           Driver
1570           Configuration.
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1572           make
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1574           for the Kernel
1575           Driver
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1578           make
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1580           for the Kernel
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1587           Driver
1588           Configuration.
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1590           make
1591           memory
1592           for the Kernel
1593           Driver
1594           Configuration.
1595
1596           make
1597           memory
1598           for the Kernel
1599           Driver
1600           Configuration.
1600
1601           make
1602           memory
1603           for the Kernel
1604           Driver
1
```

Kconf

Kernel configuration for make menuconfig.

```

80
81 source "drivers/hid/Kconfig"
82
83 source "drivers/usb/Kconfig"
84
85 source "drivers/uwb/Kconfig"
86
87 source "drivers/mmc/Kconfig"
88
89 source "drivers/memstick/Kconfig"
90
91 source "drivers/leds/Kconfig" Red circle around this line
92
93 source "drivers/nfc/Kconfig"
94
95 source "drivers/accessibility/Kconfig"
96

```

Kernel folder/driver folder

```

if (argc != 3 || sscanf(argv[1], "%d", &led_no)
    on < 0 || on > 1 || led_no < 0
    fprintf(stderr, "Usage: leds led_no 0|1"
    exit(1);
}

fd = open("/dev/leds0", 0); Red circle around this line
if (fd < 0) {
    fd = open("/dev/leds", 0);
}
if (fd < 0) {
    perror("open device leds");
}

```

Note: 1°

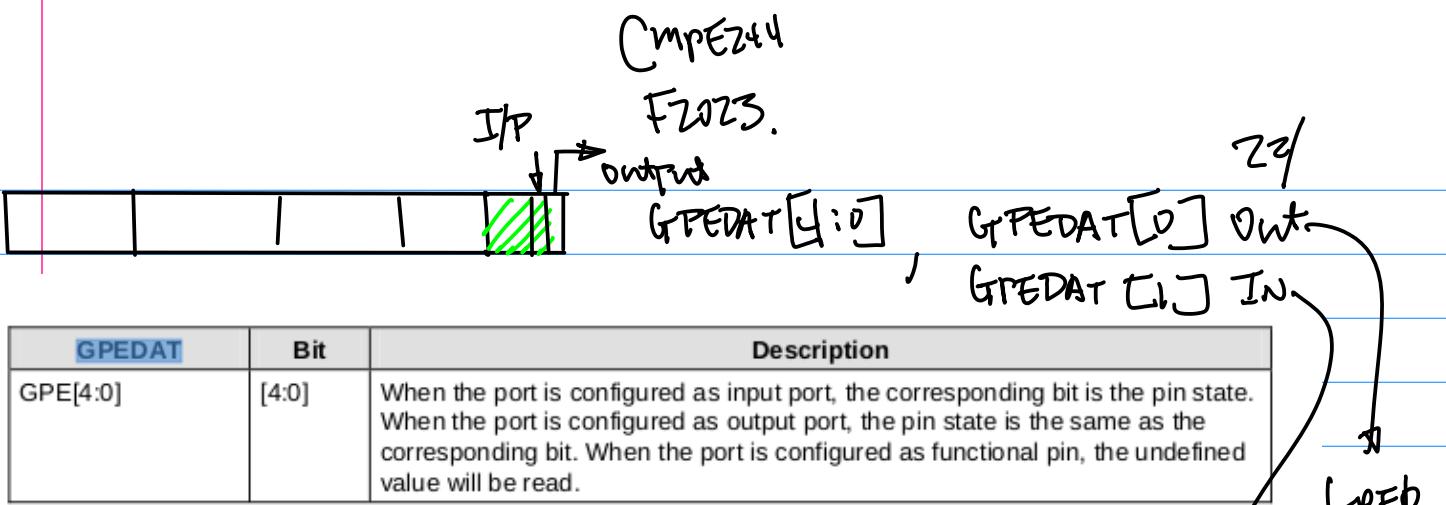
Note 2° SPR. Naming convention/addr. e.g.
pointer from CPU Data sheet.

```

35 static long sbc2440_leds_ioctl(struct file *filp, unsigned int cmd, unsigned long arg)
36 {
37     switch(cmd) {
38         unsigned tmp;
39     case 0:
40     case 1:
41         if (arg > 4) {
42             return -EINVAL;
43         }
44         tmp = readl(S3C64XX_GPKDAT);
45         tmp &= ~(1 <(4 + arg));
46         tmp |= ((!cmd) <(4 + arg));
47        	writel(tmp, S3C64XX_GPKDAT);
48         //printk (DEVICE_NAME": %d %d\n", arg, cmd);
49         return 0;
50     default:
51         return -EINVAL;
52     }
53 }

```

↳ Bitwise Operations.



Note: Each bit (pin) can be set as an input or output by GPECON.

PP 320.

GPDCON	Bit	Description	Initial State
GPE0	[3:0]	0000 = Input 0010 = PCM SCLK[1] 0100 = AC97 BITCLK 0110 = Reserved	0000
GPE1	[7:4]	0000 = Input 0010 = PCM EXTCLK[1] 0100 = AC97 RESETn 0110 = Reserved	0000
GPE2	[11:8]	0000 = Input 0010 = PCM FSYNC[1] 0100 = AC97 SYNC 0110 = Reserved	0000
GPE3	[15:12]	0000 = Input 0010 = PCM SIN[1] 0100 = AC97 SDI 0110 = Reserved	0000
GPE4	[19:16]	0000 = Input 0010 = PCM SOUT[1] 0100 = AC97 SDO 0110 = Reserved	0000

Find the Binary Pattern to set these 2 pins.

$$GPECON[3:4] = 0001 \quad (O/P)$$

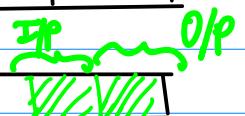
$$GPECON[7:4] = 0000 \quad (I/P)$$

for init & config.

Define Bitwise Operation mask

Design the Binary Pattern.

GPECON



mask to be designed

static void __exit dev_exit(void)

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Bitwise "OR"

Note: 1° Init module
2°

```
66 static int __init dev_init(void)
67 {
68     int ret;
69
70     {
71         unsigned tmp;
72         tmp = readl(S3C64XX_GPECON);
73         tmp = (tmp & ~(0xffffU<<16)) | (0x1111U<<16);
74        	writel(tmp, S3C64XX_GPECON);
75
76         tmp = readl(S3C64XX_GPEDAT);
77         tmp |= (0xF << 4);
78        	writel(tmp, S3C64XX_GPEDAT);
79     }
80
81     ret = misc_register(&misc);
82
83     printk (DEVICE_NAME"\Harry: PGE initialized\n");
84
85     return ret;
86 }
```

From 2023F-105c-mini6410_leds.c

#define DEVICE_NAME "leds0"

static long sbc2440_leds_ioctl(struct file *filp, unsigned int cmd, unsigned long arg)

static int __init dev_init(void)

static void __exit dev_exit(void)

GPIO SPI for Configuration

Hardware
Software
User Code
Driver Code
CPU
Datasheet

Sept. 27 (Wed).

Note 1: Homework 1 #2.

Note 2: Inspection of the Prototype System

GPIO Testing.

Example: Architecture

Device Driver

OS Kernel Image

Note: PWM + I2C
for the future discussion

Let's consider Configure + Build OS. Kernel Image.

Step 1. Download OS Distribution

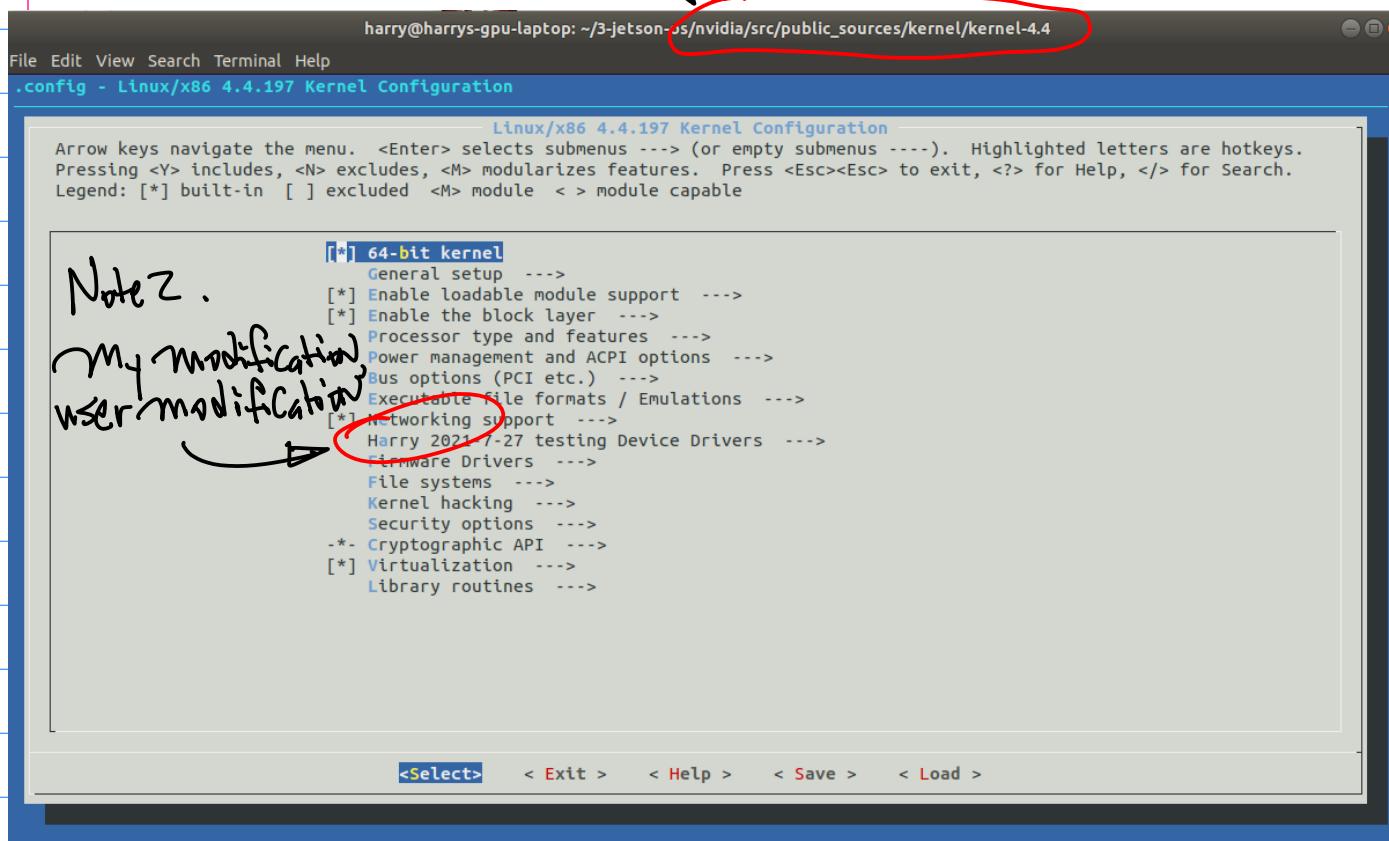
↓
Step 2. Menutools to Build OS.

By the manufacturer's Default
setting



Step 3. Create User-Defined
Kernel image.

Note1: menuconfig UI



Now, Similar Setup for Sam's Arm11, Check Kconf for UI Customization
at the Root folder.)

```

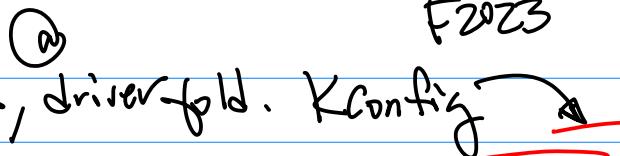
x harry@harry-laptop: /opt/FriendlyARM/mini6410/linux/linux-2.6.38
1 #
2 # For a description of the syntax of this configuration file,
3 # see Documentation/kbuild/kconfig-language.txt.
4 #
5 mainmenu "Linux/$ARCH $KERNELVERSION Kernel Configuration"
6
7 config SRCARCH
8     string
9     option env="SRCARCH"
10
11 source "arch/$SRCARCH/Kconfig"

```

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Next Level, driver-fold. Kconfig 

```
x - harry@harry-laptop: /opt/FriendlyARM/mini6410/linux/linux-2.6.38/drivers
1 menu "Device Drivers"
2
3 source "drivers/base/Kconfig"
4
5 source "drivers/connector/Kconfig"
6
7 source "drivers/mtd/Kconfig"
8
9 source "drivers/of/Kconfig"
10
11 source "drivers/parport/Kconfig"
12
13 source "drivers/pnp/Kconfig"
14
15 source "drivers/block/Kconfig"
16
17 # misc before ide - BLK_DEV_SGIIOC4 depends on SGI_IOC4
18
19 source "drivers/misc/Kconfig"
20
21 source "drivers/ide/Kconfig"
22
```

Next Level to "Char" folder, Kconfig.

```
x - harry@harry-laptop: /opt/FriendlyARM/mini6410/linux/linux-2.6.38/drivers/char
1 #
2 # Character device configuration
3 #
4
5 menu "Character devices"
6
7 config VT
8     bool "Virtual terminal" if EXPERT
9         depends on !S390
10        select INPUT
11        default y
12        ---help---
13            If you say Y here, you will get support for terminal devices with
14            display and keyboard devices. These are called "virtual" because you
15            can run several virtual terminals (also called virtual consoles) on
16            one physical terminal. This is rather useful, for example one
17            virtual terminal can collect system messages and warnings, another
18            one can be used for a text-mode user session, and a third could run
19            an X session, all in parallel. Switching between virtual terminals
20            is done with certain key combinations, usually Alt-<function key>.
21
22            The setterm command ("man setterm") can be used to change the
23            properties (such as colors or beeping) of a virtual terminal. The
```

```

100 #
109 # Harry: Feb 17, 2016
110 #
111 config MINI6410_I2CSEN_MODULE
112     tristate "Harry 2021-2-3: I2C sensor module"
113     depends on CPU_S3C6410
114     help
115         I2C sensor module Feb 17, 2016.
116 #
117 #
118 #
119 # Harry: Here is my modification
120 #
---[END_OF_KERNEL_MODULE]

```

Ref: 2023 F-109, Readme.

Oct. 2nd (Monday) . Oct. 8 (Sun)

Note1. Homework, Due 1 week

Continuation from the Homework
of O.S. Kernel Source Distribution
installation.

Modify Kconfig, to

1° Add user defined device
Driver Option as a char
device.

The option appears as.

FirstName_LastName_CMPE244_driverX, see Ref Below.

```

harry@harry-laptop: /opt/FriendlyARM/mini6410/linux/linux-2.6.38
.config - Linux/arm 2.6.38 Kernel Configuration

Character devices

Arrow keys navigate the menu. <Enter> selects submenus --->. Highlighted letters are hotkeys. Pressing <Y> includes, <N> excludes, <M> modularizes features. Press <Esc><Esc> to exit, <?> for Help, </> for Search. Legend: [*] built-in [ ] excluded [M] module < > module capable

-# Virtual terminal
[ ] Support for binding and unbinding console drivers
[ ] /dev/kmem virtual device support
<M> LED Support for Mini6410 GPIO LEDs
<M> Harry 2021-2-3: I2C sensor module
<M> Harry: 2016-Feb-22, CMPE 242 Mini6410 module sample
<M> Harry: Mini6410 Test module

```

2° Provide Screen Capture
of your UI.

3° provide Kconfig file
which realizes this
function.

4° Hardware Side.
Motor Drive Board.

Note: place comments to highlight the modification

```

105      This option enables support for LEDs connected to GPIO lines
106      on Mini6410 boards.
107
108 #-----#
109 # Harry: Feb 17, 2016
110 #
111 config MINI6410_I2CSEN_MODULE
112     tristate "Harry 2021-2-3: I2C sensor module"
113     depends on CPU_S3C6410
114     help
115         I2C sensor module Feb 17 2016

```

Option to consider.

Be Careful, Power budget
for A4988 is
16mA.



A4988 Stepper
Motor Driver...

\$5.89

Amazon.com
Free shipping

Note 2: Quiz is scheduled A
week from today Oct. 9th
(Monday).

1° Bring the target Board &
Prototype Board to the Class

2° Be sure to have a way
to capture the UI.

3° Scope of the Quiz:

CPU Datasheet, CPU Architecture
Memory-map, SPRs (Special
Purpose Registers) for GPP.

→ ARM11, Background Info
from LPC;

4° Execute GPIO Code

5° take a photo of your
entire System Setup.

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6° Screen Capture from your target Board to show the execution of the code with Personal ID is in the Screen Capture.

Time to Complete: 20 min
for the Quiz, 15 min. to
Prepare the Submission

Example: Continuation on KConfig.

7° Python Code.

8° Submission.

→ photos in png/jpeg.

Code

A piece of paper with
handwritten Answer.



Take a photo to Capture
your answer sheet, then
Convert it to pdf.

Then, place all the files
(2 photos, 1 pdf, 1 code)

into one package, Zip it.

Naming the file:

FirstName - LastName - SID - 244.zip.
(4 digits)

Submission to the CANVAS.

CMPE242

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Objectives: To Be Able to Customize OS, Kernel, e.g. by modifying KConfig to have the following feature.

The screenshot shows a terminal window titled ".config - Linux/arm 2.6.38 Kernel Configuration". The menu path is ". Character devices". A callout arrow points from the handwritten note "To Be Able to Customize OS, Kernel, e.g. by modifying KConfig to have the following feature." to this menu. The menu lists various kernel modules under the "Virtual terminal" section, including support for Mini6410 development boards, Harry sensor modules, and serial drivers. At the bottom, there are buttons for "<Select>", "< Exit >", and "< Help >".

Note 1. The Architecture of the KConfig.

```
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/linux-2.6.38$ cd drivers/char/
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/linux-2.6.38/drivers/char$ ls
Kconfig
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/linux-2.6.38/drivers/char$ vi Kconfig
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/linux-2.6.38/drivers/char$ cd ..
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/linux-2.6.38$ cd ..
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/linux-2.6.38$ ls Kconfig
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/linux-2.6.38$ cd drivers/
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/linux-2.6.38$ ls Kconfig
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/linux-2.6.38$ cd char
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/linux-2.6.38$ ls Kconfig
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/linux-2.6.38$ cd char
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/linux-2.6.38$ ls
```

Annotations:

- a) at the Root
- b. drivers
- c. Char. ==

Note: To Create an entry, use "Config"

```

107
108 #
109 # Harry: Feb 17, 2016
110 #
111 config MINI6410_I2CSEN_MODULE
112 tristate "Harry 2021-2-3: I2C sensor module"
113 depends on CPU_S3C6410
114 help
115     I2C sensor module Feb 17, 2016.
116 #
117
118 #

```

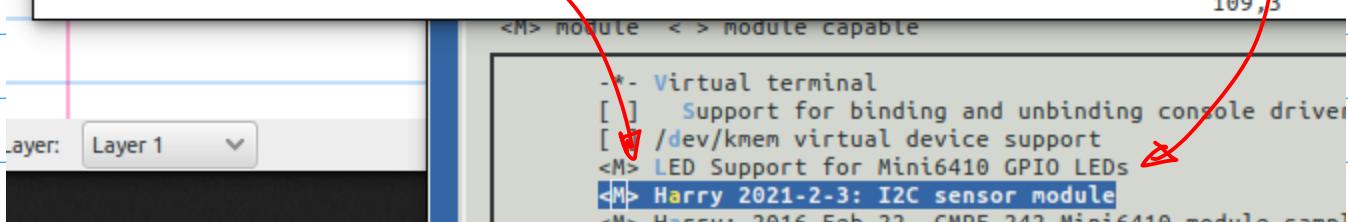
Note: To define the target CPU, use "depends on" followed by Manufacturer ID & Device ID.

```

107
108 #
109 # Harry: Feb 17, 2016
110 #
111 config MINI6410_I2CSEN_MODULE
112 tristate "Harry 2021-2-3: I2C sensor module"
113 depends on CPU_S3C6410
114 help
115     I2C sensor module Feb 17, 2016.
116 #
117
118 #
119 # Harry: Here is my modification
120 #

```

Note:



Note 2: To pre-select, use default "y"

```

70
91 config DEVKMEM
92     bool "/dev/kmem virtual device support"
93     default y
94     help
95         Say Y here if you want to support the /dev/kmem device. The
96         /dev/kmem device is rarely used, but can be used for certain
97         kind of kernel debugging operations.
98         When in doubt, say "N".

```

Note: To provide Description for the option, use "help"

Once the KConfig is updated with matching Name of the Device Driver, then \$make all

\$insmod *driverName*
\$printk()
\$rmmod *driverName*

Oct. 4 (Wed).

Consider Debugging the Device
Driver(s) from Manufacturer's
Distribution.

Example: Embedded Software in this

Example: UserSmartphone → Jetson Nano → User APP. → Device
WebServer Program Driver

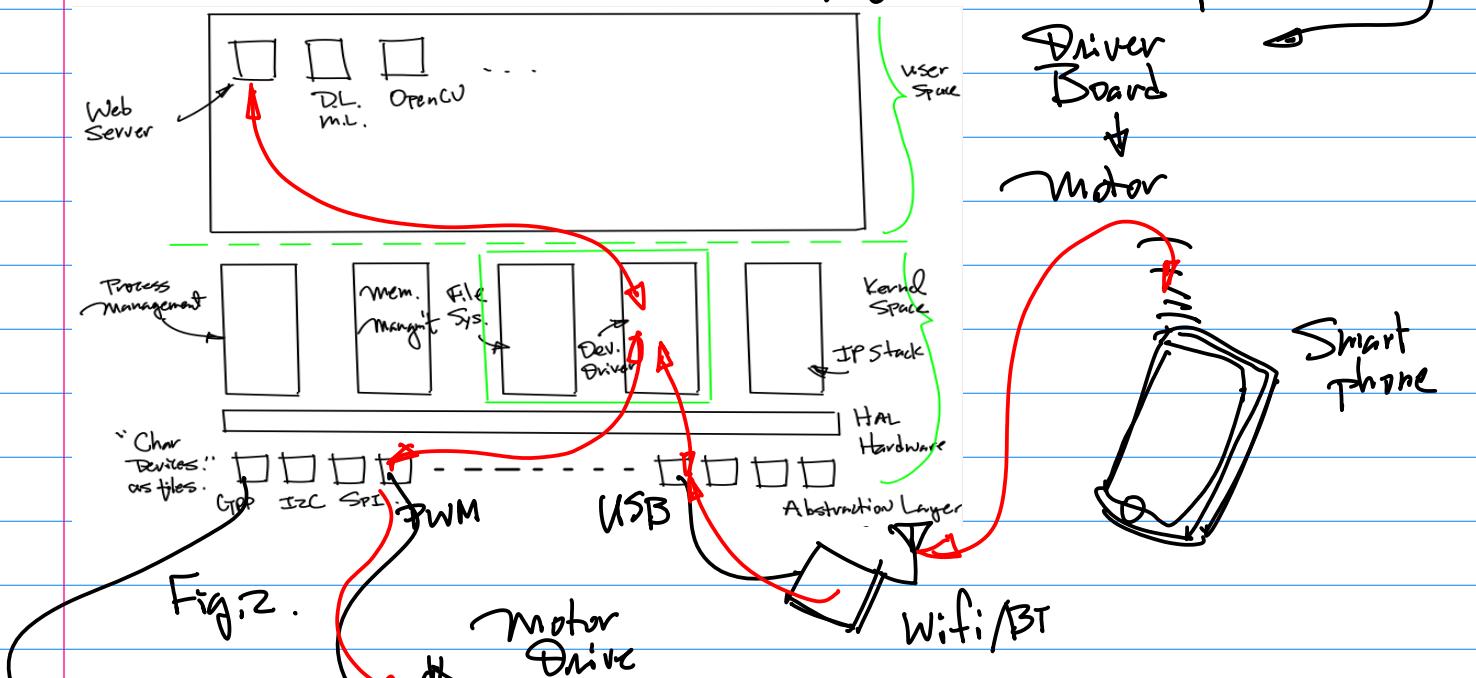


Fig. 2.

Background On the Motor & motor Driver Board.

1° Stepper motor pins. (4)

A^+, A^-, B^+, B^- .

2° Driver Board Pins

✓ Infant Group

{ Output Group. (4 pins)

ENABLE>Select.

Speed Input pin, PWM f_{PWM}

Direction Control .GPP

Others. { Configuration Pins. x

Al, Cu, Bi, S, Others, ...

- others, ...

2^x No. of Config. Patterns

Table 1. Connectivity Table
Driver Board to the Stepper Motor.

Driver Board	NEMA 17
A+	A+
A-	A-
B+	B+
B-	B-

Now, for the Configuration of the driver board.

Background On the Stepper motor Drive Board.

Note: 1 Full Step of the Stepper Motor.

$$\frac{2\pi}{200} \Rightarrow \frac{360}{200}$$

1.8 degree/step

1 half Step. 0.9 Degree/
Half Step

$\frac{1}{4}$ Step 0.45 Degree

$\frac{1}{8}$ Step 0.225 Degree.

:

A typical Driver Board consists of 4 pins for Configuration Conn1, Conn2, Conn3, Conn4

Example: f_{pwm} is set to its target frequency, $f_{pwm} = 2 \times 10^3$

And Duty Cycle 5% to 95% Allows the Control of the Speed.

Sample code to Realize this Control function.

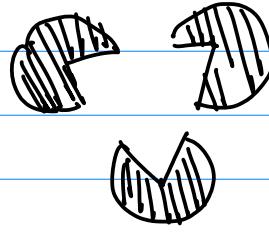
a. Set f_{pwm}

b. Set & Change Duty Cycle.

Ref: Ref code to Be posted on line. To Be Referenced for your design & debugging

Note 1.

```
harry@harry-laptop:~/opt/FriendlyARM/mini6410/linux/examples/pwm$ makefile pwm_test pwm_test.c pwm_testNew.c temp.c
```



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34/

```

99     open_buzzer();
100
101    printf( "\nBUZZER TEST ( PWM Control )\n" );
102    printf( "Press +/- to increase/reduce the frequency of the BUZZER\n" );
103    printf( "Press 'ESC' key to Exit this program\n\n" );
104
105
106    while( 1 )

```

Note: Set f_{PWM} , But Need to set duty cycle as well.

```

109
110    set_buzzer_freq(freq);
111    printf( "\tFreq = %d\n", freq );
112
113    key = getch();
114
115    switch(key) {

```

Note: Access to the Device Driver By "fd" (file Descriptor).

```

4/
48 static int fd = -1;
49 static void close_buzzer(void);
50 static void open_buzzer(void)
51 {
52     fd = open("/dev/pwm", 0);
53     if (fd < 0) {
54         perror("open pwm_buzzer");
55         exit(1);
56     }
57 }

```

Oct 8th (Monday)

Example: Debugging PWM Driver (ATMEL Example).

References with C code have been posted, And IDs are provided to the class.

C } user Space Code.
 } Kernel Space Code.

Objective: To modify the Device Driver Code to include Duty function.

To upgrade the user Code to Allow Both f_{PWM} and

f_{PWM}

f_{PWM} .

modification of this module?
Add duty cycle if possible.

Duty Cycle to Be Defined and Selected by user.

Step 1. Modify / Upgrade User Space Code, to Add duty function.

Step 2. Modify / Upgrade Kernel Space Code, e.g., device Driver.

Control / Config. f_{PWM} .

Control / Config. Duty Cycle

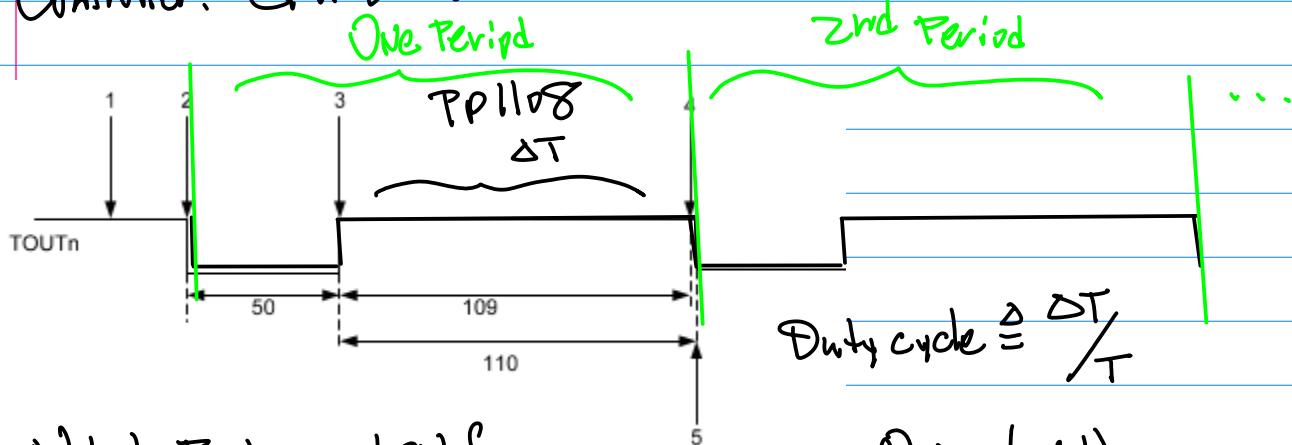
Step 3. Inspection of Control / Configuration Registers, e.g., SFRs to Allow Duty to Be a part of the Driver function.

CPU Data sheet.

Step 4. Option, But if the Name of the Device Driver is Changed One to

the upgrade, then we need to change/update the script in "KConfig".

Discussion on PWM Peripheral Controller. CPU Datasheet



Note 1. Background on f_{PWM}

System Clock \rightarrow PCLK \rightarrow PWM
 f_{sys} $\xrightarrow{\text{peripheral clock.}}$ f_{PCLK} $\xrightarrow{\text{f}_{PWM}}$

SPR(s) to Control/Config.

PCLK.

$\frac{1}{2}, \frac{1}{4}, \frac{1}{8}, \dots$

16 bits.

$$f_{PWM} = \frac{f_{PCLK}}{DUSR * \cancel{\text{Prescaler}}} \dots (1)$$

Not necessarily tied to a commercial product.

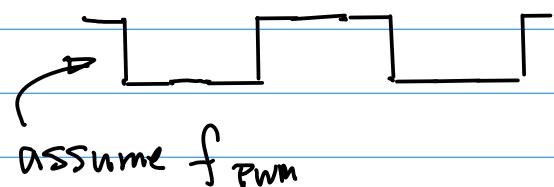
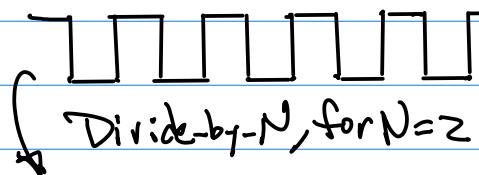
Oct. 11 (Wed)

Continuation on PWM Driver Debugging & Update

f_{PWM}
Duty

Note 1. Waveform for Divide-by-N Counter

Input CLK
PCLK



If N is 8 bits, then

$$N \in [0, 255]$$

Question: How many different frequencies for f_{PWM} can we have with this N ?

Alternative to Increase the No. of f_{PWM} by introducing a Product

$$N = N_1 * N_2$$

where N_1 is 8 bit, N_2 is 8 bit

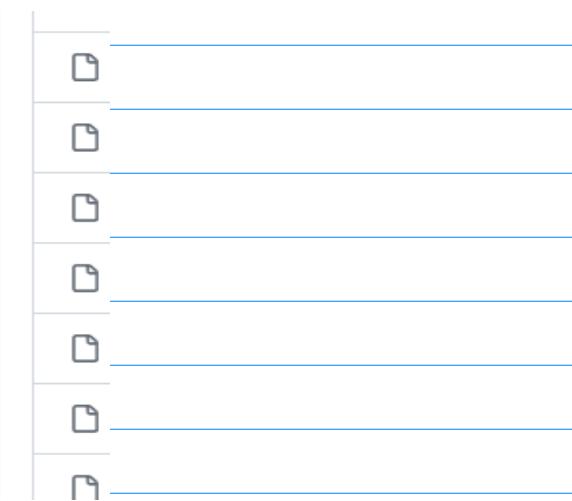
To Achieve the increase the No. of f_{PWM} .

Consider A Duty Cycle Implementation

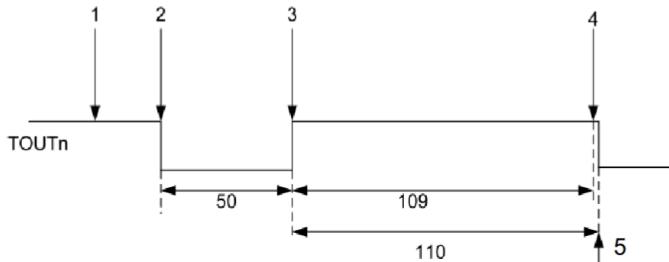
We need { A Counter { Count Up
Count Down.
} Interrupt }

Ref. from github for CmPEZ42

- 2022S-107a-PID-v5-2019-4-25.pdf
- 2022S-107b-pwm-pid.pdf
- 2022S-107c-pwm-config-v4-hl-2022-3-3.pdf
- 2022S-107d-pwm-nano-coding-hl-2021-12-19.pdf
- 2022S-107e-pwm-waveform-v3-2018-3-4.jpg
- 2022S-107f-pwm-specialPurposeRegister-v3-20...
- 2022S-107g-pwm-calculation-v3-2018-3-4.pdf
- 2022S-107h-spec-motor-drive-WS55-1800 (copy...)
- 2022S-108-L5M2023IUC.pdf



PWM Operation



Example:

1. Initialize the TCNTBn with 159(50+109) and the TCMPBn with 109.
2. Start Timer by setting the start bit and manual update bit off.
- The TCNTBn value of 159 is loaded into the down-counter, the output is driven low.
3. When down-counter counts down to the value in the TCMPBn register 109, the output is changed from low to high.
4. When the down-counter reaches 0, the interrupt request is generated.
5. The down-counter is automatically reloaded with TCNTBn, which restarts the cycle.

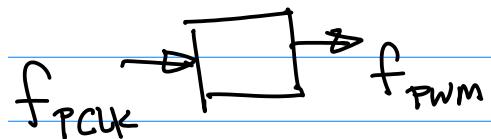
Example: Given $f_{sys} = 800 \text{ MHz}$.

$$\text{assume } f_{PCLK} = 800/8 = 100 \text{ MHz}$$

assume

$$f_{PWM} = 2 \text{ kHz}$$

find



Try:

$$TCNTB\phi = \frac{f_{PCLK}}{f_{PWM}}$$

from the given condition

TCFG0, TCNTBn and TCMPBn

32.4.1.1 TCFG0 (Timer Configuration Register), pp 1118

Register	Offset	R/W	Description
TCFG0	0x7F006000	R/W	Timer Configuration Register 0 that configures the two 8-bit Prescaler and DeadZone Length

Timer input clock Frequency = PCLK / ({prescaler value + 1}) / {divider value}
{prescaler value} = 1~255
{divider value} = 1, 2, 4, 8, 16, TCLK

32.4.1.2 TCFG1 (Timer Configuration Register)

Register	Offset	R/W	Description
TCFG1	0x7F006004	R/W	Timer Configuration Register 1 that controls 5 MUX and DMA Mode Select Bit

32.4.1.3 TCON (Timer Control Register)

Register	Offset	R/W	Description
TCON	0x7F006008	R/W	Timer Control Register

32.4.1.5 TCMPB0 (Timer0 Compare Register)

Register	Offset	R/W	Description
TCMPB0	0x7F006010	R/W	Timer 0 Compare Buffer Register

Harry Li, Ph.D.

32.4 SPECIAL FUNCTION REGISTERS

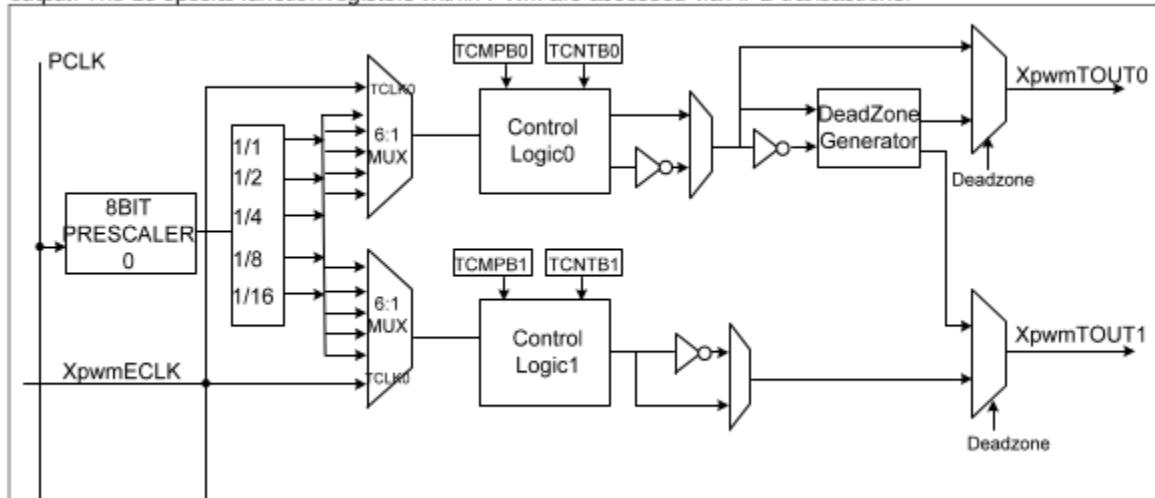
32.4.1 REGISTER MAP

Note1. TCNTB0PP1117
CNTB : Count Buffer

Register	Offset	R/W	Description	Reset Value
TCFG0	0x7F006000	R/W	Timer Configuration Register 0 that configures the two 8-bit Prescaler and DeadZone Length	0x0000_0101
TCFG1	0x7F006004	R/W	Timer Configuration Register 1 that controls 5 MUX and DMA Mode Select Bit	0x0000_0000
TCON	0x7F006008	R/W	Timer Control Register	0x0000_0000
<u>1</u> TCNTB0	<u>0x7F00600C</u>	R/W	<u>Timer 0 Count Buffer Register</u>	0x0000_0000
<u>2</u> TCMPB0	<u>0x7F006010</u>	R/W	<u>Timer 0 Compare Buffer Register</u>	0x0000_0000
TCNTO0	0x7F006014	R	Timer 0 Count Observation Register	0x0000_0000
TCNTB1	0x7F006018	R/W	Timer 1 Count Buffer Register	0x0000_0000
TCMPB1	0x7F00601c	R/W	Timer 1 Compare Buffer Register	0x0000_0000
TCNTO1	0x7F006020	R	Timer 1 Count Observation Register	0x0000_0000
TCNTB2	0x7F006024	R/W	Timer 2 Count Buffer Register	0x0000_0000
TCNTO2	0x7F00602c	R	Timer 2 Count Observation Register	0x0000_0000
TCNTB3	0x7F006030	R/W	Timer 3 Count Buffer Register	0x0000_0000
TCNTO3	0x7F006038	R	Timer 3 Count Observation Register	0x0000_0000
TCNTB4	0x7F00603c	R/W	Timer 4 Count Buffer Register	0x0000_0000
TCNTO4	0x7F006040	R	Timer 4 Count Observation Register	0x0000_0000
TINT_CSTAT	0x7F006044	R/W	Timer Interrupt Control and Status Register	0x0000_0000

Reference for f_{Pwm} formula.

output. The 16 special function registers within PWM are accessed via APB transactions.



Oct 16 (mon).

Note1. Homework Assignment

On CANVAS:

PWM Device Driver + Board Implementation.

CMPE 244 Homework PWM Driver Debugging and Stepper Motor Actuation Demo

Part I:

1. Download the PWM user program and driver program from the class github, see the figure below for the document ID:

2023F-105d-user-p...	Add files via upload	3 weeks ago
2023F-105e-user-p...	Add files via upload	3 weeks ago
2023F-105f-#20-20...	Add files via upload	3 weeks ago

The github for the pwm user space program:

https://github.com/hualili/CMPE244/blob/main/2023F-105d-user-pwm_test.c

Example: Continuation of the PWM modification.

SPR.

Define the Counts value to Achieve Required Duty Cycle.

T_{CNTBn} is compared against $T_{CMPBn} = 109$.

Then, if equal, trig the waveform change from the default "0" to high "1".

Design Requirements for the example:

Suppose 33% Duty Cycle.

Initialize $T_{CMPBn} = ?$

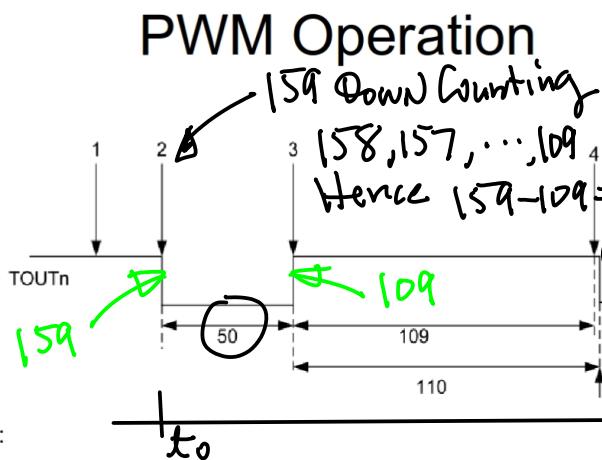
$$\therefore T_{CNPBn} = 50 \times 10^3$$

We can now,

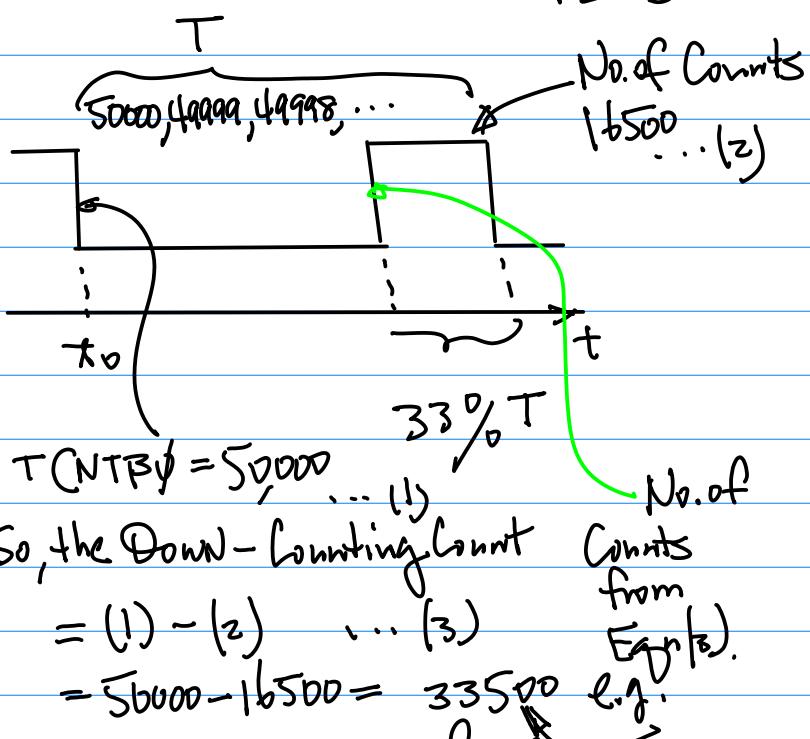
$$0.33 \times 50 \times 10^3$$

$$= 16500$$

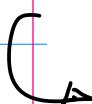
Now, to visualize it, we have



1. Initialize the $TCNTBn$ with 159(50+109) and the $TCMPBn$ with 109.
2. Start Timer by setting the start bit and manual update bit off.
3. When down-counter counts down to the value in the $TCMPBn$ register 109, the output is changed from low to high.
4. When the down-counter reaches 0, the interrupt request is generated.
5. The down-counter is automatically reloaded with $TCNTBn$, which restarts the cycle.



Now, Read C code of Device Driver.



On the Class
github.

2023F-105F-#20-2021S-9-
mini6410_pwmHarry (1).c

```

multi-thread.py 2022S-103c-#nn_sample_2022.py 2023F-105F-#20..._pwmHar
1  /*
2   * Program: mini6410_pwmHarry.c;
3   * Modified by: HL; Date: Feb 10, 2016 *
4   * Purpose: To add PWM duty cycle change function *
5   *           by altering CMP compare register. *
6   */
7
8 #include <linux/module.h>
9 #include <linux/kernel.h>
10 #include <linux/fs.h>
11 #include <linux/init.h>
12 #include <linux/delay.h>
13 #include <linux/poll.h>
14 #include <asm/irq.h>
15 #include <asm/io.h>
16 #include <linux/interrupt.h>
17 #include <asm/uaccess.h>
18 #include <mach/hardware.h>
19 #include <plat/regs-timer.h>
20 #include <mach/regs-irq.h>
21 #include <asm/mach/time.h>
22 #include <linux/clk.h>
23 #include <linux/cdev.h>
24 #include <linux/device.h>
25 #include <linux/miscdevice.h>
26
27 #include <mach/map.h>
28 #include <mach/regs-clock.h>
29 #include <mach/regs-gpio.h>
```

Note 1. Driver Name in the User Space,

```

35 #define DEVICE_NAME "pwm"
36
37 #define PWM_IOCTL_SET_FREQ 1
38 #define PWM_IOCTL_STOP 0
39
40 static struct semaphore lock;
41
42

```

`OPEN("drivers/pwm" ...)`

Initially Enabled.

Note 2. Add the function
to change duty cycle.
`PWM_IOCTL_SET_DUTY`
for Example.

```

41 static struct semaphore lock;
42
43 /* freq: pclk/50/16/65536 ~ pclk/50/16
44 * if pclk = 50MHz, freq is 1Hz to 62500Hz
45 * human ear : 20Hz~ 20000Hz
46 */
47 //static void PWM_Set_Freq( unsigned long freq)
48 static void PWM_Set_Freq( unsigned long freq, duty ) //Hz
49 {
50     unsigned long tcon;
51     unsigned long tcnt;
52     unsigned long tduy; //Harry
53     unsigned long tcfg1;
54     unsigned long tcfg0;
55
56     struct clk *clk_p;
57     unsigned long pclk;
58
59     unsigned tmp;
60
61     tmp = readl(S3C64XX_GPFCON);
62     tmp &= ~(0x3U << 28);
63     tmp |= (0x2U << 28);
64    	writel(tmp, S3C64XX_GPFCON);
65
66     tcon = __raw_readl(S3C_TCON);
67     tcfg1 = __raw_readl(S3C_TCFG1);
68     tcfg0 = __raw_readl(S3C_TCFG0);
69

```

Note 3. Preserve the module Name
for minimum Modification
or, update to
`PWM_Set_Freq_Duty()`.
New Parameter for the
Duty Cycle is added.

32.4.1.3 TCON (Timer Control Register)

Register	Offset	R/W	Descr
TCON	0x7F006008	R/W	Timer Control Register
TCON	Bit	R/W	

TP 1119

Read Datasheet, for Example "iveshot"
V.S. "Auto-Reload" etc.

Oct. 18 (Wed)

Note: Roadmap of the Class



Introduction.

CPU/SPR/Driver

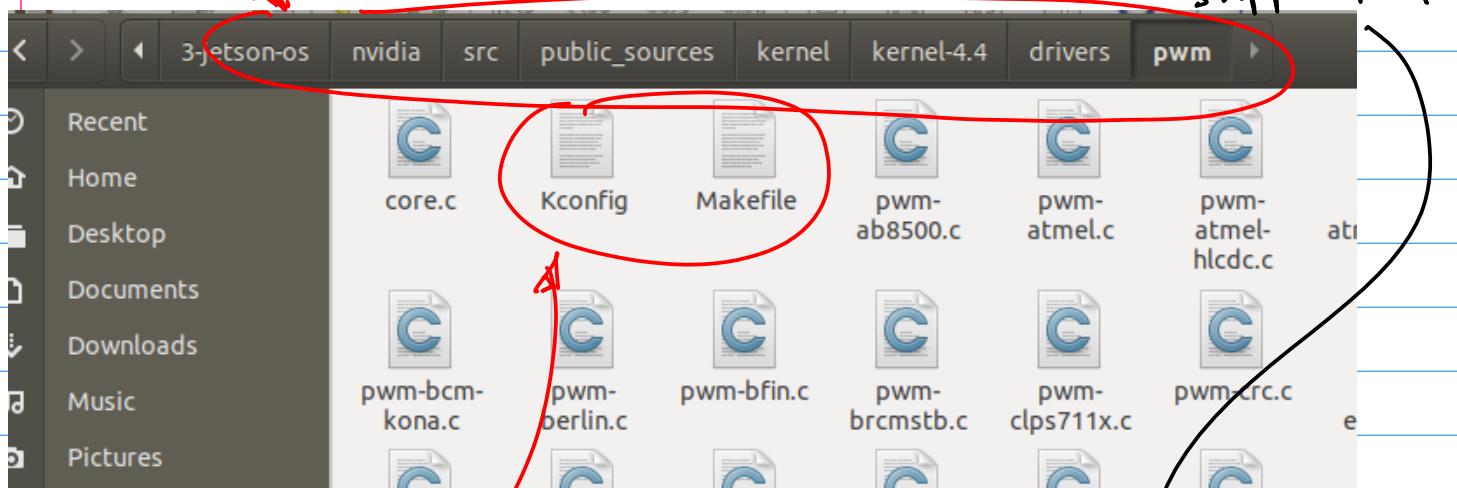
Device Driver
Debug Development
PWM

In About a week Time frame,
in-Class Brief presentation (Update, e.g.
one paragraph Description for the
Semester Long Project.)

Oct. 25 (Wed)

2 Person Team OR
individual.

Q & A : Note 1. Device Driver folder, PWM Device Driver, Target Platform Device Driver: Note 2. Kernel 4.4 is chosen for my need with Ubuntu 18.04 on Jetson NAND. To Support AI.



Note 3. Two files.

KConfig → UI for menuconfig

Script per the
Developer choice
To Build Kernel
image and Device
Drivers.

makefile.

Per NVIDIA Requirements.

```

Open ▾ 3-jetson-os/nvidia/src/public_sources/Kconfig
1 menuconfig PWM
2   bool "Pulse-Width Modulation (PWM) Support"
3   help
4     Generic Pulse-Width Modulation (PWM) support.
5
6     In Pulse-Width Modulation, a variation of the width of pulses
7     in a rectangular pulse signal is used as a means to alter the
8     average power of the signal. Applications include efficient
9     power delivery and voltage regulation. In computer systems,
10    PWMs are commonly used to control fans or the brightness of
11    display backlights.
12
13    This framework provides a generic interface to PWM devices
14    within the Linux kernel. On the driver side it provides an API
15    to register and unregister a PWM chip, an abstraction of a PWM
16    controller, that supports one or more PWM devices. Client
17    drivers can request PWM devices and use the generic framework
18    to interface with them directly.

```

Some support Target CPU.

```

44 config PWM_ATMEL
45     tristate "Atmel PWM support"
46     depends on ARCH_AT91 || AVR32
47     help
48         Generic PWM framework driver for Atmel SoC.
49
50         To compile this driver as a module, choose M here: the module
51         will be called pwm-atmel.
52

```

Note: Broadcom

```

77 config PWM_BCM_KONA
78     tristate "Kona PWM support"
79     depends on ARCH_BCM_MOBILE
80     help
81         Generic PWM framework driver for Broadcom Kona PWM block.
82
83         To compile this driver as a module, choose M here: the module
84         will be called pwm-bcm-kona.
85
86 config PWM_BCM2835
87     tristate "BCM2835 PWM support"
88     depends on ARCH_BCM2835
89     help
90         PWM framework driver for BCM2835 controller (Raspberry Pi)

```

Graphics Acceleration
Unit.

Note: CPU from NXP

```

201
202 config PWM_LPC18XX_SCT
203     tristate "LPC18xx/43xx PWM/SCT support"
204     depends on ARCH_LPC18XX
205     help
206         Generic PWM framework driver for NXP LPC18
207         supports 16 channels.
208         A maximum of 15 channels can be requested
209         must have the same period.
210
211         To compile this driver as a module, choose
212         will be called pwm-lpc18xx-sct.
213
214 config PWM_LPC32XX
215     tristate "LPC32XX PWM support"
216     depends on ARCH_LPC32XX
217     help
218         Generic PWM framework driver for LPC32XX.

```

Activities Text Editor ▾

Open ▾     en  

Wed 17:07 Kconfig -/3-jetson-os/nvidia/src/public_sources/kernel/kernel-4.4/drivers/pwm Save   

```

354 netp Generic PWM framework driver for STiH4xx SoCs.
355
356 To compile this driver as a module, choose M here: the module
357 will be called pwm-sti.
358
359
360 config PWM SUN4I
361 tristate "Allwinner PWM support"
362 depends on ARCH_SUNXI || COMPILER_TEST
363 depends on HAS_IOMEM && COMMON_CLK
364 help
365 Generic PWM framework driver for Allwinner SoCs.
366
367 To compile this driver as a module, choose M here: the module
368 will be called pwm-sun4i.
369
370 config PWM TEGRA
371 tristate "NVIDIA Tegra PWM support"
372 depends on ARCH_TEGRA
373 help
374 Generic PWM framework driver for the PWM controller found on NVIDIA
375 Tegra SoCs.
376
377 To compile this driver as a module, choose M here: the module
378 will be called pwm-tegra.
379
380 config PWM TEGRA_DFL
381 tristate "NVIDIA Tegra DFL PWM support"
382 depends on ARCH_TEGRA
383 help
384 PWM driver support for the Tegra DFL module found on NVIDIA
385 Tegra SoCs.
386
387 To compile this driver as a module, choose M here: the module
388 will be called pwm-tegra-dfl.
389
390 config PWM TEGRA_PMC_BLINK
391 tristate "NVIDIA Tegra PMC blink PWM support"
392 depends on ARCH_TEGRA
393 help
394 PWM driver support for the Tegra PMC blink module found on NVIDIA
395 Tegra SoCs.
396
397 To compile this driver as a module, choose M here: the module

```

Note. TEGRA CPUs for Jetson NAND
one of

Plain Text ▾ Tab Width: 8 ▾ Ln 330, Col 19 ▾ INS

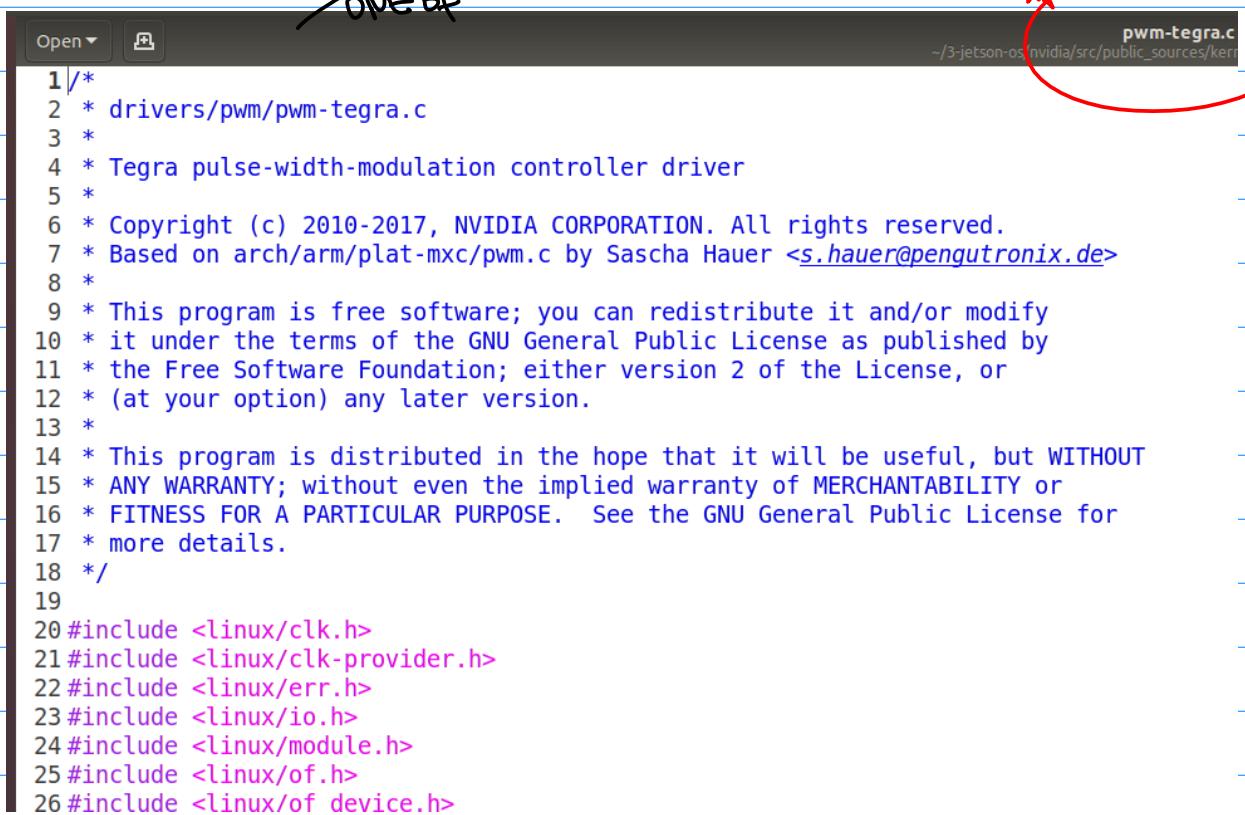
CMPE244

F2023

Note: makefile as the result output from KConf. Drivers Built 44|
per Developer Selection.

```
File Edit View Search Terminal Help  
Subdir-ccflags-y += -Werror  
  
obj-$(CONFIG_PWM) += core.o  
obj-$(CONFIG_PWM_SYSFS) += sysfs.o  
obj-$(CONFIG_PWM_AB8500) += pwm-ab8500.o  
obj-$(CONFIG_PWM_ATMEL) += pwm-atmel.o  
obj-$(CONFIG_PWM_ATMEL_HLCD_C_PWM) += pwm-atmel-hlcdc.o  
obj-$(CONFIG_PWM_ATMEL_TCB) += pwm-atmel-tcb.o  
obj-$(CONFIG_PWM_BCM_KONA) += pwm-bcm-kona.o  
obj-$(CONFIG_PWM_BCM2835) += pwm-bcm2835.o  
obj-$(CONFIG_PWM_BERLIN) += pwm-berlin.o  
obj-$(CONFIG_PWM_BFIN) += pwm-bfin.o  
obj-$(CONFIG_PWM_BRCMSTB) += pwm-brcmstb.o  
obj-$(CONFIG_PWM_CLPS711X) += pwm-clps711x.o  
obj-$(CONFIG_PWM_CRC) += pwm-crc.o  
obj-$(CONFIG_PWM_EP93XX) += pwm-ep93xx.o  
obj-$(CONFIG_PWM_FSL_FTM) += pwm-fsl-ftm.o  
obj-$(CONFIG_PWM_IMG) += pwm-img.o  
obj-$(CONFIG_PWM_IMX) += pwm-imx.o  
obj-$(CONFIG_PWM_JZ4740) += pwm-jz4740.o  
obj-$(CONFIG_PWM_LP3943) += pwm-lp3943.o  
obj-$(CONFIG_PWM_LPC18XX_SCT) += pwm-lpc18xx-sct.o  
obj-$(CONFIG_PWM_LPC32XX) += pwm-lpc32xx.o  
obj-$(CONFIG_PWM_LPSS) += pwm-lpss.o  
obj-$(CONFIG_PWM_LPSS_PCI) += pwm-lpss-pci.o  
obj-$(CONFIG_PWM_LPSS_PLATFORM) += pwm-lpss-platform.o  
obj-$(CONFIG_PWM_MTK_DISP) += pwm-mtk-disp.o  
obj-$(CONFIG_PWM_MXS) += pwm-mxs.o  
obj-$(CONFIG_PWM_PCA9685) += pwm-pca9685.o  
obj-$(CONFIG_PWM_PUV3) += pwm-puv3.o  
obj-$(CONFIG_PWM_PXA) += pwm-pxa.o  
obj-$(CONFIG_PWM_RCAR) += pwm-rcar.o  
obj-$(CONFIG_PWM_RENESAS_TPU) += pwm-renesas(tpu).o  
obj-$(CONFIG_PWM_ROCKCHIP) += pwm-rockchip.o  
obj-$(CONFIG_PWM_SAMSUNG)
```

Note: Inspection of PWM Driver
ONE OF



```

1 /*
2  * drivers/pwm/pwm-tegra.c
3  *
4  * Tegra pulse-width-modulation controller driver
5  *
6  * Copyright (c) 2010-2017, NVIDIA CORPORATION. All rights reserved.
7  * Based on arch/arm/plat-mxc/pwm.c by Sascha Hauer <s.hauer@pengutronix.de>
8  *
9  * This program is free software; you can redistribute it and/or modify
10 * it under the terms of the GNU General Public License as published by
11 * the Free Software Foundation; either version 2 of the License, or
12 * (at your option) any later version.
13 *
14 * This program is distributed in the hope that it will be useful, but WITHOUT
15 * ANY WARRANTY; without even the implied warranty of MERCHANTABILITY or
16 * FITNESS FOR A PARTICULAR PURPOSE. See the GNU General Public License for
17 * more details.
18 */
19
20 #include <linux/clk.h>
21 #include <linux/clk-provider.h>
22 #include <linux/err.h>
23 #include <linux/io.h>
24 #include <linux/module.h>
25 #include <linux/of.h>
26 #include <linux/of_device.h>
```

Example: Continued from

PWM Driver Code.

```

66 tcon = __raw_readl(S3C_TCON);
67 tcfg1 = __raw_readl(S3C_TCFG1);
68 tcfg0 = __raw_readl(S3C_TCFG0);
69 ... - - -
```

32.4.1.3 TCON (Timer Control Register)

Register	Offset	R/W	Description
TCON	0x7F006008	R/W	Timer Control Register

TCON	Bit	R/W	Description
Reserved	[31:23]	R	Reserved Bits
Timer 4 Auto Reload on/off	[22]	R/W	0: One-Shot 1: Interval Mode(Auto-F
Timer 4 Manual Update	[21]	R/W	0: No Operation 1: Update TCNTB4
Timer 4 Start/Stoo	[20]	R/W	0: Stop 1: Start Timer 4

Oct. 23rd (Monday).

4b/

Note 1. Project Assignment on CANVAS

CMPE258

Semester Long Team Project On Embedded Software Systems

HL

1. Design and implement a team project based on each 2-person team (or individual person). The project requirements are listed in details below. Note this project counts **total 10 points** and is due at the end of the semester and it requires a team presentation in the last week of the semester.

2. The technical requirements of the projects:

(2.1) Design and implement your team project which has to utilize embedded Linux OS on your chosen

Votez. This Coming Wednesday

Presentation of your
project proposal, e.g.,

The Abstract.

3. One page project executive summary:

(3.1) Create one page executive summary of your project, with the following information

a. Title of the Project

b. List of each team members: First Name, Last Name, SID, Email Address, and Affiliation (such as Computer Engineering, Software Engineering, MS AI);

c. Team coordinator: Identify the team coordinator;

d. Abstract (up to one page):

Describe

(i) the objectives of the project ;

(ii) the technical challenges;

(iii) the proposed methodology to be employed;

(iv) the software tools and hardware platform;

(v) results and deliverable;

(vi) Experience gained and/or lessons learned.

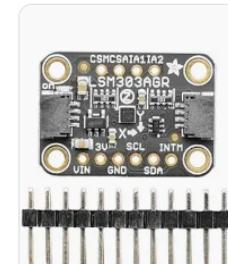
e. table with list of the work contributed by each team member

In-Class Presentation on
Wednesday.

Homework : Nov. 1st (Wed) In-Class Demo.

1^o Buy LSm303 sensor. 2^o Enable
(I2C Interface)

PWM Driver on Your target platform
Then use Python, DR C/C++

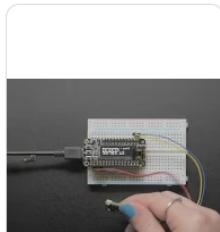


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\$12.50

DigiKey

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To write an user program to read sensor information, and display the Sensor information on the console.

Slope: OS, Kernel Build.

Device Drivers,
Kconfig.

Note 2: Quiz (Nov. b).

3' In-Class Demo Requirements:

Bring your prototype Board together with the Sensor interface to the Class for Demo.

Ref 1. from the github, First 25 slides.

[CMPE244 / 2021F-116a3-i2c-v2-hl-2021-11-18.pdf](#)

Ref 2. Command Line Commands for I2C Device Detection, and Python Sample Code.

[2023S-102-i2c-command-line-2023S-104-i2c-v2-jetson-nano-2023-02-8.pdf](#) (SPRs)

Note: Midterm Exam is to be scheduled Once the I2C Sensor interface work is covered and homework is done. Most likely in the 2nd ~ 3rd week of November.

Oct. 25 (Wed).

Note 1. Quiz Next Monday.

Please Bring Your Laptop/Prototype System to the Class.

Note 3. Midterm Exam.

Nov. 13 (Monday).

- ① Architecture CPU
Datasheet; Device Drivers (GPIO, PWM, I2C)
- ② Cooling \rightarrow Register Level
- ③ Hard calculation for Code Debugging.

Oct. 30 Monday

Note 1. The road map for the 2nd half of the class.

- (1) Enable/design/deploy webserver solution by using GI (Gate Way Interfaces), e.g., WSGI and CGI, the first one is the backend code (engine) written in Python, the 2nd one is CGI for C/C++ based backend solution.
- (2) Design/develop/deploy ChatGPT API Version 3.5 to build technical/user support system.
- (3) APP development for the Android platform.

(4) Embedded software system will provide scalability and vertical integration. On hardware side, we will add I2C sensor interface, LSM 303.

Note 2. Midterm exam is scheduled on Nov. 13 (Monday),

(1) One hour exam, one page formula is permitted. But close book and close notes.

(2) 15 minutes for prep for CANVAS submission.

Note: all the submission has to via CANVAS to be official, no late submission will be accepted. If the system is crashed or not responding to the subssion, please do screen capture to keep the record with time stamps and your ID.

(3) Scope of the midtem: from the introduction to I2C SPR's init and configuration.

(4) format of the exam:

a. Combination of hand calculation and execution of your code.

b. you will need to bring your target platform to the exam.

c. The submitted homework, code can be reused.

d. Development platform, OS kernel compilation and build, which is a part of the subjects to be includeded.

kernel space debugging;

Kconf,

make menconfiguration;

e. Please bring your smart phone, you will need to take photos of your prototype board and the photo(s) of the actual implementation, be sure to place SID card next to your board.

f. Scree captures may be needed, to capture the execution of your code with your ID.

(5) Prepare for the submission:

a. photos to be converted to pdf;

b. take photos of your hand calculation

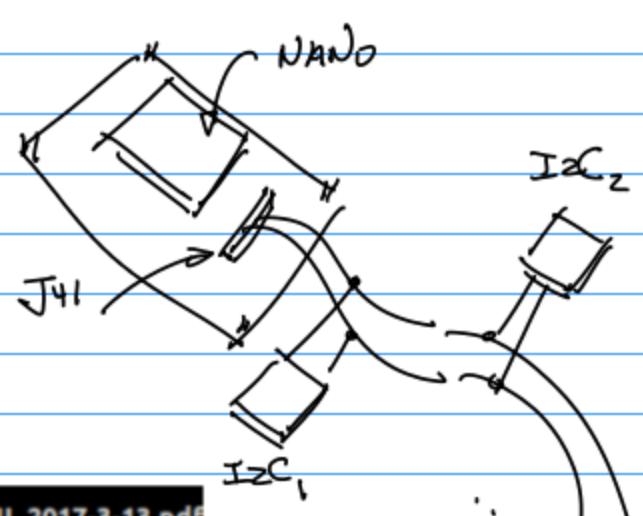
then convert the photos to pdf
c. combine all the pdf in a proper orcler into one pdf document.

Note: please use 1024x768 resolution as a reference when taking photos.

Example: On I2C protocole and I2C sensor interface.

Ref. 1.

2022S-101-note-part2-cmpe242-2022-05-9.pdf



L 2017-3-13.pdf

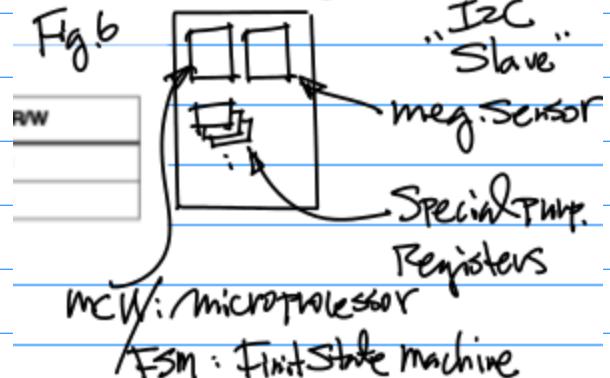
Fig.3

pp. 8

Slave Device.

LSM303

Fig.6



SPRs : Control & Control Data

- Note: 1. Master and Slave of I²C devices;
 2. Total number of slaves possible, theoretically, up to 7 bits, e.g., $2^7 = 128$.
 3. There is a MCU inside the slave for communication with this the master and execution of commands/instructions from the master, and perform init&config and other required task. 4. In case of LSM 303, there are 3 sensors in one package.



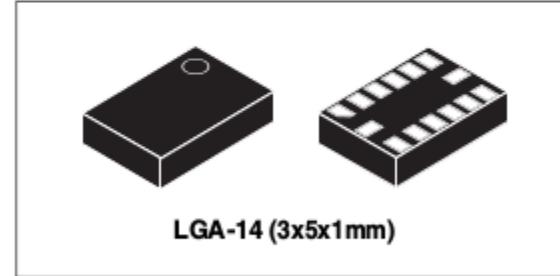
LSM303DLHC

Ultra compact high performance e-compass
 3D accelerometer and 3D magnetometer module

Preliminary data

Features

- 3 magnetic field channels and 3 acceleration channels
- From ± 1.3 to ± 8.1 gauss magnetic field full-scale
- $\pm 2g/\pm 4g/\pm 8g/\pm 16g$ selectable full-scale
- 16 bit data output
- I²C serial interface
- Analog supply voltage 2.16 V to 3.6 V
- Power-down mode/ low-power mode
- 2 independent programmable interrupt



Description

The LSM303DLHC is a system-in-package featuring a 3D digital linear acceleration sensor

Nov.1st(Wed).

PWM Stepper motor Drive

Demo. in-class.

Note 1. Optional Feature:

Add Ananconda to Jetson

NANO to Allow Better Management of Development Environment and Packages.

Later in the Class Assignment, we may need this feature.

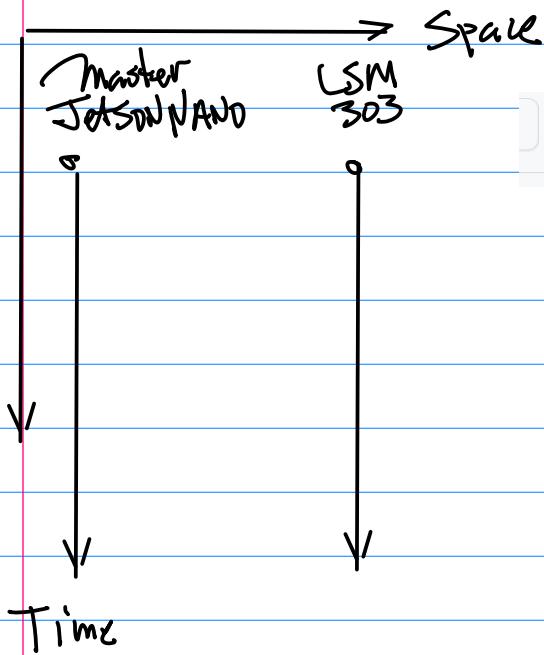
Example: Continuation of I²C

Protocol.

1. Slave Addr. → Device Datasheet
2. Additional Addr. for the master to Address to the SPRs (Special Purpose Registers) for the init & Config.
3. Information is then Read Back By the master. Which Can be realized By "Read" Command.

Space-Time Diagram to
Describe the I_C.

Spatial v.s. Temporal



Note: Read Datasheet to Complete the detailed Space-Time Diagram, then Match up to your High Level Language Code.

Ref: CMPE242-Embedded-Systems- / 2022S / 2022S-108b-AngularSensing-i2c-LSM303- final HL 2017-3-13.pdf

i2c

Nov. 6 (Monday)

Note: Midterm Exam is scheduled on Next Monday, Nov. 13 th.
Please Bring Your Prototype Board, And Blank Printer Paper.

Homework Nov. 19 (Sunday). a.

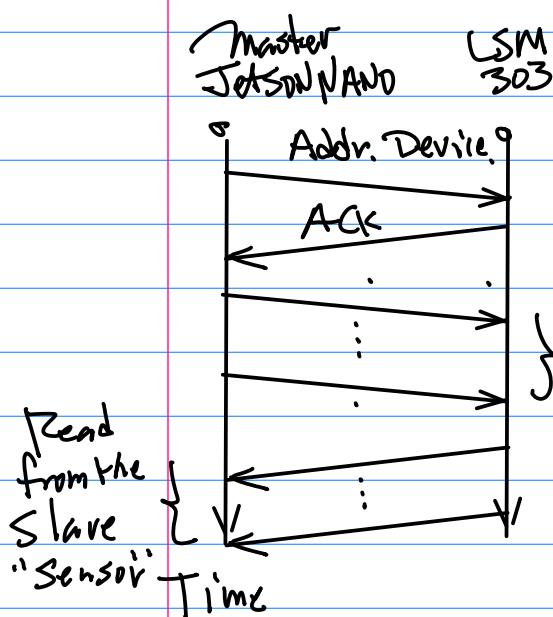
1° Integration of the target Board ;
b. Motor Drive Board. (Note, The Board Has to Be able to Drive the Stepper motor per its Configuration, e.g.

1 Full Step (1.8 degree/Step) OR A half step, etc. C. (SM303)

to SPI(s)
Write for init & config. Sensor to calculate the motor angular Displacement ;

2° Drive the motor | 5 Degree Counter Clockwise Direction, then | 5 Degree Clockwise Direction. Then Read the Angular information Back from your Sensor. (No further Calculation is Needed)

3° Submission on CANVAS, And Bring your Prototype Board to the Class for Demo.



Note: It's good Engineering Practice to Detect the Attached I_C Devices.

Note: For the team project,
it is mandatory to Integrate
ChatGPT into your Embedded
Software System.

1. ChatGPT 3.5
API or higher;

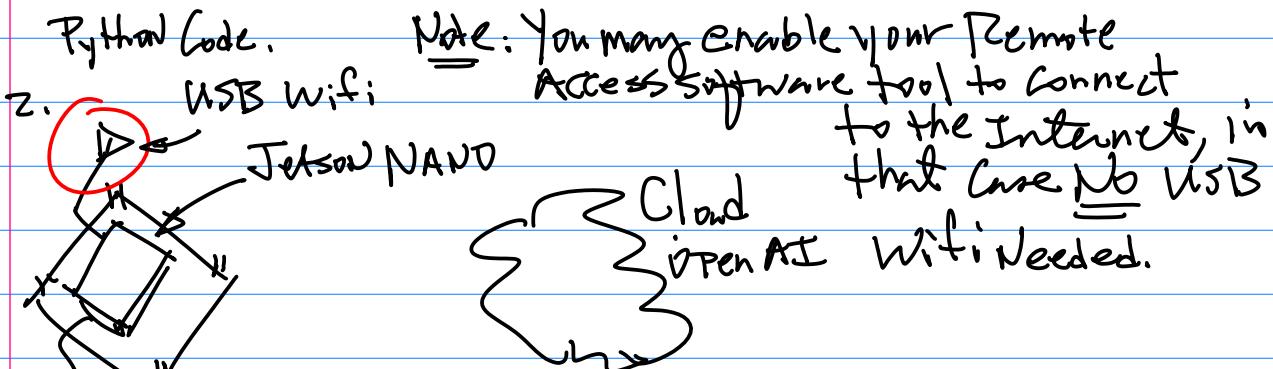


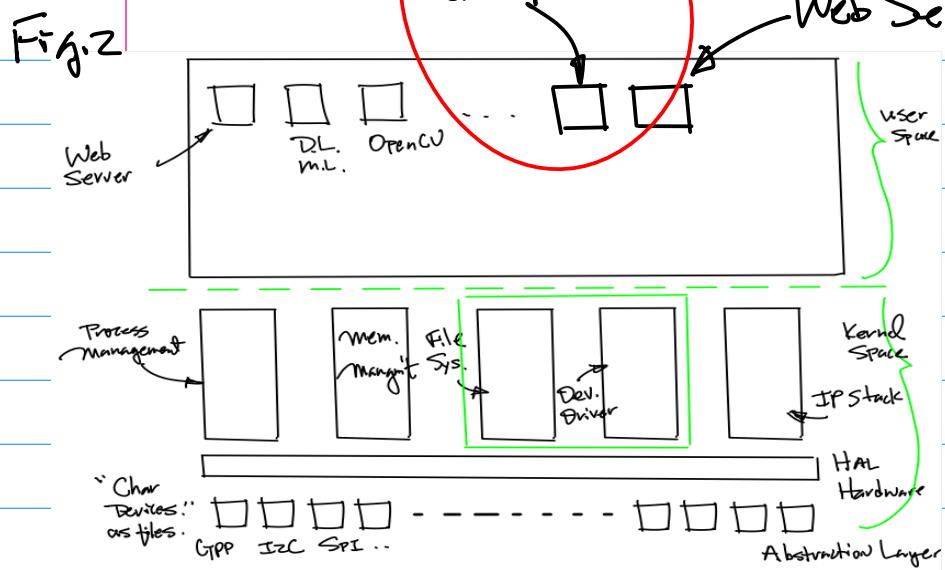
Fig.1.

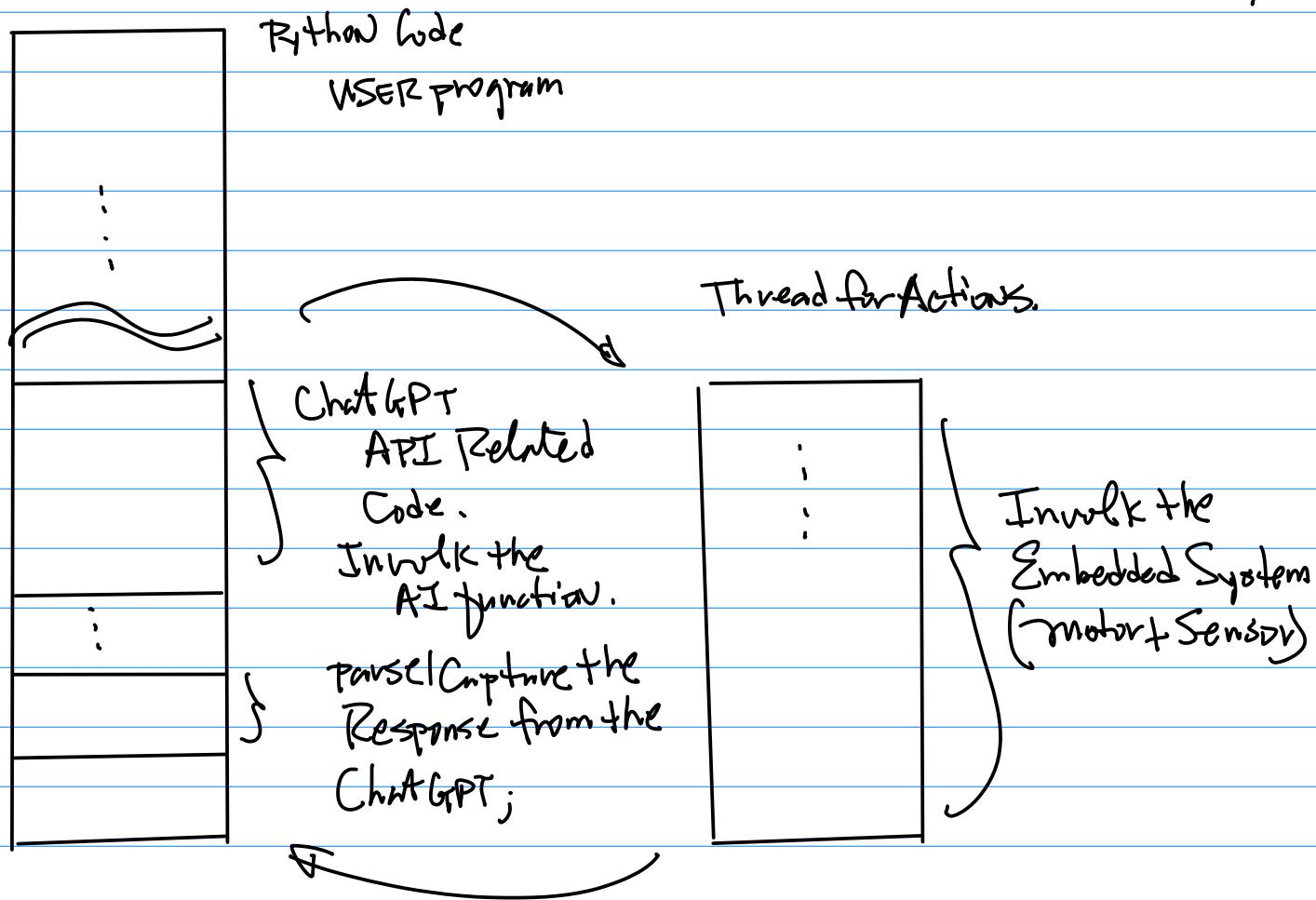
One of the program
in the User
Space.

Python for
ChatGPT API.

Web Server

Ref: github under
OpenCV > DeepLearning 2023S
2023S-104 ~





Note: Both front End and Backend are Needed in this project.

