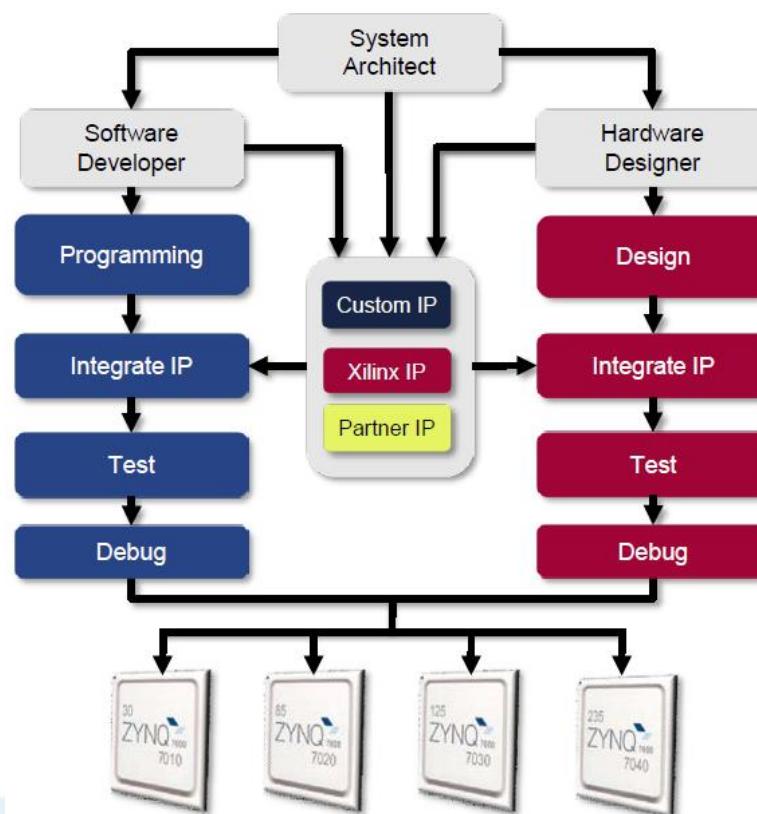


Embedded Linux on Zynq



김현옥 (hokim1972@naver.com)

- Zynq = Dual core ARM (PS: Processing System) + FPGA (PL: Programmable Logic)
 - Processor concentrated chip
 - Processor runs with minimal(?) PL programming.
 - Less flexibility / Higher Performance
 - More efficient parallel hardware and software development



- **Bare-Metal** without OS

- Possible to write fast programs

- Difficult to realize complex systems with components like webserver, FTP server, USB support and so on

- SDK Provides ARM Toolchain

- **Real-Time OS**

- For applications with strict time constraints

- Most are commercial

- **Linux**

- Greatest flexibility

- Many drivers, libraries and software package



- **Vivado GUI, CUI(2016.4)**

- Design hardware

- Generate bit/hdf files

- **HSI Hardware Software Interface**

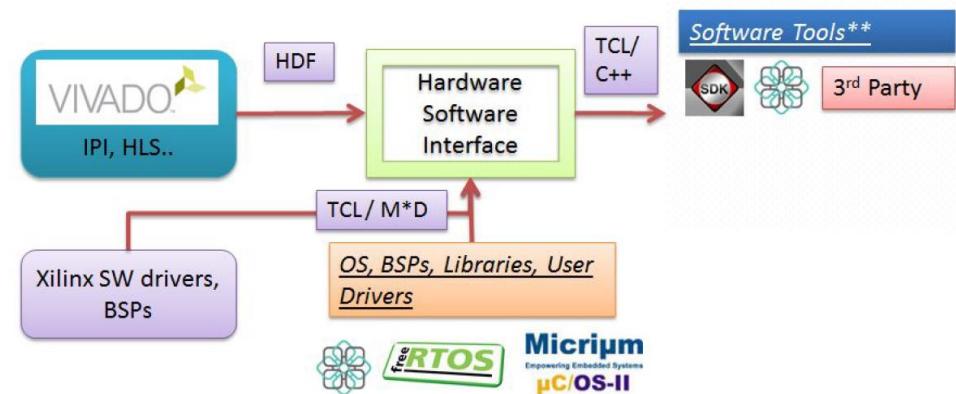
- Scalable framework enabled SW tool integration
with Vivado

- Compile FSBL / Generate DT

- **Ubuntu (16.04 LTS)**

- (Host) Compile u-boot, kernel and DT

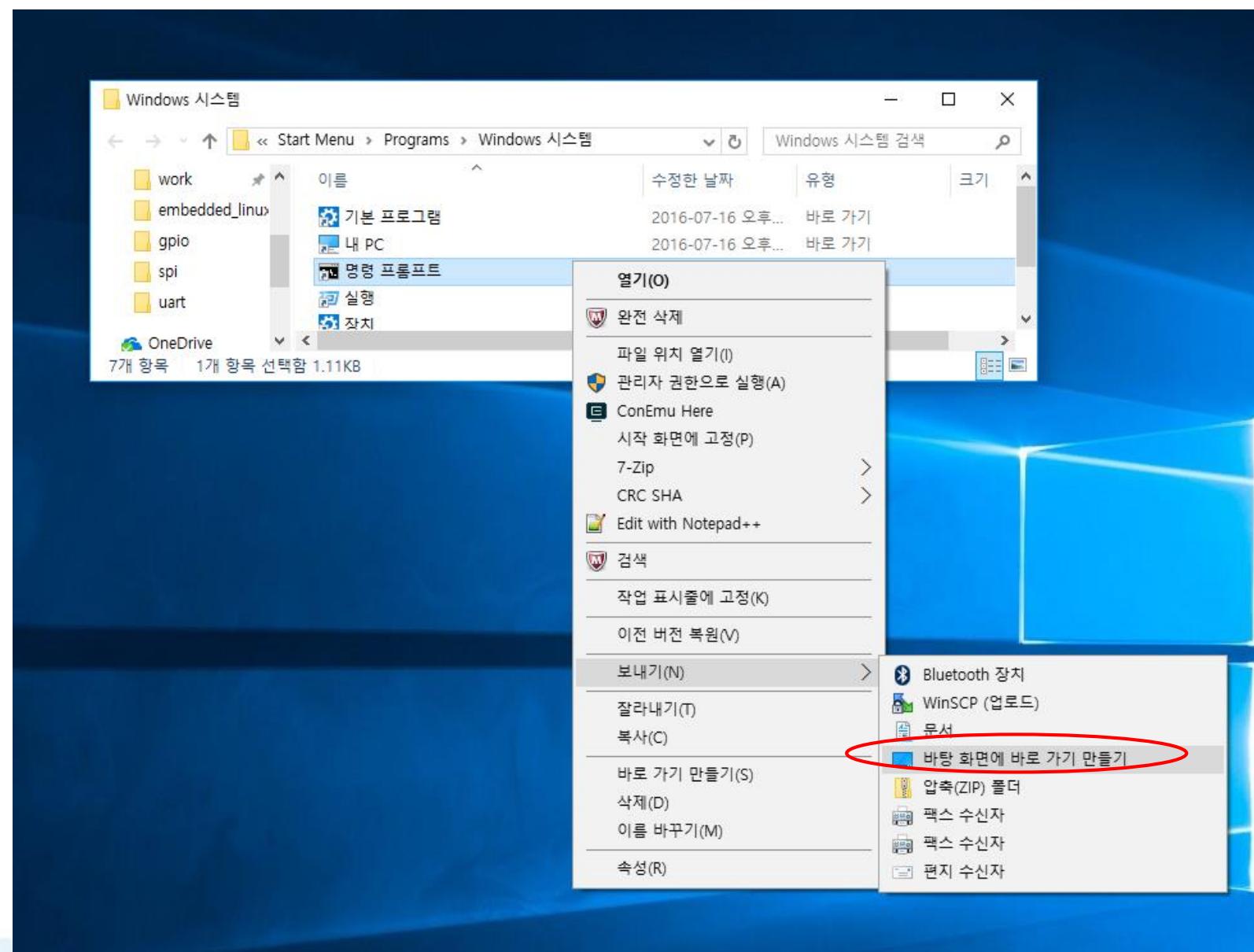
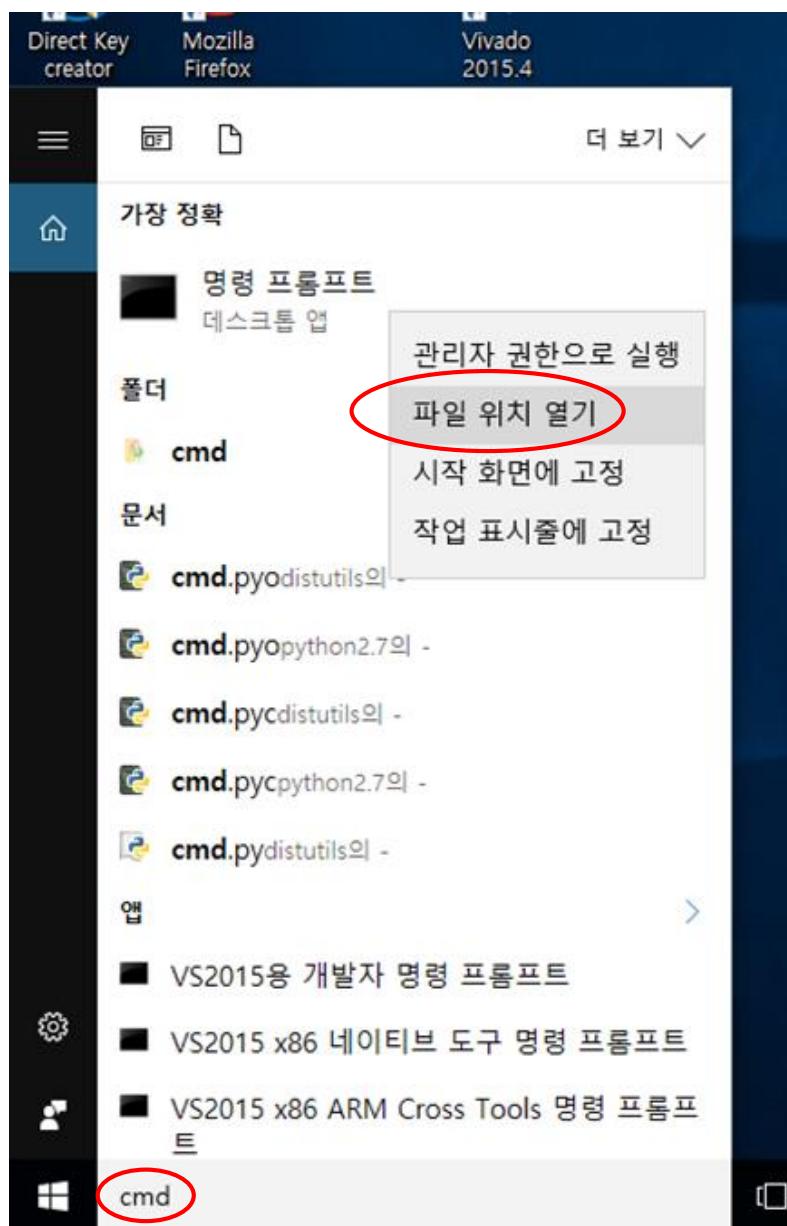
- (Target) Compile drivers / applications



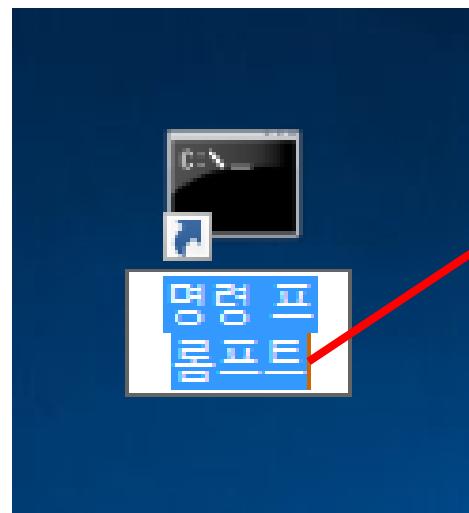
Development Environment Set-up

■ Windows 10

Install Vivado 2016.4 w/ SDK
cmd terminal for Vivado



Development Environment Set-up

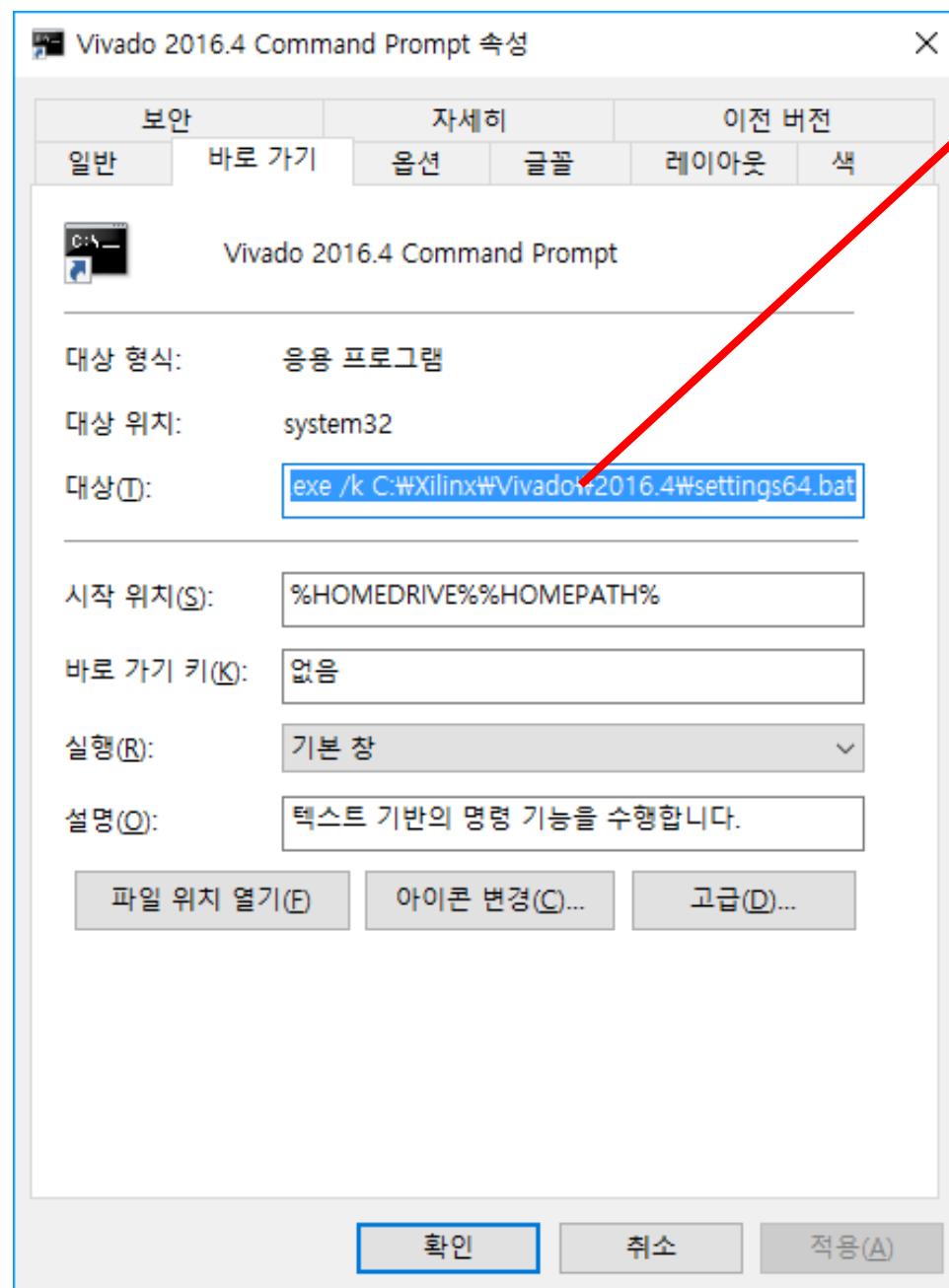


Vivado 2016.4 Command Prompt

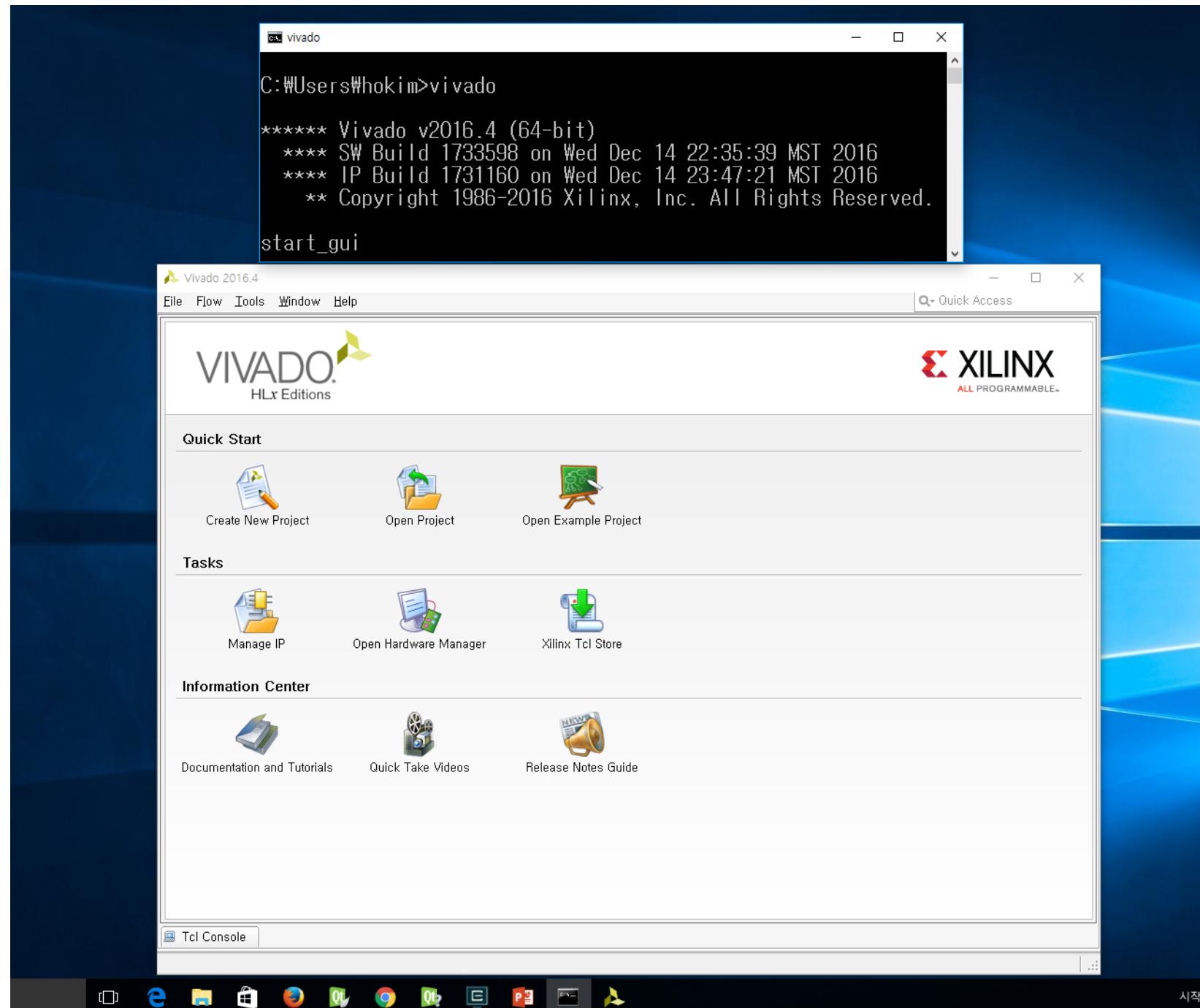


Development Environment Set-up

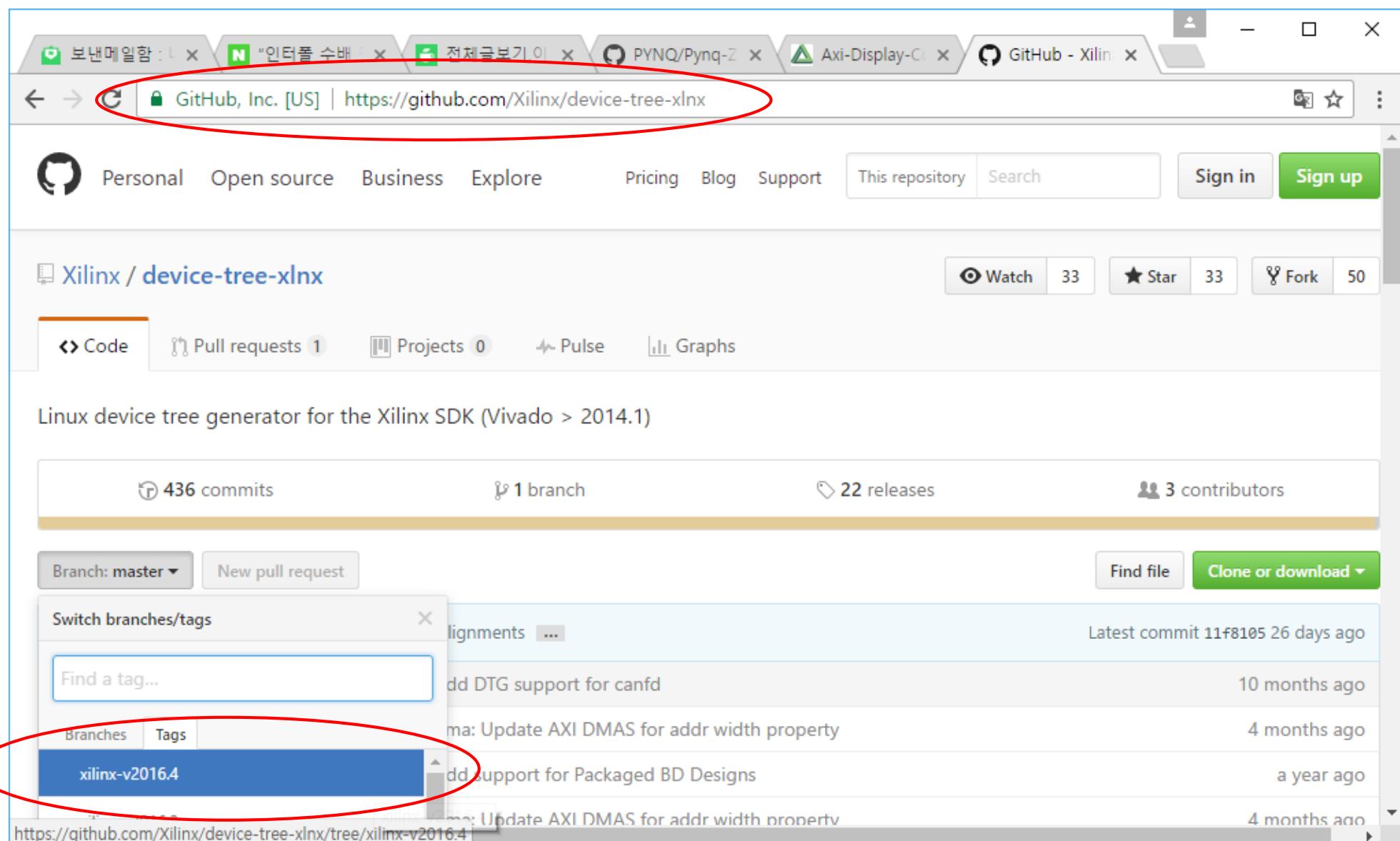
%windir%\system32\cmd.exe /k C:\Xilinx\Vivado\2016.4\settings64.bat



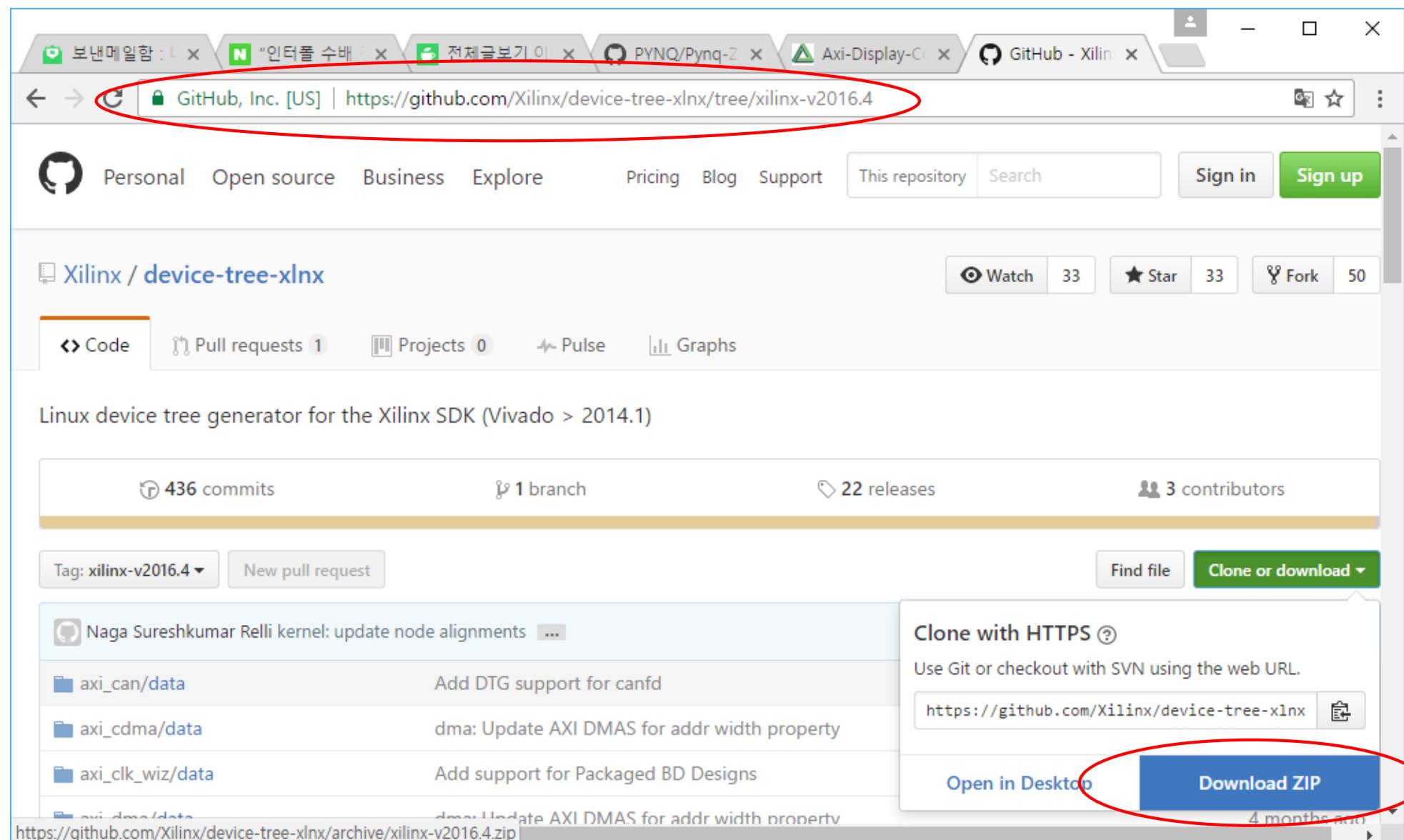
■ cmd terminal for Vivado.



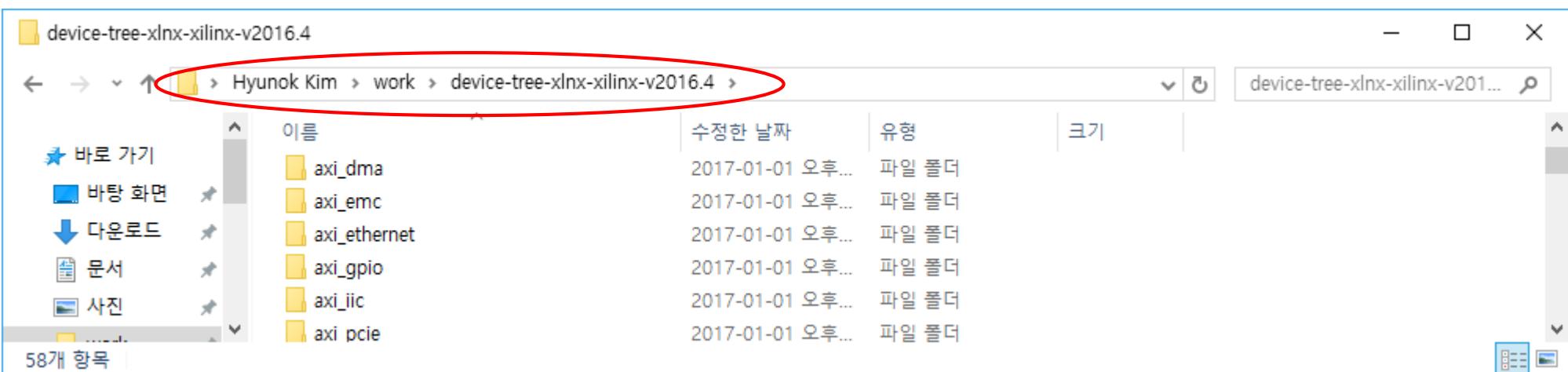
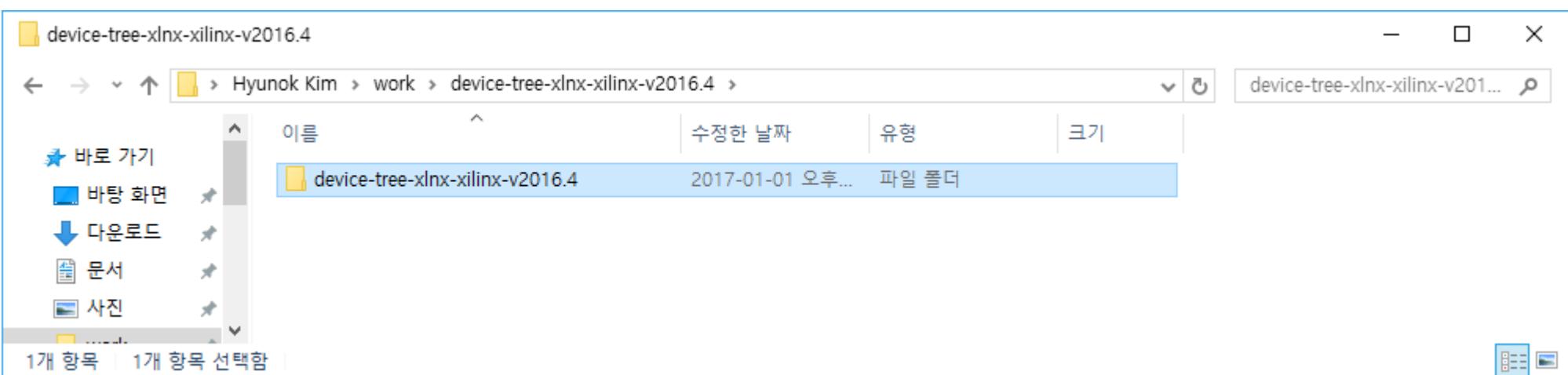
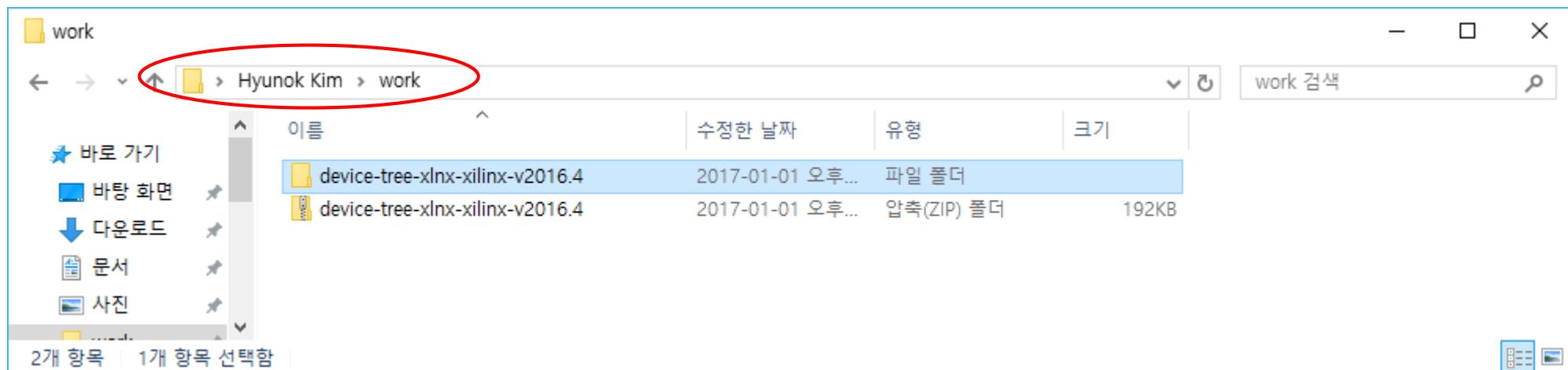
■ Device Tree Source



■ Device Tree Source

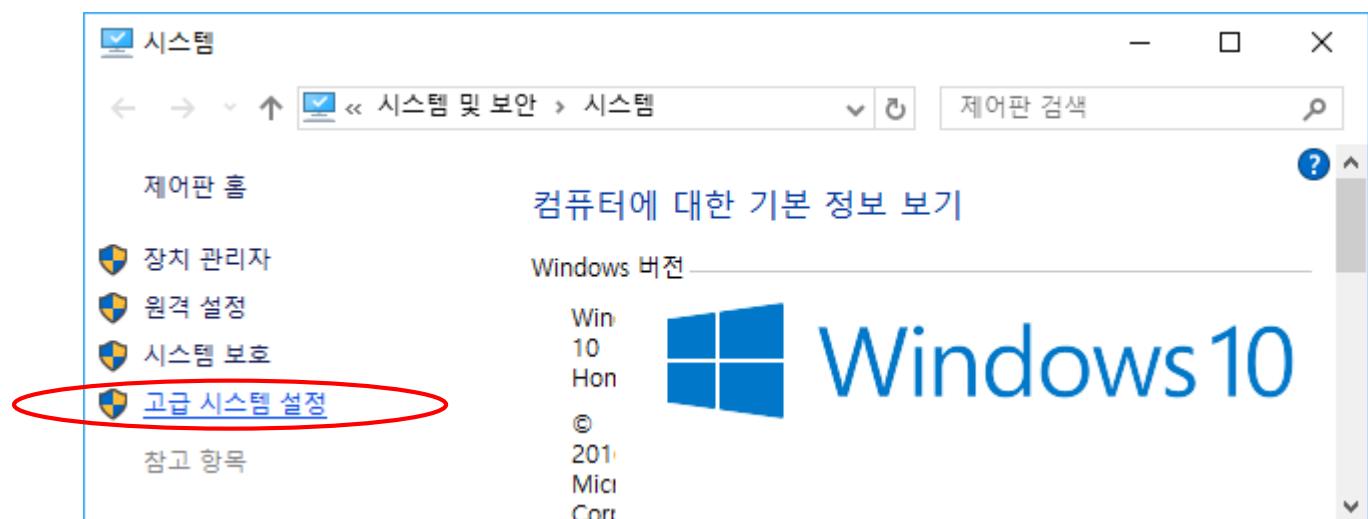
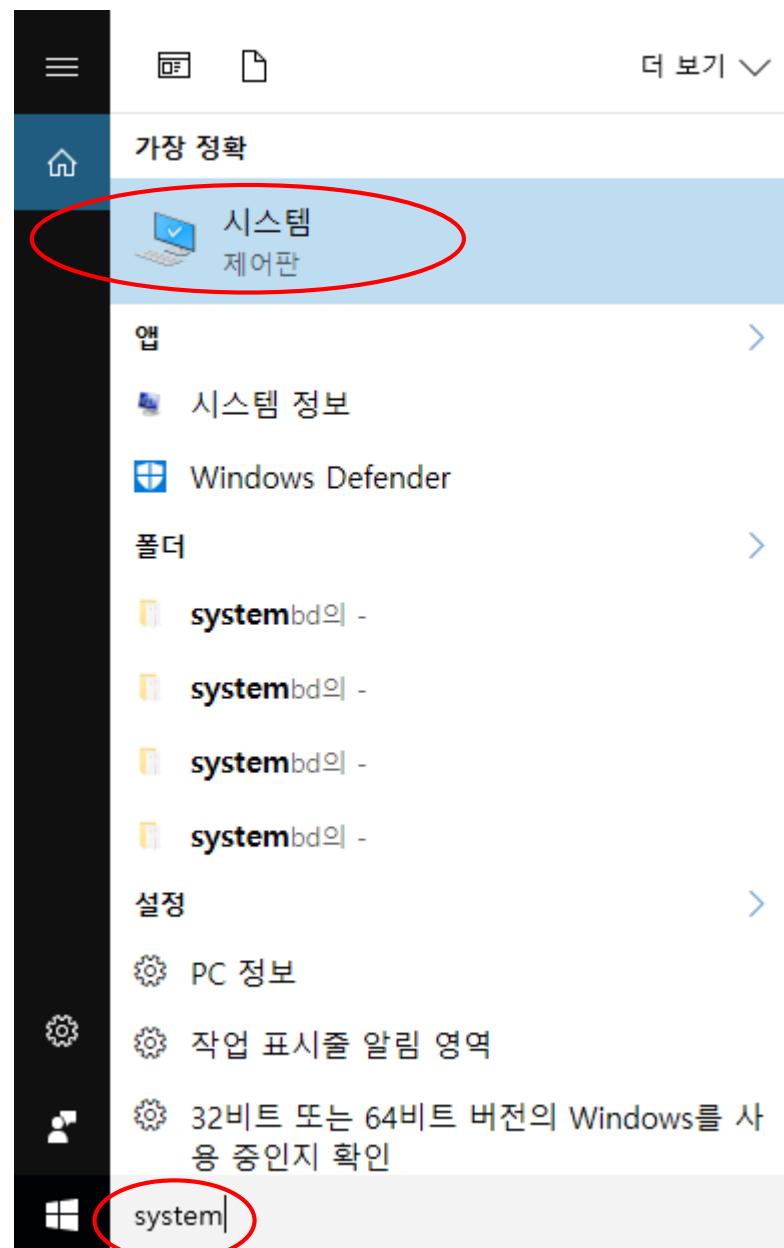


■ Device Tree Source



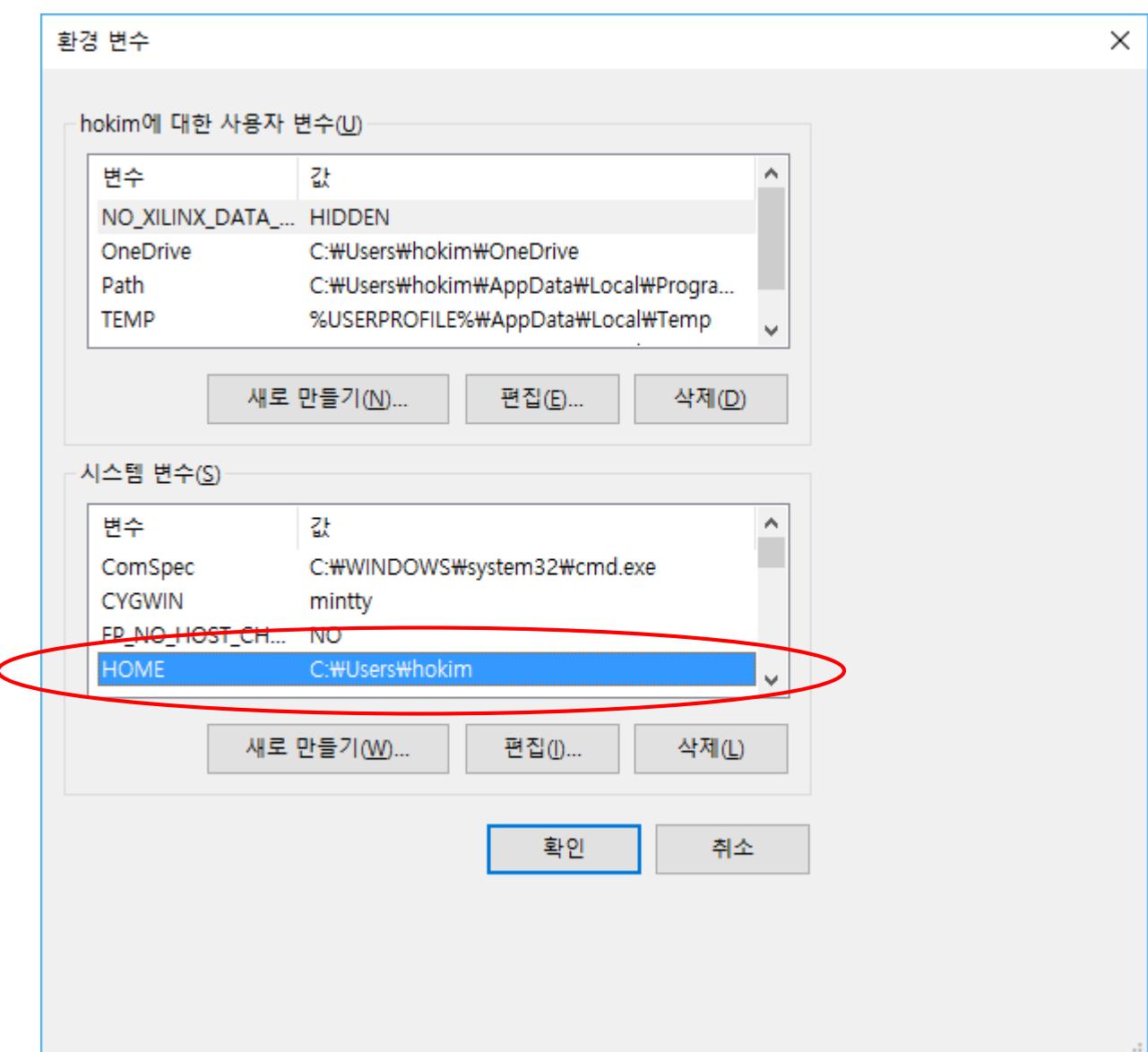
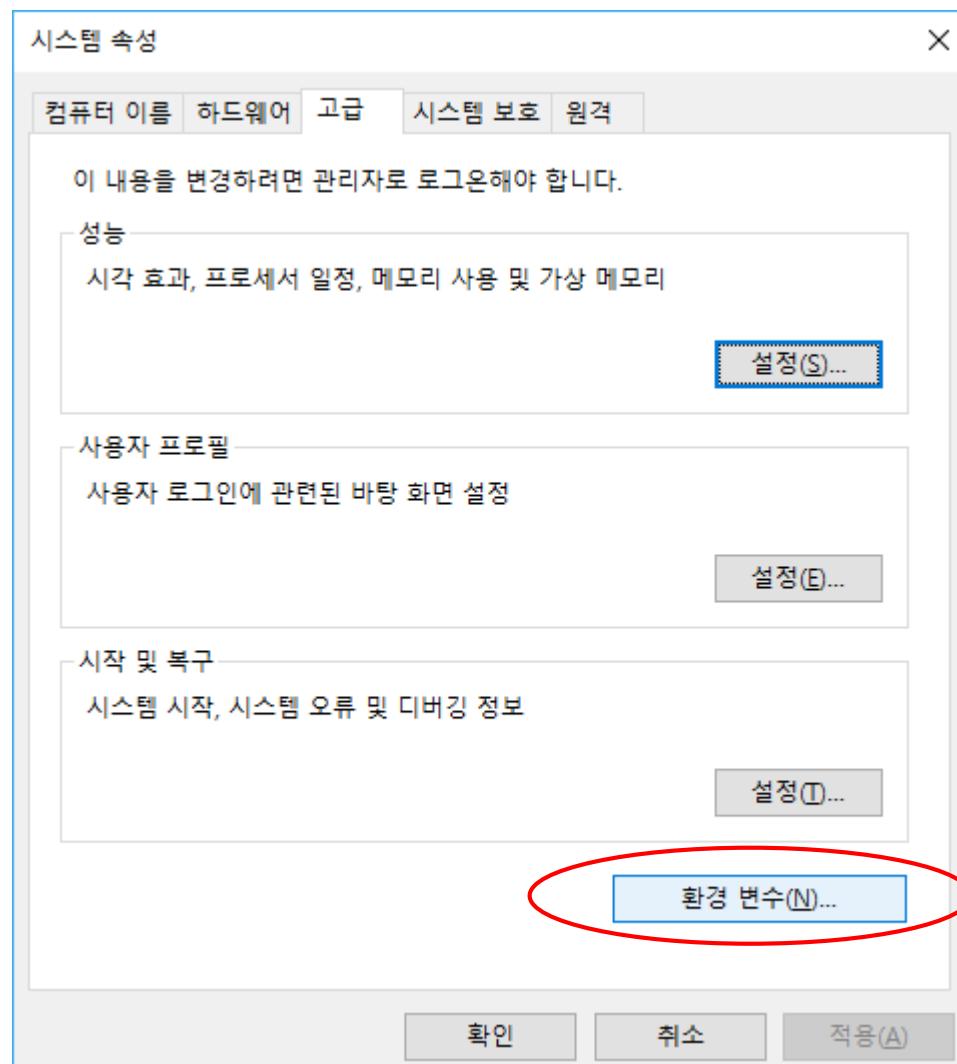
Development Environment Set-up

■ Environment Variable(HOME)



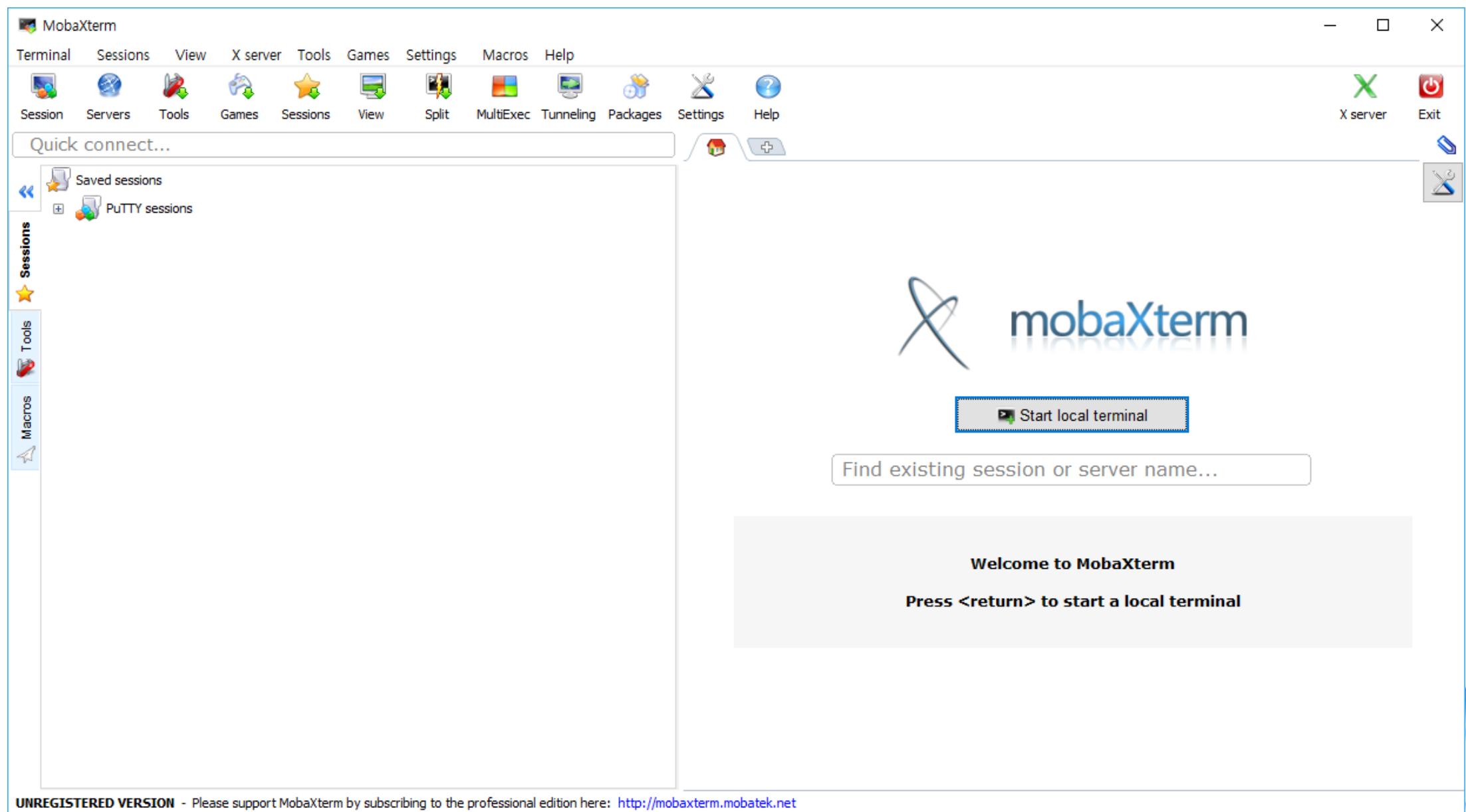
Development Environment Set-up

■ Environment Variable(HOME)

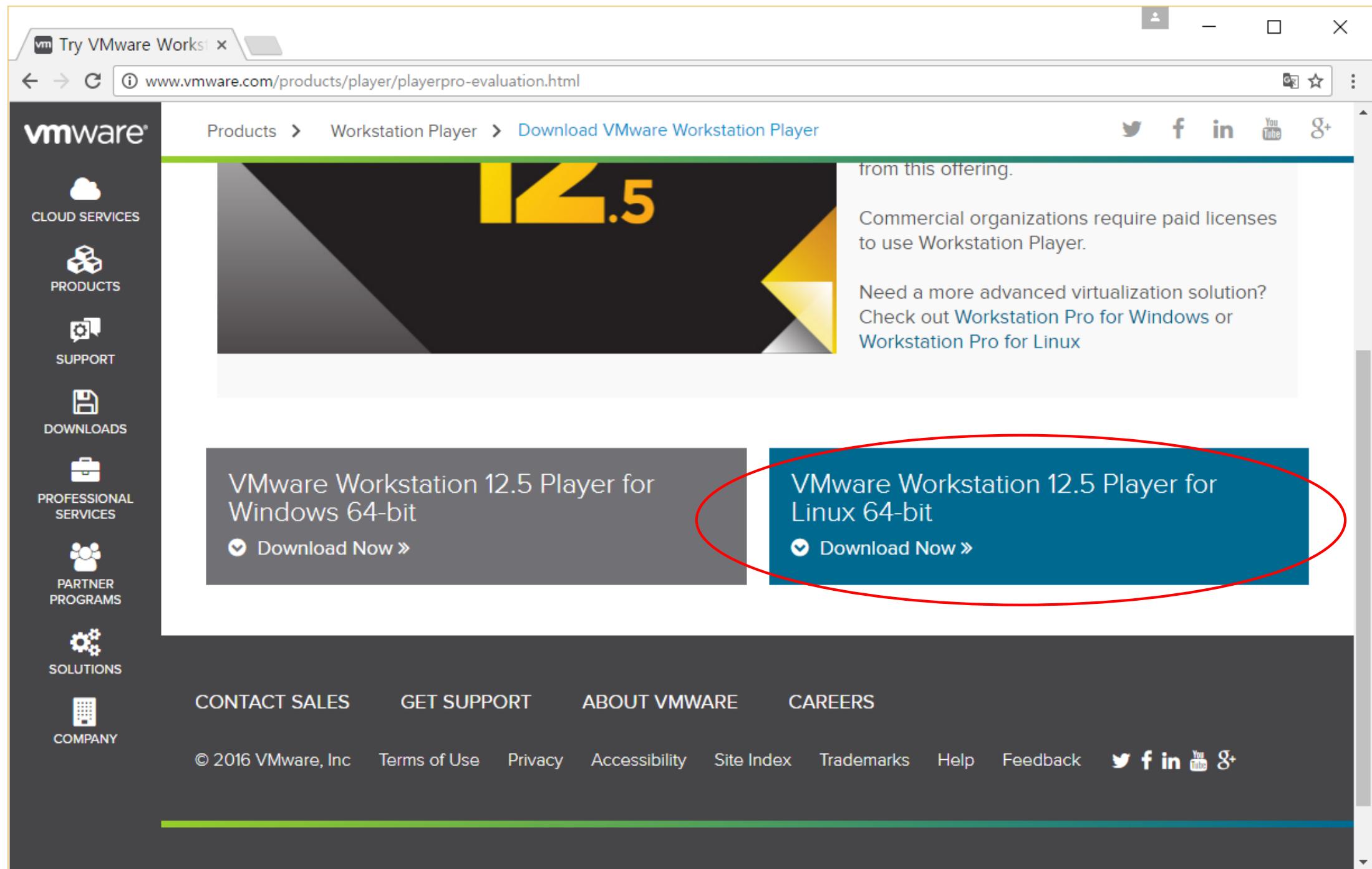


■ Windows ↔ Ubuntu

<http://mobaxterm.mobatek.net/>



■ Ubuntu on VMware-player



The screenshot shows the VMware website at www.vmware.com/products/player/playerpro-evaluation.html. The main content is for VMware Workstation Player 12.5. It features a large banner with the number '12.5' and a callout about commercial organizations requiring paid licenses. Below the banner, there are two download options: one for Windows 64-bit and one for Linux 64-bit. The Linux download link is circled in red.

from this offering.

Commercial organizations require paid licenses to use Workstation Player.

Need a more advanced virtualization solution? Check out [Workstation Pro for Windows](#) or [Workstation Pro for Linux](#)

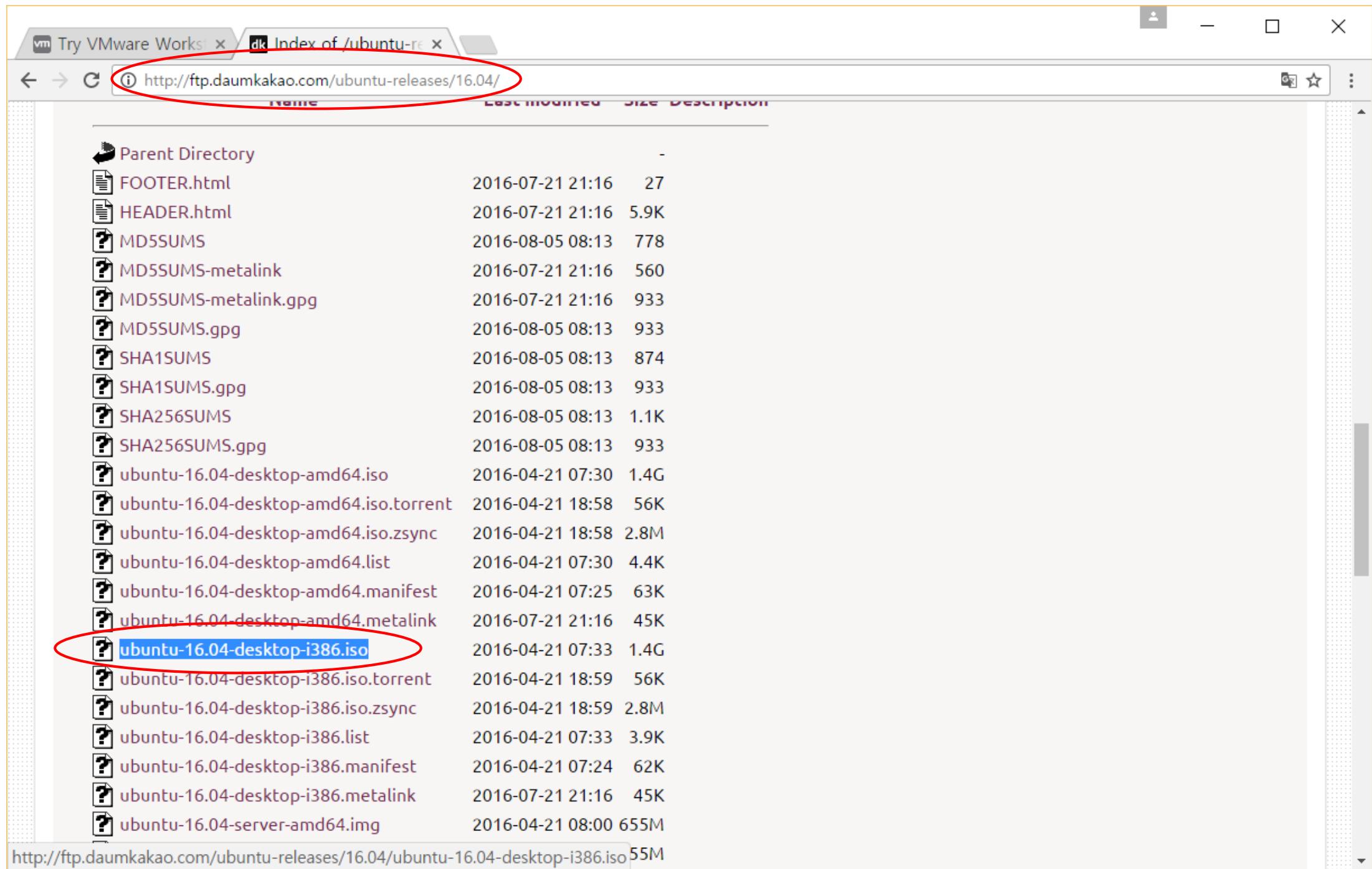
VMware Workstation 12.5 Player for Windows 64-bit
[Download Now »](#)

VMware Workstation 12.5 Player for Linux 64-bit
[Download Now »](#)

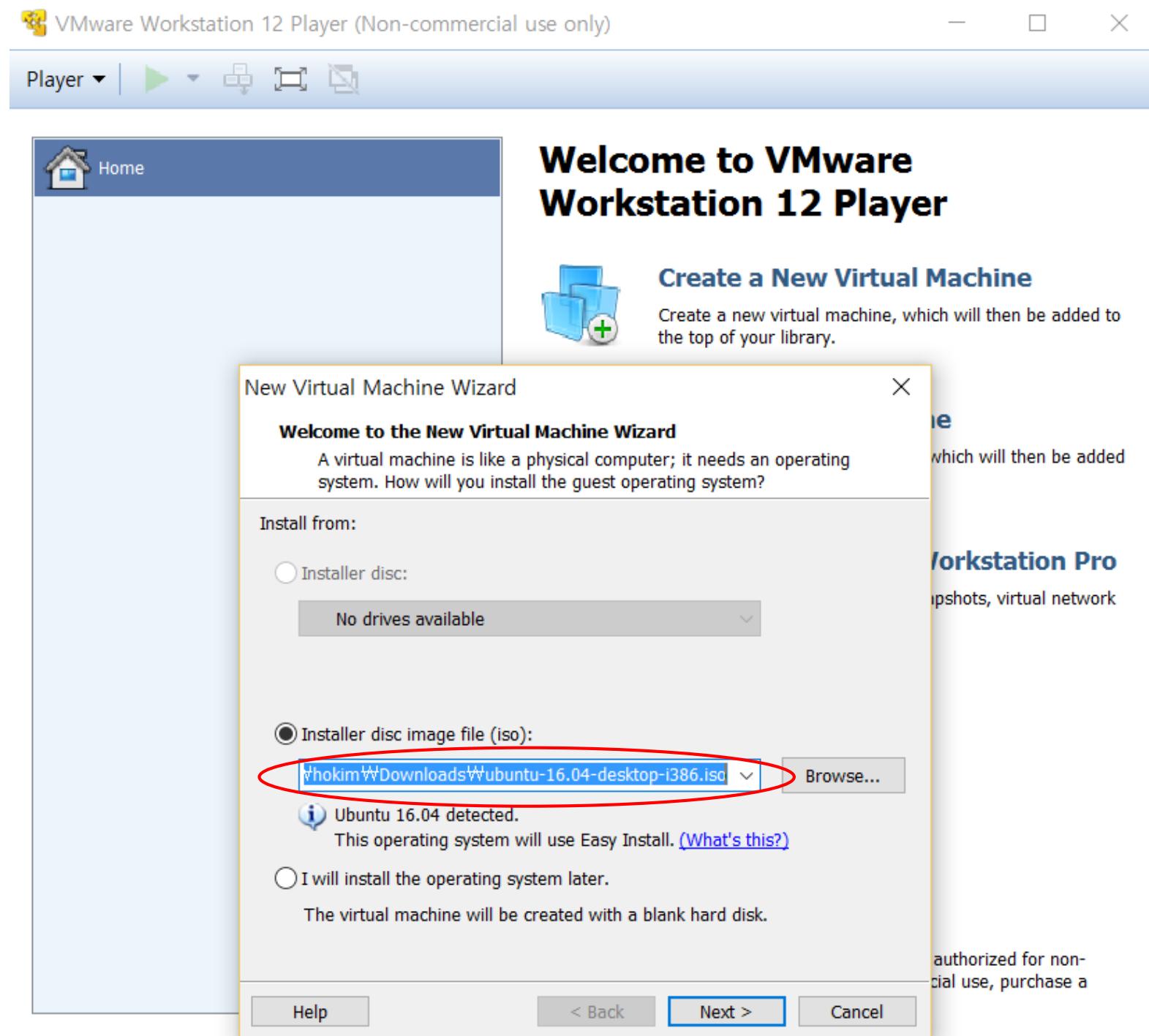
CONTACT SALES GET SUPPORT ABOUT VMWARE CAREERS

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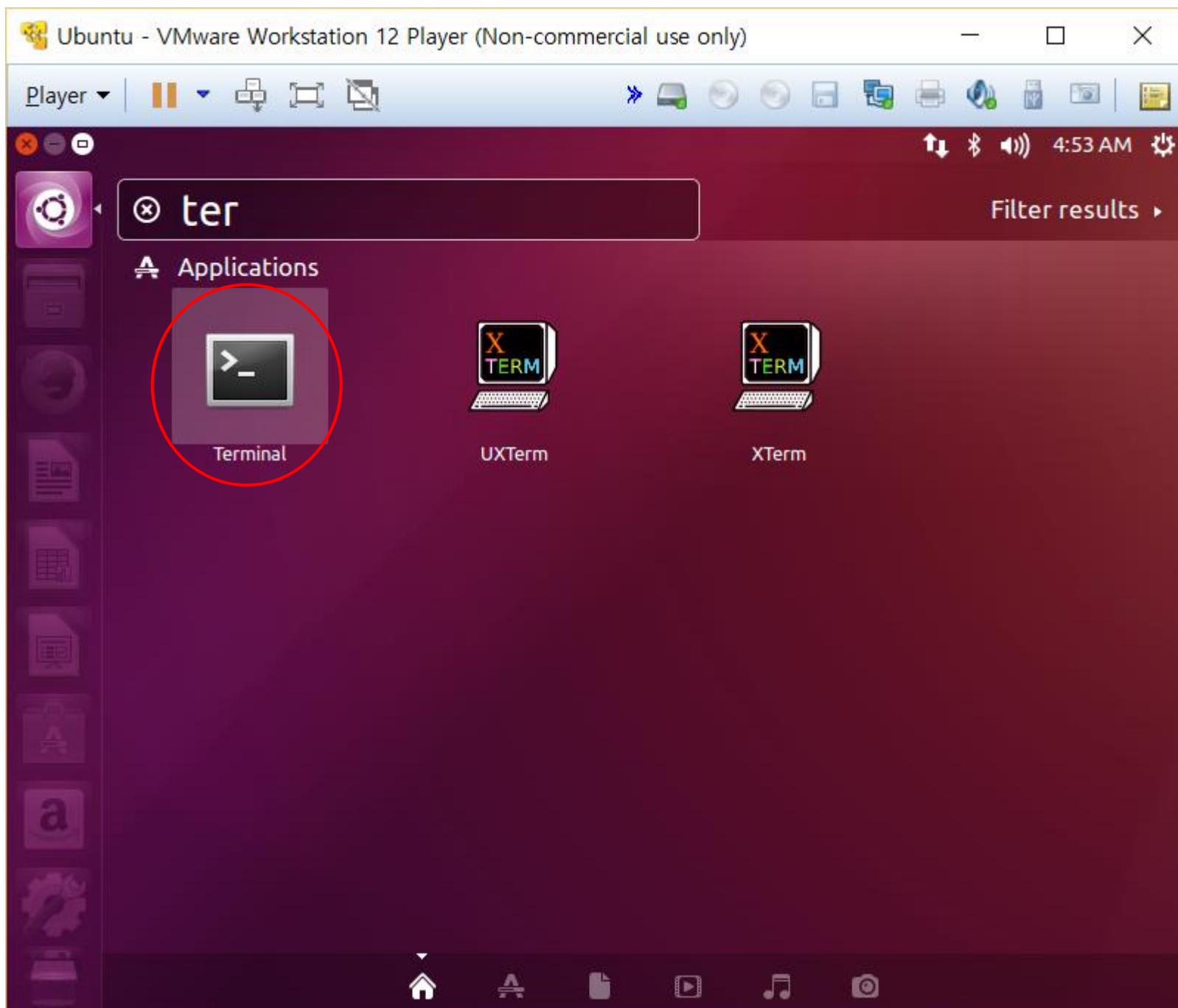
■ Ubuntu on VMware-player



■ Ubuntu on VMware-player

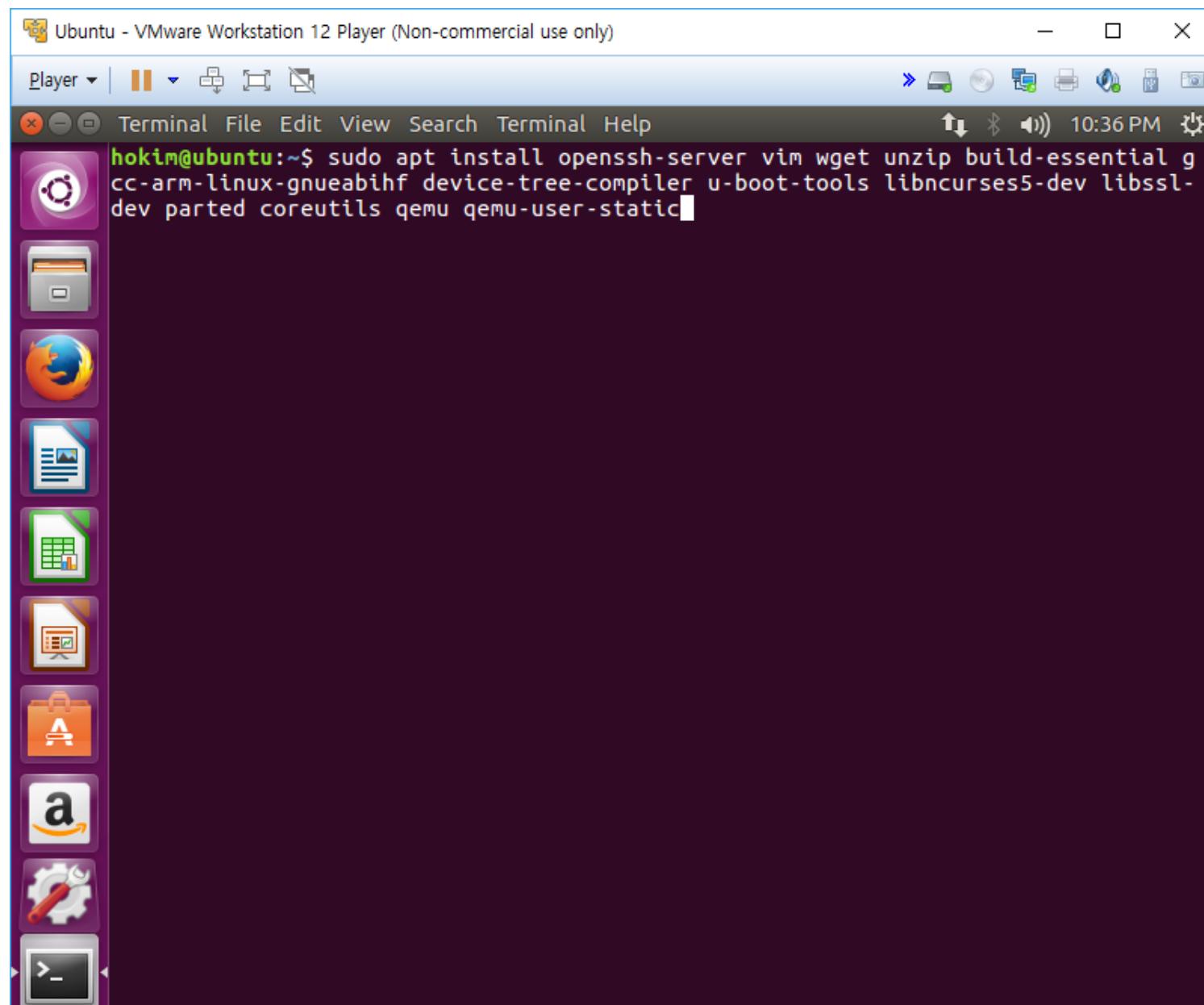


■ Ubuntu on VMware-player



■ Ubuntu on VMware-player

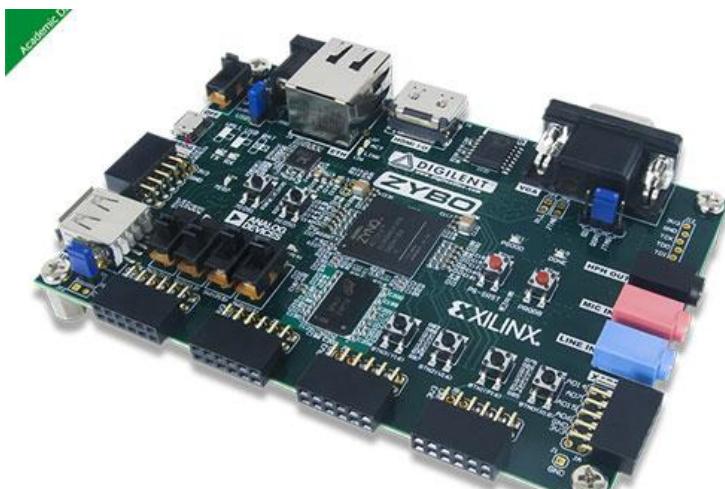
```
$ sudo apt install openssh-server vim wget unzip build-essential gcc-arm-linux-gnueabihf  
device-tree-compiler u-boot-tools libncurses5-dev libssl-dev parted coreutils qemu qemu-  
user-static
```



■ Target Board Zybo(Zynq-7010)

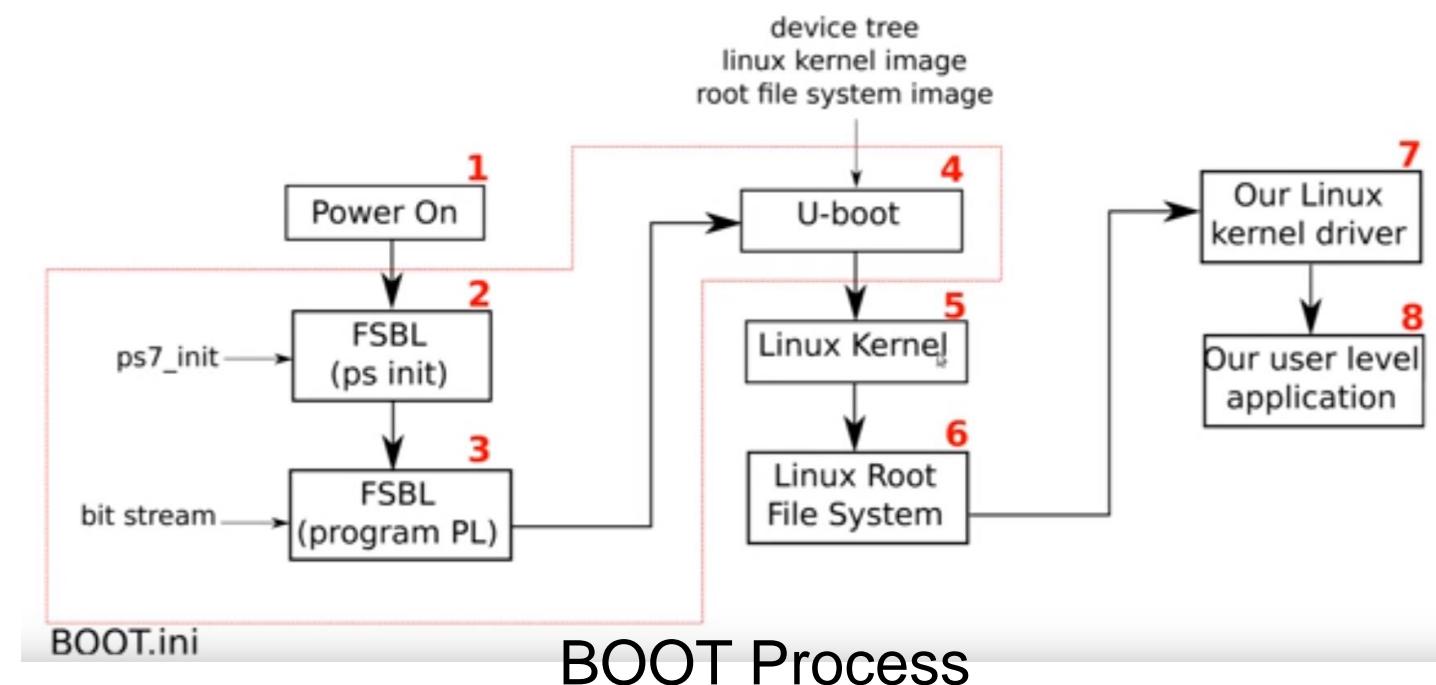
Gigabit Ethernet, USB, SD, UART

28,000 logic cells, 240 KB BRAM



■ Development Process

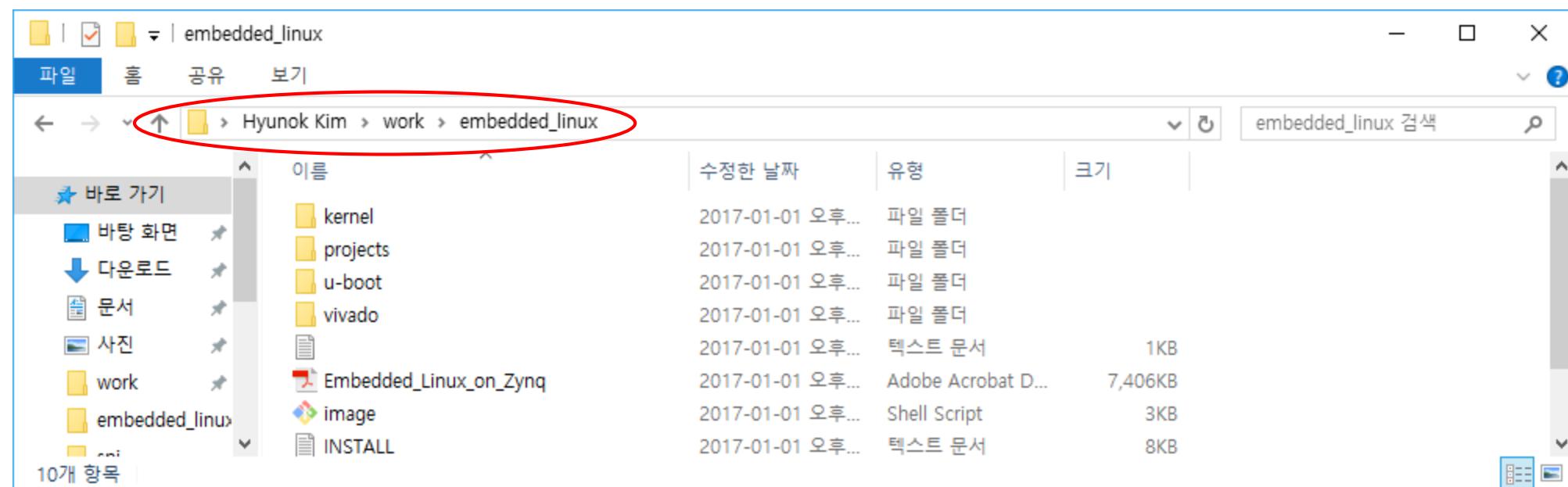
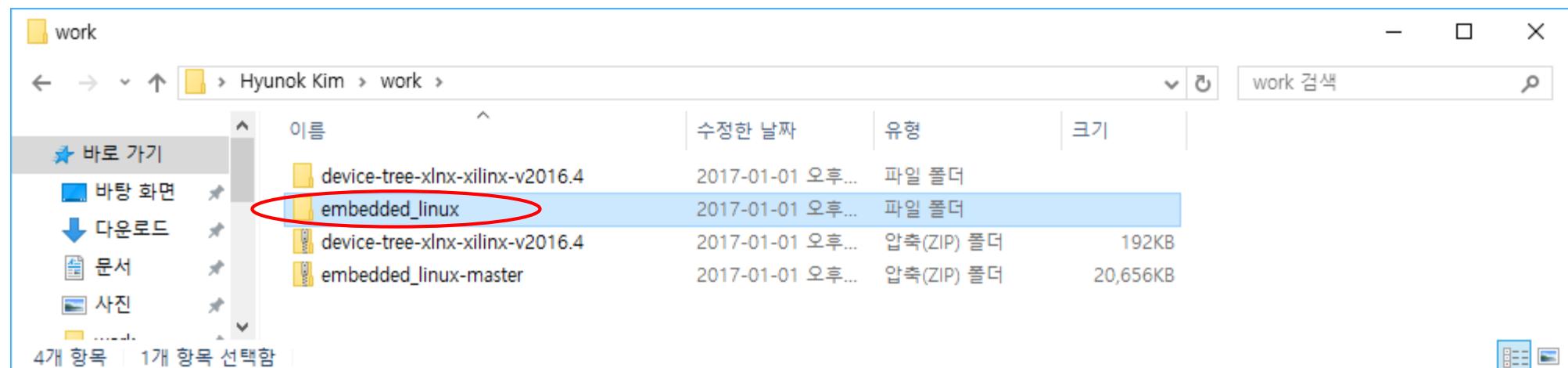
1. bit stream
2. FSBL
3. DT Generation
4. u-boot
5. DT Compile
6. linux kernel image
7. root file system image
8. BOOT.bin(fsbl + bit + u-boot)
9. Update BOOT.bin / DT / kernel
10. (user kernel driver)/user application



Development Process

■ Source code

https://github.com/inipro/embedded_linux



Design of Zynq PS Hardware

■ Vivado Design

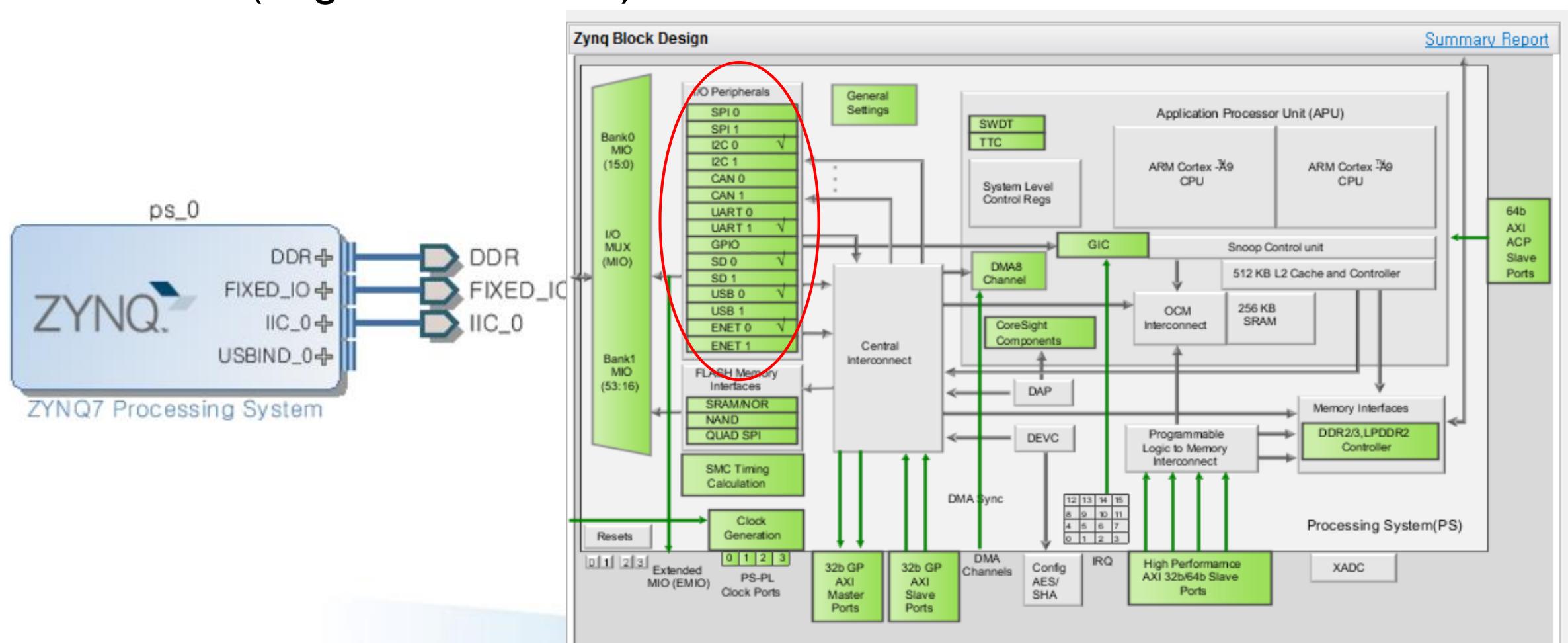
SD0 (boot files, root file system)

UART1 (console)

I2C0 (eeprom w/ Ethernet mac address; EMIO)

USB0 (usb host)

ENET0 (Gigabit Ethernet)



embedded_linux.tcl

```
set project_name embedded_linux
set part_name xc7z010clg400-1
#set ip_dir ip
set bd_path $project_name/$project_name.srcs/sources_1/bd/system
file delete -force $project_name
create_project -part $part_name $project_name $project_name
#set_property ip_repo_paths $ip_dir [current_project]
#update_ip_catalog
create_bd_design system

create_bd_cell -type ip -vlnv xilinx.com:ip:processing_system7:5.5 ps_0
source embedded_linux_preset.tcl
set_property -dict [apply_preset IPINST] [get_bd_cells ps_0]
apply_bd_automation -rule xilinx.com:bd_rule:processing_system7 -config {
    make_external {FIXED_IO, DDR}
} [get_bd_cells ps_0]
create_bd_intf_port -mode Master -vlnv xilinx.com:interface:iic_rtl:1.0 IIC_0
connect_bd_intf_net [get_bd_intf_pins ps_0/IIC_0] [get_bd_intf_ports IIC_0]

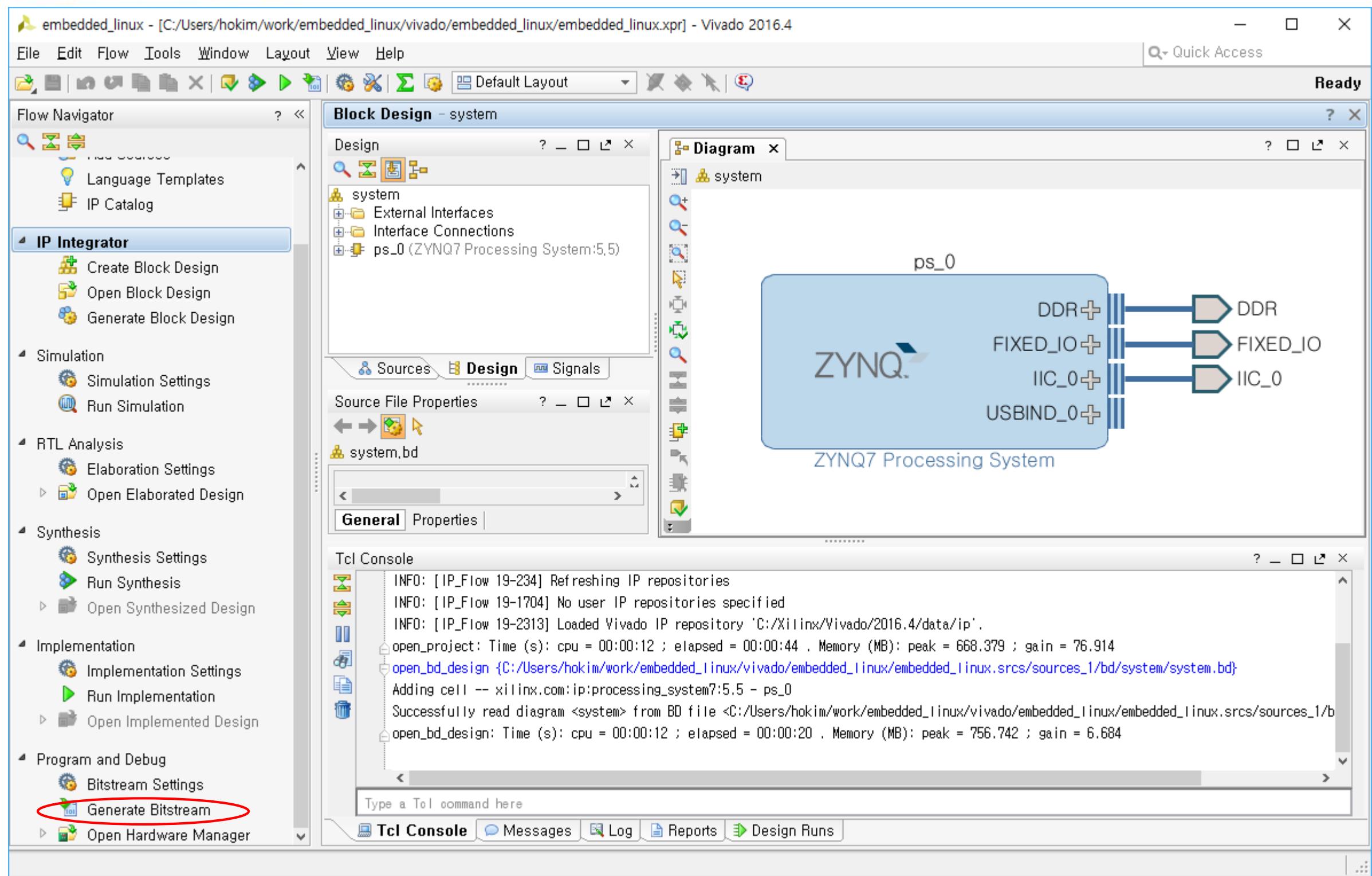
generate_target all [get_files $bd_path/system.bd]
make_wrapper -files [get_files $bd_path/system.bd] -top
add_files -norecurse $bd_path/hdl/system_wrapper.v
add_files -norecurse -fileset constrs_1 zybo.xdc
set_property verilog_define {TOOL_VIVADO} [current_fileset]
close_project
```

In cmd window for Vivado

```
C:\> cd C:\Users\hokim\work\embedded_linux\vivado
C:\> vivado -nolog -nojournal -mode batch -source embedded_linux.tcl
```

output : embedded_linux\embedded_linux.xpr...

Bit Generation



hwdef.tcl

```
# vivado -nolog -nojournal -mode batch -source hwdef.tcl

set project_name embedded_linux

open_project $project_name/$project_name.xpr

if {[get_property PROGRESS [get_runs synth_1]] != "100%"} {
    launch_runs synth_1
    wait_on_run synth_1
}

file delete -force $project_name/$project_name.hwdef

write_hwdef -force -file $project_name/$project_name.hwdef

close_project
```

```
C:\> vivado -nolog -nojournal -mode batch -source hwdef.tcl
```

```
output : embedded_linux\embedded_linux.hwdef
```



fsbl.tcl

```
# hsi -nolog -nojournal -mode batch -source fsbl.tcl

set project_name embedded_linux

set hard_path $project_name/$project_name.hard
set fsbl_path $project_name/$project_name.fsbl

file delete -force $hard_path $fsbl_path

file mkdir $hard_path
file copy -force $project_name/$project_name.hwdef $hard_path/$project_name.hdf

open_hw_design $hard_path/$project_name.hdf
create_sw_design -proc ps7_cortexa9_0 -os standalone fsbl

add_library xilffs
add_library xilrsa

generate_app -proc ps7_cortexa9_0 -app zynq_fsbl -dir $fsbl_path -compile

close_hw_design [current_hw_design]
```

C:\> hsi -nolog -nojournal -mode batch -source fsbl.tcl

output : embedded_linux\embedded_linux.fsbl\executable.elf



devicetree.tcl

```
# hsi -nolog -nojournal -mode batch -source devicetree.tcl

set project_name embedded_linux

set boot_args {console=ttyPS0,115200 root=/dev/mmcblk0p2 ro rootfstype=ext4 earlyprintk rootwait}

set hard_path $project_name/$project_name.hard
set tree_path $project_name/$project_name.tree

file delete -force $hard_path $tree_path

file mkdir $hard_path
file copy -force $project_name/$project_name.hwdef $hard_path/$project_name.hdf

set_repo_path $::env(HOME)/work/device-tree-xlnx-xilinx-v2016.4

open_hw_design $hard_path/$project_name.hdf
create_sw_design -proc ps7_cortexa9_0 -os device_tree devicetree

set_property CONFIG.kernel_version {2016.4} [get_os]
set_property CONFIG.bootargs $boot_args [get_os]

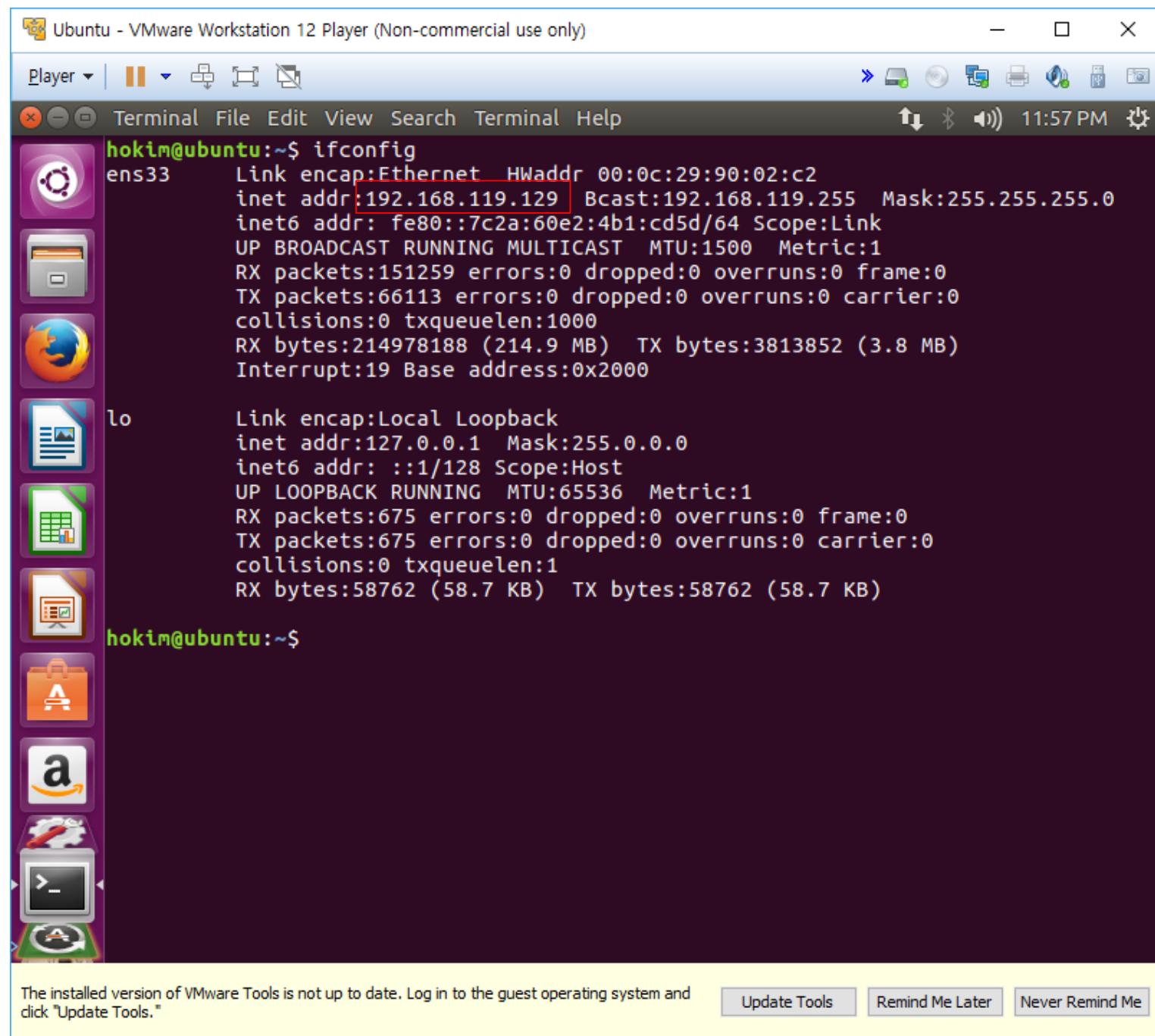
generate_bsp -dir $tree_path

close_sw_design [current_sw_design]
close_hw_design [current_hw_design]
```

```
C:\> hsi -nolog -nojournal -mode batch -source devicetree.tcl
```

```
output : embedded_linux\embedded_linux.tree/*
```

Ubuntu network IP



```
Ubuntu - VMware Workstation 12 Player (Non-commercial use only)
Player Terminal File Edit View Search Terminal Help 11:57 PM
hokim@ubuntu:~$ ifconfig
ens33      Link encap:Ethernet HWaddr 00:0c:29:90:02:c2
           inet addr:192.168.119.129 Bcast:192.168.119.255 Mask:255.255.255.0
           inet6 addr: fe80::7c2a:60e2:4b1:cd5d/64 Scope:Link
             UP BROADCAST RUNNING MULTICAST MTU:1500 Metric:1
             RX packets:151259 errors:0 dropped:0 overruns:0 frame:0
             TX packets:66113 errors:0 dropped:0 overruns:0 carrier:0
             collisions:0 txqueuelen:1000
             RX bytes:214978188 (214.9 MB) TX bytes:3813852 (3.8 MB)
             Interrupt:19 Base address:0x2000

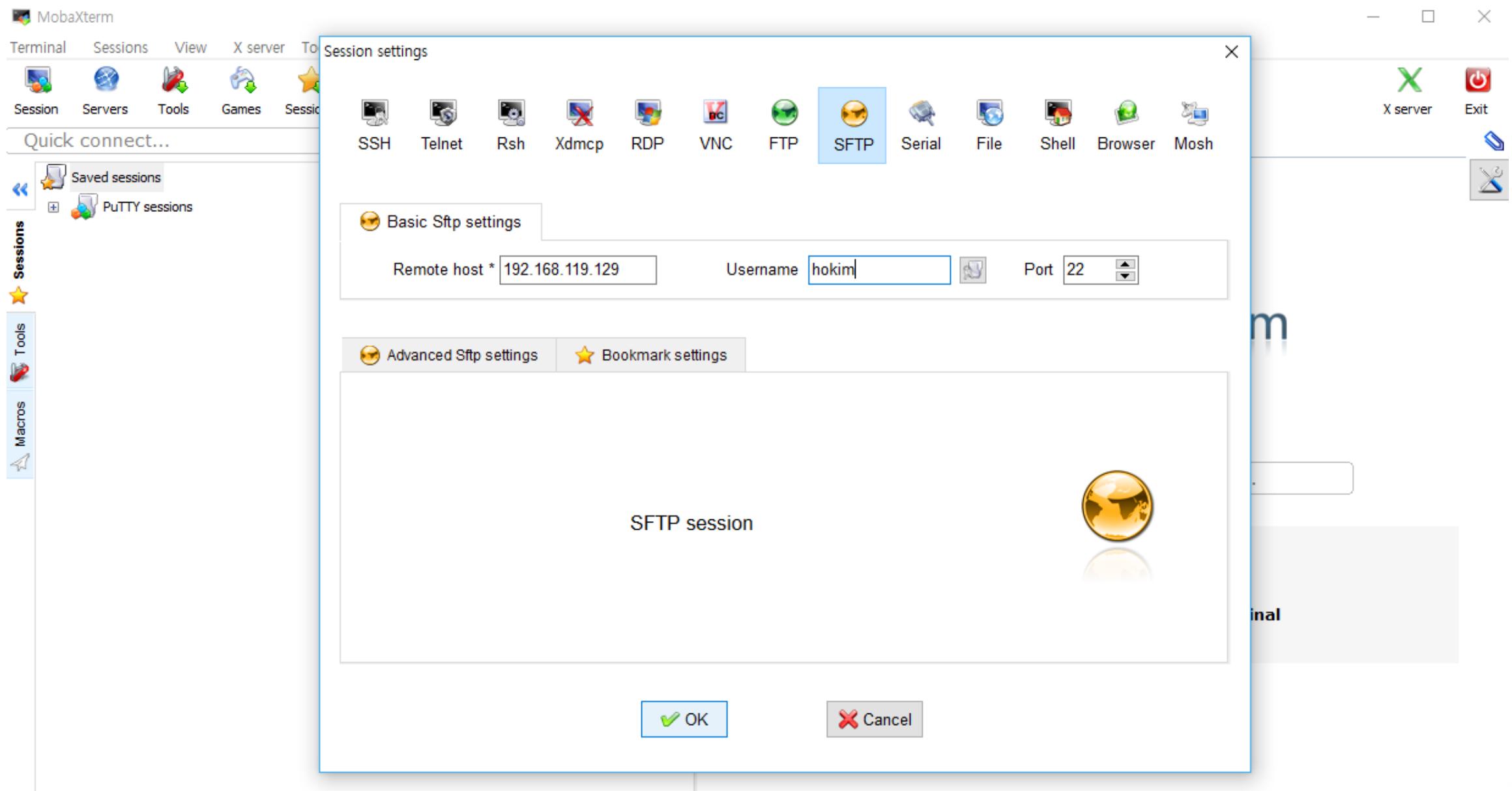
lo         Link encap:Local Loopback
           inet addr:127.0.0.1 Mask:255.0.0.0
           inet6 addr: ::1/128 Scope:Host
             UP LOOPBACK RUNNING MTU:65536 Metric:1
             RX packets:675 errors:0 dropped:0 overruns:0 frame:0
             TX packets:675 errors:0 dropped:0 overruns:0 carrier:0
             collisions:0 txqueuelen:1
             RX bytes:58762 (58.7 KB) TX bytes:58762 (58.7 KB)

hokim@ubuntu:~$
```

The installed version of VMware Tools is not up to date. Log in to the guest operating system and click "Update Tools."

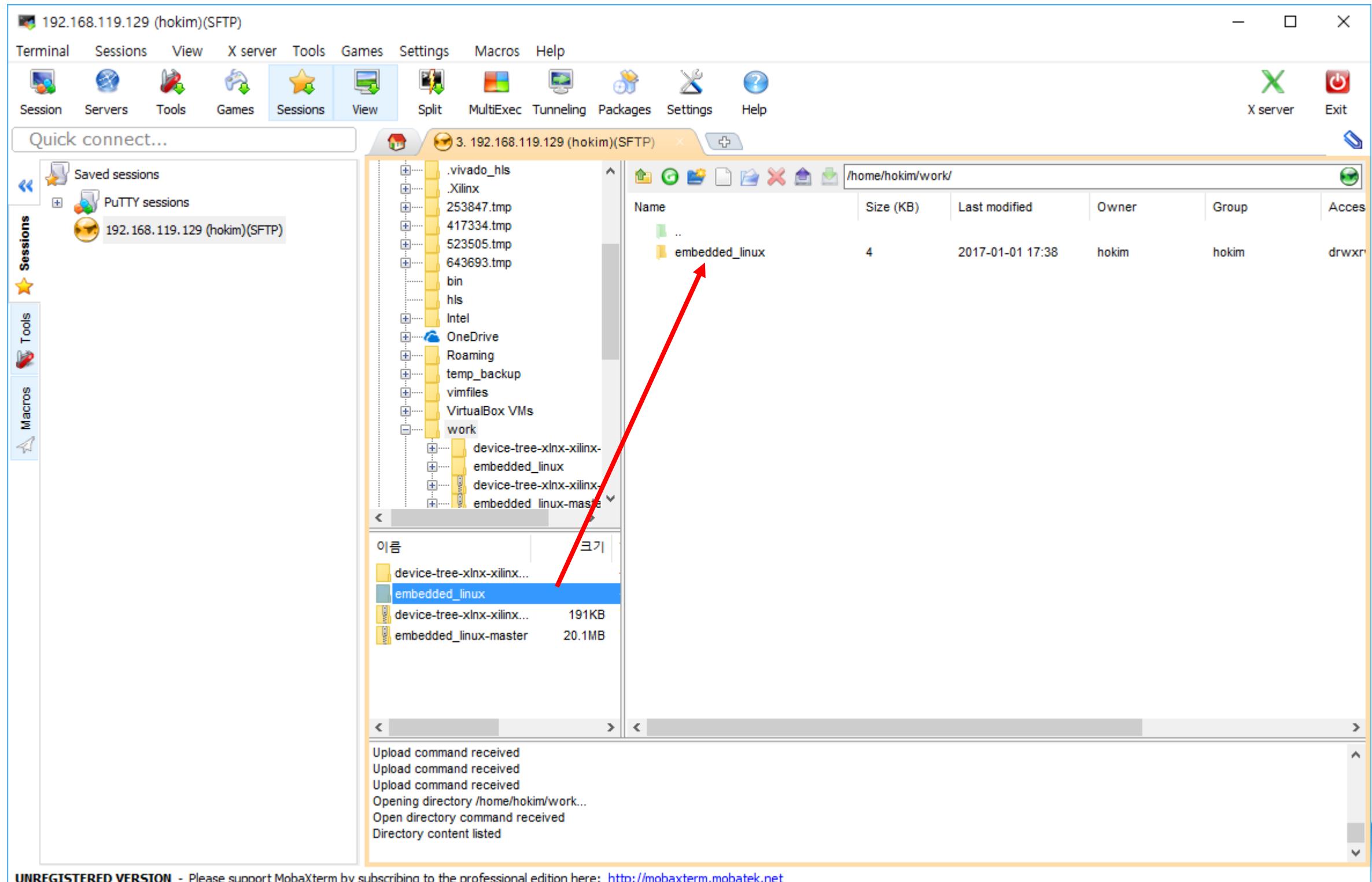
Update Tools Remind Me Later Never Remind Me

embedded_linux using MobaXterm

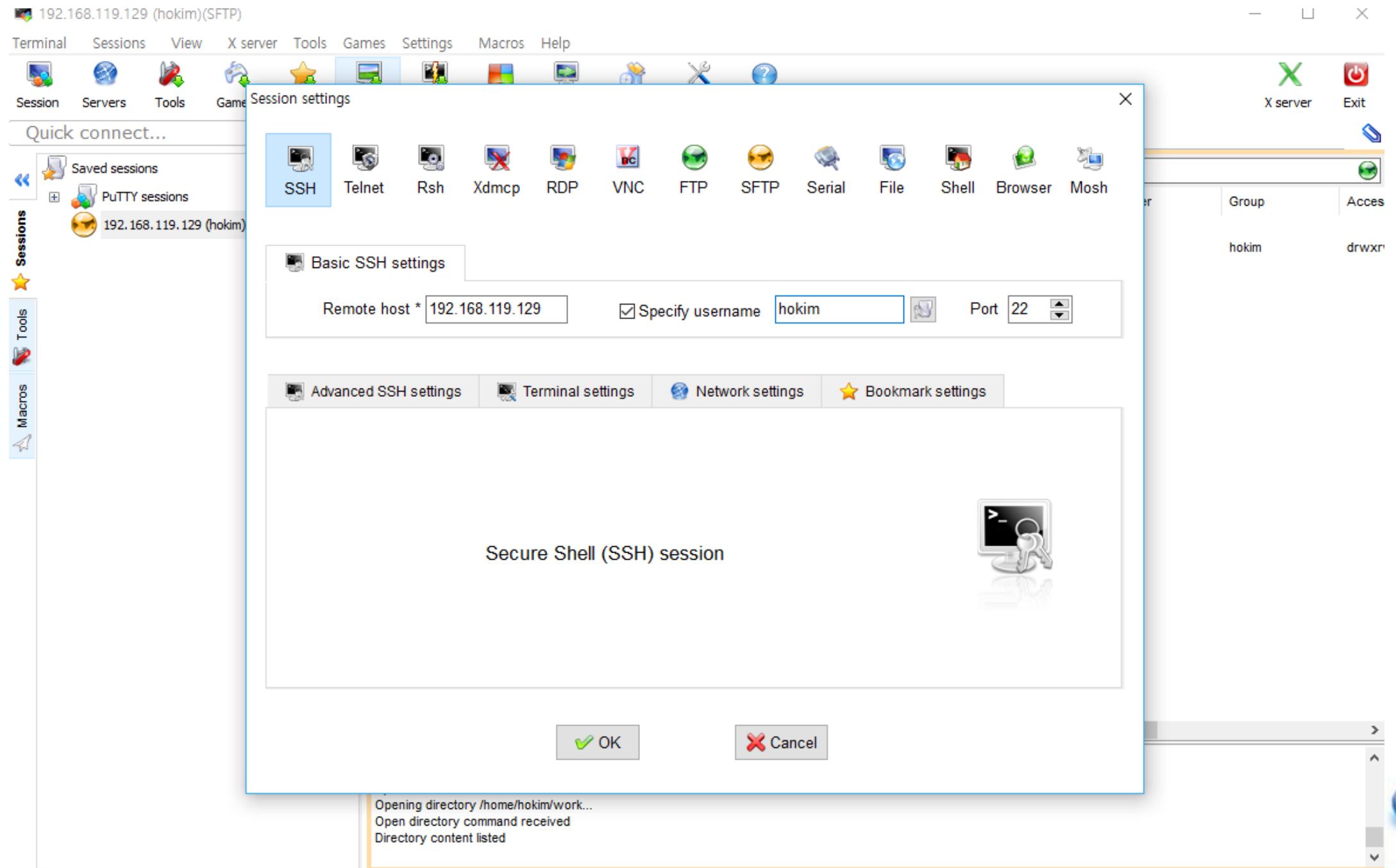


SFTP File Transfer (Windows → Ubuntu)

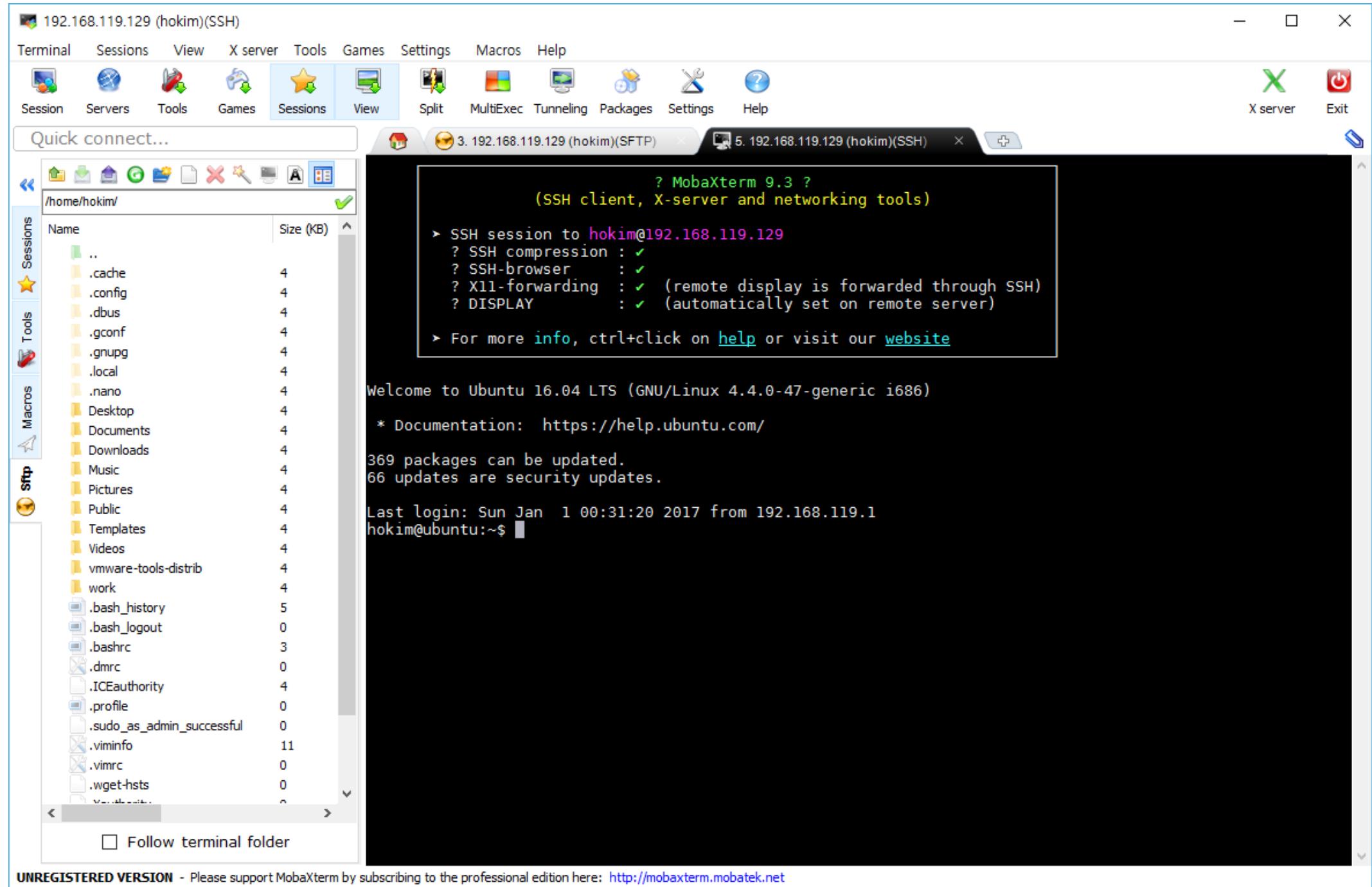
embedded_linux using MobaXterm



SSH Login (Windows → Ubuntu)



SSH Login (Windows → Ubuntu)



■ **Boot loader for linux**

Load linux kernel(uImage, devicetree.dtb) from SD to DRAM.

Set ethernet using mac address from i2c eeprom.

Boot uImage.



Log into VMWare Ubuntu using Mobaterm

Use nano or leafpad for editing

- : deletion
- + : insertion

```
$ cd ~/work/embedded_linux
$ mkdir -p dl
$ wget https://github.com/Xilinx/u-boot-xlnx/archive/xilinx-v2016.4.tar.gz -O dl/u-boot-xlnx-xilinx-v2016.4.tar.gz
$ cd u-boot
$ tar xvzf ../dl/u-boot-xlnx-xilinx-v2016.4.tar.gz
$ cd u-boot-xlnx-xilinx-v2016.4
$ cp ../*.dts arch/arm/dts
$ cp ../*.h include/configs
$ cp ../*.defconfig configs
```

zynq-zyboc.dts

```
.....
/dts-v1/;
#include "zynq-7000.dtsi"

{
    model = "Zynq ZYBOC Development Board";
    compatible = "inipro,zynq-zyboc", "xlnx,zynq-7000";

    aliases {
        ethernet0 = &gem0;
        serial0 = &uart1;
        spi0 = &qspi;
        mmc0 = &sdhci0;
    };

    memory {
        device_type = "memory";
        reg = <0x0 0x20000000>;
    };

    chosen {
        bootargs = "";
        stdout-path = "serial0:115200n8";
    };

    usb_phy0: phy0 {
        compatible = "usb-nop-xceiv";
        #phy-cells = <0>;
        reset-gpios = <&gpio0 46 1>;
    };
}
```

```
&clkc {
    ps-clk-frequency = <50000000>;
};

&gem0 {
    status = "okay";
    phy-mode = "rgmii-id";
    phy-handle = <&ethernet_phy>;
    ethernet_phy: ethernet-phy@0 {
        reg = <0>;
    };
};

&qspi {
    u-boot,dm-pre-reloc;
    status = "okay";
};

&sdhci0 {
    u-boot,dm-pre-reloc;
    status = "okay";
};

&uart1 {
    u-boot,dm-pre-reloc;
    status = "okay";
};

&usb0 {
    status = "okay";
    dr_mode = "host";
    usb-phy = <&usb_phy0>;
};
```

zynq_zyboc.h

```
.....
#ifndef __CONFIG_ZYNQ_ZYBOC_H
#define __CONFIG_ZYNQ_ZYBOC_H

#define CONFIG_ZYNQ_I2C0
#define CONFIG_ZYNQ_I2C1
#define CONFIG_SYS_I2C_EEPROM_ADDR_LEN      1
#define CONFIG_CMD_EEPROM
#define CONFIG_ZYNQ_GEM_EEPROM_ADDR        0x50
#define CONFIG_ZYNQ_GEM_I2C_MAC_OFFSET    0xFA
#define CONFIG_DISPLAY
#define CONFIG_I2C_EDID

/* Define ZYBO PS Clock Frequency to 50MHz */
#define CONFIG_ZYNQ_PS_CLK_FREQ      50000000UL

#include <configs/zynq-common.h>

#endif /* __CONFIG_ZYNQ_ZYBOC_H */
```

zynq_zyboc_defconfig

```
CONFIG_ARM=y
CONFIG_SYS_CONFIG_NAME="zynq_zybo"
CONFIG_ARCH_ZYNQ=y
CONFIG_DEFAULT_DEVICE_TREE="zynq-zybo"
CONFIG_SPL=y
CONFIG_FIT=y
CONFIG_FIT_VERBOSE=y
CONFIG_FIT_SIGNATURE=y
CONFIG_SYS_NO_FLASH=y
CONFIG_HUSH_PARSER=y
CONFIG_SYS_PROMPT="Zynq> "
# CONFIG_CMD_IMLS is not set
# CONFIG_CMD_FLASH is not set
CONFIG_CMD_MMC=y
CONFIG_CMD_SF=y
CONFIG_CMD_I2C=y
CONFIG_CMD_USB=y
CONFIG_CMD_DFU=y
CONFIG_CMD_GPIO=y
# CONFIG_CMD_SETEXPR is not set
CONFIG_CMD_TFTPPUT=y
CONFIG_CMD_DHCP=y
CONFIG_CMD_MII=y
CONFIG_CMD_PING=y
CONFIG_CMD_CACHE=y
CONFIG_CMD_EXT2=y
CONFIG_CMD_EXT4=y
CONFIG_CMD_EXT4_WRITE=y
CONFIG_CMD_FAT=y
CONFIG_CMD_FS_GENERIC=y
CONFIG_OF_EMBED=y
CONFIG_NET_RANDOM_ETHADDR=y
CONFIG_SPL_DM_SEQ_ALIAS=y
```

```
CONFIG_ZYNQ_SDHCI=y
CONFIG_SPI_FLASH=y
CONFIG_SPI_FLASH_BAR=y
CONFIG_SPI_FLASH_SPANSION=y
CONFIG_ZYNQ_GEM=y
CONFIG_DEBUG_UART=y
CONFIG_DEBUG_UART_ZYNQ=y
CONFIG_DEBUG_UART_BASE=0xe0001000
CONFIG_DEBUG_UART_CLOCK=50000000
CONFIG_ZYNQ_QSPI=y
CONFIG_USB=y
CONFIG_USB_EHCI_HCD=y
CONFIG_USB_ULPI_VIEWPORT=y
CONFIG_USB_ULPI=y
CONFIG_USB_STORAGE=y
CONFIG_USB_GADGET=y
CONFIG_CI_UDC=y
CONFIG_USB_GADGET_DOWNLOAD=y
CONFIG_G_DNL_MANUFACTURER="Xilinx"
CONFIG_G_DNL_VENDOR_NUM=0x03fd
CONFIG_G_DNL_PRODUCT_NUM=0x0300
```



```
$ nano arch/arm/dts/Makefile
```

```
dtb-$(CONFIG_ARCH_ZYNQ) += zynq-zc702.dtb \
    zynq-zc706.dtb \
    zynq-zed.dtb \
    zynq-zybo.dtb \
    zynq-microzed.dtb \
    zynq-cc108.dtb \
    zynq-afx-nand.dtb \
    zynq-afx-nor.dtb \
    zynq-afx-qspi.dtb \
    zynq-cse-nand.dtb \
    zynq-cse-nor.dtb \
    zynq-cse-qspi.dtb \
    zynq-picozed.dtb \
    zynq-zc770-xm010.dtb \
    zynq-zc770-xm011.dtb \
    zynq-zc770-xm012.dtb \
    - zynq-zc770-xm013.dtb
+ zynq-zc770-xm013.dtb \
+ zynq-zyboc.dtb
```

```
$ make arch=ARM zynq_zyboc_defconfig
$ make arch=ARM CROSS_COMPILE=arm-linux-gnueabihf- CFLAGS="-O2
-mtune=cortex-a9 -mfpu=neon -mfloat-abi=hard" all
$ cp u-boot ~/work/embedded_linux/vivado/u-boot.elf
```

- **Kernel driver** for platform devices

- = Kernel source code + Device Tree

- Hierarchy of Devices

- Provide register address, irq number, so on as property of device.

- **Platform device**

- Instead of being dynamically detected, must be statically described in either:

- Kernel source code or Device Tree

- The devices on I2C buses or SPI buses, or the devices directly part of the system-on-chip.



Device Tree Compile

```
$ cd ~/work/embedded_linux/vivado  
$ cp embedded_linux/embedded_linux.tree/system.dts .  
$ nano system.dts
```

system.dts

```
&clkc {  
    fclk-enable = <0x0>;  
    ps-clk-frequency = <50000000>;  
};  
  
+&i2c0 {  
+    eeprom@50 {  
+        /* Microchip 24AA02E48 */  
+        compatible = "microchip,24c02";  
+        reg = <0x50>;  
+        pagesize = <8>;  
+    };  
+};
```

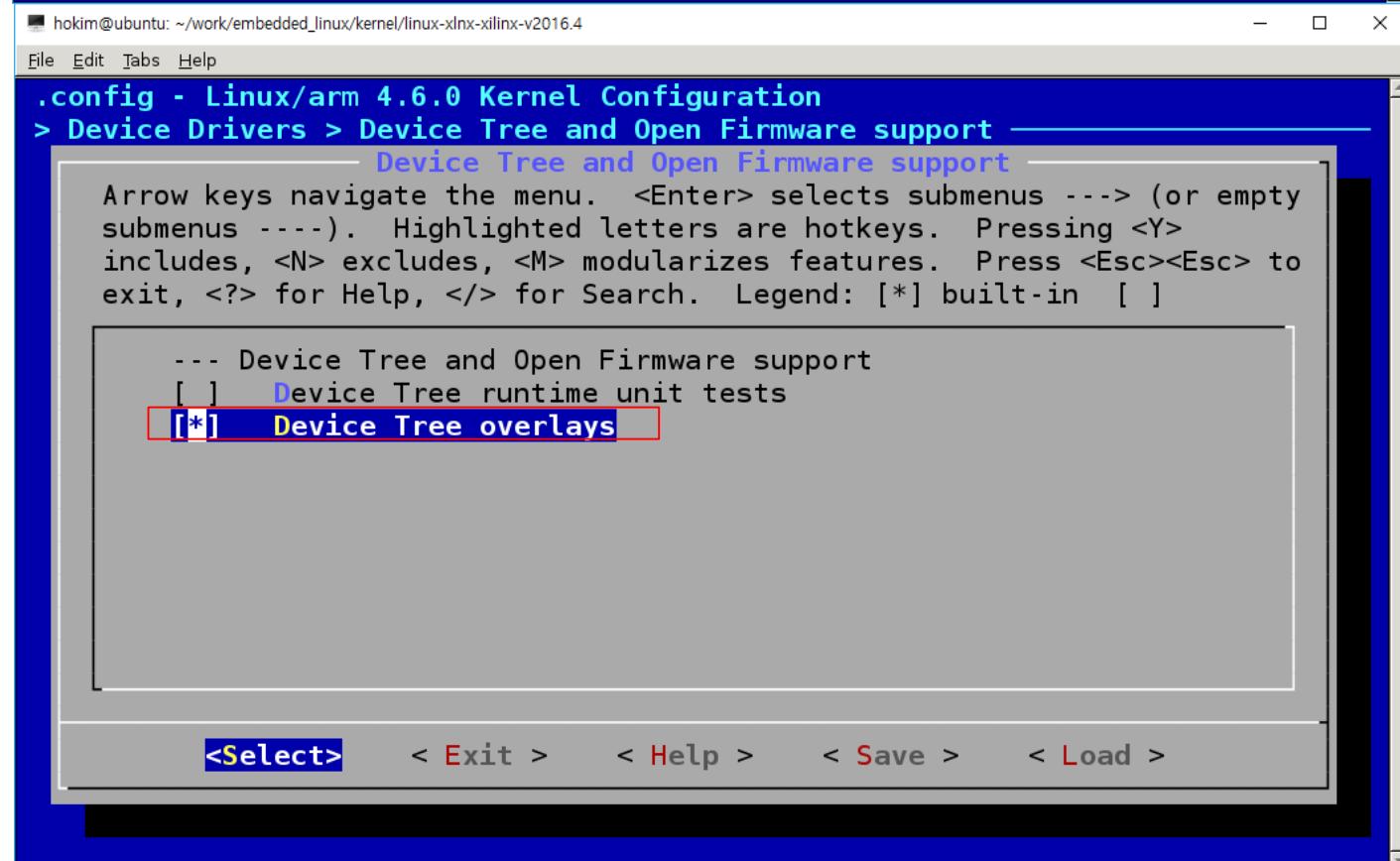
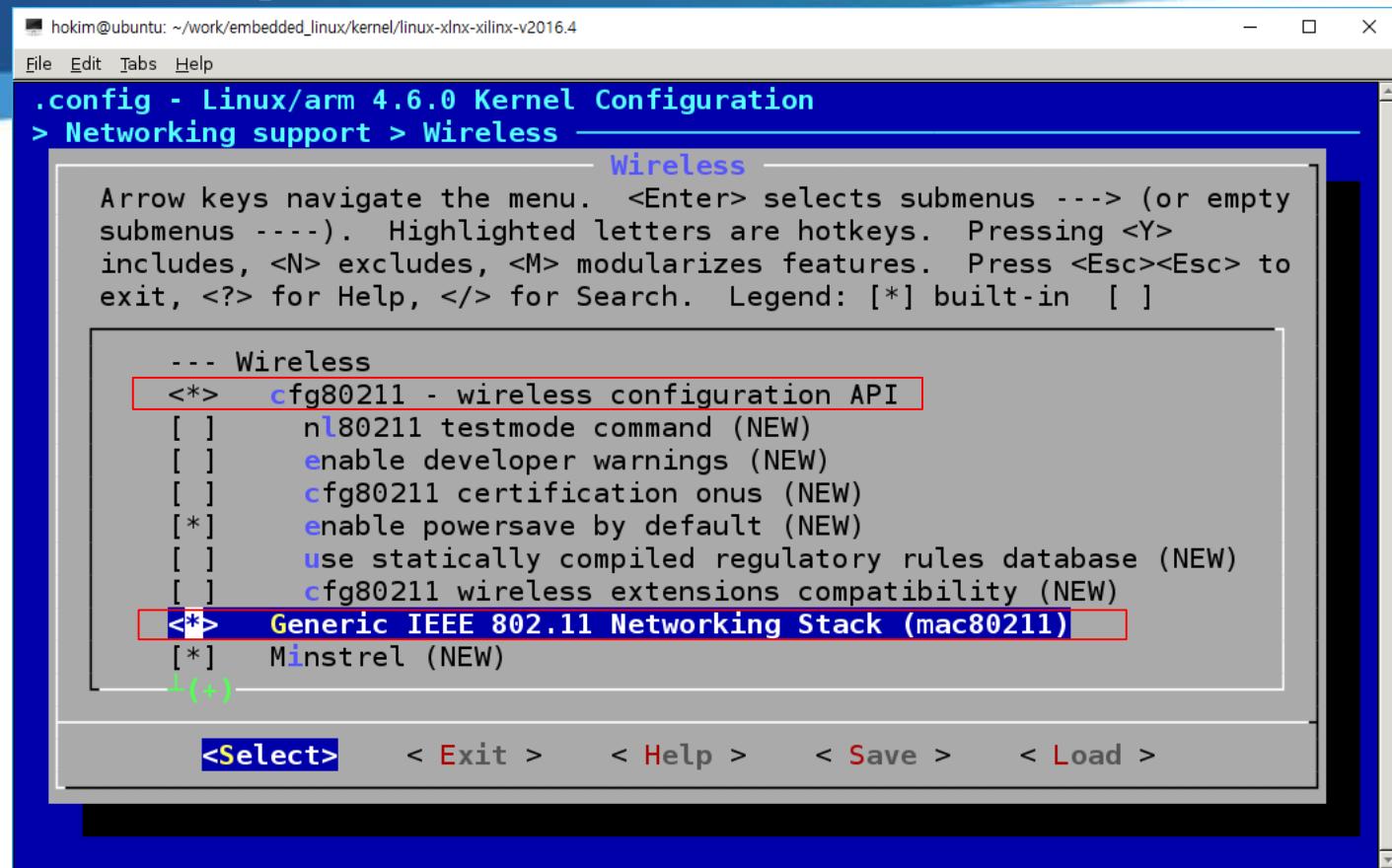
```
+/ {  
+    usb_phy0: phy0 {  
+        compatible = "ulpi-phy";  
+        #phy-cells = <0>;  
+        reg = <0xe0002000 0x1000>;  
+        view-port = <0x0170>;  
+        drv-vbus;  
+    };  
+};  
+&usb0 {  
+    usb-phy = <&usb_phy0>;  
+};
```

```
$ dtc -O dtb -I dts -i embedded_linux/embedded_linux.tree/ -o devicetree.dtb  
system.dts
```

```
$ cd ~/work/embedded_linux
$ wget https://github.com/Xilinx/linux-xlnx/archive/xilinx-v2016.4.tar.gz -O
dl/linux-xlnx-xilinx-v2016.4.tar.gz
$ cd kernel
$ tar xvzf ../dl/linux-xlnx-xilinx-v2016.4.tar.gz
$ cd linux-xlnx-xilinx-v2016.4
$ make ARCH=arm xilinx_zynq_defconfig
$ make ARCH=arm menuconfig
```



Linux Kernel Compile



Linux Kernel Compile

```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > Network device support > Wireless LAN
    └── Wireless LAN
        Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
        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 [ ]
        ^{(-)
            < >      Marvell 88W8xxx PCI/PCIe Wireless support (NEW)
            [*]      MediaTek devices
            < >      MediaTek MT7601U (USB) support (NEW)
            [*]      Ralink devices
            < >      Ralink driver support (NEW)    -----
            [*]      Realtek devices
            < >      Realtek 8180/8185/8187SE PCI support (NEW)
            < >      Realtek 8187 and 8187B USB support (NEW)
            < >      Realtek rtlwifi family of devices -----
            < >      RTL8723AU/RTL8188[CR]U/RTL819[12]CU (mac80211) support (N
        J{(+)
        <Select>   < Exit >   < Help >   < Save >   < Load >
```

```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers
    └── Device Drivers
        Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
        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 [ ]
        ^{(-)
            [*] DMA Engine support --->
            [ ] Auxiliary Display support -----
            <*> Userspace I/O drivers --->
            [ ] Virtualization drivers -----
            [ ] Virtio drivers --->
            Microsoft Hyper-V guest support -----
            [*] Staging drivers --->
            [ ] Platform support for Goldfish virtual devices -----
            [ ] Platform support for Chrome hardware -----
            [ ] Common Clock Framework --->
        L{(+)
        <Select>   < Exit >   < Help >   < Save >   < Load >
```

Linux Kernel Compile

```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > Staging drivers
Staging drivers
Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
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 [ ]
--- Staging drivers
< > Prism2.5/3 USB driver (NEW)
< > Data acquisition support (comedi) (NEW)
< > RealTek RTL8192U Wireless LAN NIC driver (NEW)
< > Support for rtllib wireless devices (NEW)
< > RealTek RTL8712U (RTL8192SU) Wireless LAN NIC driver (NEW)
<+> Realtek RTL8188EU Wireless LAN NIC driver
[*]   Realtek RTL8188EU AP mode (NEW)
< > Realtek PCI-E Card Reader RTS5208/5288 support (NEW)
< > VIA Technologies VT6655 support (NEW)
J{(+)

<Select> < Exit > < Help > < Save > < Load >
```

```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > SPI support
SPI support
Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
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 [ ]
^(-)
< > Rockchip SPI controller driver
< > NXP SC18IS602/602B/603 I2C to SPI bridge
< > Analog Devices AD-FMCOMMS1-EBZ SPI-I2C-bridge driver
<*> Xilinx SPI controller common module
<*> Xilinx Zynq QSPI controller
[ ]   Xilinx Zynq QSPI Dual stacked configuration
< > Xilinx ZynqMP GQSPI controller
*** SPI Protocol Masters ***
<+> User mode SPI device driver support
< > spi loopback test framework support
J{(+)

<Select> < Exit > < Help > < Save > < Load >
```

Linux Kernel Compile

```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > GPIO Support > Memory mapped GPIO drivers
    Memory mapped GPIO drivers
        Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
        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 [ ]
        ^(-)
        - *- Generic memory-mapped GPIO controller support (MMIO platform
        < > Aeroflex Gaisler GRGPIO support
        [ ] MPC512x/MPC8xxx/QoriQ GPIO support
        [ ] PrimeCell PL061 GPIO support
        < > GPIO based on SYSCON
        < > VIA VX855/VX875 GPIO
        <*> Xilinx GPIO support
            [ ] LSI ZEVIO SoC memory mapped GPIOs
            <*> Xilinx Zynq GPIO support
            [ ] ZTE ZX GPIO support
        <Select> < Exit > < Help > < Save > < Load >
```

```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > I2C support > I2C Hardware Bus support
    I2C Hardware Bus support
        Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
        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 [ ]
        ^(-)
        < > GPIO-based bitbanging I2C
        < > ST-Ericsson Nomadik/Ux500 I2C Controller
        < > OpenCores I2C Controller
        < > PCA9564/PCA9665 as platform device
        < > Rockchip RK3xxx I2C adapter
        < > Simtec Generic I2C interface
        < > ARM Versatile/Realview I2C bus support
        <*> Xilinx I2C Controller
            *** External I2C/SMBus adapter drivers ***
        < > Diolan U2C-12 USB adapter
        <(+>
        <Select> < Exit > < Help > < Save > < Load >
```

Linux Kernel Compile

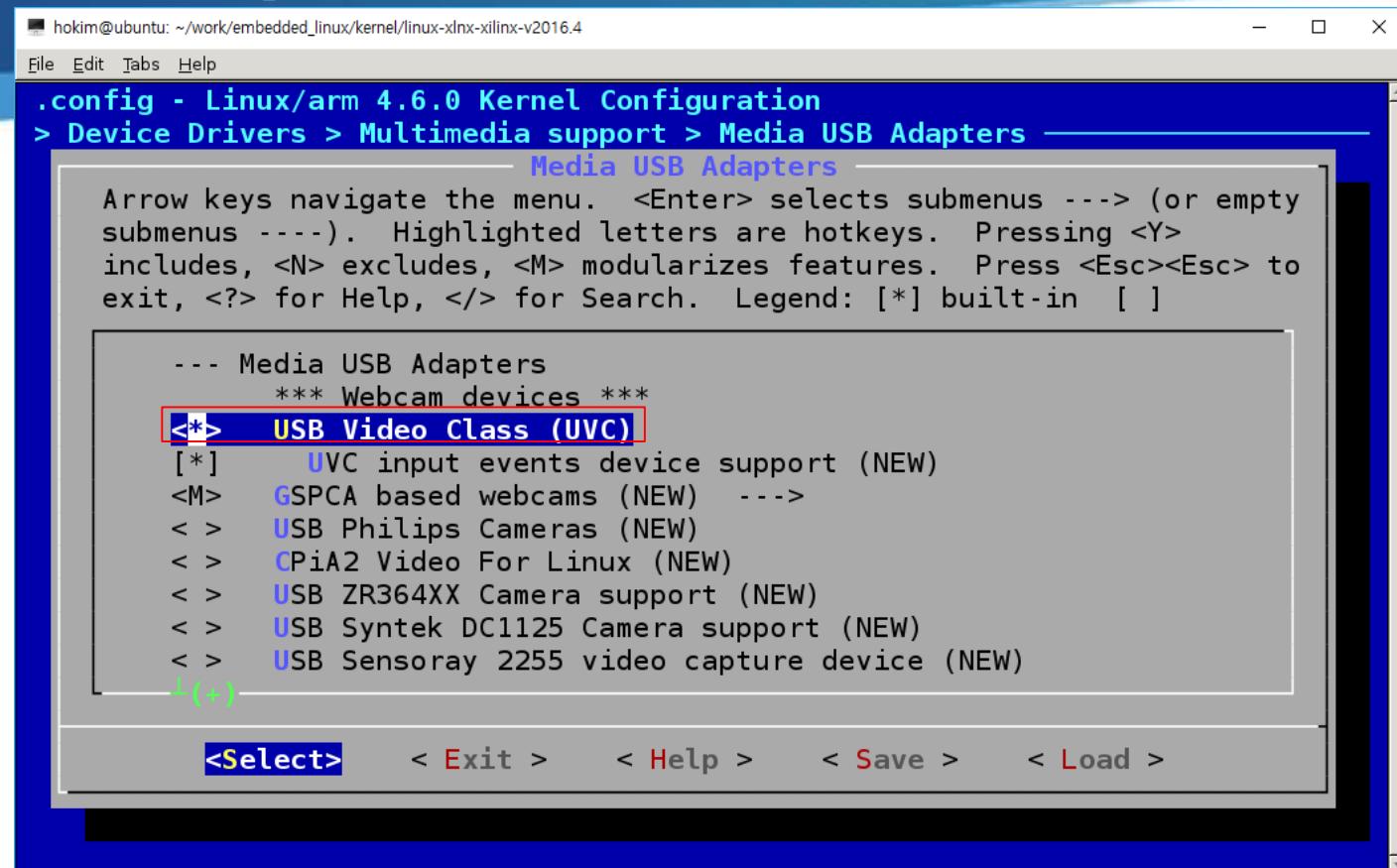
```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > Character devices > Serial drivers
    └── Serial drivers
        Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
        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 [ ]
< > 8250/16550 and compatible serial support
    *** Non-8250 serial port support ***
< > ARM AMBA PL010 serial port support
< > ARM AMBA PL011 serial port support
[ ] Early console using ARM semihosting
< > MAX3100 support
< > MAX310X support
[*] Xilinx uartlite serial port support
    [ ] Support for console on Xilinx uartlite serial port (NEW)
    < > Digi International NEO and Classic PCI Support
└{+}

<Select>  < Exit >  < Help >  < Save >  < Load >
```

```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > Multimedia support
    └── Multimedia support
        Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
        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 [ ]
^(-)
[ ] Software defined radio support
[ ] Remote Controller support
[*] Media Controller API
[ ] Enable Media controller for DVB (EXPERIMENTAL)
[*] V4L2 sub-device userspace API
[ ] Enable advanced debug functionality on V4L2 drivers
[ ] Enable old-style fixed minor ranges on drivers/video device
    *** Media drivers ***
[*] Media USB Adapters --->
[ ] Media PCI Adapters ----
└{+}

<Select>  < Exit >  < Help >  < Save >  < Load >
```

Linux Kernel Compile



```
$ make ARCH=arm CROSS_COMPILE=arm-linux-gnueabihf- CFLAGS="-O2  
-mtune=cortex-a9 -mfpu=neon -mfloat-abi=hard" -j $(nproc)  
UIMAGE_LOADADDR=0x8000 ulmage  
$ cp arch/arm/boot/ulmage ../../
```

Root File System Build

```
$ cd ~/work/embedded_linux  
$ sudo sh ./image.sh
```

image.sh

```
mkdir -p dl  
  
UBUNTU_URL=http://cdimage.ubuntu.com/ubuntu-base/releases/16.04/release  
UBUNTU=ubuntu-base-16.04-core-armhf.tar.gz  
if [ ! -f dl/$UBUNTU ]; then  
    wget $UBUNTU_URL/$UBUNTU -O dl/$UBUNTU  
fi  
  
ARCH=armhf  
SIZE=3500  
mkdir -p img  
IMAGE=img/ubuntu-core_${ARCH}_16.04.img  
dd if=/dev/zero of=$IMAGE bs=1M count=$SIZE  
DEVICE=$(losetup -f)  
losetup $DEVICE $IMAGE  
parted -s $DEVICE mklabel msdos  
parted -s $DEVICE mkpart primary fat16 4MB 128MB  
parted -s $DEVICE mkpart primary ext4 128MB 100%  
BOOT_DEV=/dev/$(lsblk -lno NAME $DEVICE | sed '2!d')  
ROOT_DEV=/dev/$(lsblk -lno NAME $DEVICE | sed '3!d')  
mkfs.vfat -v $BOOT_DEV  
mkfs.ext4 -F -j $ROOT_DEV  
ROOT_DIR=root  
mkdir -p $ROOT_DIR  
mount $ROOT_DEV $ROOT_DIR  
cd $ROOT_DIR  
tar xvf .../dl/$UBUNTU  
rm -fr boot  
cd ..
```

Root File System Build

image.sh

```
cat > $ROOT_DIR/etc/fstab << EOF_CAT
# /etc/fstab: static file system information.
# <file system> <mount point> <type> <options>          <dump> <pass>
/dev/mmcblk0p1 /boot      vfat  errors=remount-ro  0   0
/dev/mmcblk0p2 /        ext4   errors=remount-ro  0   1
EOF_CAT

cp /etc/resolv.conf      $ROOT_DIR/etc/
cp /usr/bin/qemu-arm-static $ROOT_DIR/usr/bin/
chroot $ROOT_DIR << EOF_CHROOT
sed -i 's/^# deb http://ports.ubuntu.com/ubuntu-ports/ xenial universe.*/deb http://ports.ubuntu.com/ubuntu-ports/
xenial universe/' /etc/apt/sources.list
sed -i 's/^# deb http://ports.ubuntu.com/ubuntu-ports/ xenial-updates universe.*/deb http://ports.ubuntu.com/ubuntu-
ports/ xenial-updates universe/' /etc/apt/sources.list
apt-get update
apt-get -y upgrade
DEBIAN_FRONTEND=noninteractive apt-get -y install lsb-release vim nano sudo openssh-server udev usbinits u-boot-tools
device-tree-compiler kmod net-tools wpa-supplicant parted rfkill lshw wireless-tools gcc g++ cmake python git i2c-tools iputils-
ping lxterminal leafpad linux-firmware
echo "Asia/Seoul" > /etc/timezone
ln -fs /usr/share/zoneinfo/Asia/Seoul /etc/localtime
locale-gen "en_US.UTF-8"
DEBIAN_FRONTEND=noninteractive dpkg-reconfigure locales
EOF_CHROOT
rm $ROOT_DIR/etc/resolv.conf
rm $ROOT_DIR/usr/bin/qemu-arm-static

mkdir -pv $ROOT_DIR/etc/systemd/system/serial-getty@ttyPS0.service.d
cat > $ROOT_DIR/etc/systemd/system/serial-getty@ttyPS0.service.d/autologin.conf << EOF_CAT
[Service]
ExecStart=
ExecStart=-/sbin/agetty --autologin root -s %I 115200,38400,9600 linux
EOF_CAT
umount -l $ROOT_DIR
rmdir $ROOT_DIR
losetup -d $DEVICE
```

using MobaXterm

Ubuntu	Windows
~/work/embedded_linux/ ulimage	C:\Users\hokim\work\embedded_linux
~/work/embedded_linux/vivado/ u-boot.elf, devicetree.dtb	C:\Users\hokim\work\embedded_linux\vivado
~/work/embedded_linux/img/ ubuntu-core_armhf_16.04.img	C:\Users\hokim\work

ubuntu-core_armhf_16.04.img
https://1drv.ms/u/s!AugbD-Nk6q_jhTrgintgtHWlbwl0



bootbin.tcl

```
# tclsh bootbin.tcl

set project_name embedded_linux

set fileId [open $project_name/boot.bif "w"]
puts $fileId "img:{\[bootloader\]} $project_name/$project_name.fsbl/executable.elf
$project_name/$project_name.runs/impl_1/system_wrapper.bit u-boot.elf}"
close $fileId

file delete -force boot.bin

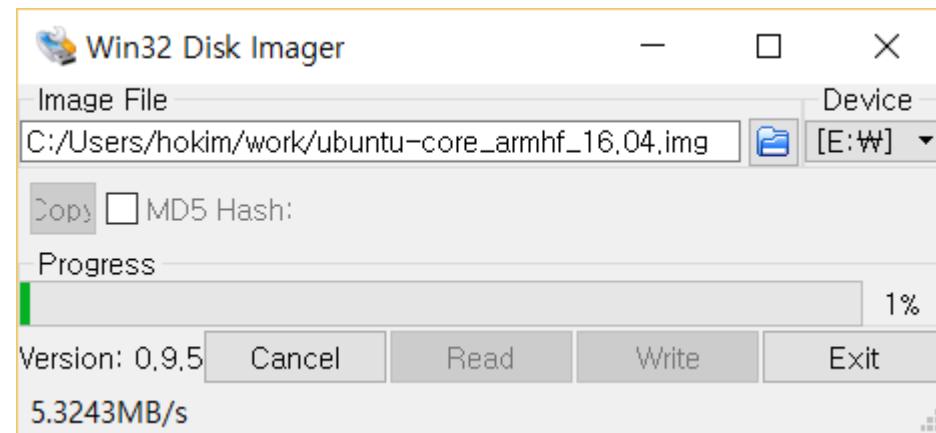
exec bootgen -image $project_name/boot.bif -w -o i boot.bin >&@stdout
```

In cmd window for Vivado

```
C:\> cd c:\Users\hokim\work\embedded_linux\vivado
C:\> tclsh bootbin.tcl
```

output : boot.bin

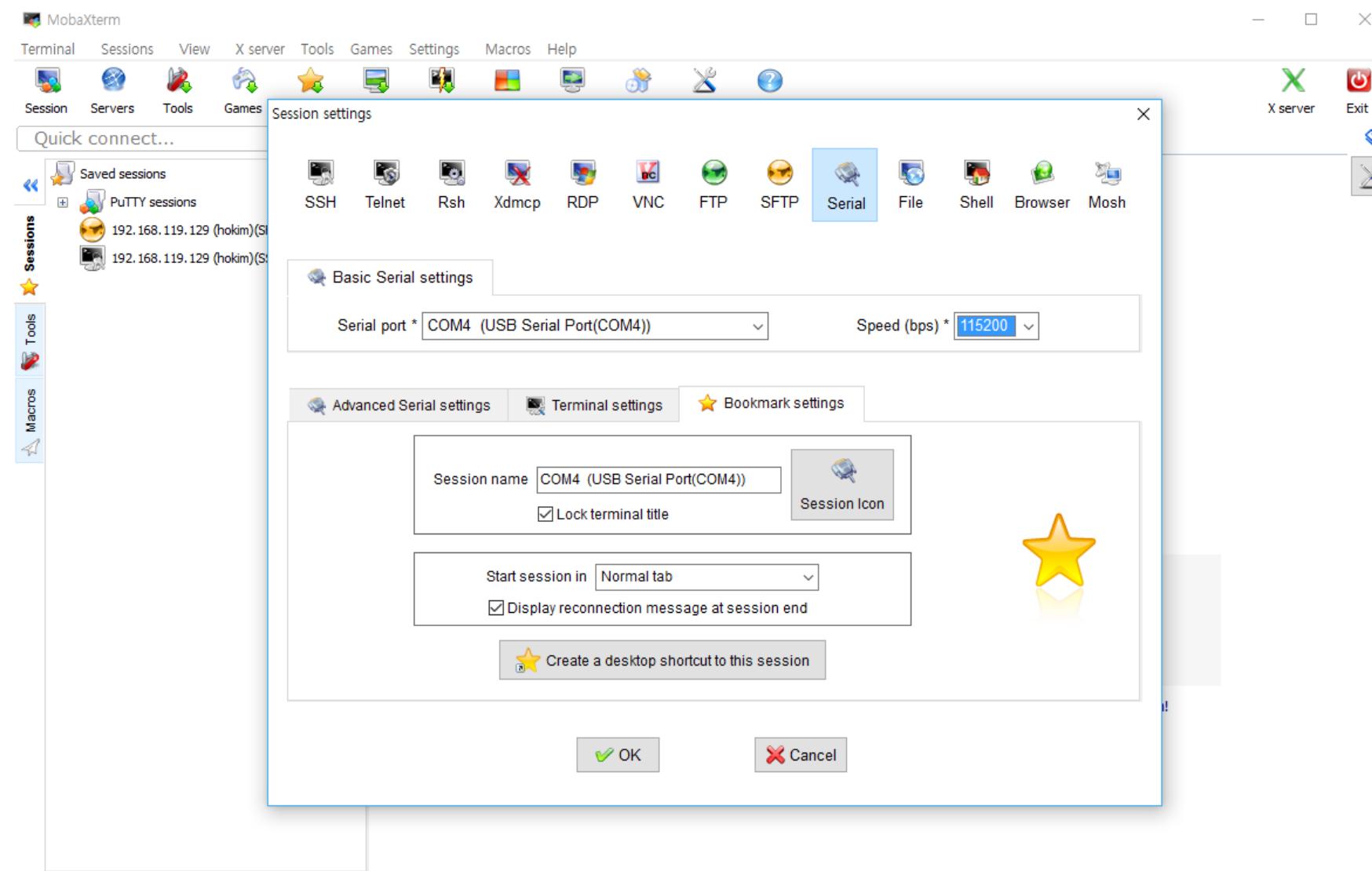
<https://sourceforge.net/projects/win32diskimager/>



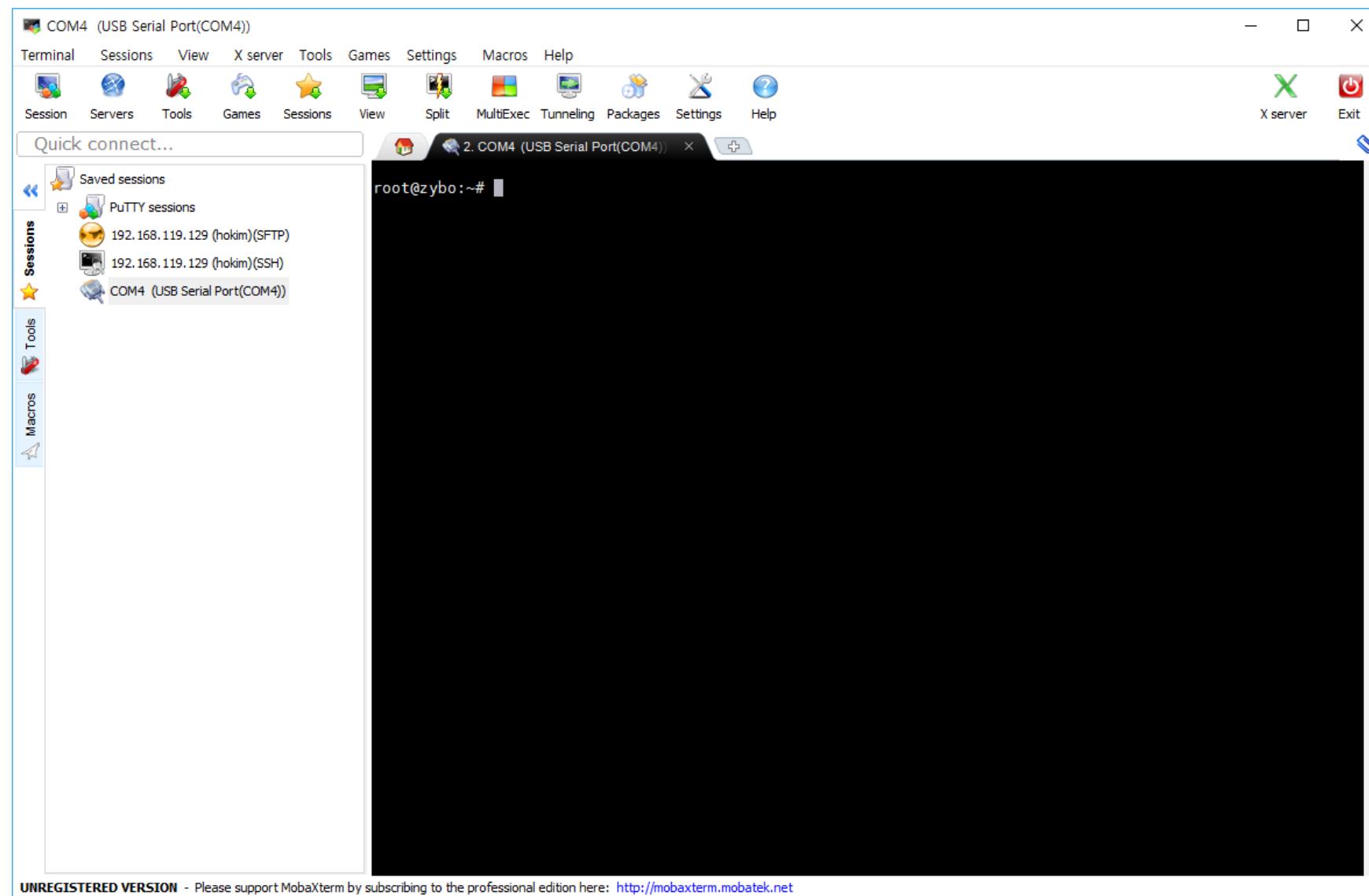
Copy
uImage, uEnv.txt,
vivado\boot.bin, vivado\devicetree.dtb
To E:

Boot zybo with SD card

Log in through UART console using MobaXterm



Log in through UART console using MobaXterm



```
# groupadd -g 1000 hokim
# groupadd -g 1001 admin
# useradd -u 1000 -g 1000 -G adm,dialout,cdrom,audio,dip,video,plugdev,admin
-d /home/hokim -m -s /bin/bash hokim
# passwd hokim
# nano /etc/network/interfaces.d/eth0
```

/etc/network/interfaces.d/eth0

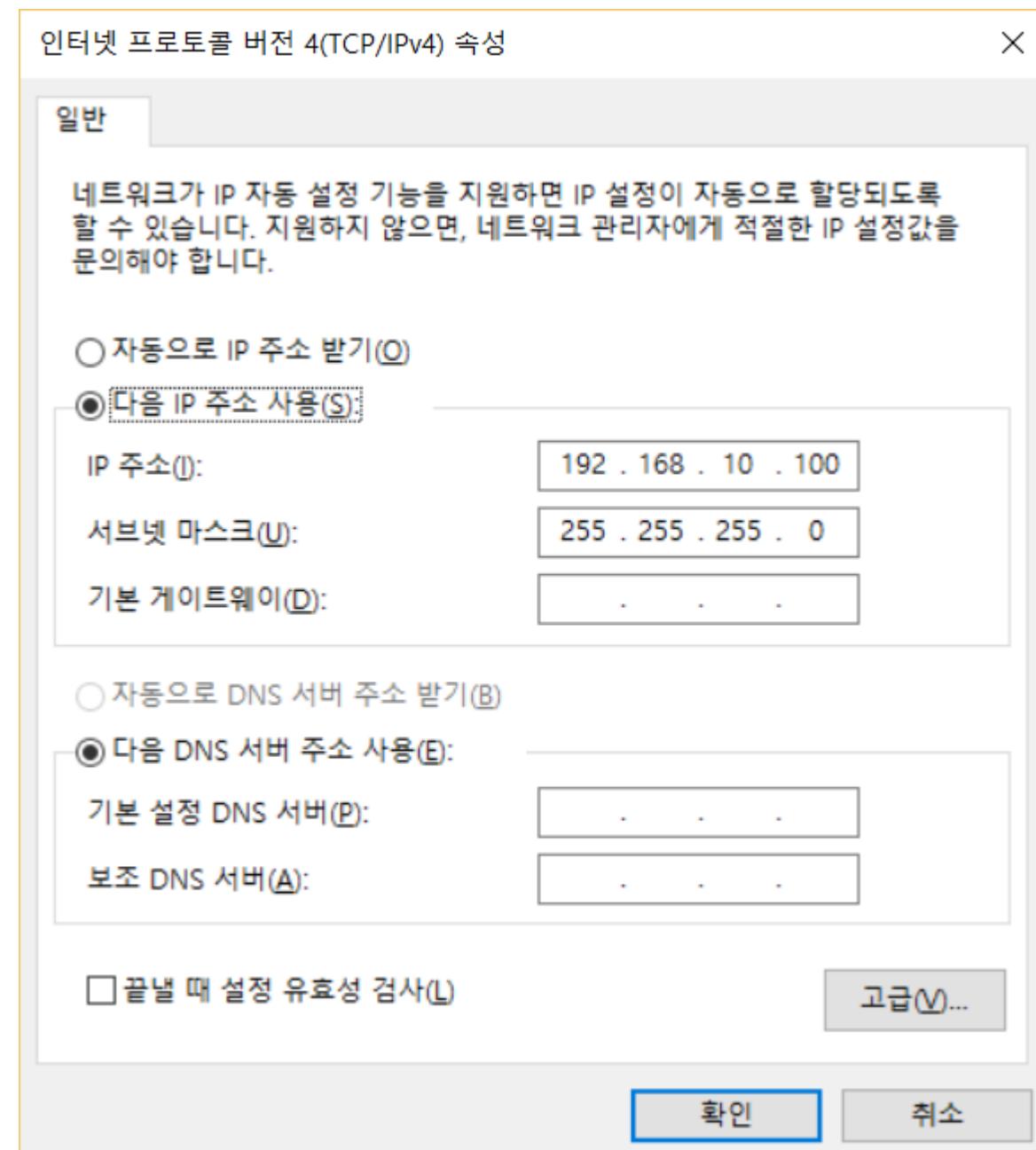
```
allow-hotplug eth0
iface eth0 inet static
address 192.168.10.10
netmask 255.255.255.0
```

```
# halt
```

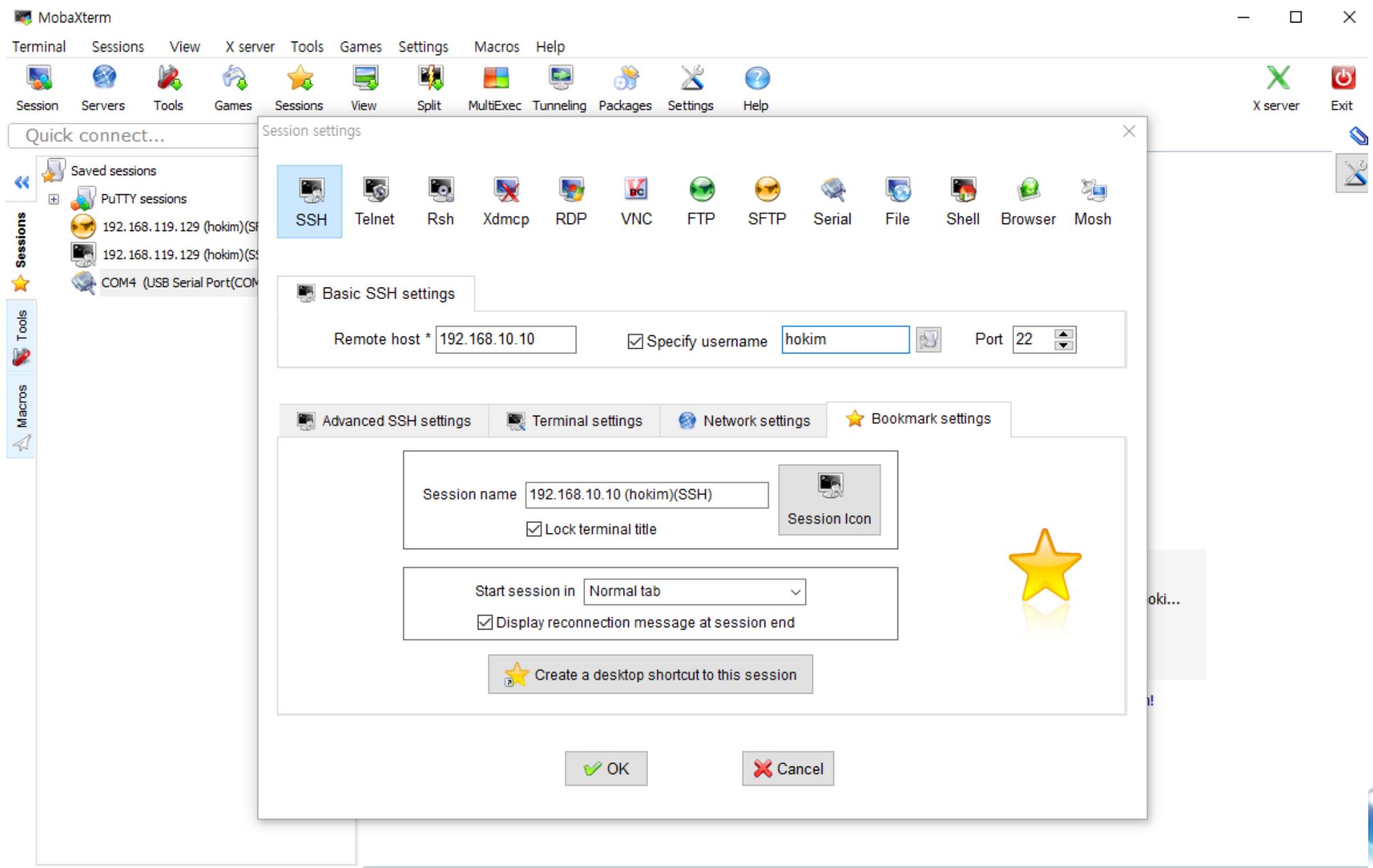
Turn off/on zybo



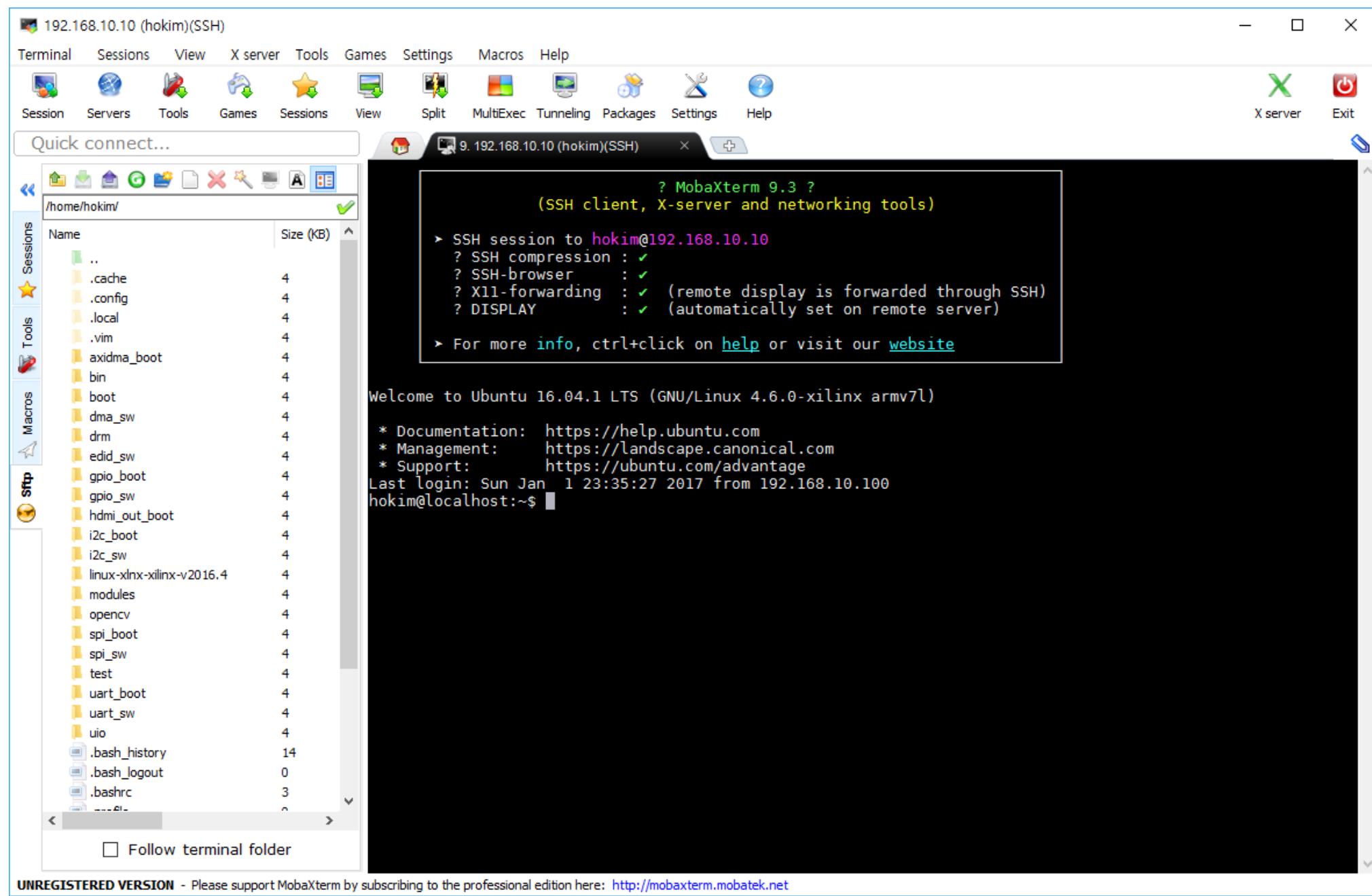
Log in through Ethernet using MobaXterm



Log in through Ethernet using MobaXterm



Log in through Ethernet using MobaXterm



```
$ sudo nano /etc/hostname
```

/etc/hostname

```
-localhost.localdomain  
+zybo
```

```
$ sudo nano /etc/hosts
```

/etc/hosts

```
127.0.0.1      localhost  
127.0.1.1      zybo  
  
# The following lines are desirable for IPv6 capable hosts  
::1            ip6-localhost ip6-loopback  
fe00::0        ip6-localnet  
ff00::0        ip6-mcastprefix  
ff02::1        ip6-allnodes  
ff02::2        ip6-allrouters
```

```
$ lsusb
```

```
Bus 001 Device 002: ID 0bda:8179 Realtek Semiconductor Corp. RTL8188EUS 802.11n Wireless Network Adapter  
Bus 001 Device 001: ID 1d6b:0002 Linux Foundation 2.0 root hub
```



```
$ sudo nano /etc/udev/rules.d/10-network.rules
```

```
/etc/udev/rules.d/10-network.rules
```

```
ACTION=="add", SUBSYSTEM=="net", ATTRS{idVendor}=="0bda", ATTRS{idProduct}=="8179", NAME="wlan0"
```

```
$ sudo nano /etc/network/interfaces.d/wlan0
```

```
/etc/network/interfaces.d/wlan0
```

```
allow-hotplug wlan0
iface wlan0 inet dhcp
    pre-up wpa_supplicant -B -D wext -i wlan0 -c /etc/wpa_supplicant.conf
    post-down killall -q wpa_supplicant
    udhcpc_opts -t7 -T3
```

```
$ sudo nano /etc/wpa_supplicant.conf
```

```
/etc/wpa_supplicant.conf
```

```
ctrl_interface=DIR=/var/run/wpa_supplicant GROUP=netdev
update_config=1
```

```
network={
    ssid="INIPRO"
    key_mgmt=WPA-PSK
    psk="20471047"
}
```



```
$ sudo halt
```

Turn off/on zybo

```
$ sudo -s  
# echo -e "d\n2\nw" | fdisk /dev/mmcblk0  
# parted -s /dev/mmcblk0 mkpart primary ext4 128M 100%  
# halt
```

Turn off / on zybo

Log in through Ethernet using putty

```
$ sudo resize2fs /dev/mmcblk0p2  
$ df -h
```

output:

Filesystem	Size	Used	Avail	Use%	Mounted on
/dev/root	7.0G	632M	6.0G	10%	/
devtmpfs	242M	0	242M	0%	/dev
tmpfs	250M	0	250M	0%	/dev/shm
tmpfs	250M	6.5M	244M	3%	/run
tmpfs	5.0M	0	5.0M	0%	/run/lock
tmpfs	250M	0	250M	0%	/sys/fs/cgroup
/dev/mmcblk0p1	118M	6.3M	112M	6%	/boot



```
$ ifconfig
```

```
eth0    Link encap:Ethernet HWaddr 00:0a:35:00:01:22
        inet addr:192.168.10.10 Bcast:192.168.10.255 Mask:255.255.255.0
              inet6 addr: fe80::20a:35ff:fe00:122/64 Scope:Link
                  UP BROADCAST RUNNING MULTICAST MTU:1500 Metric:1
                  RX packets:463 errors:0 dropped:0 overruns:0 frame:0
                  TX packets:300 errors:0 dropped:0 overruns:0 carrier:0
                  collisions:0 txqueuelen:1000
                  RX bytes:37295 (37.2 KB) TX bytes:39886 (39.8 KB)
                  Interrupt:145 Base address:0xb000

lo     Link encap:Local Loopback
        inet addr:127.0.0.1 Mask:255.0.0.0
              inet6 addr: ::1/128 Scope:Host
                  UP LOOPBACK RUNNING MTU:65536 Metric:1
                  RX packets:0 errors:0 dropped:0 overruns:0 frame:0
                  TX packets:0 errors:0 dropped:0 overruns:0 carrier:0
                  collisions:0 txqueuelen:1
                  RX bytes:0 (0.0 B) TX bytes:0 (0.0 B)

wlan0   Link encap:Ethernet HWaddr 00:e0:4c:15:44:d8
        inet addr:192.168.0.5 Bcast:192.168.0.255 Mask:255.255.255.0
              inet6 addr: fe80::2e0:4cff:fe15:44d8/64 Scope:Link
                  UP BROADCAST RUNNING MULTICAST MTU:1500 Metric:1
                  RX packets:960 errors:0 dropped:1808 overruns:0 frame:0
                  TX packets:26 errors:0 dropped:0 overruns:0 carrier:0
                  collisions:0 txqueuelen:1000
                  RX bytes:308669 (308.6 KB) TX bytes:3036 (3.0 KB)
```

- **Virtual memory management is a key aspect of Linux**

The Memory Management Unit(MMU) of the processor translates virtual address to physical addresses

- **Linux divides virtual memory into kernel space and user space**

Kernel space is the memory area for the kernel and device drivers

kernel space is the top 1 GB of memory, 0xC0000000 to 0xFFFFFFFF

User space is the memory area for user application software

User space is the bottom 3 GB of memory, 0 to 0xBFFFFFFF

Other kernel/user space memory configurations are configurable in the kernel such as 2 GB kernel and 2GB user space



- **Linux uses the processor modes to create privilege levels**

The kernel executes at a higher privilege level than user space code such that it can access any resources in the system

Applications execute at a lower privilege level such that they must use the kernel to get to the restricted resources in the system

- **Library functions run in user space and provide a more convenient interface for the programmer**

Linux applications require a C library to build which is provided by the tools

The Xilinx Linux GNU tools are based on the GNU C Library(glibc)

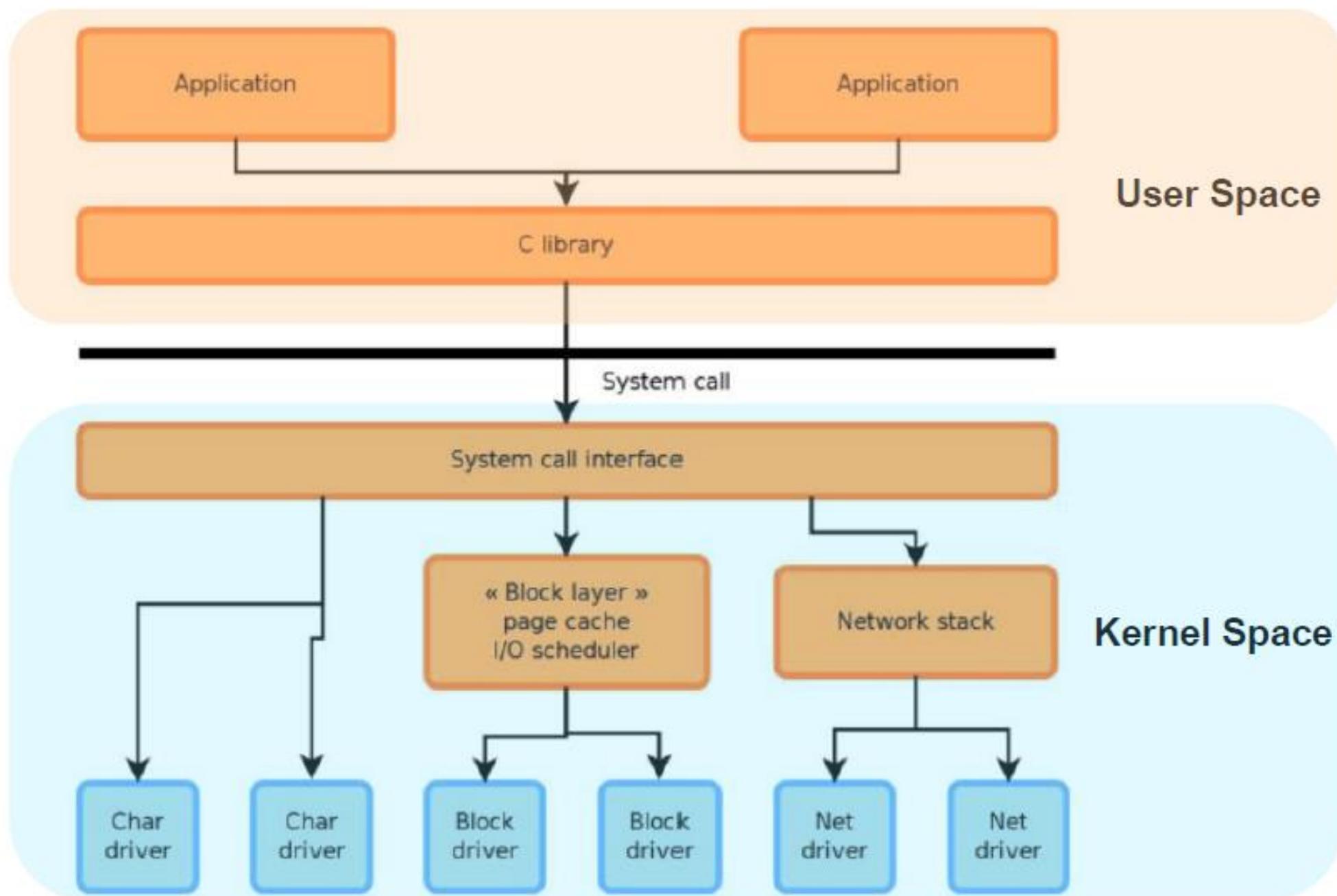
The Xilinx standalone GNU tools are based on newlib library rather than glibc

- **System calls run in kernel mode on the user's behalf and are provided by the kernel itself**



- A library function calls one or more system calls, and these system calls execute in supervisor mode since they are part of kernel itself
- Once the system call complete its task, it returns an execution is transferred back to user mode
- The user space application is typically blocked until the library function and system call return (just like a function call)
- System calls may interact with the kernel proper, or with specific drivers and frameworks of the kernel





- You don't have to be a kernel expert, but understanding some terms will help a lot
- The Linux Device model is built around the concept of buses, devices and drivers
- All devices in the system are connected to a bus of some kind
- A bus may be a software abstraction rather than a real bus
- Buses primarily exist to gather similar devices together and coordinate initialization, shutdown and power management
- When a device in the system is found to match a driver, they are bound together. The specifics about how to match devices and drivers are bus-specific



■ **Network devices**

These are represented as network interfaces, visible in userspace using the ifconfig utility

■ **Block devices**

These are used to provide userspace applications access to raw storage devices (hard disks, USB keys)

Visible to the applications as device files in /dev

■ **Character devices**

These are used to provide userspace applications access to all other types of devices (input, sound, graphics, serial, etc.)

They are also visible to the applications as device files in /dev

Many devices are character devices and a lot of user IP could be accessed as a character device



- Many device drivers are not directly implemented as character devices or block devices. They are implemented under a framework, specific to a device type (framebuffer, V4L, serial, etc.)
- The framework factors out the common parts of drivers for the same type of devices to reduce code duplication
- From userspace, many are still seen as normal character devices
- The frameworks provide a coherent userspace interface (ioctl numbering and semantics, etc.) for every type of device, regardless of the driver

The network framework of Linux provides a socket API such that an application can connect to a network using any network driver without knowing the details of the network driver

- sockfd = socket(AF_INET, SOCK_STREAM, 0)

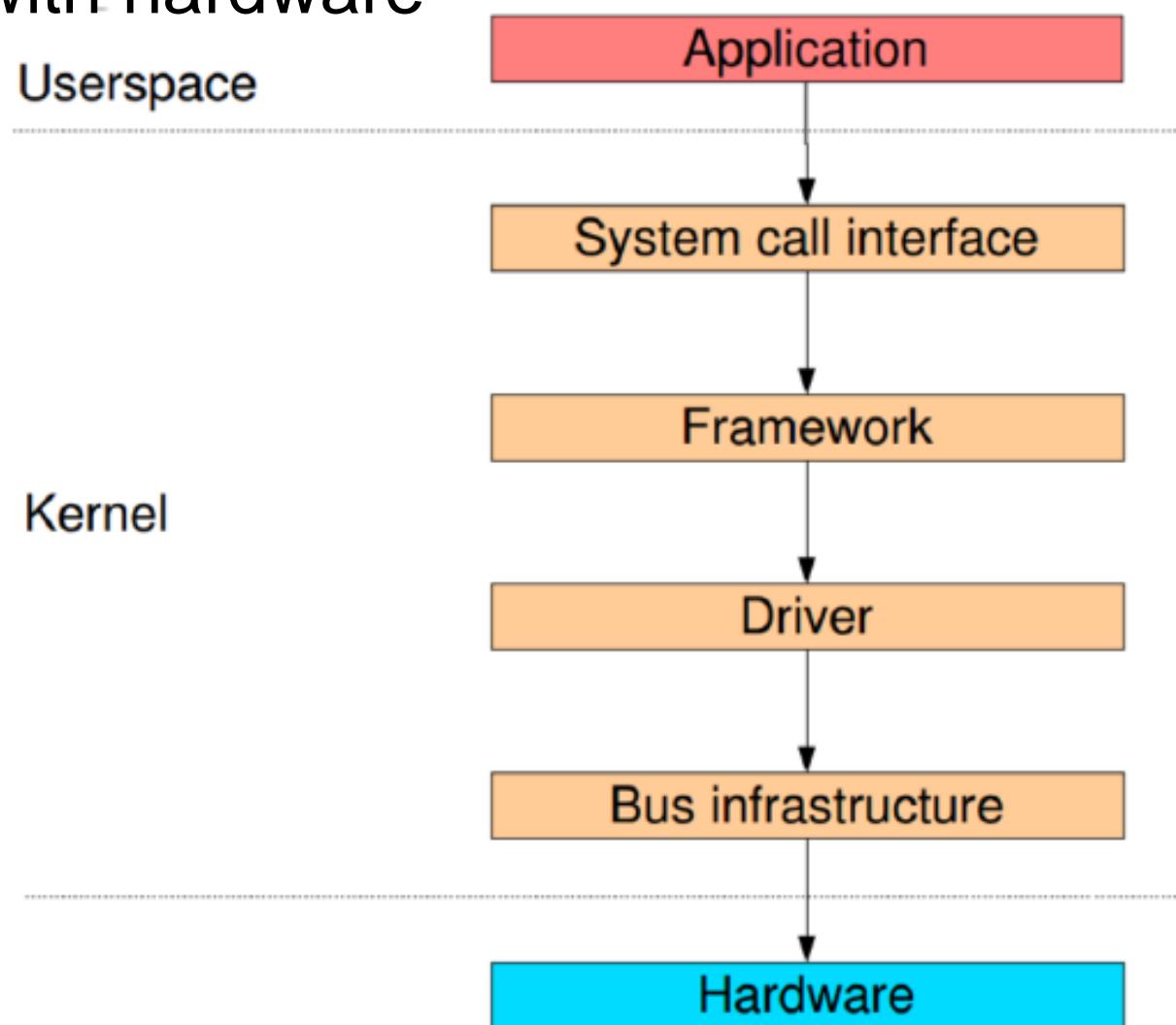


Linux Kernel Layers Focused on Frameworks

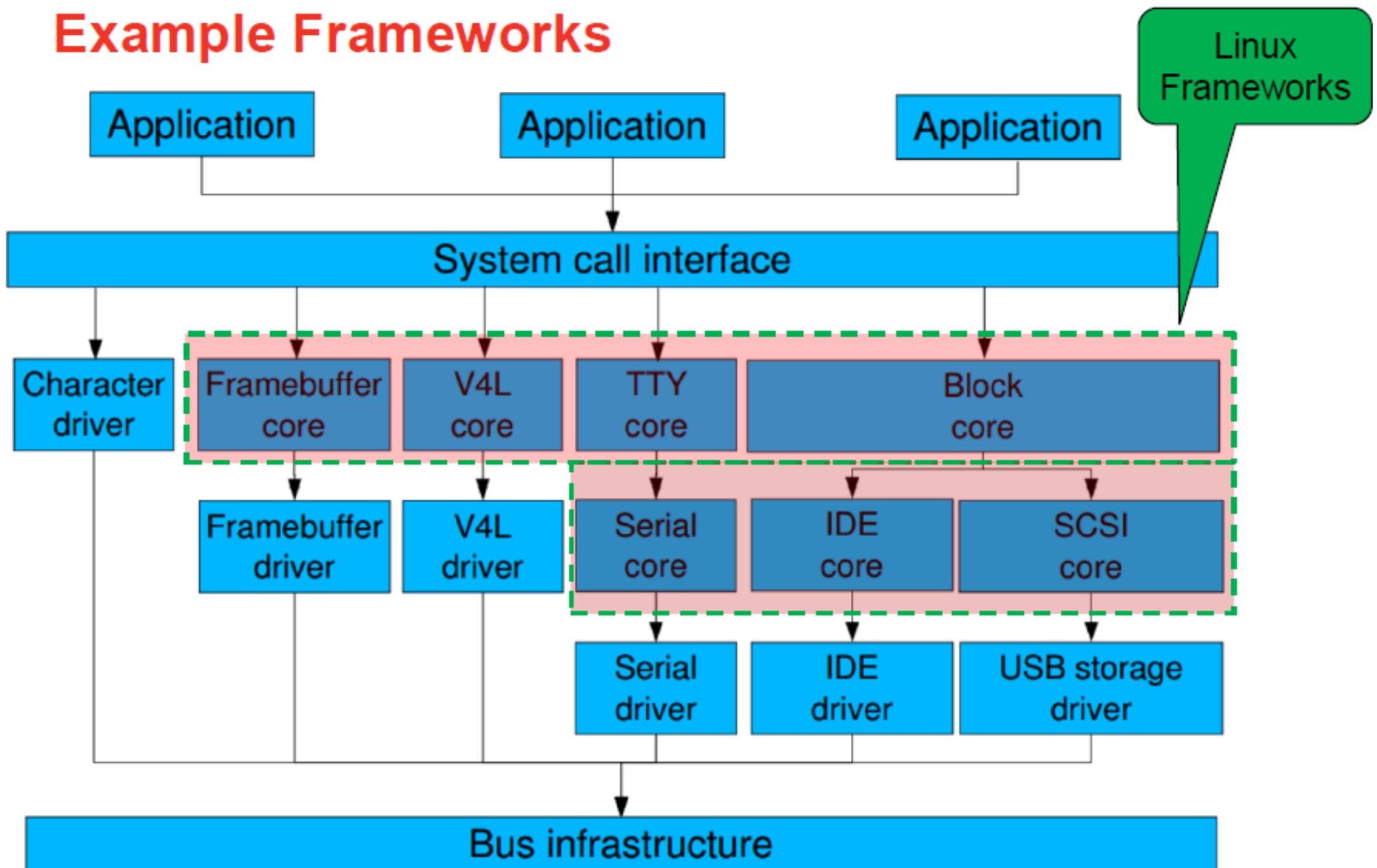
- A driver is always interfacing with:

- A framework that allows the driver to expose the hardware features to userspace applications

- A bus infrastructure (part of the device model), to detect /communicate with hardware



Example Frameworks



- **System and kernel information**

- Presented to user space application as virtual file systems

- Created dynamically and only exist in memory

- **Two virtual filesystems most known to users**

- proc, mounted on /proc, contains operating system related information (processes, memory management parameters...)

- This is an older mechanism that became somewhat chaotic

- sysfs, mounted on /sys, contains representation of the system as a set of devices and buses together with information about these devices

- This is the newer mechanism and is the preferred place to add system information



- **The `sysfs` virtual filesystem is a mechanism for the kernel to export operating details to user space**
- **The kernel exports the following items to userspace**
 - The bus, device, drivers, etc. structures internal to the kernel
 - `/sys/bus/` contains the list of buses
 - `/sys/devices/` contains the list of devices
 - `/sys/class/` enumerates devices by class (net, input, block...), whatever the bus they are connected to
- **Used for example by udev to provide automatic module loading, firmware loading, device file creation, etc.**



Device Tree In A Nutshell

- The principle of the Device Tree is to separate a large part of the hardware description from the kernel sources
- Device Tree allows a single kernel image to run on different boards with the differences being described in the device tree
- This mechanism takes its roots from OpenFirmware (OF) used on PowerPC platforms. This is why the “of” is part of some kernel functions.
- Device Tree is a tree of nodes that models the hierarchy of devices in the system, from the devices inside the processor to the devices on the board
- Each node can have a number of properties describing various properties of the devices: address, interrupts, clocks, etc.
- Written in a specialized language, the Device Tree source code is compiled into a Device Tree Blob by the Device Tree Compiler (DTC)

Device Tree In A Nutshell

- The DTC checks the device tree syntax but the semantics of the device tree are checked at runtime by the kernel and drivers
- At boot time, the kernel is given a compiled device tree, referred to as a Device Tree Blob, which is parsed to instantiate all the devices described in the device tree
- Device trees are located in the kernel tree at ~~arch/<arm or microblaze>/boot/dts~~ <https://github.com/Xilinx/device-tree-xlnx>
- The device tree compiler is part of the Linux kernel tree
- Some key properties in a device tree node, referred to as bindings

The `compatible` property is used to bind a device with a device driver

The `interrupts` property contains the interrupt number used by the device

The `reg` property contains the memory range used by the device

- There is limited documentation for the device tree bindings for each device such that driver code inspection may be necessary

The docs are in the kernel tree at Documentation/devicetree/bindings



Device Tree Details and A Simple Example



- A simple example below illustrates a node of device tree

An AMBA bus with GPIO that has registers mapped to 0x41200000 and is using interrupt 91

91 – 32 = 59, where 32 is the first Shared Peripheral Interrupt

The device is compatible with a driver containing a matching compatible string of “`xlnx,simple`”

The device driver source code may be the only way to really understand what properties it is expecting from the device tree

```
ps7_axi_interconnect_0: amba@0 {
    #address-cells = <1>;
    #size-cells = <1>;
    compatible = "xlnx,ps7-axi-interconnect-1.00.a", "simple-bus";
    ranges ;
    axi_gpio_0: gpio@41200000 {
        #gpio-cells = <2>;
        compatible = "xlnx,simple";
        gpio-controller ;
        interrupt-parent = <&ps7_scugic_0>;
        interrupts = <0 59 4>;
        reg = <0x41200000 0x10000>;
        xlnx,is-dual = <0x1>;
    };
};
```



Device Tree In A Nutshell

- The dtsi files are included files while the dts file is the final device tree
- A dts file includes dtsi files and the inclusion process works by overlaying the tree of the including file over the tree of the included file
- When properties are repeated in dtsi files the last one is the final
- The PL and PS are separate DTSI files while there is top level dts file that includes them
- The device tree compiler can be used to create the final device tree which is handy for debug (by specifying DTS input and output)



Device Tree – Inclusion Example

ps.dtsi (included file)

```
ps7_ttc_1: ps7-ttc@0xf8002000 {  
    clocks = <&clkc 6>;  
    compatible = "xlnx,ps7-ttc-1.00.a";  
    interrupt-parent = <&ps7_scugic_0>;  
    interrupts = <0 37 4>, <0 38 4>, <0 39 4>;  
    reg = <0xF8002000 0x1000>;  
    status = "disabled";  
};
```

system-top.dts (including file)

```
/include/ "ps.dtsi"  
  
&ps7_ttc_1 {  
    compatible = "xlnx,psttc", "generic-uio";  
    status = "okay";  
};
```

Note the “&” used to reference an existing node (rather than creating a new node)

```
ps7_ttc_1: ps7-ttc@0xf8002000 {  
    clocks = <&clkc 6>;  
    compatible = "xlnx,psttc", "generic-uio";  
    interrupt-parent = <&ps7_scugic_0>;  
    interrupts = <0 37 4>, <0 38 4>, <0 39 4>;  
    reg = <0xF8002000 0x1000>;  
    status = "okay";  
};
```

The result for the duplicated (red) properties is the same as the including file.

- General Purpose Input/Output
- Pin connection two electronic components (chips)
- Voltage is held at one of two level to indicate 1 or 0 logic
- Controlled by one chip, sensed by the other
- Usually grouped in banks
- Per GPIO pin configuration
- Configure pin direction mode to input or output
- Input mode

Sense the logic level

Interrupt source (asynchronous notification)

- Output mode

Set voltage logic level to 0 or 1



- Documented in Documentation/gpio.txt
- gpiolib framework
- Gpio drivers : drivers/gpio/(gpio-zynq.c, gpio-xilinx.c)
- GPIO control interface is via sysfs under /sys/class/gpio, and includes following control files:

export Make a specific GPIO pin available for userspace control. Write the pin number N (e.g. “55”, ASCII); the gpioN directory should appear.

unexport Make a specific GPIO pin unavailable. Write the pin number; the gpioN directory should disappear

gpioN/direction Write “in” or “out” to set pin direction

gpioN/value Read the current pin status in input. For output, write “0” or “1” to set the pin status.



Linux GPIO Userspace Interface

Kernel Configuration

```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > GPIO Support > Memory mapped GPIO drivers
    Memory mapped GPIO drivers
Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
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 [ ]
^(-)
- *- Generic memory-mapped GPIO controller support (MMIO platform
< > Aeroflex Gaisler GRGPIO support
[ ] MPC512x/MPC8xxx/QorIQ GPIO support
[ ] PrimeCell PL061 GPIO support
< > GPIO based on SYSCON
< > VIA VX855/VX875 GPIO
<*> Xilinx GPIO support
[ ] LSI ZEVIO SoC memory mapped GPIOs
<*> Xilinx Zynq GPIO support
[ ] ZTE ZX GPIO support

<Select> < Exit > < Help > < Save > < Load >
```

```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > GPIO Support
    GPIO Support
Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
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 [ ]
--- GPIO Support
[ ] Debug GPIO calls
[*] /sys/class/gpio/... (sysfs interface)
    Memory mapped GPIO drivers --->
        I2C GPIO expanders --->
        MFD GPIO expanders ----
        PCI GPIO expanders --->
        SPI GPIO expanders --->
        SPI or I2C GPIO expanders --->
        USB GPIO expanders ----

<Select> < Exit > < Help > < Save > < Load >
```

Linux GPIO Userspace Interface

gpio_sw/driver/gpio.c

```
#include <fcntl.h>
#include <stdio.h>
#include <string.h>
#include <stdlib.h>
#include <unistd.h>

#include "gpio.h"

int setGpio(unsigned int index, const char *direction){
    int fd;
    char buf[50];
    sprintf(buf, "/sys/class/gpio/gpio%d/direction", index);
    if(access(buf, F_OK) != -1)
        unsetGpio(index);
    if((fd = open("/sys/class/gpio/export", O_WRONLY)) == -1)
        return -1;
    sprintf(buf, "%d", index);
    if(write(fd, buf, strlen(buf)) == -1)
        return -1;
    close(fd);

    sprintf(buf, "/sys/class/gpio/gpio%d/direction", index);
    if((fd = open(buf, O_WRONLY)) == -1)
        return -1;
    if(write(fd, direction, strlen(direction)) == -1)
        return -1;
    close(fd);
    return 0;
}
```

```
int unsetGpio(unsigned int index){
    int fd;
    char buf[50];
    if((fd = open("/sys/class/gpio/unexport", O_WRONLY)) == -1)
        return -1;
    sprintf(buf, "%d", index);
    if(write(fd, buf, strlen(buf)) == -1)
        return -1;
    close(fd);
    return 0;
}

int writeGpio(unsigned int index, int value){
    int fd;
    char buf[50];
    sprintf(buf, "/sys/class/gpio/gpio%d/value", index);
    if((fd = open(buf, O_WRONLY)) == -1)
        return -1;
    sprintf(buf, "%d", value);
    if(write(fd, buf, strlen(buf)) == -1)
        return -1;
    close(fd);
    return 0;
}

int readGpio(unsigned int index){
    int fd;
    char buf[50];
    sprintf(buf, "/sys/class/gpio/gpio%d/value", index);
    if((fd = open(buf, O_RDONLY)) == -1)
        return -1;
    if(read(fd, buf, 10) == -1)
        return -1;
    close(fd);
    return atoi(buf);
}
```

Legacy UserSpace Driver Methods

(/dev/mem)

- A character driver referred to as `/dev/mem` exists in the kernel that will map device memory into userspace
- With this driver userspace applications can access device memory
- Must be root user
- A great tool for prototyping or maybe testing new hardware, but is not considered to be an acceptable production solution for a userspace device driver
- Since it can map any address into userspace, a buggy userspace driver could crash the kernel



Linux GPIO Userspace Interface



gpio_sw/mmap/main.c

```
#include <stdio.h>
#include <stdint.h>
#include <unistd.h>
#include <fcntl.h>
#include <sys/mman.h>
#include <signal.h>
#include "xgpio.h"

XGpio_Config XGpio_ConfigTable[3] = {
    { 0, 0, 1, 0 },
    { 1, 0, 1, 0 },
    { 2, 0, 1, 0 }
};

static int loop_exit;

void sig_handler(int signo)
{
    if (signo == SIGINT)
        loop_exit = 1;
}

int main()
{
    int fd;
    uint32_t btns, leds, sws;

    if ((fd = open("/dev/mem", O_RDWR)) < 0)
    {
        perror("open");
        return 1;
    }
```

```
        btns = (uint32_t)mmap(NULL, sysconf(_SC_PAGESIZE),
PROT_READ|PROT_WRITE, MAP_SHARED, fd, 0x40001000);
        leds = (uint32_t)mmap(NULL, sysconf(_SC_PAGESIZE),
PROT_READ|PROT_WRITE, MAP_SHARED, fd, 0x40000000);
        sws = (uint32_t)mmap(NULL, sysconf(_SC_PAGESIZE),
PROT_READ|PROT_WRITE, MAP_SHARED, fd, 0x40002000);

        XGpio_ConfigTable[0].BaseAddress = btns;
        XGpio_ConfigTable[1].BaseAddress = leds;
        XGpio_ConfigTable[2].BaseAddress = sws;

        if (signal(SIGINT, sig_handler) == SIG_ERR) {
            fprintf(stderr, "can't catch SIGINT\n");
            return 1;
        }

        XGpio Gpio;
        int Status;
        Status = XGpio_Initialize(&Gpio, 1);
        if (Status != XST_SUCCESS) {
            return XST_FAILURE;
        }

        loop_exit = 0;
        while (1) {
            XGpio_DiscreteWrite(&Gpio, 1, 0xF);
            sleep(1);
            XGpio_DiscreteWrite(&Gpio, 1, 0x0);
            sleep(1);
            if (loop_exit == 1) break;
        }

        munmap((void*)btns, sysconf(_SC_PAGESIZE));
        munmap((void*)leds, sysconf(_SC_PAGESIZE));
        munmap((void*)sws, sysconf(_SC_PAGESIZE));
        close(fd);
        return 0;
    }
```

Zynq7 PS Re-customize IP for GPIO



Based on Zynq7 PS Re-customize IP of embedded_linux project

Re-customize IP

ZYNQ7 Processing System (5.5)

Documentation Presets IP Location Import XPS Settings Summary Report

Page Navigator <>

Zynq Block Design

PS-PL Configuration

Peripheral I/O Pins

Search:

Bank 0 LVC MOS 3,3V Bank 1 LVC MOS 1,8V

Peripherals

- Quad SPI Flash
- SRAM/NOR Flash
- NAND Flash
- Ethernet 0 (checked)
- Ethernet 1
- USB 0 (checked)
- USB 1
- SD 0 (checked)
- SD 1
- SPI 0
- SPI 1
- UART 0
- UART 1 (checked)
- I2C 0 (checked)
- I2C 1
- CAN 0
- CAN 1
- TTC0
- TTC1
- SWDT
- PJTAG
- TPIU
- GPIO MIO (checked)
- GPIO FMI0

Bank 0: Quad SPI Flash, SRAM/NOR Flash, NAND Flash, Enet0, Enet1, USBO, SD0, SD1, SPI1, UART0, UART1, I2C0, I2C1, CAN0, CAN1, TTC0, SWDT, PJTAG, Trace.

Bank 1: SRAM/NOR Flash, addr[0-24], NAND Flash, Enet0, Enet1, USBO, SD0, SD1, SPI1, UART0, UART1, I2C0, I2C1, CAN0, CAN1, TTC0, SWDT, PJTAG, Trace.

EMIO: Ethernet, USB, SD, SPI, UART, I2C, CAN, TTC, SWDT, PJTAG.

OK Cancel

The screenshot shows the Zynq7 PS Re-customize IP software interface. The main window displays a grid of pins from 0 to 53, categorized by peripheral components like Quad SPI Flash, SRAM/NOR Flash, NAND Flash, Ethernet, USB, SD, SPI, UART, I2C, CAN, TTC, SWDT, and PJTAG. The left sidebar lists these peripherals with checkboxes. Two specific rows of pins, pin 0-16 and pin 45-53, are circled in red at the bottom of the grid, indicating they are selected for re-customization. The top menu bar includes options like Documentation, Presets, IP Location, Import XPS Settings, and a Summary Report. The bottom right features OK and Cancel buttons.

Zynq7 PS Re-customize IP for GPIO



Based on Zynq7 PS Re-customize IP of embedded_linux project

Re-customize IP

ZYNQ7 Processing System (5.5)

Documentation Presets IP Location Import XPS Settings

Page Navigator <>

Zynq Block Design

PS-PL Configuration

Peripheral I/O Pins

MIO Configuration

Clock Configuration

DDR Configuration

SMC Timing Calculation

Interrupts

MIO Configuration

Bank 0 I/O Voltage LVCMS 3,3V Bank 1 I/O Voltage LVCMS 1,8V

Search:

Peripheral	IO	Signal	IO Type	Speed	Pullup	Direction	Polarity
GPIO							
GPIO MIO	MIO	gpio[0]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 0	gpio[1]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 1	gpio[2]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 2	gpio[3]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 3	gpio[4]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 4	gpio[5]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 5	gpio[6]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 6	gpio[7]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 7	gpio[8]	LVCMS 3,3V	slow	disabled	out	
GPIO	MIO 8	gpio[9]	LVCMS 3,3V	slow	disabled	out	
GPIO	MIO 9	gpio[10]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 10	gpio[11]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 11	gpio[12]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 12	gpio[13]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 13	gpio[14]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 14	gpio[15]	LVCMS 3,3V	slow	disabled	inout	
GPIO	MIO 46	gpio[46]	LVCMS 1,8V	slow	disabled	inout	
GPIO	MIO 47	gpio[47]	LVCMS 1,8V	slow	disabled	inout	
GPIO	MIO 50	gpio[50]	LVCMS 1,8V	slow	disabled	inout	
GPIO	MIO 51	gpio[51]	LVCMS 1,8V	slow	disabled	inout	
EMIO GPIO (Width)							

OK Cancel

Zynq7 PS Re-customize IP for GPIO



Based on Zynq7 PS Re-customize IP of embedded_linux project

Re-customize IP

ZYNQ7 Processing System (5.5)

Documentation Presets IP Location Import XPS Settings

Page Navigator <> Zynq Block Design

PS-PL Configuration

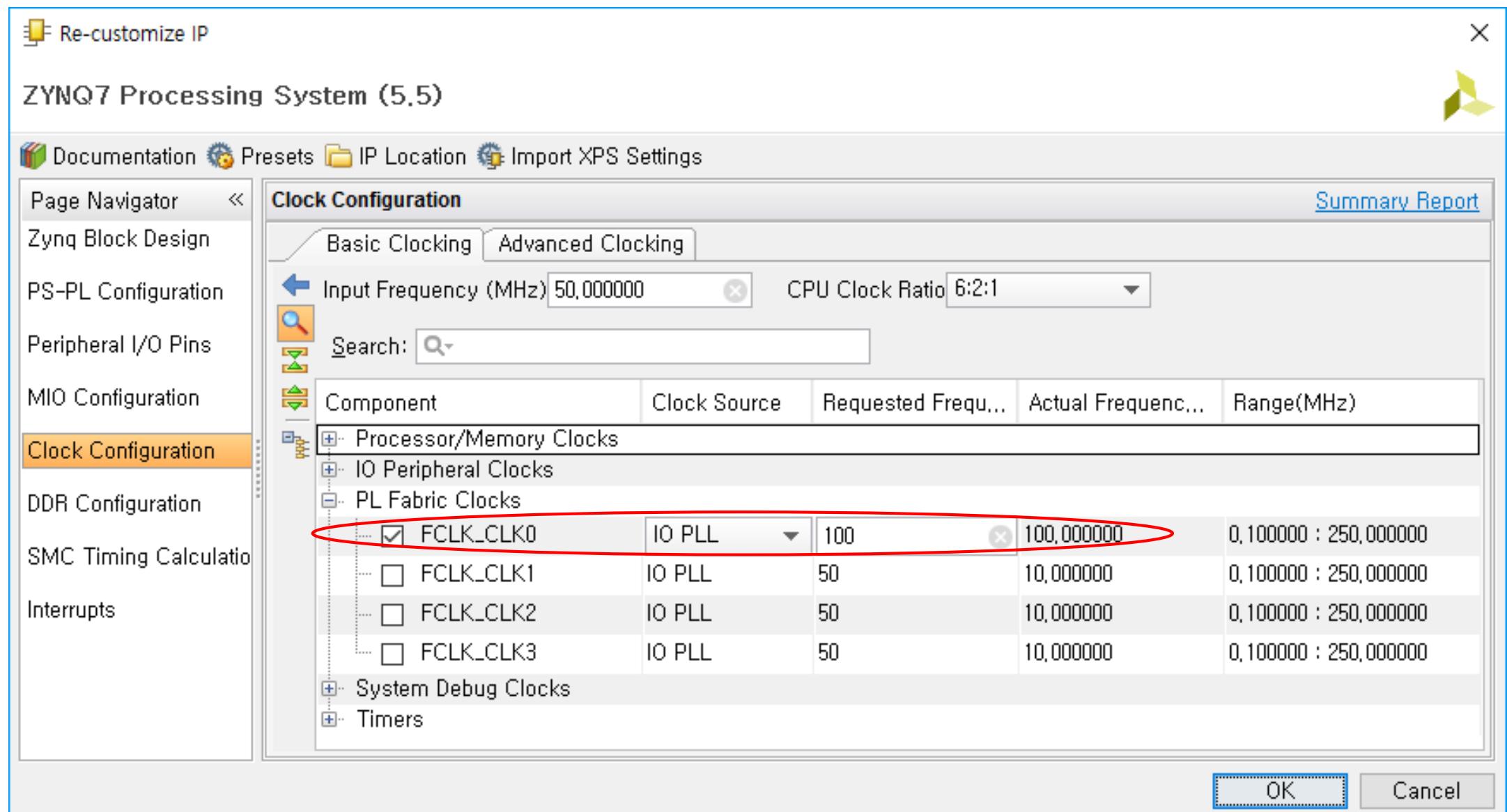
Search:

Name	Select	Description
General		
- UART0 Baud Rate	115200	Baud rate is generated with internally fixed UART Ref Clock Freq=10...
- UART1 Baud Rate	115200	Baud rate is generated with internally fixed UART Ref Clock Freq=10...
- PL AXI idle Port	<input type="checkbox"/>	Enables idle AXI signal to the PS used to indicate that there are no ...
- DDR ARB bypass Port	<input type="checkbox"/>	Enables DDR urgent/arbitration signal used to signal a critical memory sta...
- PS-PL Debug interface	<input type="checkbox"/>	Enables PL debug signals to PS and vice-versa
- FTM Trace data interface	<input type="checkbox"/>	Enables FTM Trace AXI stream interface used to capture data from PL ... to PS debug system
- FTM Trace buffer	0	Stores trace data in the FIFO when the data changes as marked by ...
- FTM Data edge detector	0	FTM Trace buffer FIFO size
- FTM Trace buffer FIFO size	128	Number of clock cycles interval for a trace data output from FIFO be...
- FTM Trace buffer clock delay	12	Number of clock cycles interval for a trace data output from FIFO be...
- Include ACP transaction checker	<input type="checkbox"/>	Enables ACP transaction checker.
- Trace data/control signal pipeline width	8	Enables configurable number of pipeline stages on the TRACE DAT...
- Power-on reset(POR) 4k timer	<input type="checkbox"/>	Enables power-on reset(POR) 4k timer. By default, 64k timer is used.
- Processor event interface	<input type="checkbox"/>	Enables event bus which provides a low-latency and direct mecha...
- Address Editor		
- Enable Clock Triggers		
- Enable Clock Resets		
- FCLK_RESET0_N	<input checked="" type="checkbox"/>	Enables general purpose reset signal 0 for PL logic
- FCLK_RESET1_N	<input type="checkbox"/>	Enables general purpose reset signal 1 for PL logic
- FCLK_RESET2_N	<input type="checkbox"/>	Enables general purpose reset signal 2 for PL logic
- FCLK_RESET3_N	<input type="checkbox"/>	Enables general purpose reset signal 3 for PL logic
- AXI Non Secure Enablement	0	Enable AXI Non Secure Transaction
- GP Master AXI Interface		
- M AXI GP0 interface	<input checked="" type="checkbox"/>	Enables General purpose AXI master interface 0
- M AXI GP1 interface	<input type="checkbox"/>	Enables General purpose AXI master interface 1
- GP Slave AXI Interface		

OK Cancel

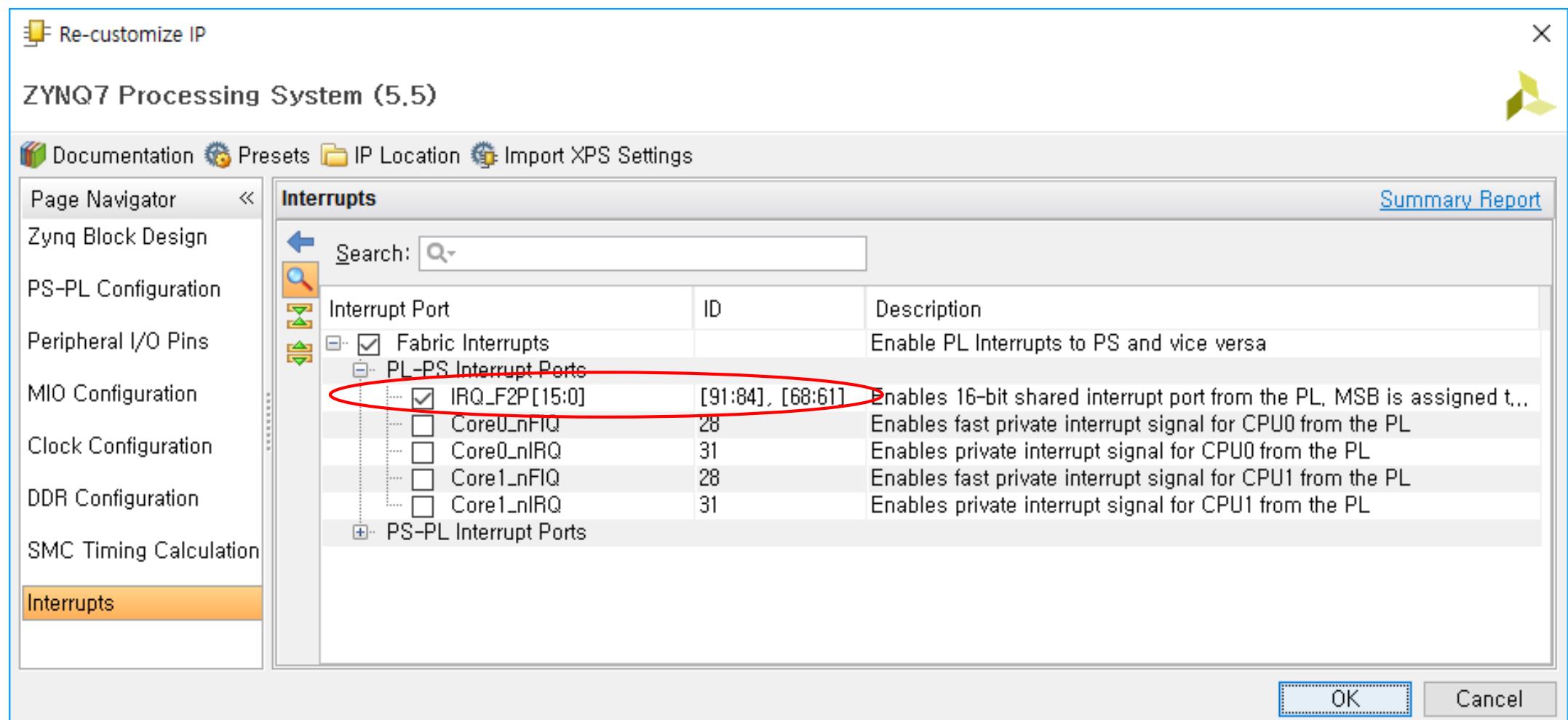
Zynq7 PS Re-customize IP for GPIO

Based on Zynq7 PS Re-customize IP of embedded_linux project



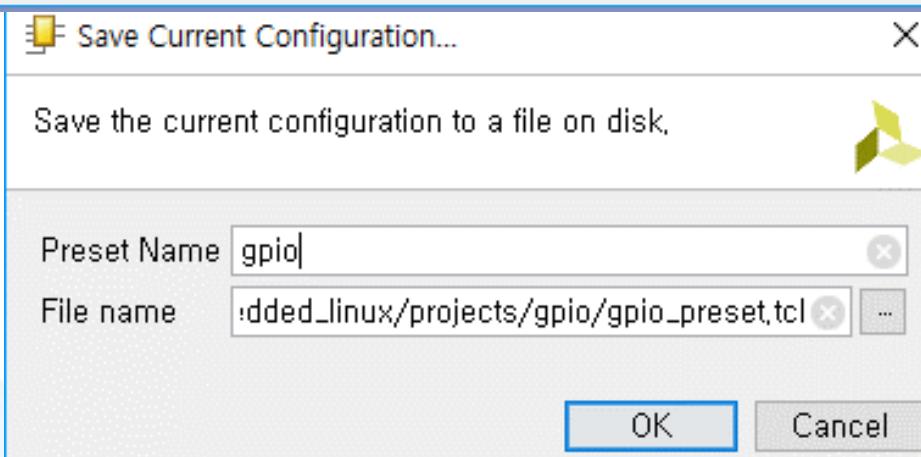
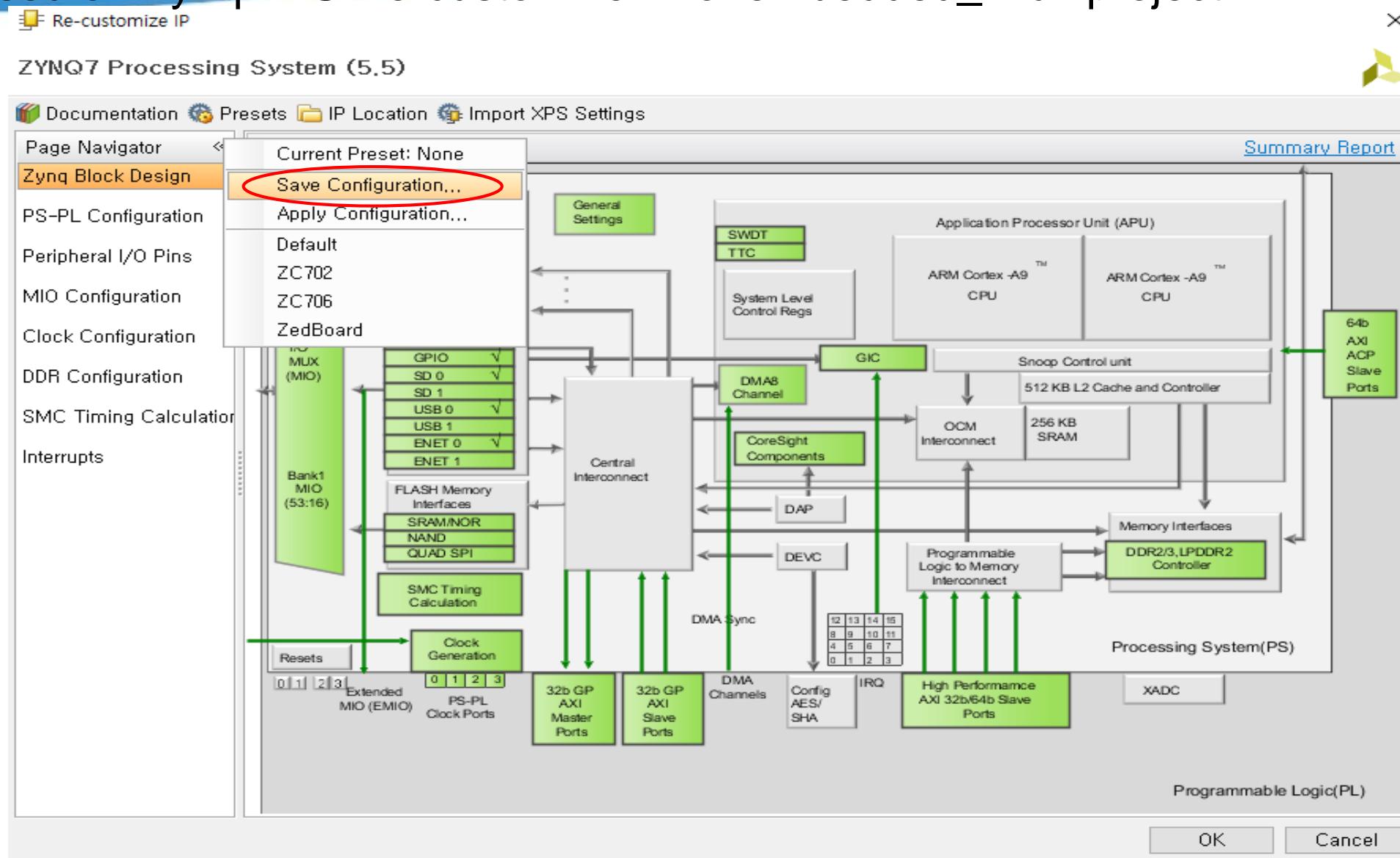
Zynq7 PS Re-customize IP for GPIO

Based on Zynq7 PS Re-customize IP of embedded_linux project



Zynq7 PS Re-customize IP for GPIO

Based on Zynq7 PS Re-customize IP of embedded_linux project



https://github.com/inipro/embedded_linux/projects/gpio

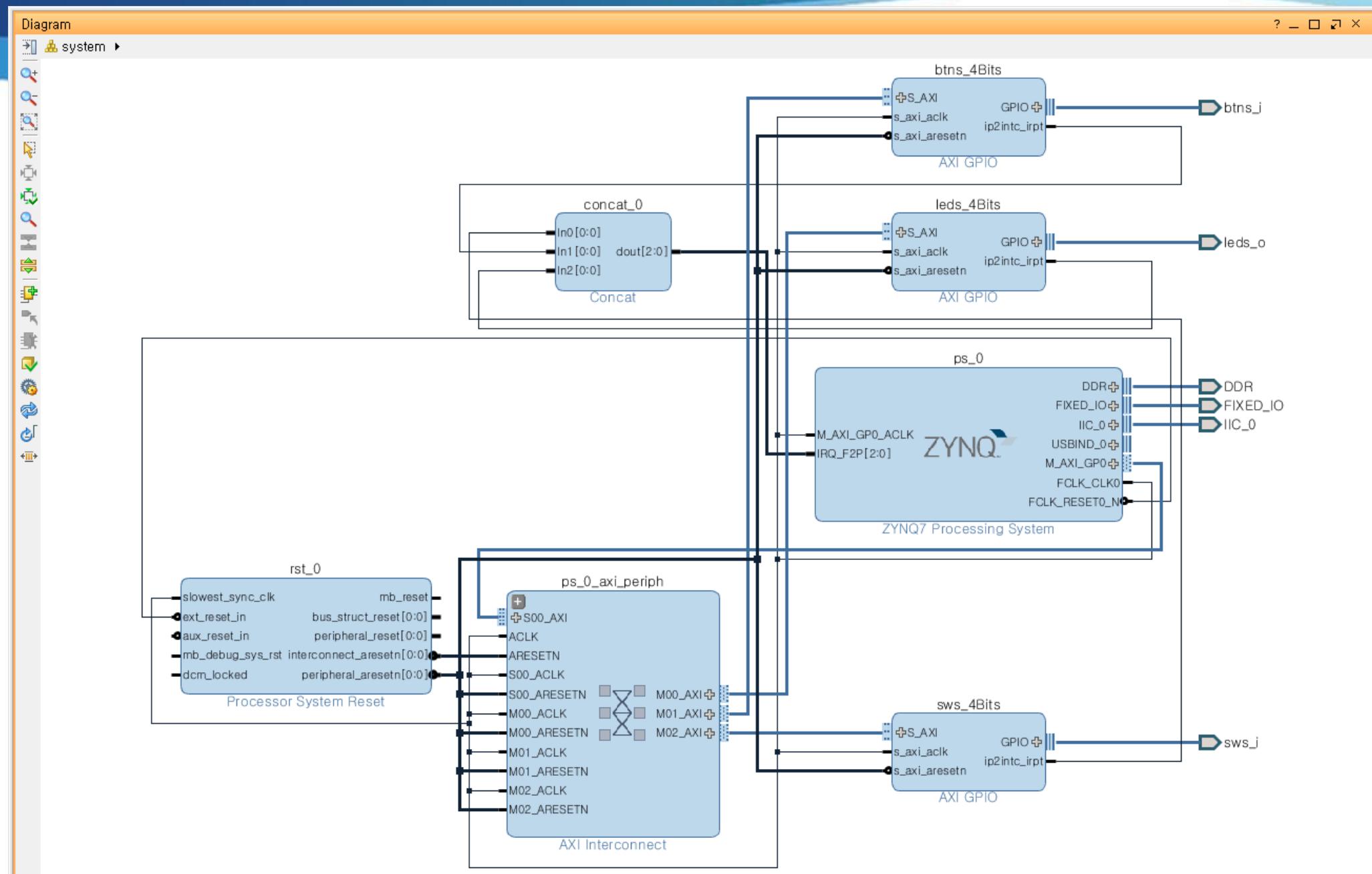
In cmd window for Vivado

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\gpio  
C:\> vivado -nolog -nojournal -mode batch -source gpio.tcl
```

output : gpio\gpio.xpr...



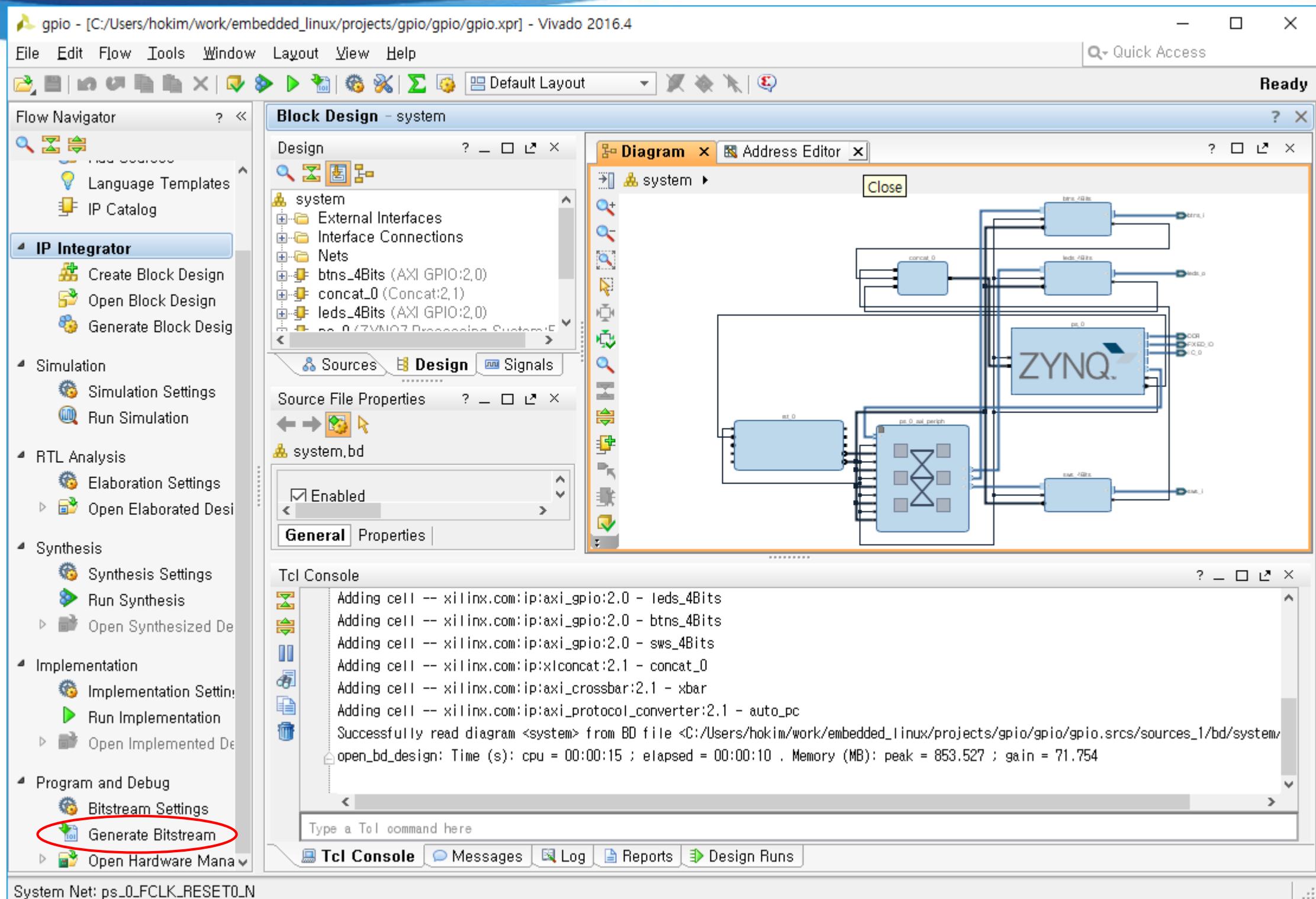
Project for GPIO



Address Editor

Cell	Slave Interface	Base Name	Offset Address	Range	High Address
ps_0	S_AXI	Reg	0x4000_1000	4K	0x4000_1FFF
btms_4Bits	S_AXI	Reg	0x4000_0000	4K	0x4000_0FFF
leds_4Bits	S_AXI	Reg	0x4000_2000	4K	0x4000_2FFF

Bit Generation for GPIO



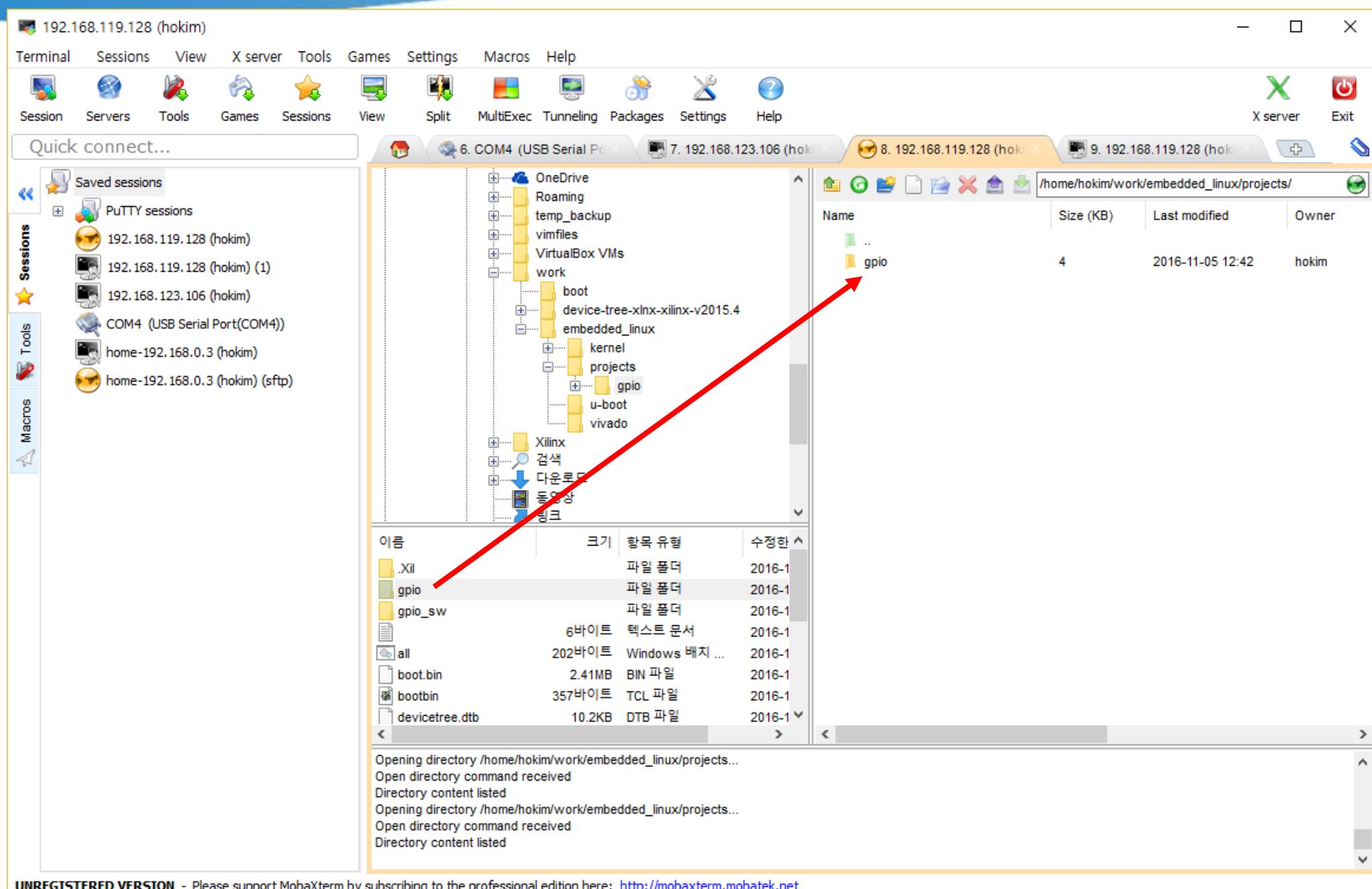
C:\Users\hokim\work\embedded_linux\projects\gpio\all.bat

```
call vivado -nolog -nojournal -mode batch -source hwdef.tcl  
call hsi -nolog -nojournal -mode batch -source fsbl.tcl  
call tclsh bootbin.tcl  
  
call hsi -nolog -nojournal -mode batch -source devicetree.tcl
```

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\gpio  
C:\> all
```



Device Tree Compile for GPIO



```
$ cd ~/work/embedded_linux/projects/gpio
$ cp gpio/gpio.tree/system.dts system_gpio.dts
$ nano system_gpio.dts
```

Device Tree Compile for GPIO

system_gpio.dts

```
/dts-v1/;  
/include/ "zynq-7000.dtsi"  
/include/ "pl.dtsi"  
.....  
.....  
&clkc {  
    fclk-enable = <0x1>;  
    ps-clk-frequency = <50000000>;  
};  
+&i2c0 {  
+    eeprom@50 {  
+        /* Microchip 24AA02E48 */  
+        compatible = "microchip,24c02";  
+        reg = <0x50>;  
+        pagesize = <8>;  
+    };  
+};
```

```
+/ {  
+    usb_phy0: phy0 {  
+        compatible = "ulpi-phy";  
+        #phy-cells = <0>;  
+        reg = <0xe0002000 0x1000>;  
+        view-port = <0x0170>;  
+        drv-vbus;  
+    };  
+};  
+&usb0 {  
+    usb-phy = <&usb_phy0>;  
+};
```



Device Tree Compile for GPIO

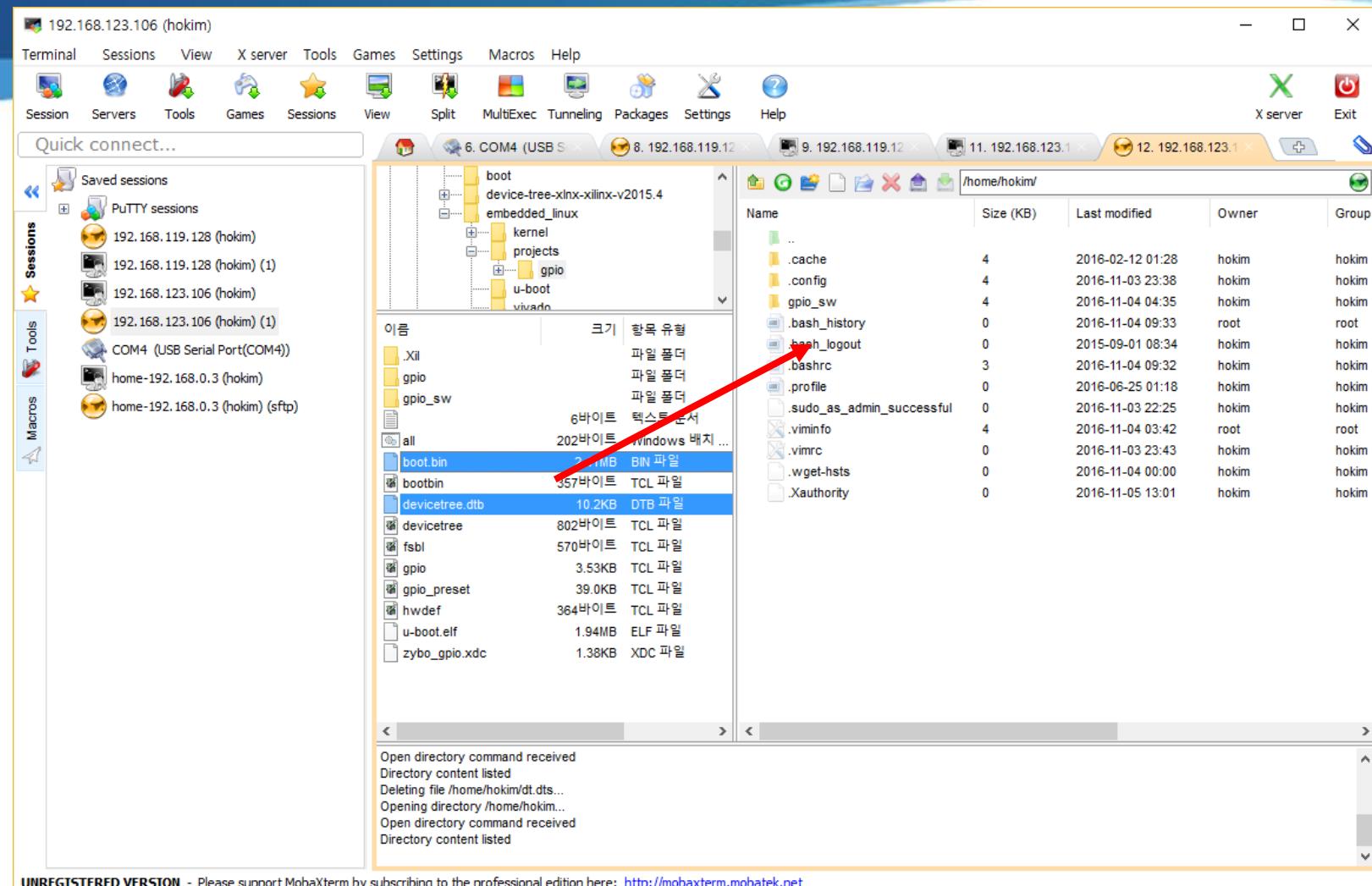
gpio/gpio.tree/pl.dtsi

```
/ {  
    amba_pl: amba_pl {  
        #address-cells = <1>;  
        #size-cells = <1>;  
        compatible = "simple-bus";  
        ranges ;  
        btrfs_4Bits: gpio@40001000 {  
            #gpio-cells = <2>;  
            compatible = "xlnx,xps-  
gpio-1.00.a";  
            .....  
            reg = <0x40001000  
0x1000>;  
            .....  
            .....  
        };  
        leds_4Bits: gpio@40000000 {  
            #gpio-cells = <2>;  
            compatible = "xlnx,xps-  
gpio-1.00.a";  
            .....  
            reg = <0x40000000  
0x1000>;  
            .....  
            .....  
        };  
    };  
};
```

```
sws_4Bits: gpio@40002000 {  
    #gpio-cells = <2>;  
    compatible = "xlnx,xps-  
gpio-1.00.a";  
    .....  
    .....  
    reg = <0x40002000  
0x1000>;  
    .....  
    .....  
};  
};
```

```
$ dtc -O dtb -I dts -i gpio/gpio.tree/ -o devicetree.dtb system_gpio.dts
```

Update boot.bin, devicetree.dtb for GPIO



login into zybo

```
$ sudo -s
# cd /boot
# rm boot.bin devicetree.dtb
# mv ~hokim/boot.bin .
# mv ~hokim/devicetree.dtb
# sync
# reboot
```

GPIO investigation

```
hokim@zybo:/sys/class/gpio$ ls  
export gpiochip894 gpiochip898 gpiochip902 gpiochip906 unexport
```

```
hokim@zybo:/sys/class/gpio$ ls gpiochip906  
base device label ngpio power subsystem uevent
```

```
hokim@zybo:/sys/class/gpio$ cat gpiochip906/base  
906
```

```
hokim@zybo:/sys/class/gpio$ cat gpiochip906/label  
zynq_gpio
```

```
hokim@zybo:/sys/class/gpio$ cat gpiochip906/ngpio  
118
```

```
hokim@zybo:/sys/class/gpio$ ls gpiochip894  
base label ngpio power subsystem uevent
```

```
hokim@zybo:/sys/class/gpio$ cat gpiochip894/base  
894
```

```
hokim@zybo:/sys/class/gpio$ cat gpiochip894/label  
/amba_pl/gpio@40002000
```

```
hokim@zybo:/sys/class/gpio$ cat gpiochip894/ngpio  
4
```

```
hokim@zybo:/sys/class/gpio$ cat gpiochip898/base  
898
```

```
hokim@zybo:/sys/class/gpio$ cat gpiochip898/label  
/amba_pl/gpio@40000000
```

```
hokim@zybo:/sys/class/gpio$ cat gpiochip898/ngpio  
4
```

```
hokim@zybo:/sys/class/gpio$ cat gpiochip902/base  
902
```

```
hokim@zybo:/sys/class/gpio$ cat gpiochip902/label  
/amba_pl/gpio@40001000
```

```
hokim@zybo:/sys/class/gpio$ cat gpiochip902/ngpio  
4
```



```
hokim@zybo:~$ cd gpio_sw/
hokim@zybo:~/gpio_sw$ ls
driver mmap
hokim@zybo:~/gpio_sw$ cd driver
hokim@zybo:~/gpio_sw/driver$ ls
CMakeLists.txt build gpio.c gpio.h main.c
hokim@zybo:~/gpio_sw/driver$ 
hokim@zybo:~/gpio_sw/driver$ mkdir build
hokim@zybo:~/gpio_sw/driver$ cd build
hokim@zybo:~/gpio_sw/driver/build$ cmake ..
hokim@zybo:~/gpio_sw/driver/build$ sudo ./gpio_test
```

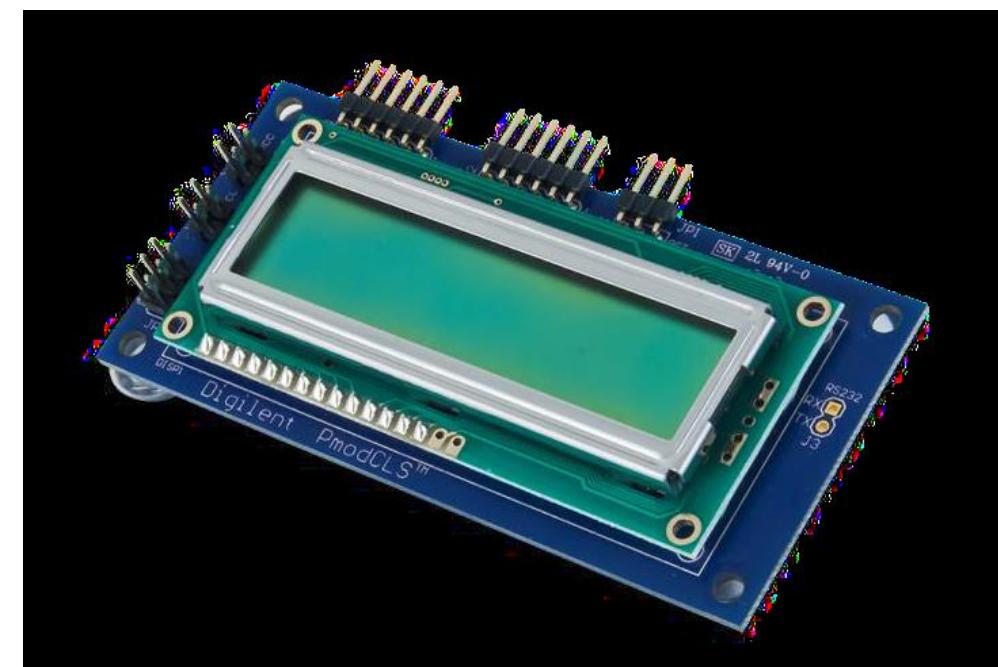
```
hokim@zybo:~$ cd gpio_sw/driver/python
hokim@zybo:~/gpio_sw/driver/python$ ls
gpio.py gpio_test.py
hokim@zybo:~/gpio_sw/driver/python$ sudo python gpio_test.py
```

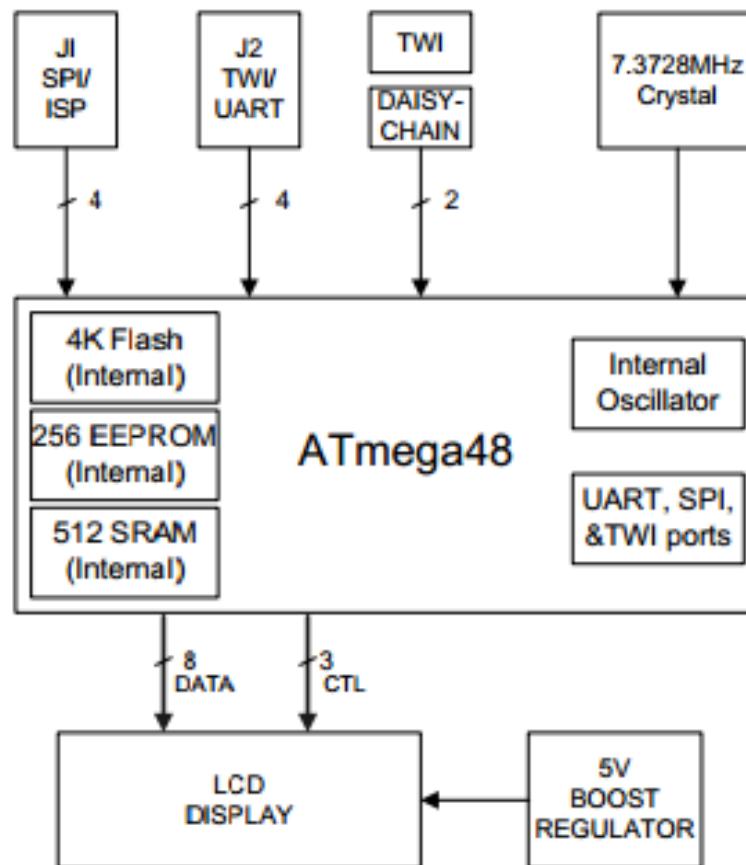
```
hokim@zybo:~$ cd gpio_sw
hokim@zybo:~/gpio_sw$ ls
driver mmap
hokim@zybo:~/gpio_sw$ cd mmap
hokim@zybo:~/gpio_sw/mmap$ ls
CMakeLists.txt lib main.c
hokim@zybo:~/gpio_sw/mmap$ mkdir build
hokim@zybo:~/gpio_sw/mmap$ cd build
hokim@zybo:~/gpio_sw/mmap/build$ cmake ..
hokim@zybo:~/gpio_sw/mmap/build$ make
hokim@zybo:~/gpio_sw/mmap/build$ sudo ./gpio_test
```



- **16x2 character LCD module**
- **Driven by ATmega48 microcontroller**
- **Multiple communication options including UART, SPI, and I2C**
- **Instruction set :**

<https://github.com/Xilinx/linux-xlnx/blob/master/Documentation/pmods/pmodcls.txt>





MD2, MD1, MD0	Protocol	Details
0,0,0	UART	2400 baud
0,0,1	UART	4800 baud
0,1,0	UART	9600 baud
0,1,1	UART	Baud rate in EEPROM
1,0,0	TWI	Address: 0x48
1,0,1	TWI	Address in EEPROM
1,1,0	SPI	
1,1,1	Specified in EEPROM	Specified in EEPROM

Header J1		
Pin	Signal	Description
1	SS	Slave Select
2	MOSI	Master-Out-Slave-In
3	MISO	Master-In-Slave-Out
4	SCK	Serial Clock
5	GND	Power Supply Ground
6	VCC	Positive Power Supply (3.3V)

Header J2		
Pin	Signal	Description
1	SCL	Serial Clock
2	SDA	Serial Data
3	TXD	Transmit Data
4	RXD	Receive Data
5	GND	Power Supply Ground
6	VCC	Positive Power Supply (3.3V)

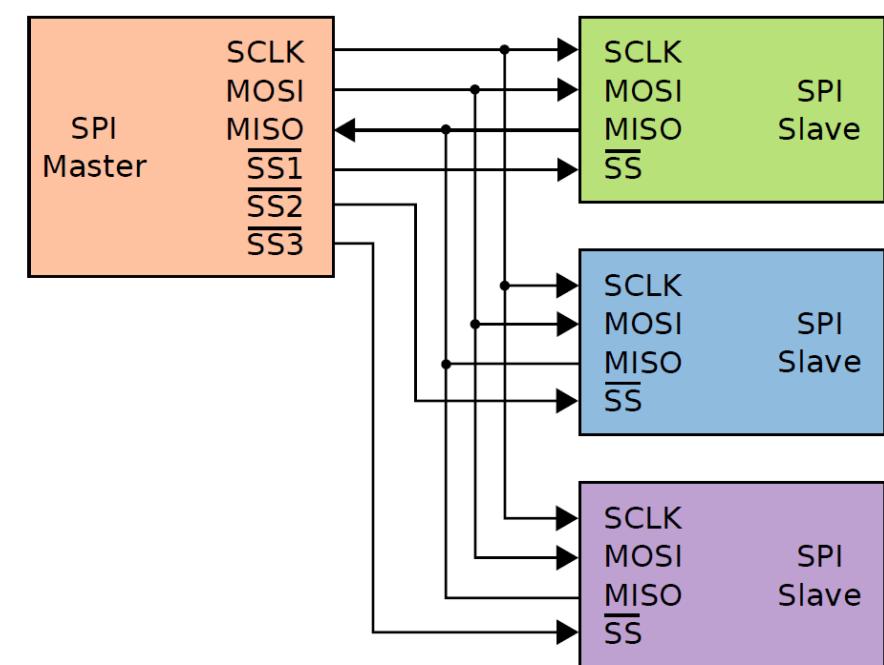
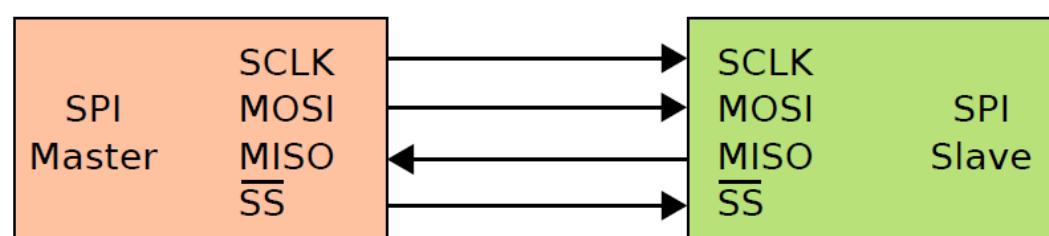
- **Synchronous serial digital data link by Motorola**
- **SPI master controls**

CLK : synchronization clock

SS or CS : slave select or chip-select; when active the slave is allowed to talk

MOSI : master out, slave in; carries data from master to slave

MISO : master in, slave out; carries data from slave to master

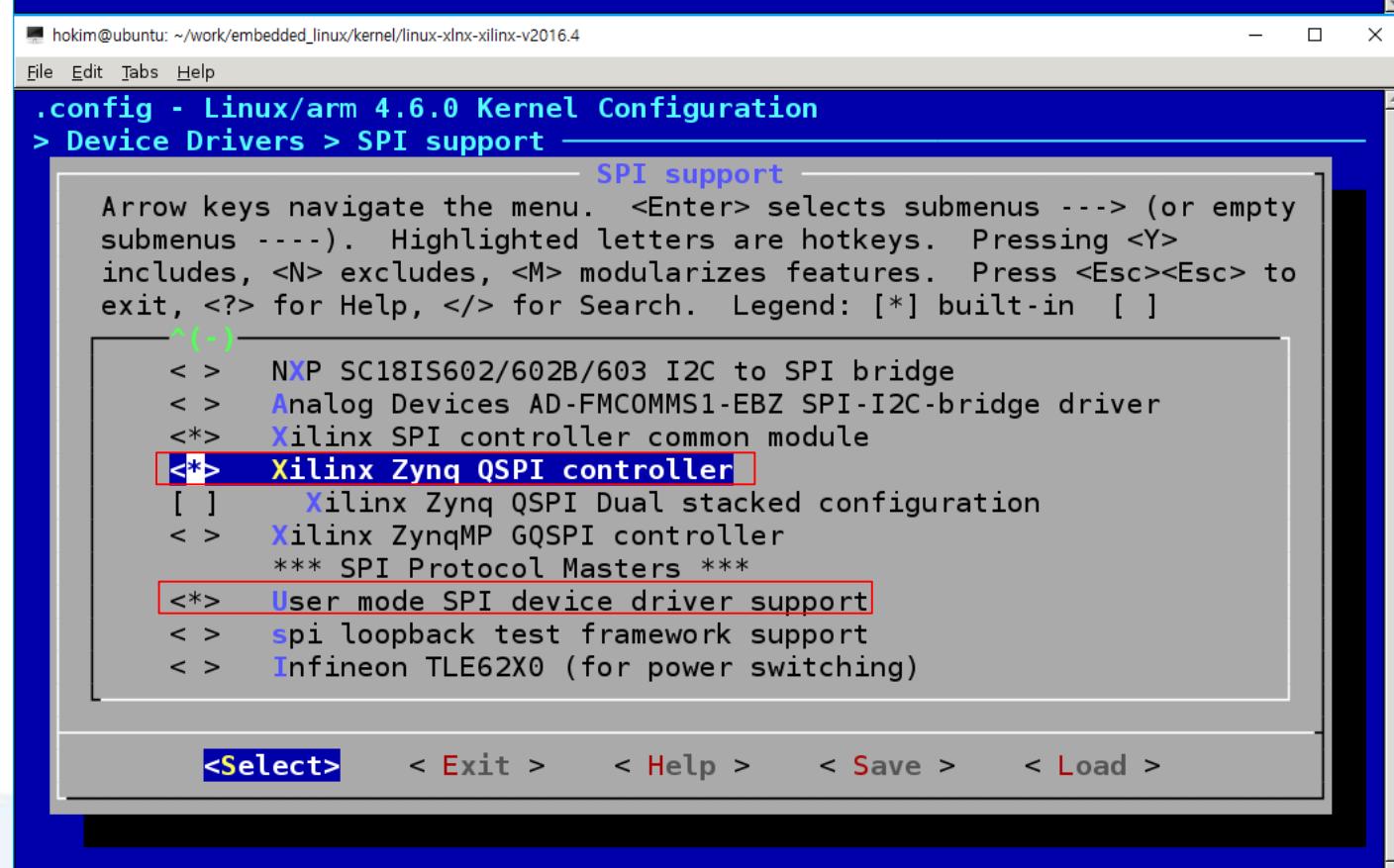
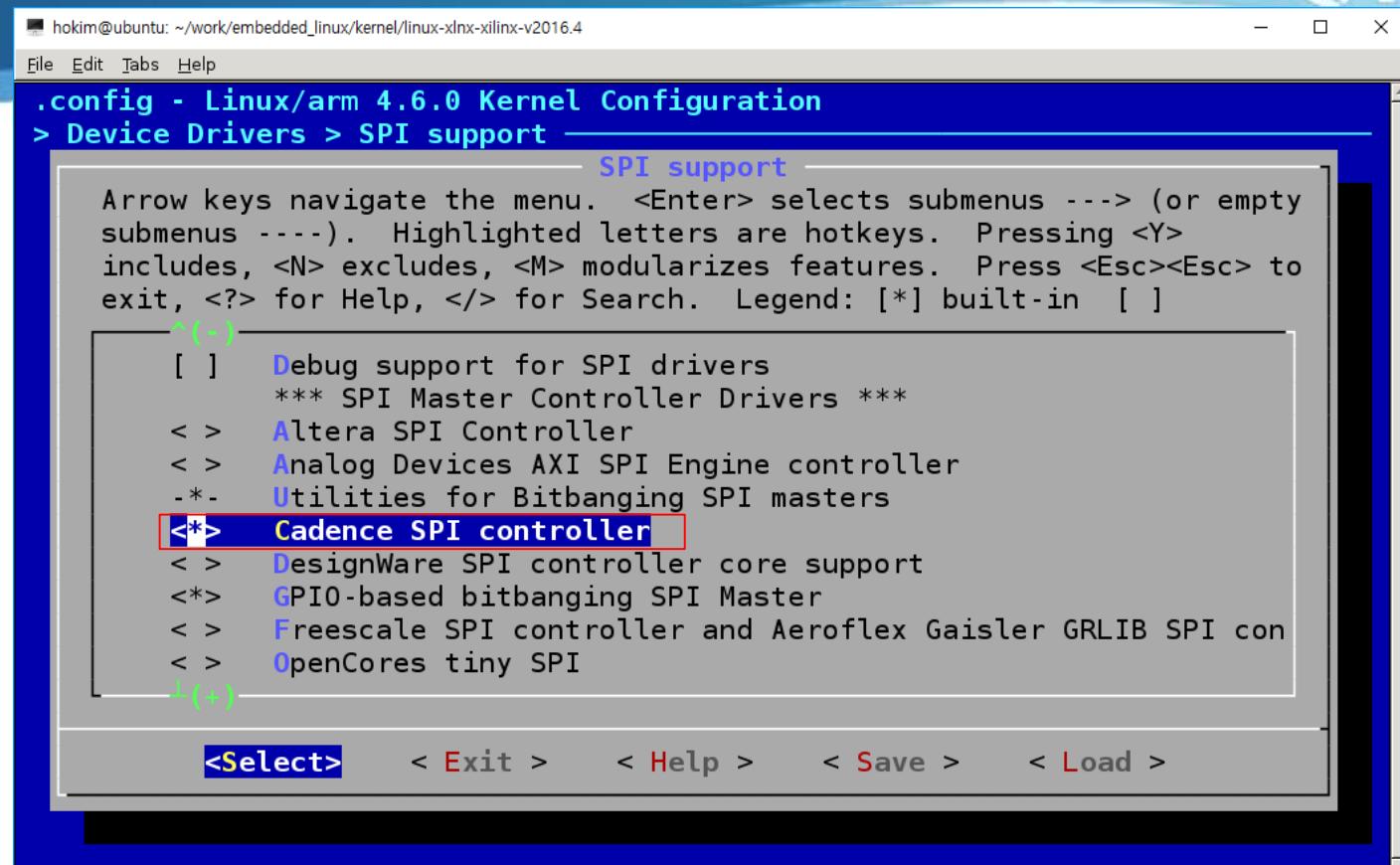


- Documented in Documentation/spi/spidev
- SPI kernel framework
- SPI master drivers : drivers/spi/(spi-cadence.c, spi-zynq-qspi.c)
- Kernel platform code registers the “spidev” platform device
- Create character device nodes at /dev/spidevB.C where:
 - B is the SPI bus (master) number
 - C is the chip-select number of specific SPI slave.



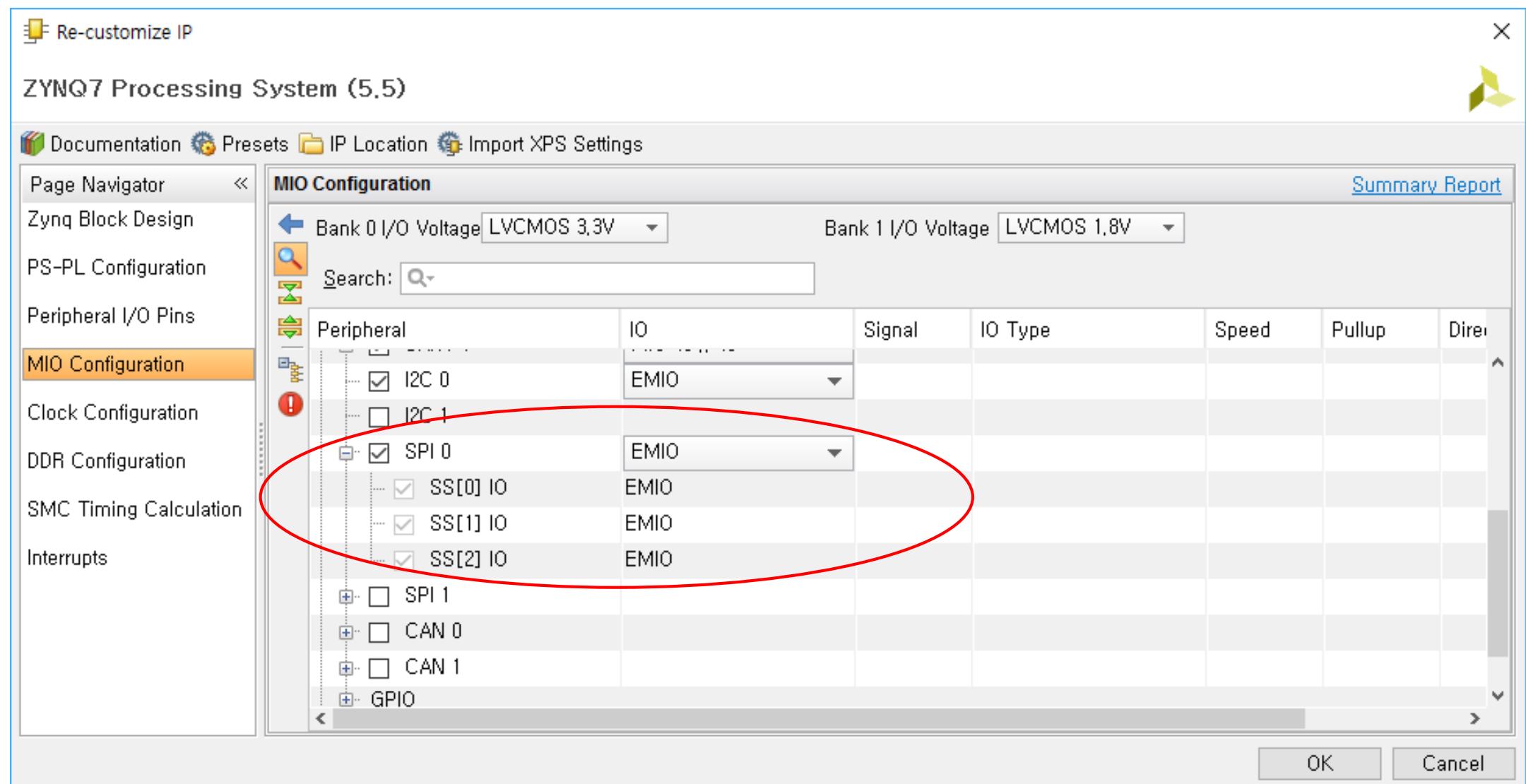
Linux SPI Userspace Interface

Kernel Configuration



Zynq7 PS Re-customize IP for SPI

Based on Zynq7 PS Re-customize IP of embedded_linux project



Zynq7 PS Re-customize IP for SPI



Based on Zynq7 PS Re-customize IP of embedded_linux project

Re-customize IP

ZYNQ7 Processing System (5.5)

Documentation Presets IP Location Import XPS Settings

Page Navigator <> Zynq Block Design

PS-PL Configuration

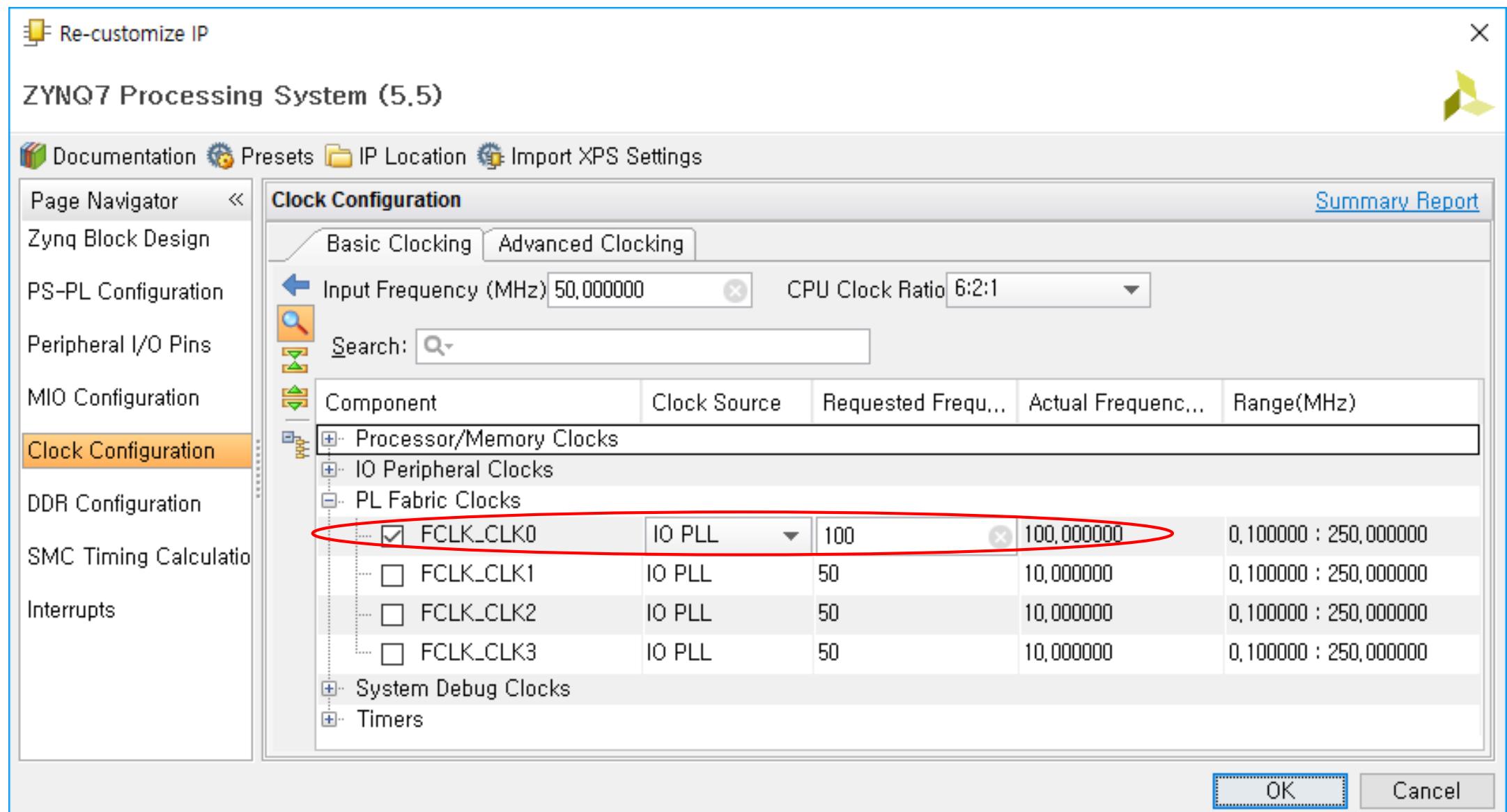
Search:

Name	Select	Description
General		
- UART0 Baud Rate	115200	Baud rate is generated with internally fixed UART Ref Clock Freq=10...
- UART1 Baud Rate	115200	Baud rate is generated with internally fixed UART Ref Clock Freq=10...
- PL AXI idle Port	<input type="checkbox"/>	Enables idle AXI signal to the PS used to indicate that there are no ...
- DDR ARB bypass Port	<input type="checkbox"/>	Enables DDR urgent/arbitration signal used to signal a critical memory sta...
- PS-PL Debug interface	<input type="checkbox"/>	Enables PL debug signals to PS and vice-versa
- FTM Trace data interface	<input type="checkbox"/>	Enables FTM Trace AXI stream interface used to capture data from PL ... to PS debug system
- FTM Trace buffer	0	Stores trace data in the FIFO when the data changes as marked by ...
- FTM Data edge detector	0	FTM Trace buffer FIFO size
- FTM Trace buffer FIFO size	128	Number of clock cycles interval for a trace data output from FIFO be...
- FTM Trace buffer clock delay	12	
- Include ACP transaction checker	<input type="checkbox"/>	Enables ACP transaction checker.
- Trace data/control signal pipeline width	8	Enables configurable number of pipeline stages on the TRACE DAT...
- Power-on reset(POR) 4k timer	<input type="checkbox"/>	Enables power-on reset(POR) 4k timer. By default, 64k timer is used.
- Processor event interface	<input type="checkbox"/>	Enables event bus which provides a low-latency and direct mecha...
- Address Editor		
- Enable Clock Triggers		
- Enable Clock Resets		
- FCLK_RESET0_N	<input checked="" type="checkbox"/>	Enables general purpose reset signal 0 for PL logic
- FCLK_RESET1_N	<input type="checkbox"/>	Enables general purpose reset signal 1 for PL logic
- FCLK_RESET2_N	<input type="checkbox"/>	Enables general purpose reset signal 2 for PL logic
- FCLK_RESET3_N	<input type="checkbox"/>	Enables general purpose reset signal 3 for PL logic
- AXI Non Secure Enablement	0	Enable AXI Non Secure Transaction
- GP Master AXI Interface		
- M AXI GP0 interface	<input checked="" type="checkbox"/>	Enables General purpose AXI master interface 0
- M AXI GP1 interface	<input type="checkbox"/>	Enables General purpose AXI master interface 1
- GP Slave AXI Interface		

OK Cancel

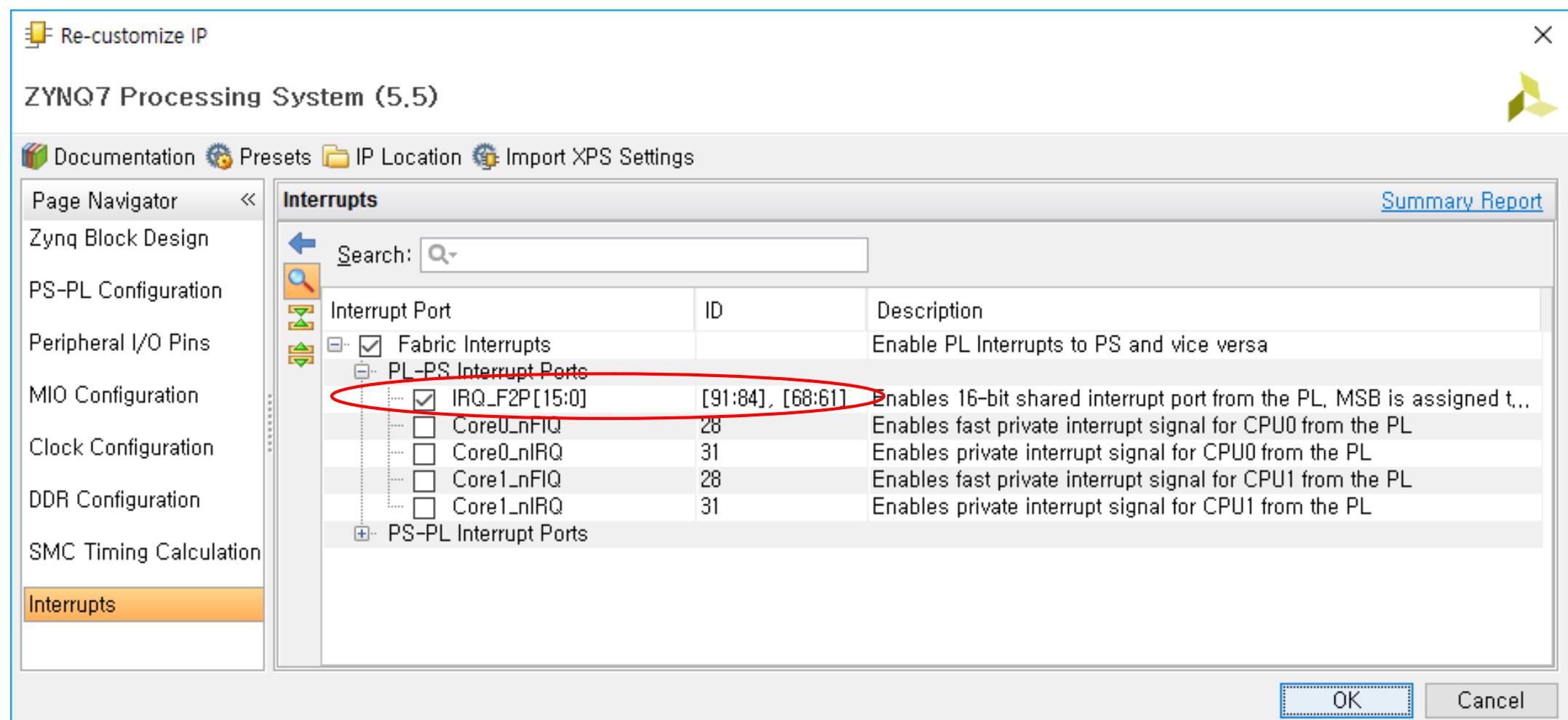
Zynq7 PS Re-customize IP for SPI

Based on Zynq7 PS Re-customize IP of embedded_linux project



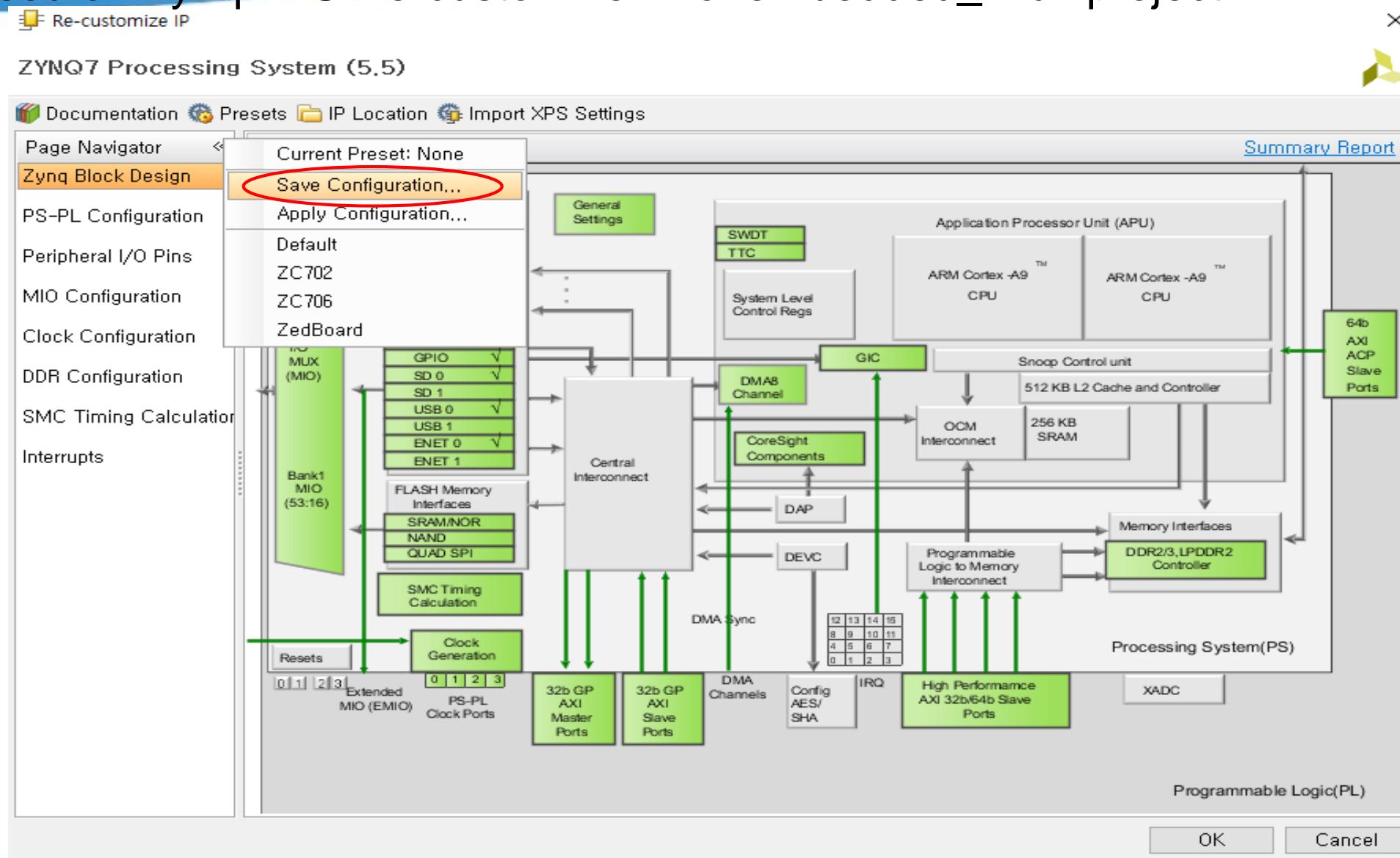
Zynq7 PS Re-customize IP for SPI

Based on Zynq7 PS Re-customize IP of embedded_linux project



Zynq7 PS Re-customize IP for SPI

Based on Zynq7 PS Re-customize IP of embedded_linux project



Save Current Configuration...

Save the current configuration to a file on disk.

Preset Name:

File name:

OK Cancel

https://github.com/inipro/embedded_linux/projects/spi

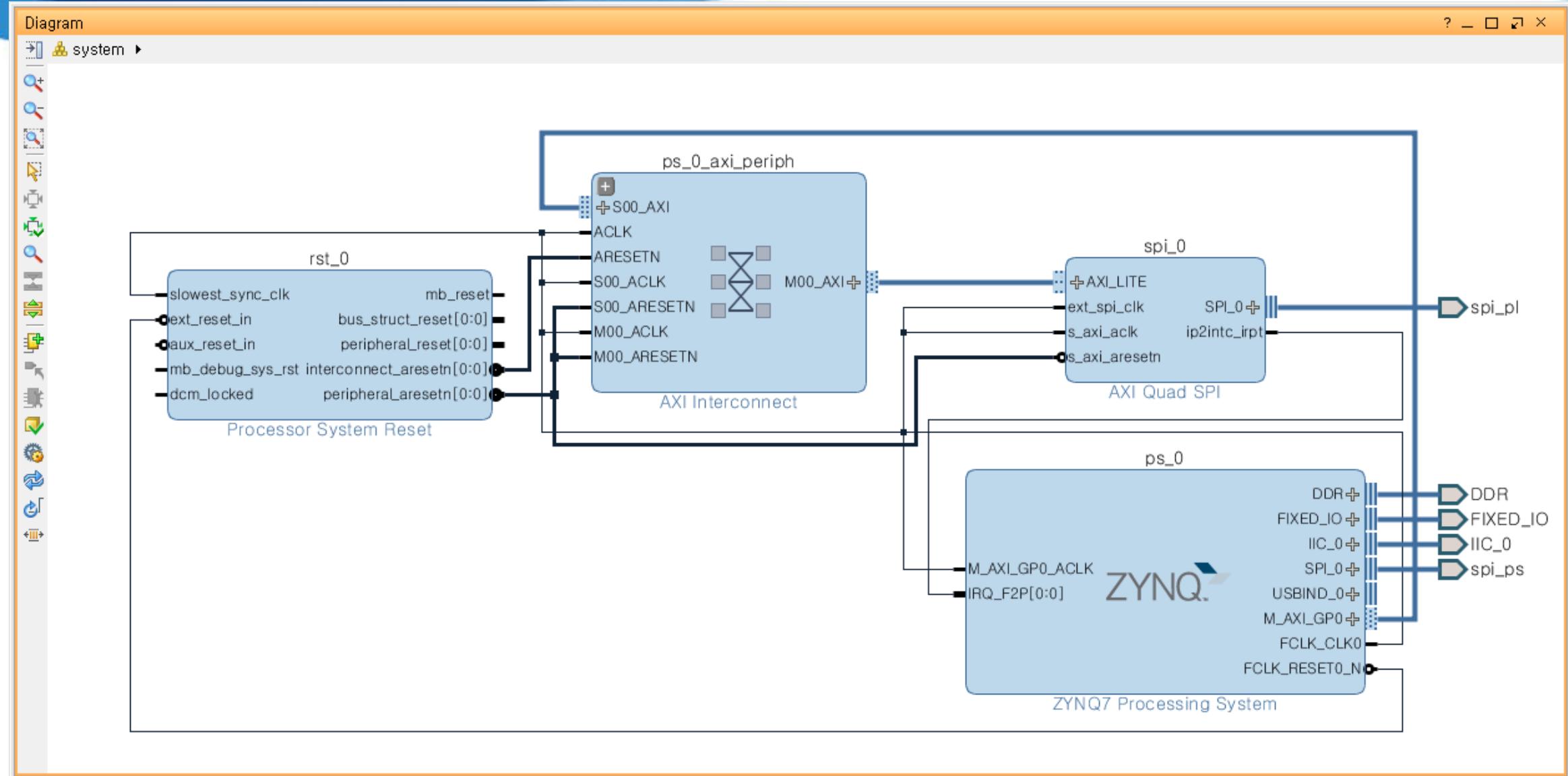
In cmd window for Vivado

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\spi  
C:\> vivado -nolog -nojournal -mode batch -source spi.tcl
```

output : spi\spi.xpr...



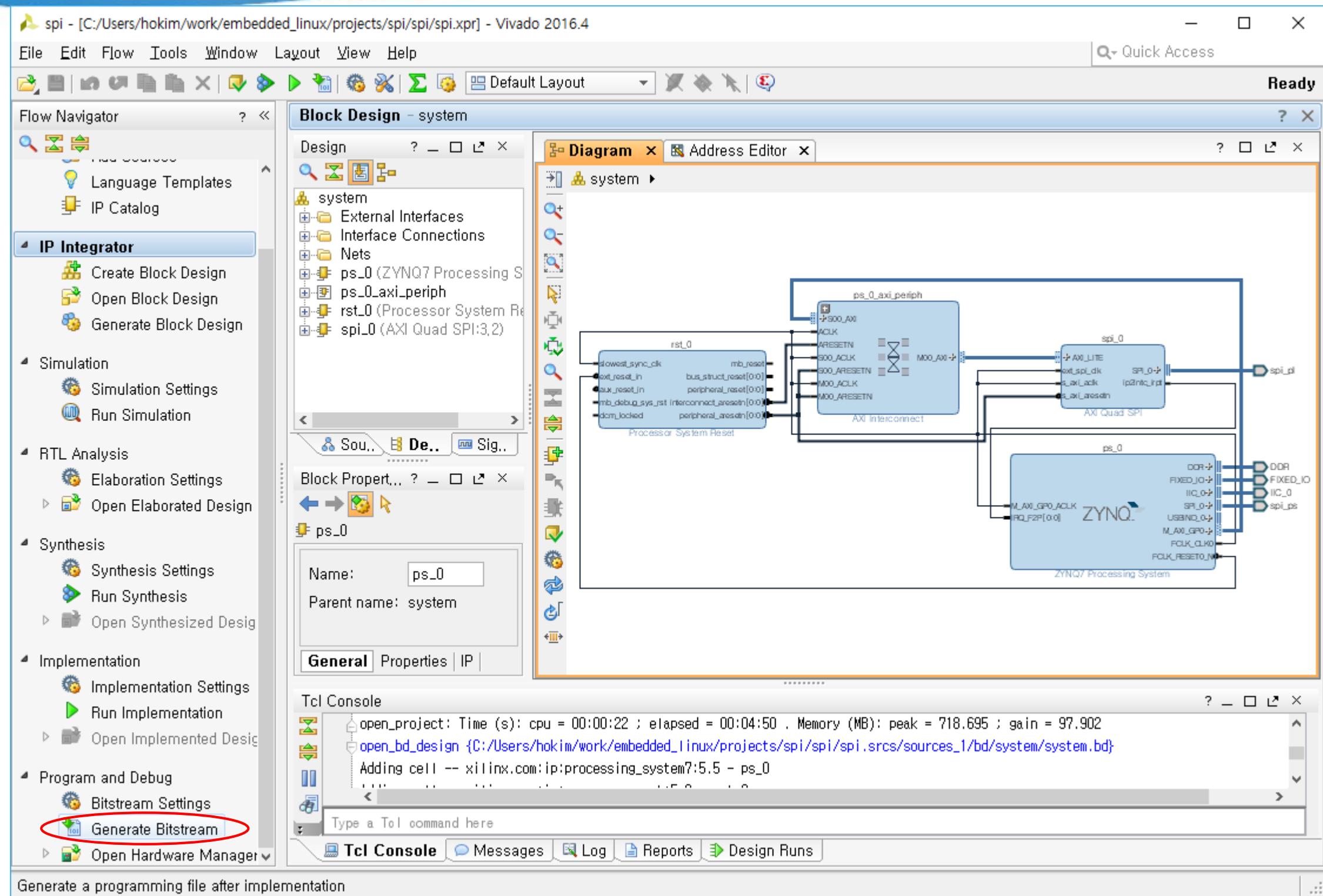
Project for SPI



Address Editor

Cell	Slave Interface	Base Name	Offset Address	Range	High Address
ps_0					
ps_0	AXILITE	Reg	0x4000_0000	4K	0x4000_0FFF

Bit Generation for SPI

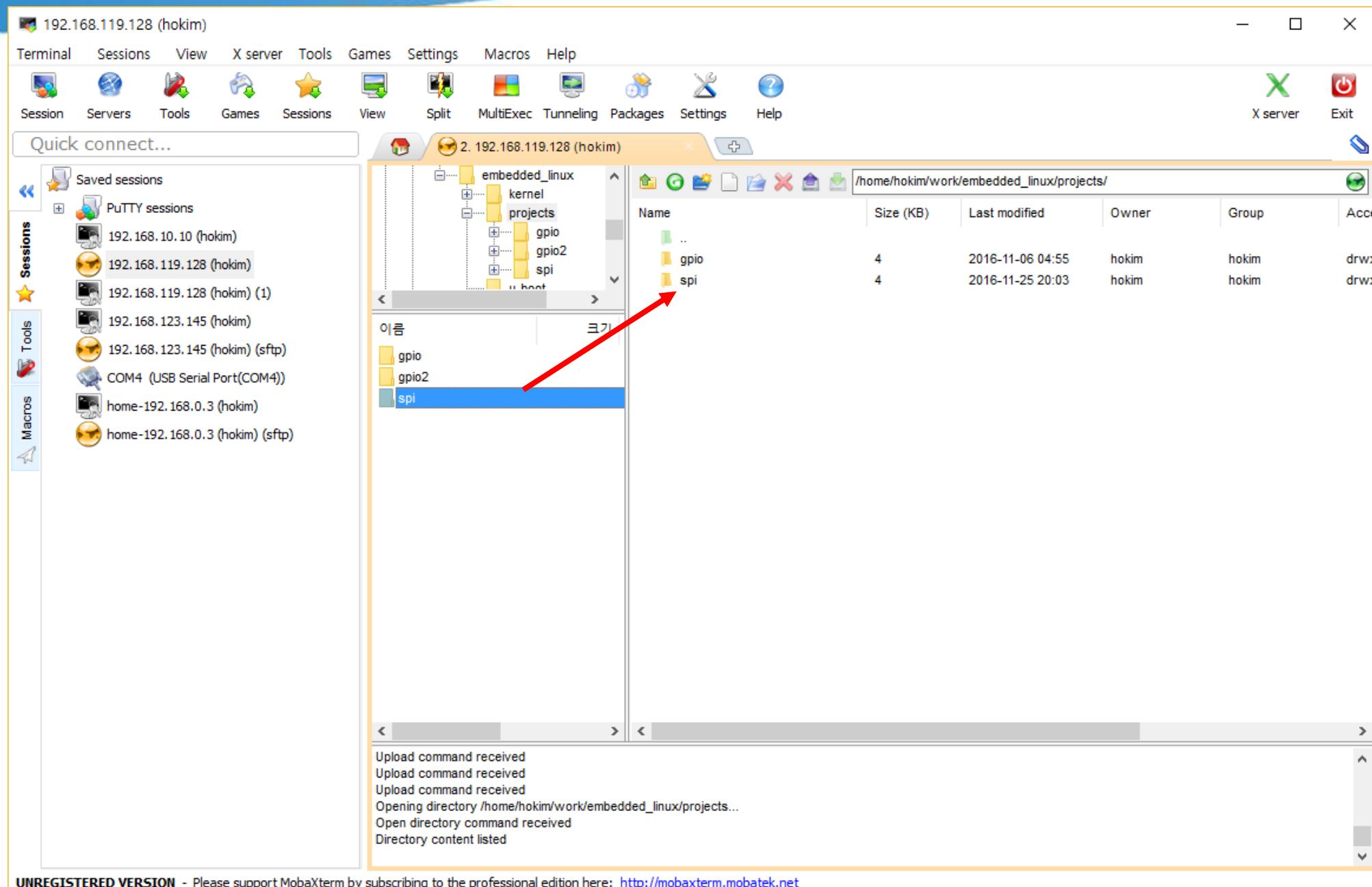


C:\Users\hokim\work\embedded_linux\projects\spi\all.bat

```
call vivado -nolog -nojournal -mode batch -source hwdef.tcl  
call hsi -nolog -nojournal -mode batch -source fsbl.tcl  
call tclsh bootbin.tcl  
  
call hsi -nolog -nojournal -mode batch -source devicetree.tcl
```

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\spi  
C:\> all
```

Device Tree Compile for SPI



```
$ cd ~/work/embedded_linux/projects/spi
$ cp spi/spi.tree/system.dts  system_spi.dts
$ nano system_spi.dts
```

Device Tree Compile for SPI

system_spi.dts

```
/dts-v1/;  
/include/ "zynq-7000.dtsi"  
/include/ "pl.dtsi"  
.....  
.....  
&clkc {  
    fclk-enable = <0x1>;  
    ps-clk-frequency = <50000000>;  
};  
  
+&i2c0 {  
+    eeprom@50 {  
+        /* Microchip 24AA02E48 */  
+        compatible = "microchip,24c02";  
+        reg = <0x50>;  
+        pagesize = <8>;  
+    };  
+};  
+/ {  
+    usb_phy0: phy0 {  
+        compatible = "ulpi-phy";  
+        #phy-cells = <0>;  
+        reg = <0xe0002000 0x1000>;  
+        view-port = <0x0170>;  
+        drv-vbus;  
+    };  
+};  
  
+&usb0 {  
+    usb-phy = <&usb_phy0>;  
+};  
+&spi0 {  
+    num-cs = <1>;  
+  
+    spidev@0 {  
+        compatible = "spidev";  
+        reg = <0>; // chipselect 0  
+        spi-max-frequency = <50000000>;  
+    };  
+};  
+  
+&spi_0 {  
+    #address-cells = <1>;  
+    #size-cells = <0>;  
+  
+    spidev@0 {  
+        compatible = "spidev";  
+        reg = <0>; // chipselect 0  
+        spi-max-frequency = <50000000>;  
+    };  
+};
```

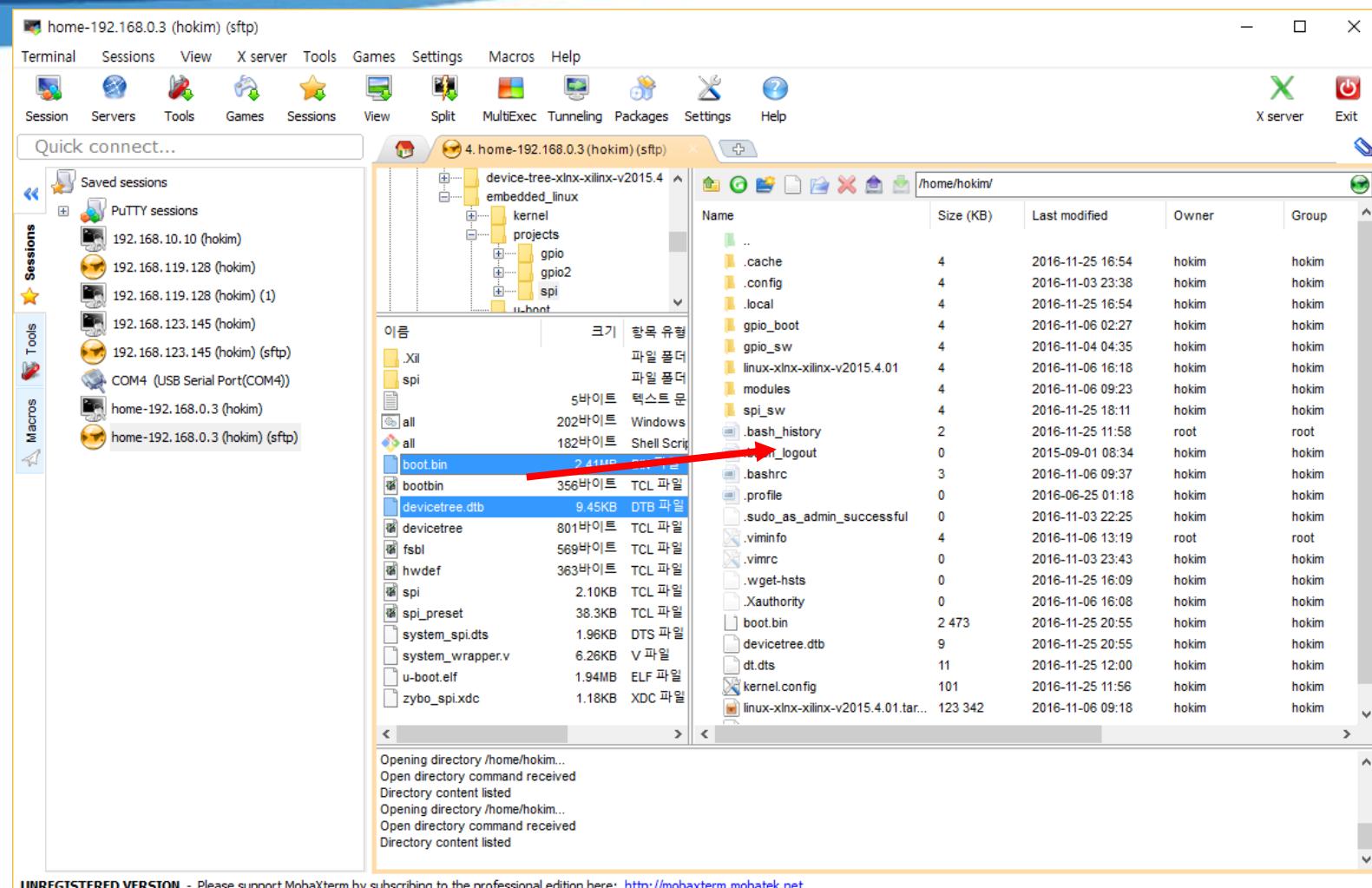
spi/spi.tree/pl.dtsi

```
/ {  
    amba_pl: amba_pl {  
        #address-cells = <1>;  
        #size-cells = <1>;  
        compatible = "simple-bus";  
        ranges ;  
        spi_0: axi_quad_spi@40000000 {  
            compatible = "xlnx,xps-spi-2.00.a";  
            interrupt-parent = <&intc>;  
            interrupts = <0 29 1>;  
            reg = <0x40000000 0x1000>;  
            xlnx,num-ss-bits = <0x1>;  
        };  
    };  
};
```

```
$ dtc -O dtb -I dts -i spi/spi.tree/ -o devicetree.dtb system_spi.dts
```



Update boot.bin, devicetree.dtb for SPI



login into zybo

```
$ sudo -s
# cd /boot
# rm boot.bin devicetree.dtb
# mv ~hokim/boot.bin .
# mv ~hokim/devicetree.dtb
# sync
# reboot
```

```
hokim@zybo:~$ ls /dev/spidev*
/dev/spidev0.0 /dev/spidev1.0
```

```
hokim@zybo:~$ cd spi_sw/
hokim@zybo:~/spi_sw$ ls
CMakeLists.txt PmodCLS.c PmodCLS.h main.c spi.c spi.h
hokim@zybo:~/spi_sw$ mkdir build
hokim@zybo:~/spi_sw/$ cd build
hokim@zybo:~/spi_sw/build$ cmake ..
hokim@zybo:~/spi_sw/build$ make
hokim@zybo:~/spi_sw/build$ sudo ./spi_test
```

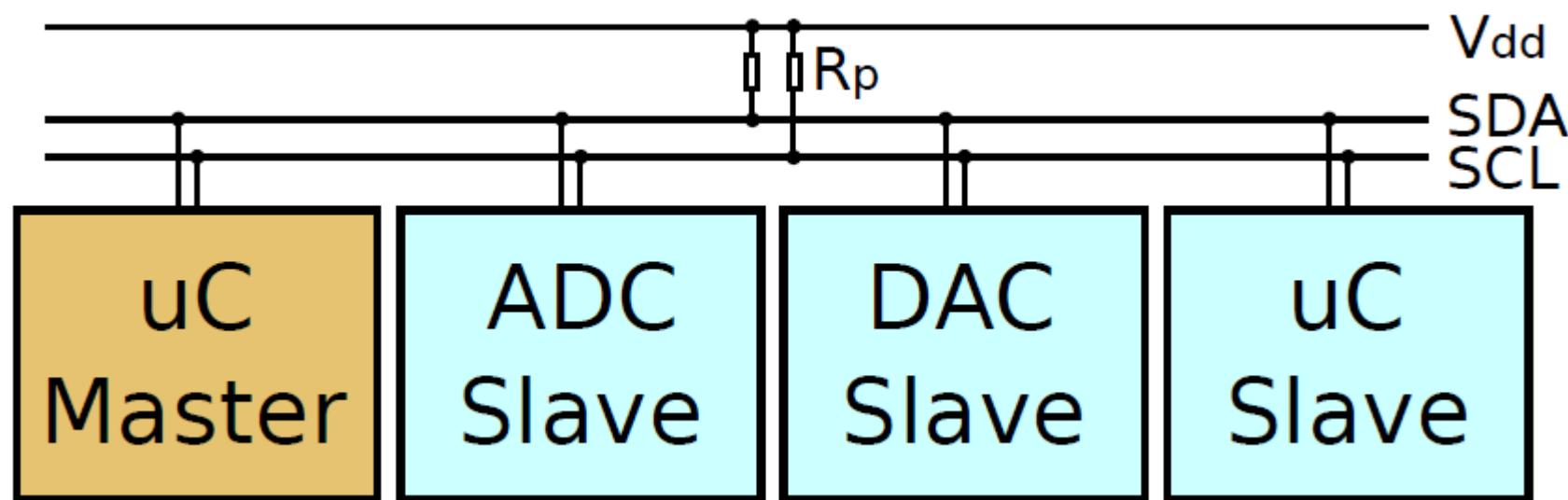
```
hokim@zybo:~$ cd spi_sw/python
hokim@zybo:~/spi_sw/python$ ls
pmodcls_spi.py spi_test.py
hokim@zybo:~/spi_sw/python$ sudo apt install python-pip
hokim@zybo:~/spi_sw/python$ pip install spidev
hokim@zybo:~/spi_sw/python$ sudo python spi_test.py
```

- Two wires are controlled by the master and slaves according to the protocol

SCL : Serial CLock

SDA : Serial DAta

- Each slave has a 7 bit address
- The 7 MSB of the first transmitted byte are slave address
- The LSB of this byte indicates read (1), or write (0)
- SMBus is a subset of I2C, with a stricter protocol definition



- Documented in Documentation/i2c/dev-interfaces
- I2C framework
- I2C master driver : drivers/i2c/busses/(i2c-cadence.c, i2c-xiic.c)
- Each master gets a character device node at /dev/i2c-N, where N is the ID master number



Linux I2C Userspace Interface

Kernel Configuration

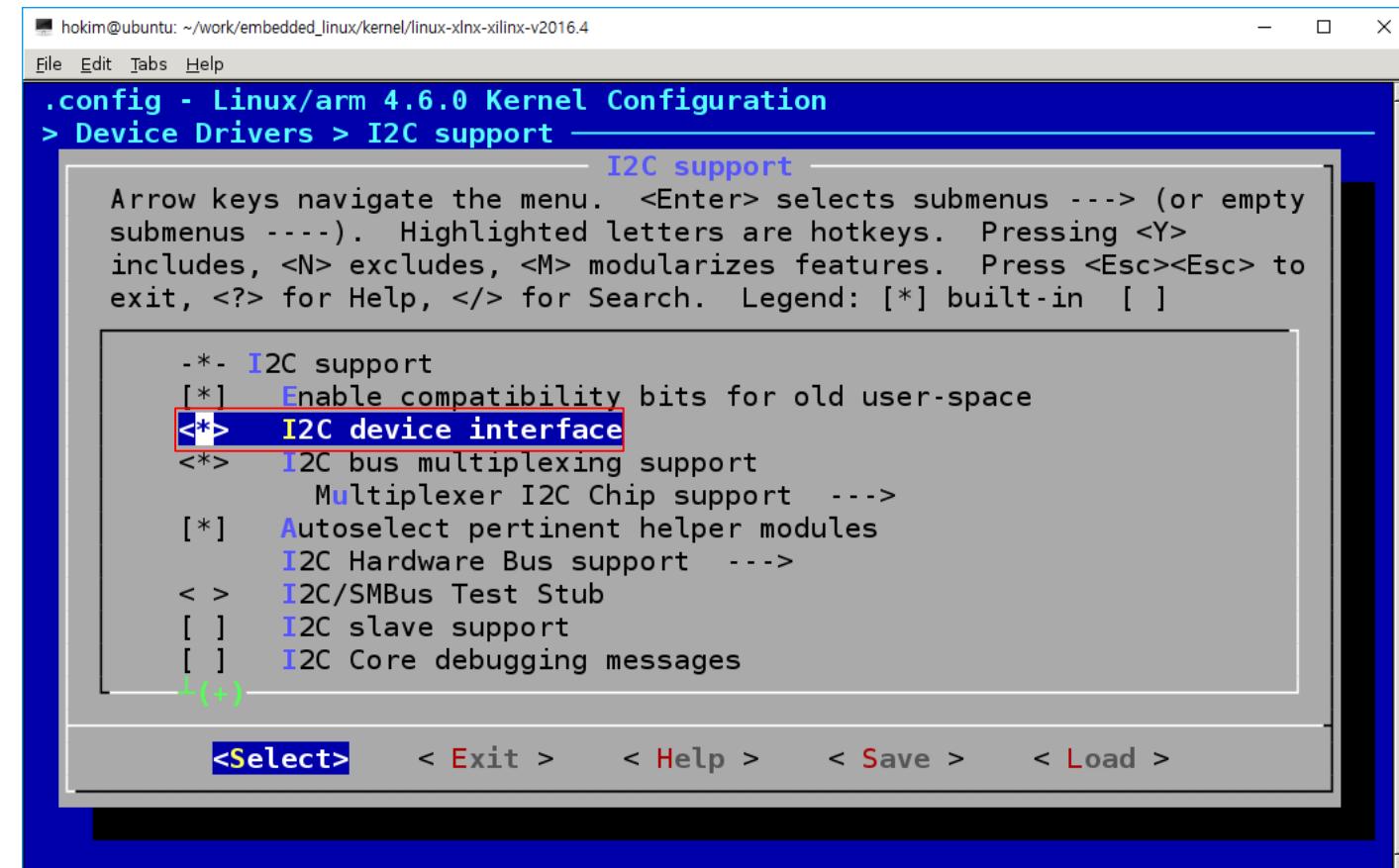
```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > I2C support > I2C Hardware Bus support
I2C Hardware Bus support
Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
submenus ----). Highlighted letters are hotkeys. Pressing <Y>
includes, <N> excludes, <M> modularizes features. Press <Esc><Esc> to
exit, <?> for Help, </> for Search. Legend: [*] built-in [ ]
^(+)
< > SIS 96x
< > VIA VT82C586B
< > VIA VT82C596/82C686/82xx and CX700/VX8xx/VX900
    *** I2C system bus drivers (mostly embedded / system-on-chip)
<*> Cadence I2C Controller
< > CBUS I2C driver
< > Synopsys DesignWare Platform
< > Synopsys DesignWare PCI
< > EMMA Mobile series I2C adapter
< > GPIO-based bitbanging I2C
L(+)

<Select> < Exit > < Help > < Save > < Load >
```

```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > I2C support > I2C Hardware Bus support
I2C Hardware Bus support
Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
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 [ ]
^(+)
< > PCA9564/PCA9665 as platform device
< > Rockchip RK3xxx I2C adapter
< > Simtec Generic I2C interface
< > ARM Versatile/Realview I2C bus support
<*> Xilinx I2C Controller
    *** External I2C/SMBus adapter drivers ***
< > Diolan U2C-12 USB adapter
< > Parallel port adapter (light)
< > RobotFuzz Open Source InterFace USB adapter
< > TAOS evaluation module
L(+)

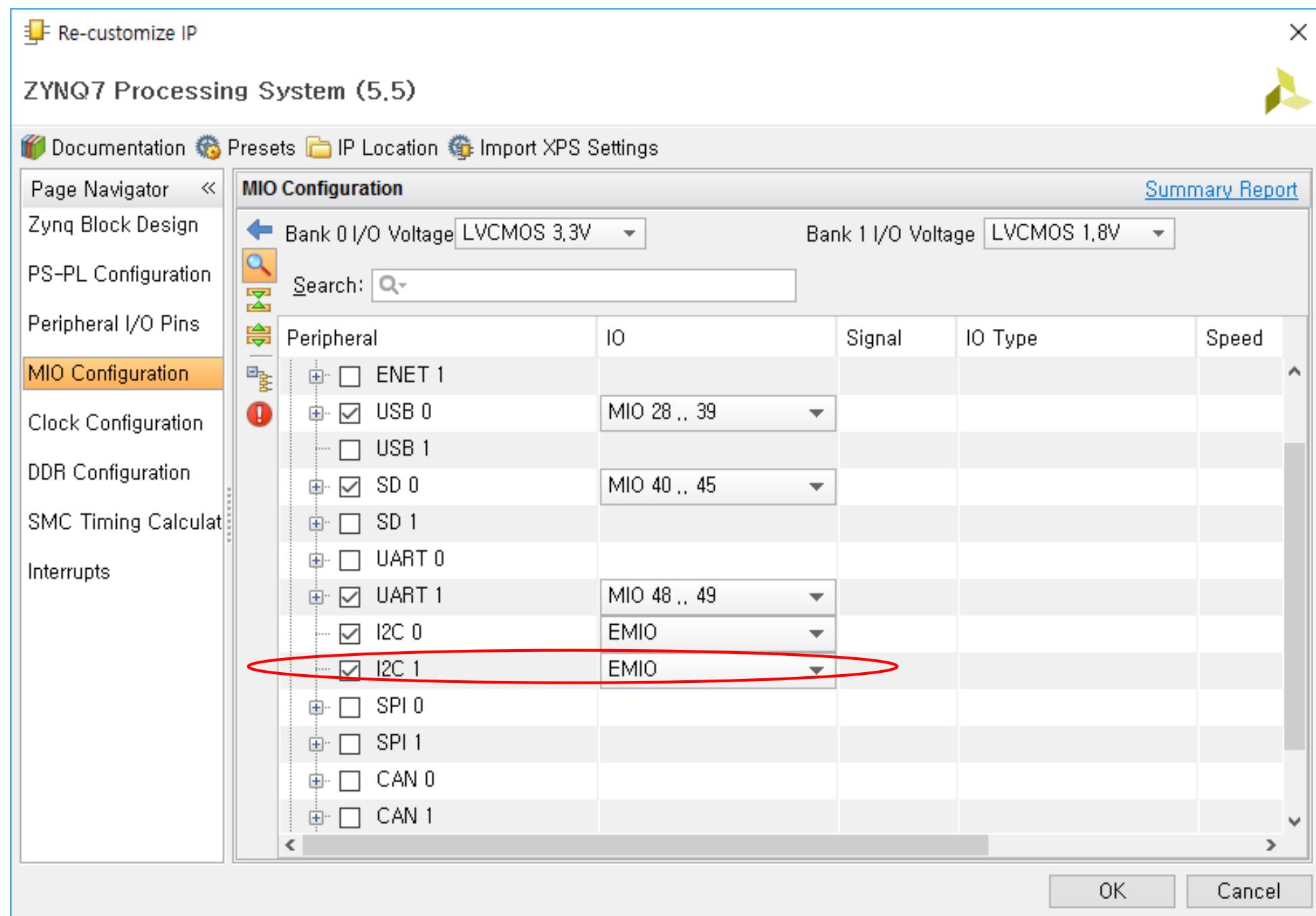
<Select> < Exit > < Help > < Save > < Load >
```

Kernel Configuration



Zynq7 PS Re-customize IP for I2C

Based on Zynq7 PS Re-customize IP of embedded_linux project



Zynq7 PS Re-customize IP for I2C



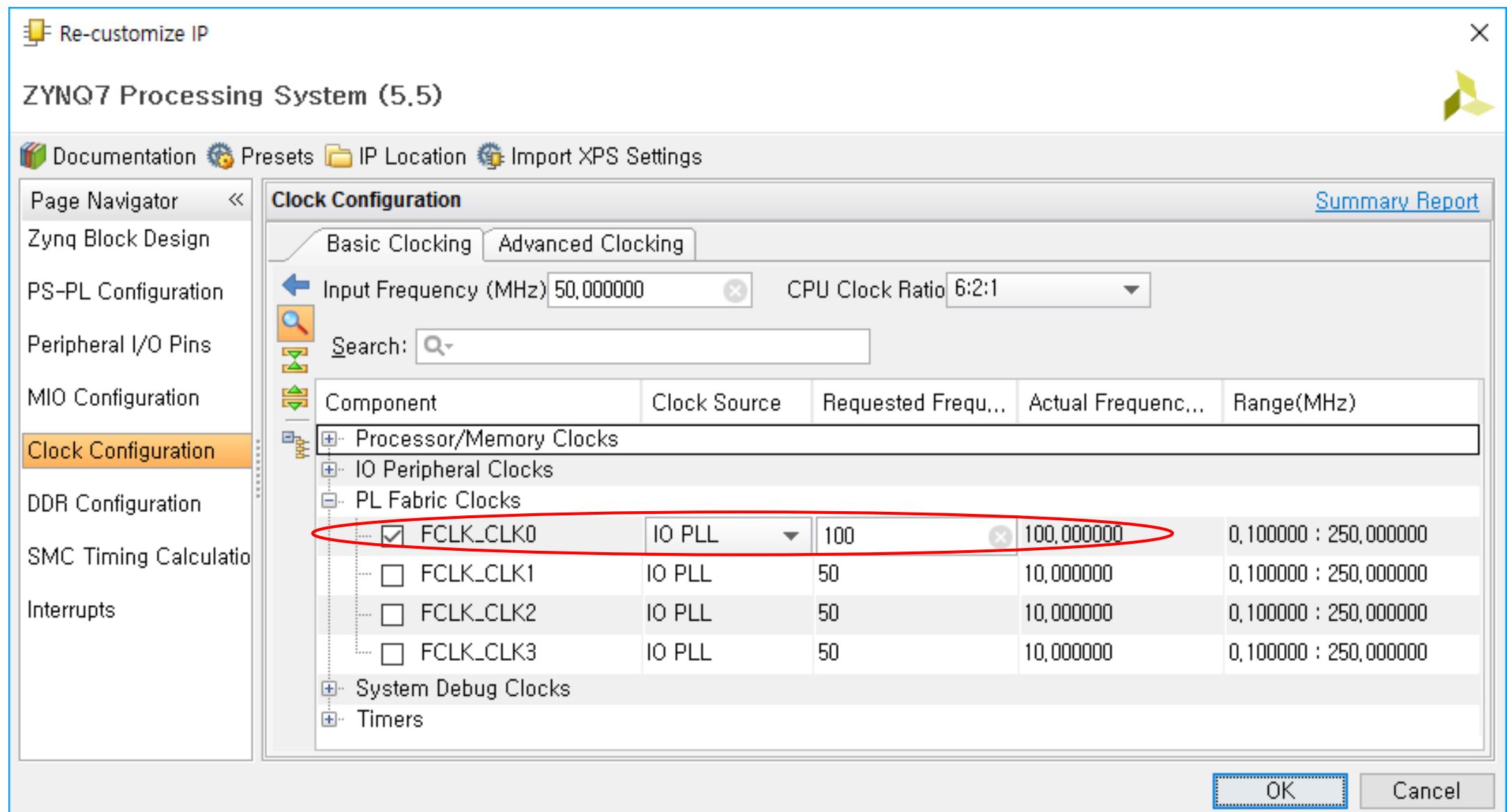
Based on Zynq7 PS Re-customize IP of embedded_linux project

The screenshot shows the Xilinx Vivado IP Re-customization tool interface for a ZYNQ7 Processing System (5.5). The left sidebar lists various configuration tabs: Page Navigator, Zynq Block Design, PS-PL Configuration (which is selected), Peripheral I/O Pins, MIO Configuration, Clock Configuration, DDR Configuration, SMC Timing Calculation, and Interrupts. The main area displays the PS-PL Configuration settings. A red circle highlights the 'Enable Clock Resets' section, specifically the row for 'FCLK_RESET0_N' where the checkbox is checked. Another red circle highlights the 'M AXI GP0 interface' under 'GP Master AXI Interface' where the checkbox is also checked. Other visible settings include UART baud rates, PL AXI idle port, DDR ARB bypass port, PS-PL Debug interface, FTM Trace data interface, FTM Trace buffer, FTM Data edge detector, FTM Trace buffer FIFO size, FTM Trace buffer clock delay, Include ACP transaction checker, Trace data/control signal pipeline width, Power-on reset(POR) 4k timer, Processor event interface, Address Editor, Enable Clock Triggers, and AXI Non Secure Enablement.

Name	Select	Description
UART0 Baud Rate	115200	Baud rate is generated with internally fixed UART Ref Clock Freq=10...
UART1 Baud Rate	115200	Baud rate is generated with internally fixed UART Ref Clock Freq=10...
PL AXI idle Port	<input type="checkbox"/>	Enables idle AXI signal to the PS used to indicate that there are no ...
DDR ARB bypass Port	<input type="checkbox"/>	Enables DDR urgent/arbitration signal used to signal a critical memory sta...
PS-PL Debug interface	<input type="checkbox"/>	Enables PL debug signals to PS and vice-versa
FTM Trace data interface	<input type="checkbox"/>	Enables FTM Trace AXI stream interface used to capture data from PL ... to PS debug system
FTM Trace buffer	0	Stores trace data in the FIFO when the data changes as marked by ...
FTM Data edge detector	0	FTM Trace buffer FIFO size
FTM Trace buffer FIFO size	128	Number of clock cycles interval for a trace data output from FIFO be...
FTM Trace buffer clock delay	12	Number of clock cycles interval for a trace data output from FIFO be...
Include ACP transaction checker	<input type="checkbox"/>	Enables ACP transaction checker.
Trace data/control signal pipeline width	8	Enables configurable number of pipeline stages on the TRACE DAT...
Power-on reset(POR) 4k timer	<input type="checkbox"/>	Enables power-on reset(POR) 4k timer. By default, 64k timer is used.
Processor event interface	<input type="checkbox"/>	Enables event bus which provides a low-latency and direct mecha...
Address Editor		
Enable Clock Triggers		
Enable Clock Resets		
FCLK_RESET0_N	<input checked="" type="checkbox"/>	Enables general purpose reset signal 0 for PL logic
FCLK_RESET1_N	<input type="checkbox"/>	Enables general purpose reset signal 1 for PL logic
FCLK_RESET2_N	<input type="checkbox"/>	Enables general purpose reset signal 2 for PL logic
FCLK_RESET3_N	<input type="checkbox"/>	Enables general purpose reset signal 3 for PL logic
AXI Non Secure Enablement		
GP Master AXI Interface		
M AXI GP0 interface	<input checked="" type="checkbox"/>	Enables General purpose AXI master interface 0
M AXI GP1 interface	<input type="checkbox"/>	Enables General purpose AXI master interface 1
GP Slave AXI Interface		

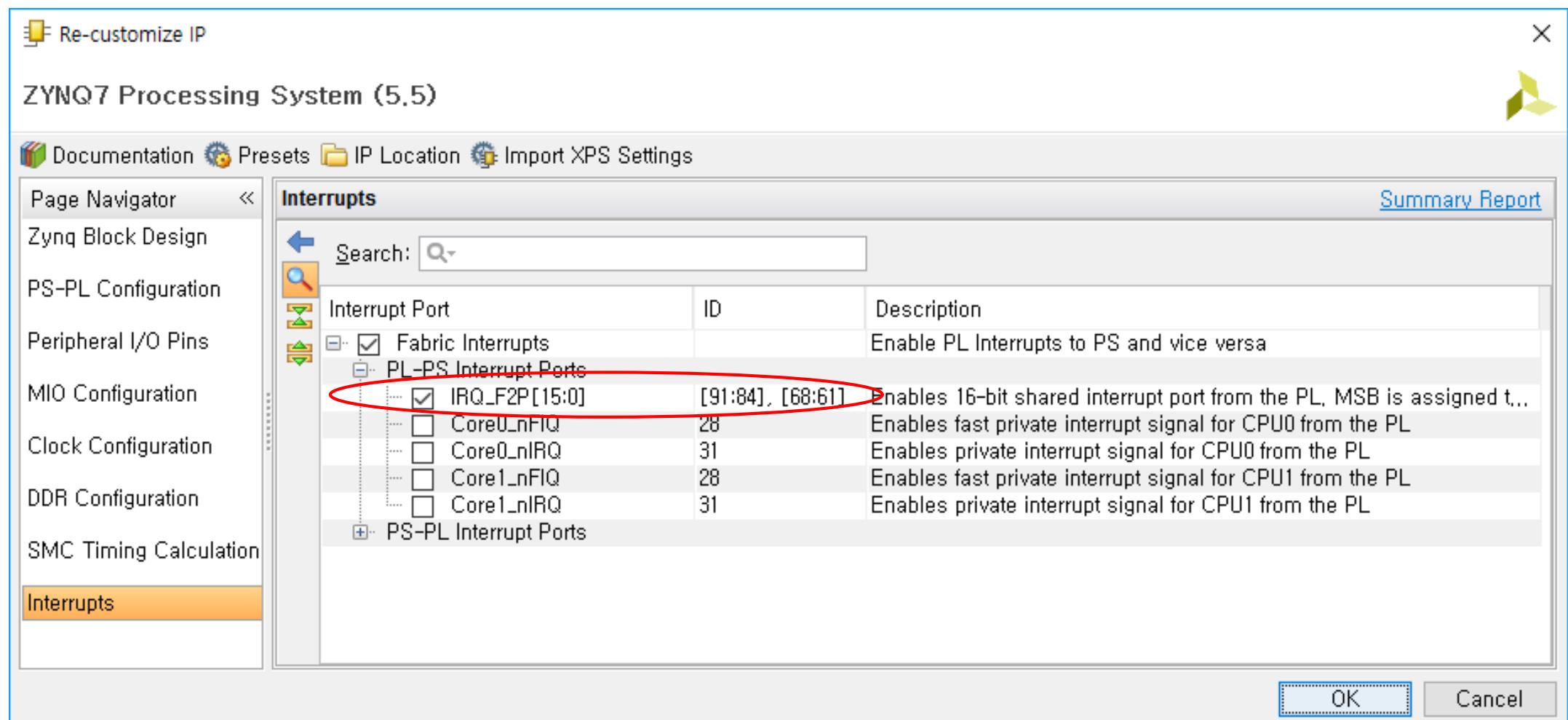
Zynq7 PS Re-customize IP for I2C

Based on Zynq7 PS Re-customize IP of embedded_linux project



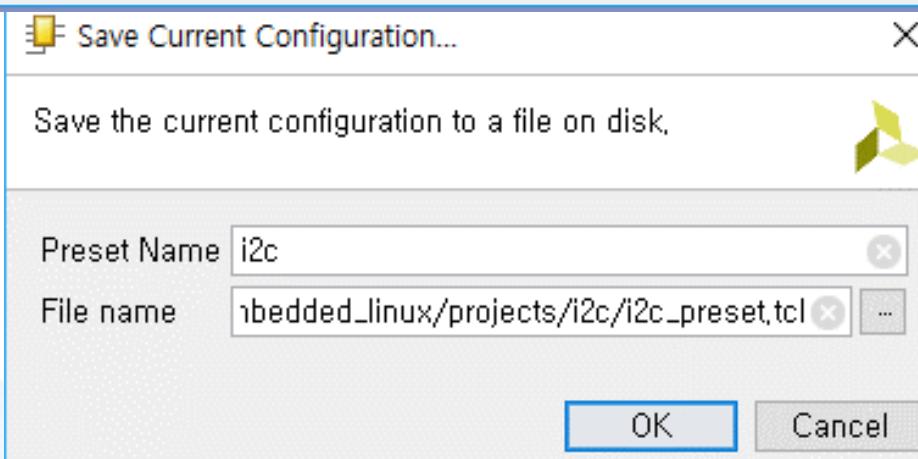
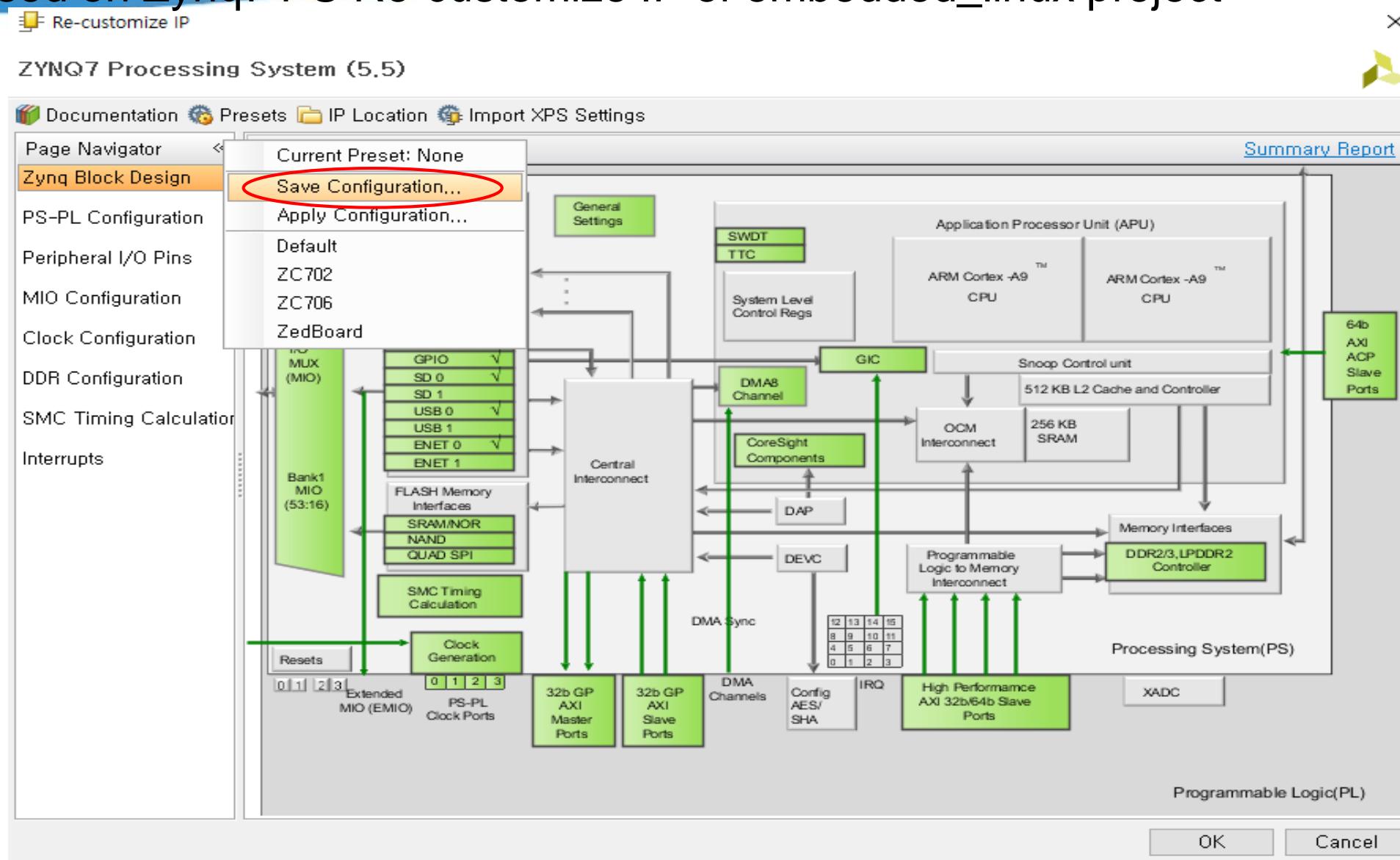
Zynq7 PS Re-customize IP for I2C

Based on Zynq7 PS Re-customize IP of embedded_linux project



Zynq7 PS Re-customize IP for I2C

Based on Zynq7 PS Re-customize IP of embedded_linux project



https://github.com/inipro/embedded_linux/projects/i2c

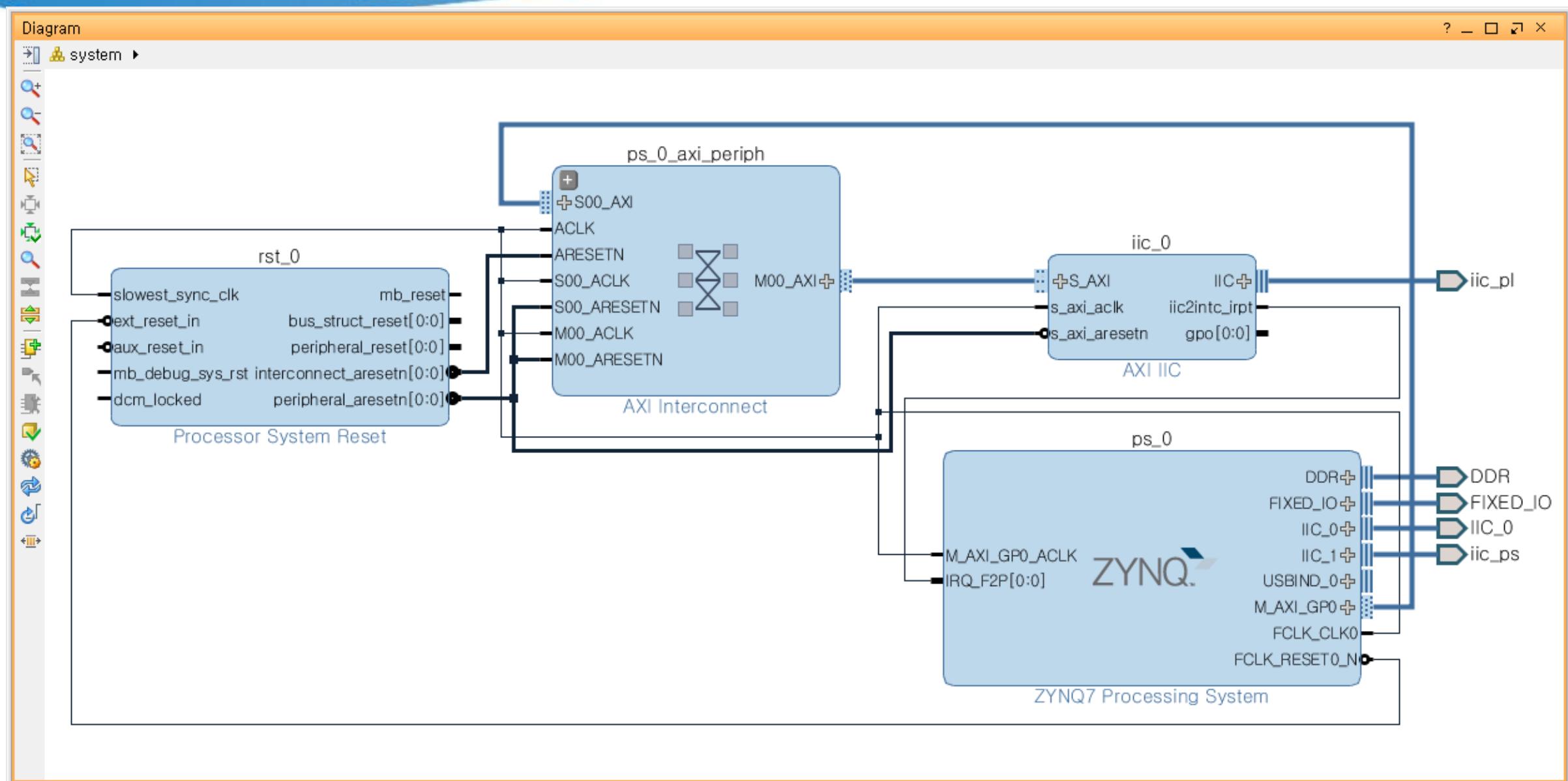
In cmd window for Vivado

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\i2c  
C:\> vivado -nolog -nojournal -mode batch -source i2c.tcl
```

output : i2c\i2c.xpr...



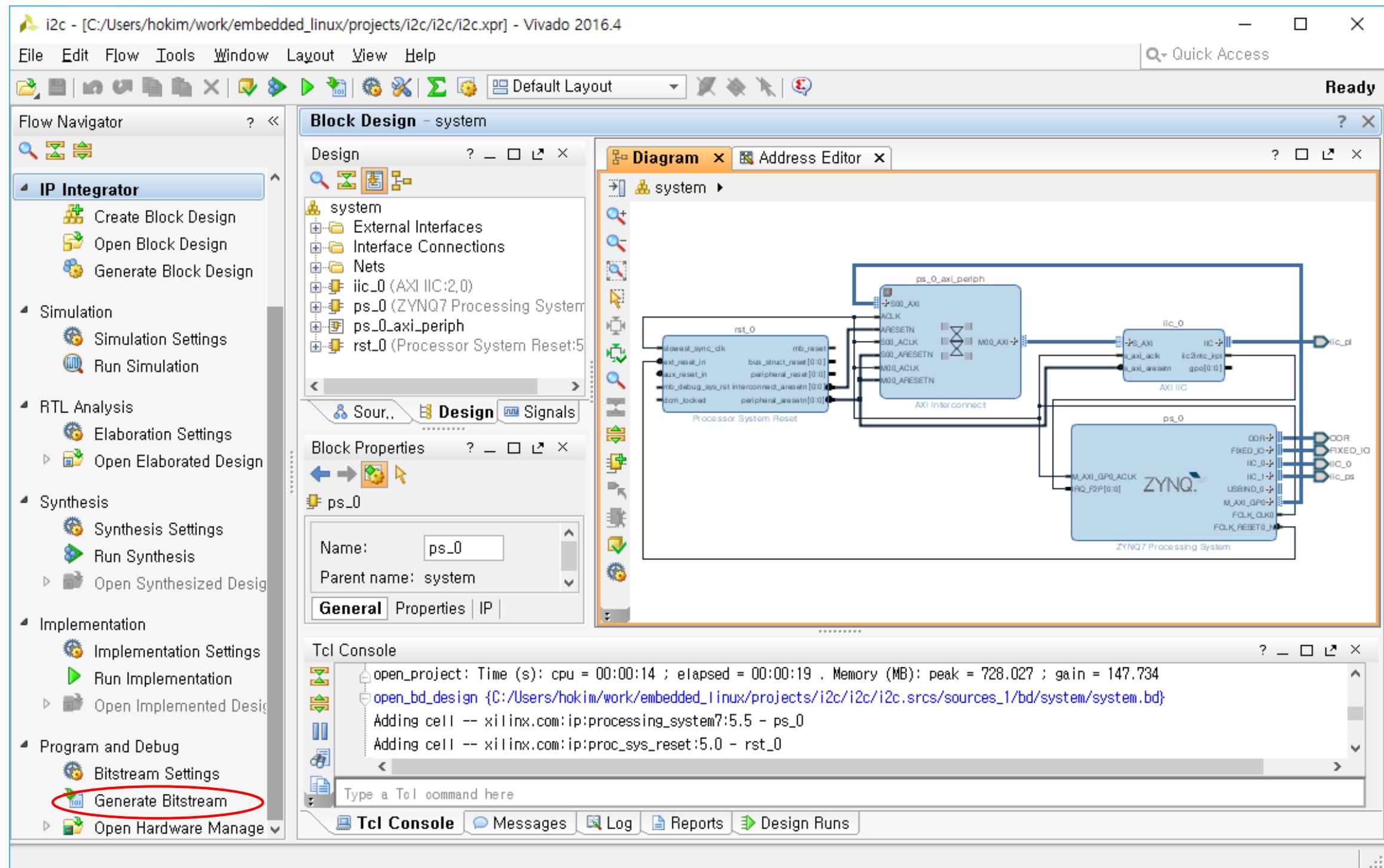
Project for I2C



Address Editor

Cell	Slave Interface	Base Name	Offset Address	Range	High Address
ps_0					
ps_0	Data (32 address bits : 0x40000000 [1G])	S_AXI	Reg	0x4000_0000	4K → 0x4000_0FFF
ps_0	iic_0				

Bit Generation for I2C



C:\Users\hokim\work\embedded_linux\projects\i2c\all.bat

```
call vivado -nolog -nojournal -mode batch -source hwdef.tcl  
call hsi -nolog -nojournal -mode batch -source fsbl.tcl  
call tclsh bootbin.tcl  
  
call hsi -nolog -nojournal -mode batch -source devicetree.tcl
```

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\i2c  
C:\> all
```



Device Tree Compile for I2C



The screenshot shows the MobaXterm interface with multiple sessions open:

- Session 1: 192.168.119.128 (hokim) - Terminal tab
- Session 2: 2. 192.168.0.5 (hokim) - File manager tab showing a directory tree for a Vivado project.
- Session 3: 3. COM4 (USB Serial Port(COM4)) - File manager tab showing a directory listing for a USB serial port.
- Session 4: 5. 192.168.119.128 (hokim) - File manager tab showing a directory listing for the target Linux system at /home/hokim/work/embedded_linux/projects/

A red arrow points to the "i2c" folder in the local directory listing of Session 2, indicating it is being selected for upload. The status bar at the bottom of the window shows the following log entries:

```
Upload command received  
Upload command received  
Upload command received  
Opening directory /home/hokim/work/embedded_linux/projects...  
Open directory command received  
Directory content listed
```

UNREGISTERED VERSION - Please support MobaXterm by subscribing to the professional edition here: <http://mobaxterm.mobatek.net>

```
$ cd ~/work/embedded_linux/projects/i2c  
$ cp i2c/i2c.tree/system.dts  system_i2c.dts  
$ nano system_i2c.dts
```

Device Tree Compile for I2C

system_i2c.dts

```
/dts-v1;
/include/ "zynq-7000.dtsi"
/include/ "pl.dtsi"

.....
.....
&clkc {
    fclk-enable = <0x1>;
    ps-clk-frequency = <50000000>;
};

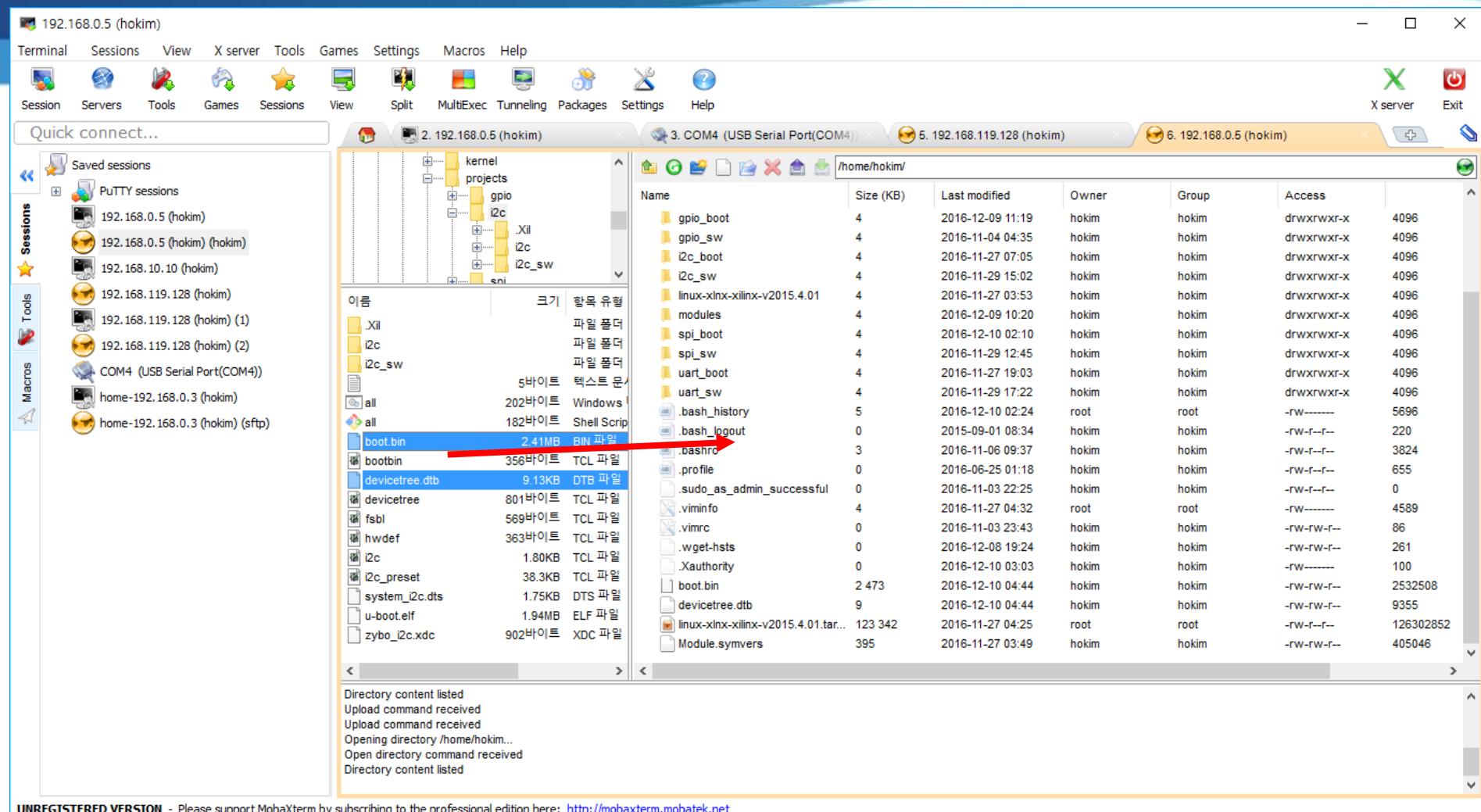
+};
+&i2c0 {
+    eeprom@50 {
+        /* Microchip 24AA02E48 */
+        compatible = "microchip,24c02";
+        reg = <0x50>;
+        pagesize = <8>;
+    };
+};
+/ {
+    usb_phy0: phy0 {
+        compatible = "ulpi-phy";
+        #phy-cells = <0>;
+        reg = <0xe0002000 0x1000>;
+        view-port = <0x0170>;
+        drv-vbus;
+    };
+};
+&usb0 {
+    usb-phy = <&usb_phy0>;
+};
```

i2c/i2c.tree/pl.dtsi

```
/ {  
    amba_pl: amba_pl {  
        #address-cells = <1>;  
        #size-cells = <1>;  
        compatible = "simple-bus";  
        ranges ;  
        iic_0: i2c@40000000 {  
            #address-cells = <1>;  
            #size-cells = <0>;  
            compatible = "xlnx,xps-iic-2.00.a";  
            interrupt-parent = <&intc>;  
            interrupts = <0 29 4>;  
            reg = <0x40000000 0x1000>;  
        };  
    };  
};
```

```
$ dtc -O dtb -I dts -i i2c/i2c.tree/ -o devicetree.dtb system_i2c.dts
```

Update boot.bin, devicetree.dtb for I2C



login into zybo

```
$ sudo -s
# cd /boot
# rm boot.bin devicetree.dtb
# mv ~hokim/boot.bin .
# mv ~hokim/devicetree.dtb
# sync
# reboot
```

I2C sw & test

```
hokim@zybo:~$ ls /dev/i2c-*
/dev/i2c-0 /dev/i2c-1 /dev/i2c-2
hokim@zybo:~$ sudo i2cdetect -l
i2c-0 i2c      Cadence I2C at e0004000
i2c-1 i2c      Cadence I2C at e0005000
i2c-2 i2c      xiic-i2c
I2C adapter
I2C adapter
I2C adapter
hokim@zybo:~$ sudo i2cdetect -y -r 0
 0 1 2 3 4 5 6 7 8 9 a b c d e f
00: -----
10: ----- 1a -----
20: -----
30: -----
40: -----
50: UU -----
60: -----
70: -----
hokim@zybo:~$ sudo i2cdetect -y -r 2
 0 1 2 3 4 5 6 7 8 9 a b c d e f
00: -----
10: -----
20: -----
30: -----
40: ----- 48 -----
50: -----
60: -----
70: -----
```

```
hokim@zybo:~$ cd i2c_sw/
hokim@zybo:~/i2c_sw$ ls
CMakeLists.txt PmodCLS.c PmodCLS.h main.c i2c.c i2c.h
hokim@zybo:~/i2c_sw$ mkdir build
hokim@zybo:~/i2c_sw$ cd build
hokim@zybo:~/i2c_sw/build$ cmake ..
hokim@zybo:~/i2c_sw/build$ make
hokim@zybo:~/i2c_sw/build$ sudo ./i2c_test
```

```
hokim@zybo:~$ cd i2c_sw/python
hokim@zybo:~/i2c_sw/python$ ls
i2c_test.py i2cdev.py pmodcls_i2c.py
hokim@zybo:~/i2c_sw/python$ sudo python i2c_test.py
```

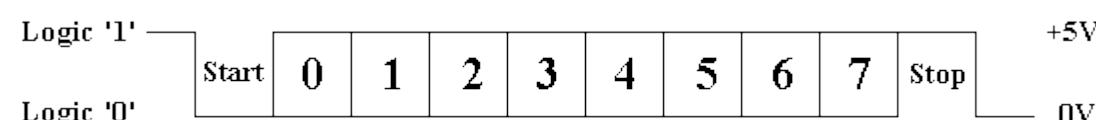


- Universal asynchronous receiver/transmitter

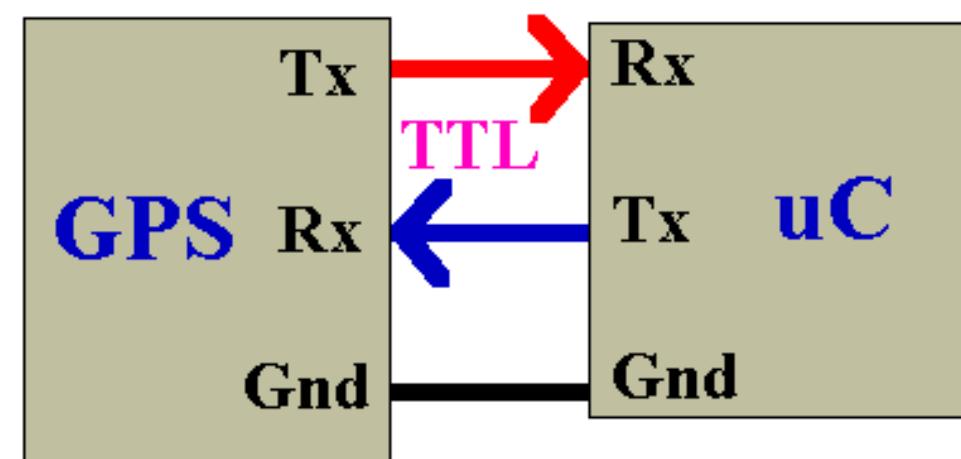
TX : Receiver

RX : Transmitter

- Data transmission from 5 bits to 9bits, with parity option and option for 1, 1.5, and 2 stop bits
- Various speeds starting from 300bps upto 4Mbps(Most commonly used baud rates : 96800, 115200)



UART Communication



- **General interface for each type terminal**

Serial Port(UART) terminal : /dev/ttySn

Pseudo terminal : /dev/pts/n

Controlling terminal : /dev/tty

Console terminal : /dev/ttyn, /dev/console

- **Documented in Document/serial**

- **Driver : drivers/tty/serial/(xilinx_uartps.c, uartlite.c)**

- **Xilinx UART character device : /dev/ttyPSn, /dev/ttyULn**

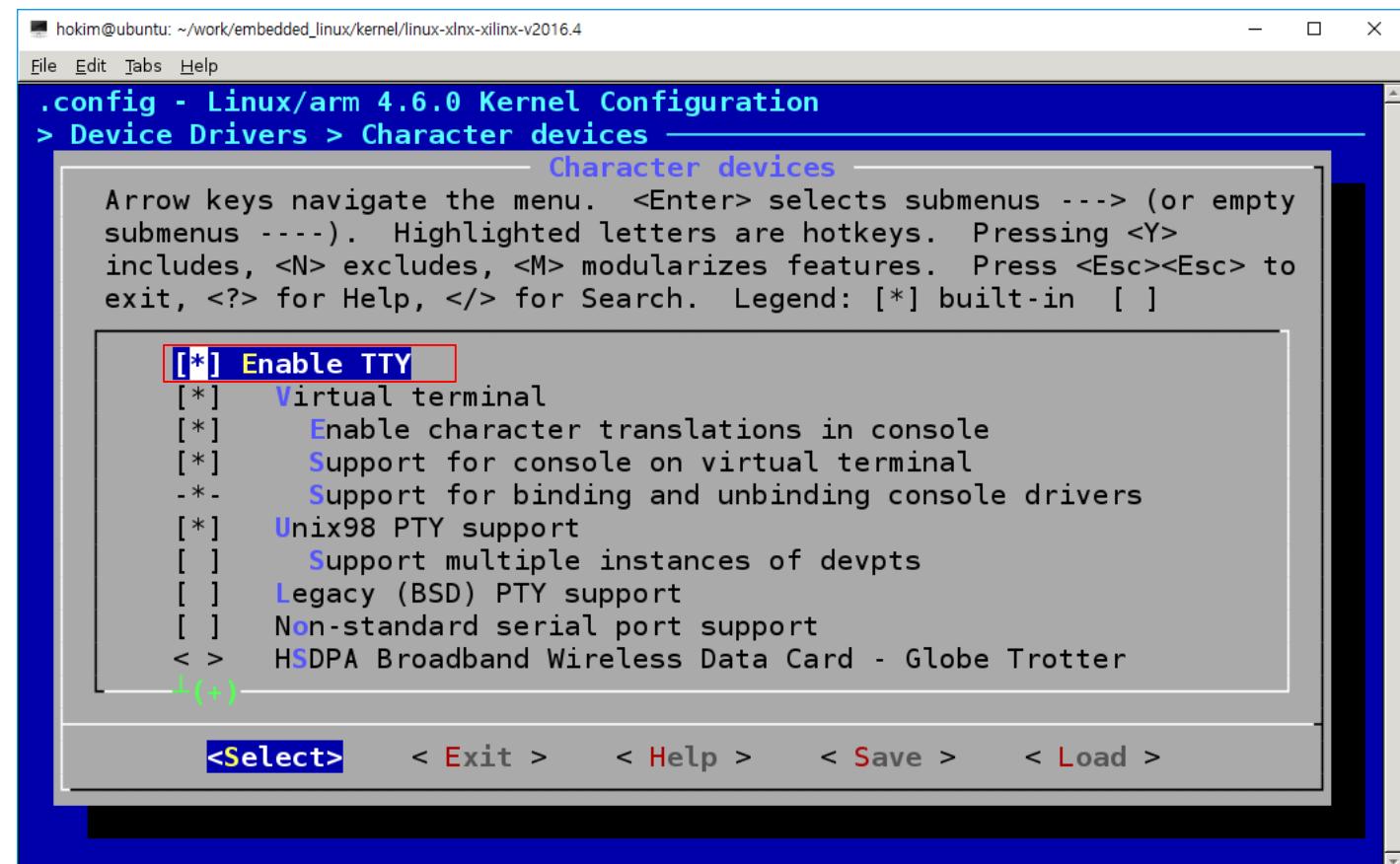
Linux UART Userspace Interface

Kernel Configuration

```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > Character devices > Serial drivers
    └── Serial drivers
        Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
        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 [ ]
        ^(-)
            < > SC16IS7xx serial support
            < > Broadcom BCM63xx/BCM33xx UART support
            < > Altera JTAG UART support
            < > Altera UART support
            < > SPI protocol driver for Infineon 6x60 modem (EXPERIMENTAL)
            <*> Cadence (Xilinx Zynq) UART support
                [*] Cadence UART console support
            < > ARC UART driver support
            < > Comtrol RocketPort EXPRESS/INFINITY support
            < > Freescale lpuart serial port support
        L(+)
        <Select> < Exit > < Help > < Save > < Load >
```

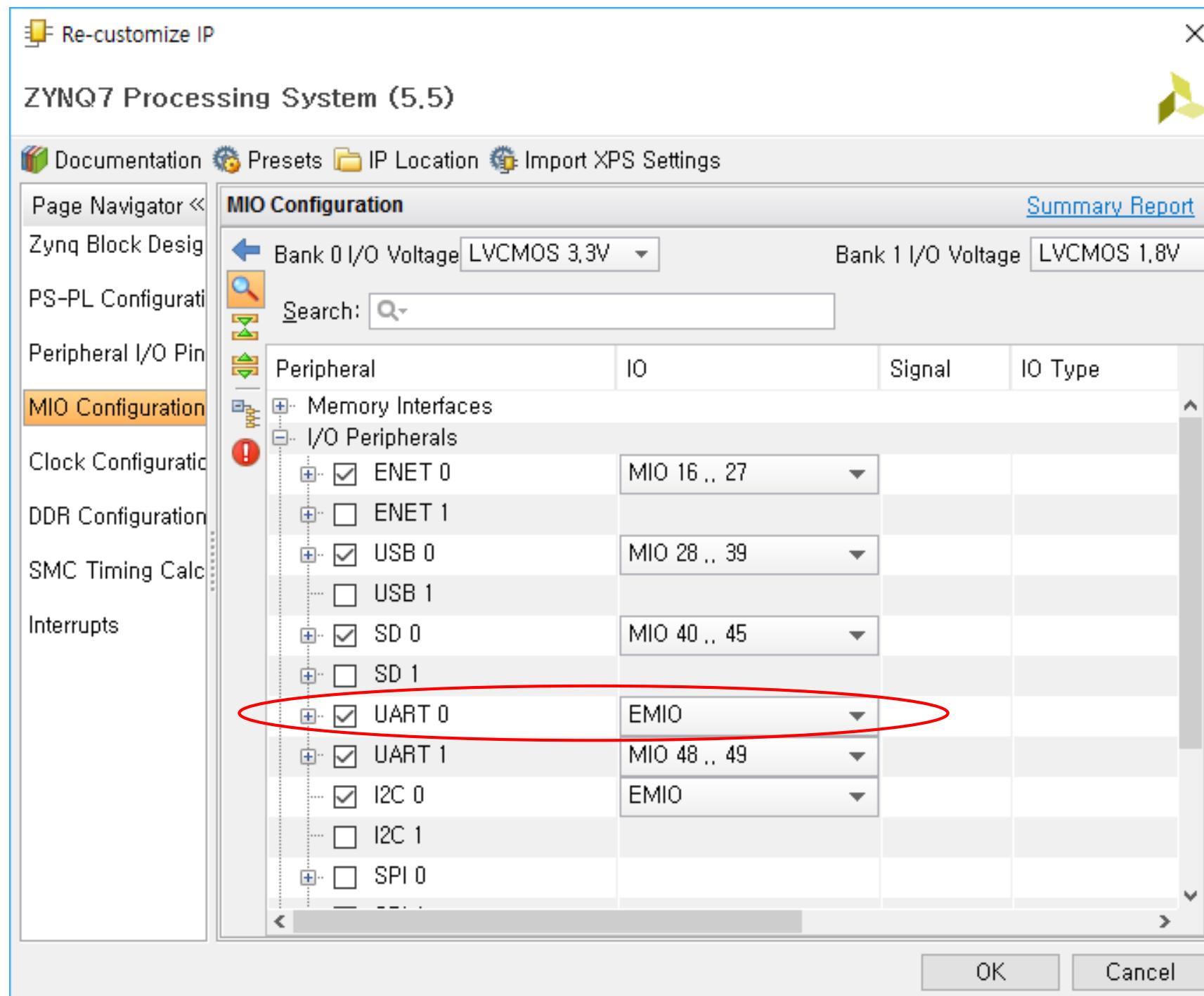
```
hokim@ubuntu: ~/work/embedded_linux/kernel/linux-xlnx-xilinx-v2016.4
File Edit Tabs Help
.config - Linux/arm 4.6.0 Kernel Configuration
> Device Drivers > Character devices > Serial drivers
    └── Serial drivers
        Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
        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 [ ]
        ^(-)
            [ ] Early console using ARM semihosting
            < > MAX3100 support
            < > MAX310X support
            <*> Xilinx uartlite serial port support
                [*] Support for console on Xilinx uartlite serial port
            < > Digi International NE0 and Classic PCI Support
            < > SCCNXP serial port support
            < > SC16IS7xx serial support
            < > Broadcom BCM63xx/BCM33xx UART support
            < > Altera JTAG UART support
        L(+)
        <Select> < Exit > < Help > < Save > < Load >
```

Kernel Configuration



Zynq7 PS Re-customize IP for UART

Based on Zynq7 PS Re-customize IP of embedded_linux project



Zynq7 PS Re-customize IP for UART

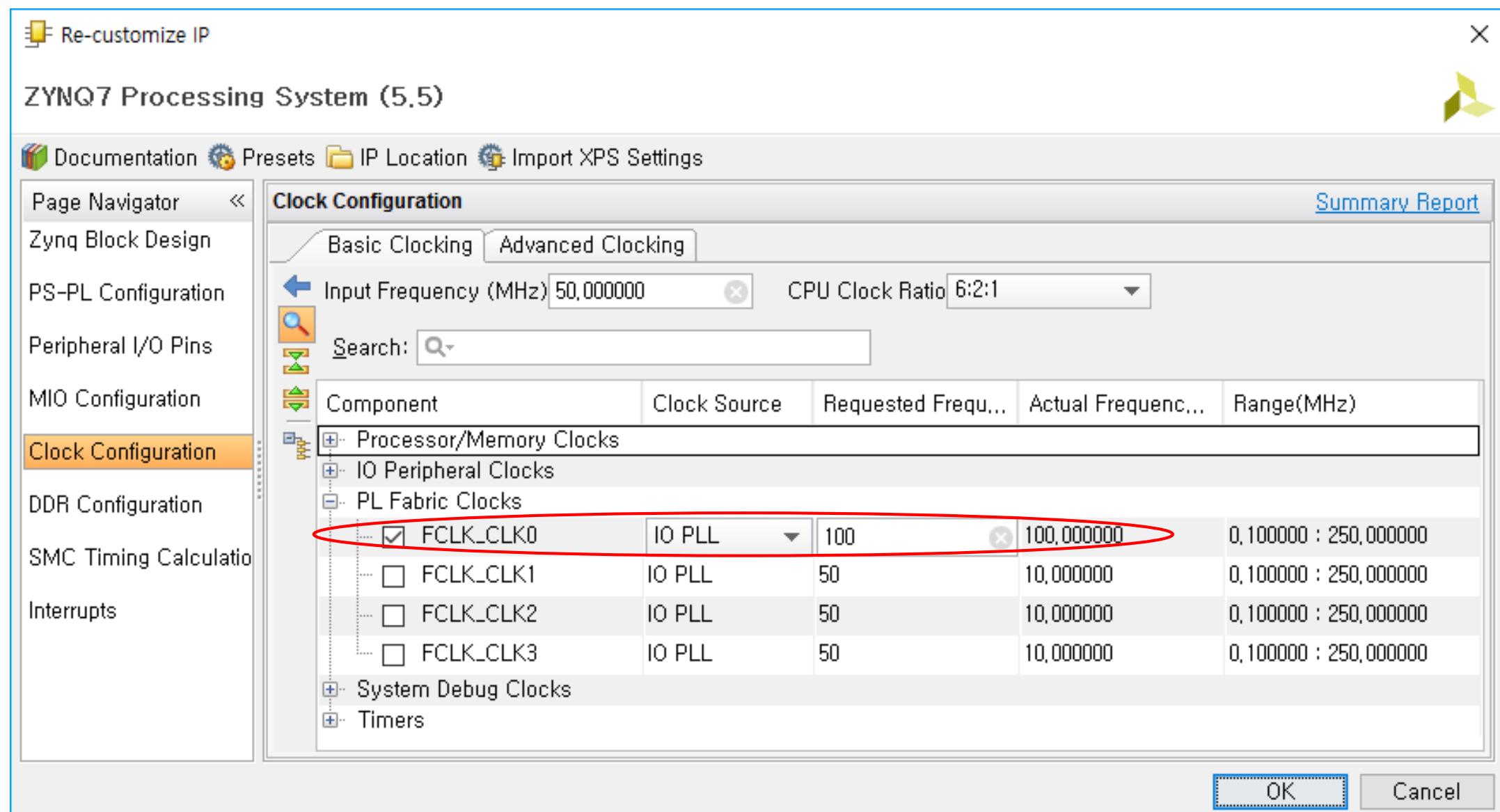


Based on Zynq7 PS Re-customize IP of embedded_linux project

The screenshot shows the 'PS-PL Configuration' window for a ZYNQ7 Processing System (5.5). The left sidebar lists various configuration categories: Page Navigator, Zynq Block Design, PS-PL Configuration (which is selected), Peripheral I/O Pins, MIO Configuration, Clock Configuration, DDR Configuration, SMC Timing Calculation, and Interrupts. The main area displays a table of configuration parameters under the 'General' section. The 'FCLK_RESET0_N' checkbox is checked and circled in red. Another red circle highlights the 'M AXI GP0 interface' checkbox, which is also checked. Other visible parameters include UART0 and UART1 Baud Rates, PL AXI idle Port, DDR ARB bypass Port, PS-PL Debug interface, FTM Trace data interface, FTM Trace buffer, FTM Data edge detector, FTM Trace buffer FIFO size, FTM Trace buffer clock delay, Include ACP transaction checker, Trace data/control signal pipeline width, Power-on reset(POR) 4k timer, Processor event interface, Address Editor, Enable Clock Triggers, and Enable Clock Resets.

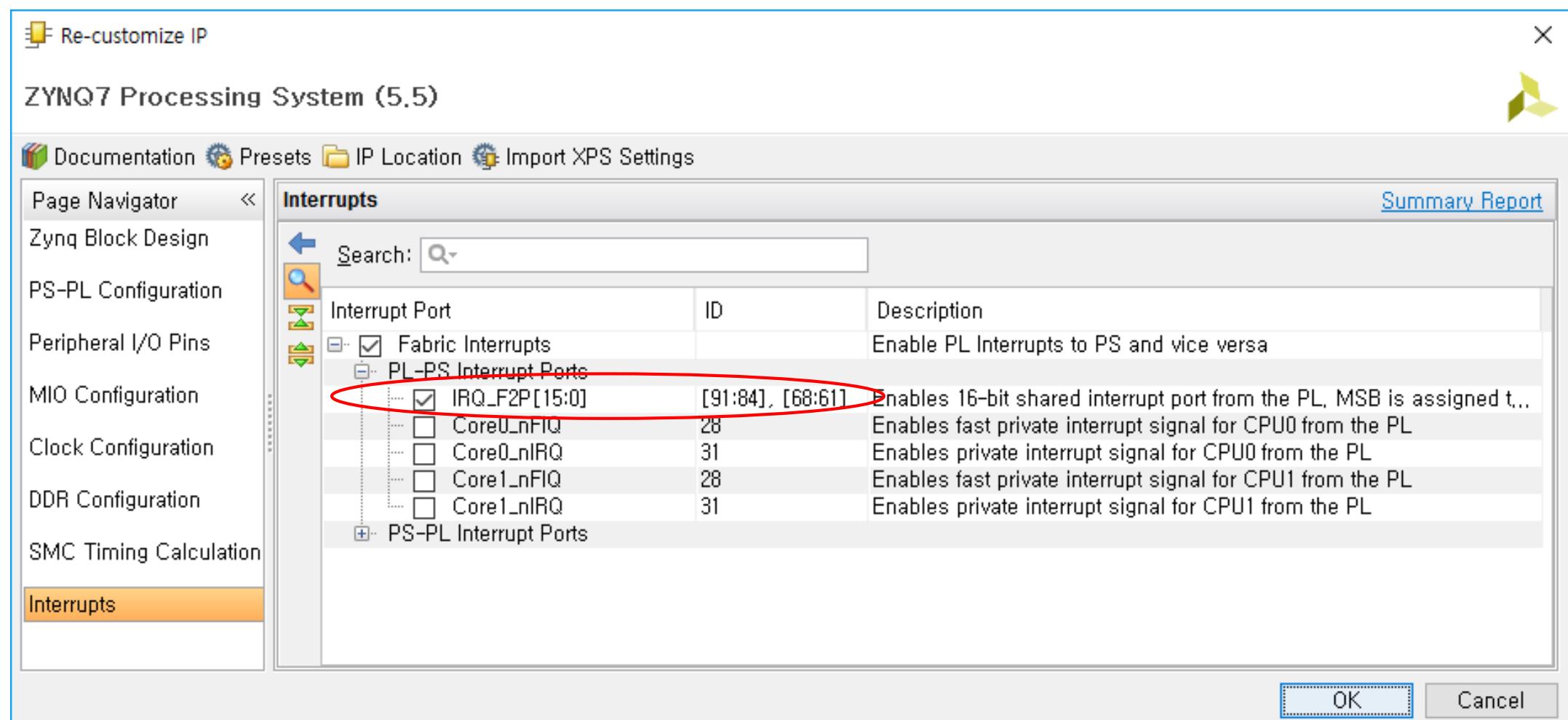
Name	Select	Description
UART0 Baud Rate	115200	Baud rate is generated with internally fixed UART Ref Clock Freq=10...
UART1 Baud Rate	115200	Baud rate is generated with internally fixed UART Ref Clock Freq=10...
PL AXI idle Port	<input type="checkbox"/>	Enables idle AXI signal to the PS used to indicate that there are no ...
DDR ARB bypass Port	<input type="checkbox"/>	Enables DDR urgent/arbitration signal used to signal a critical memory sta...
PS-PL Debug interface	<input type="checkbox"/>	Enables PL debug signals to PS and vice-versa
FTM Trace data interface	<input type="checkbox"/>	Enables FTM Trace AXI stream interface used to capture data from PL ... to PS debug system
FTM Trace buffer	0	Stores trace data in the FIFO when the data changes as marked by ...
FTM Data edge detector	0	FTM Trace buffer FIFO size
FTM Trace buffer FIFO size	128	Number of clock cycles interval for a trace data output from FIFO be...
FTM Trace buffer clock delay	12	Number of clock cycles interval for a trace data output from FIFO be...
Include ACP transaction checker	<input type="checkbox"/>	Enables ACP transaction checker.
Trace data/control signal pipeline width	8	Enables configurable number of pipeline stages on the TRACE DAT...
Power-on reset(POR) 4k timer	<input type="checkbox"/>	Enables power-on reset(POR) 4k timer. By default, 64k timer is used.
Processor event interface	<input type="checkbox"/>	Enables event bus which provides a low-latency and direct mecha...
Address Editor		
Enable Clock Triggers		
Enable Clock Resets		
FCLK_RESET0_N	<input checked="" type="checkbox"/>	Enables general purpose reset signal 0 for PL logic
FCLK_RESET1_N	<input type="checkbox"/>	Enables general purpose reset signal 1 for PL logic
FCLK_RESET2_N	<input type="checkbox"/>	Enables general purpose reset signal 2 for PL logic
FCLK_RESET3_N	<input type="checkbox"/>	Enables general purpose reset signal 3 for PL logic
AXI Non Secure Enablement		
GP Master AXI Interface		
M AXI GP0 interface	<input checked="" type="checkbox"/>	Enables General purpose AXI master interface 0
M AXI GP1 interface	<input type="checkbox"/>	Enables General purpose AXI master interface 1
GP Slave AXI Interface		

Based on Zynq7 PS Re-customize IP of embedded_linux project



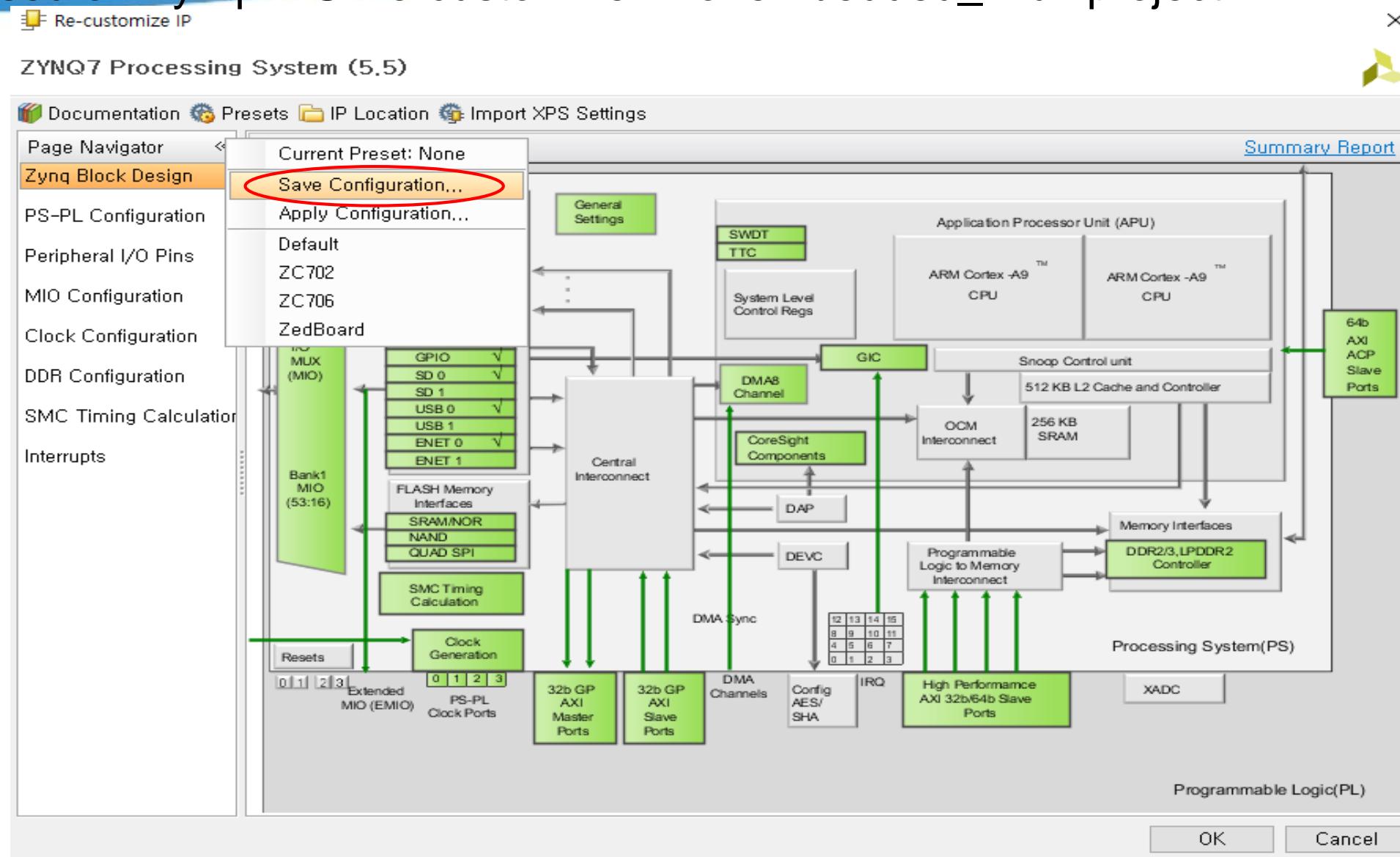
Zynq7 PS Re-customize IP for UART

Based on Zynq7 PS Re-customize IP of embedded_linux project



Zynq7 PS Re-customize IP for UART

Based on Zynq7 PS Re-customize IP of embedded_linux project



Save Current Configuration...

Save the current configuration to a file on disk.

Preset Name: uart

File name: /embedded_linux/projects/uart/uart_preset.tcl

OK Cancel

https://github.com/inipro/embedded_linux/projects/uart

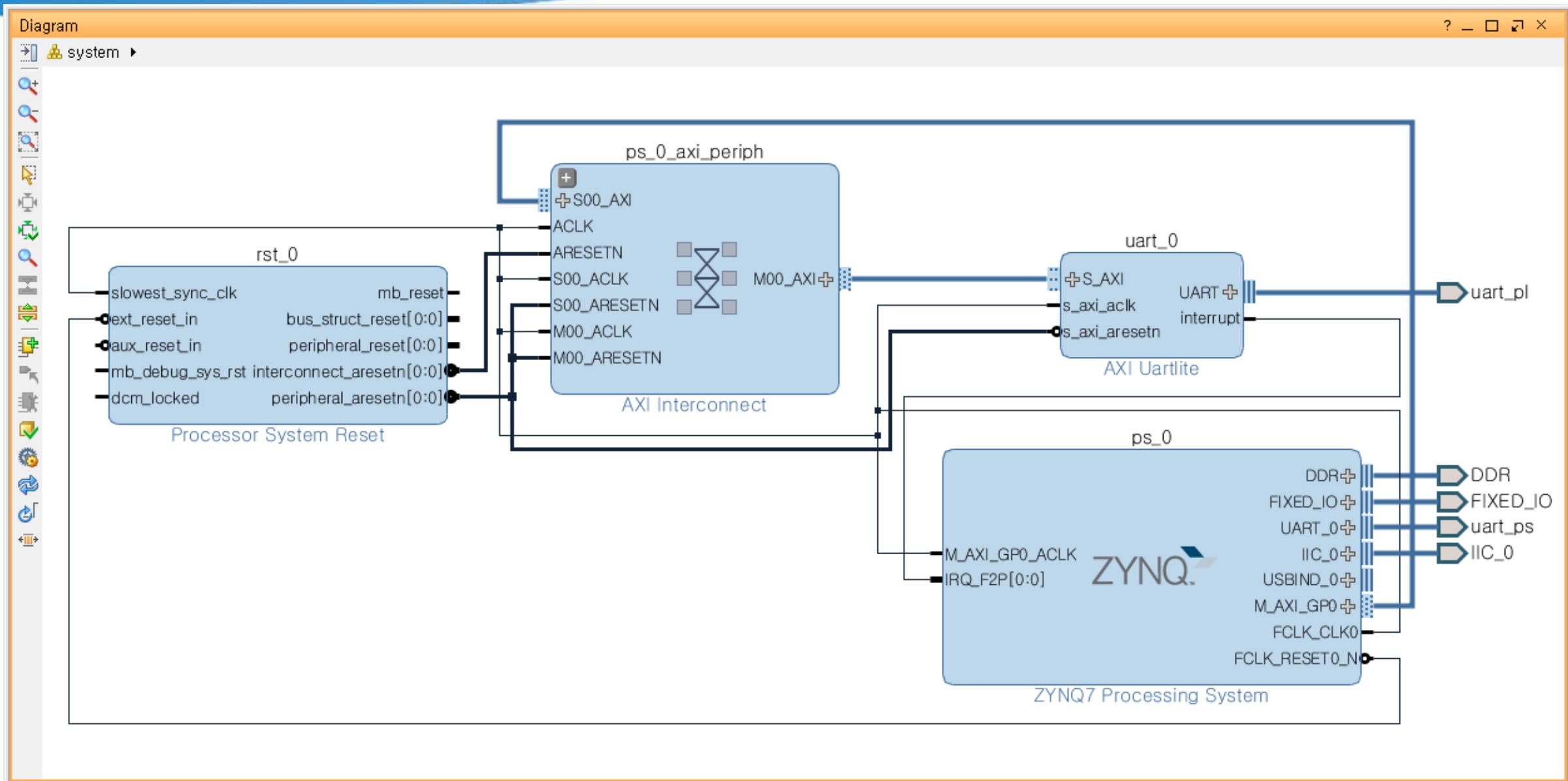
In cmd window for Vivado

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\uart  
C:\> vivado -nolog -nojournal -mode batch -source uart.tcl
```

output : uart\uart.xpr...



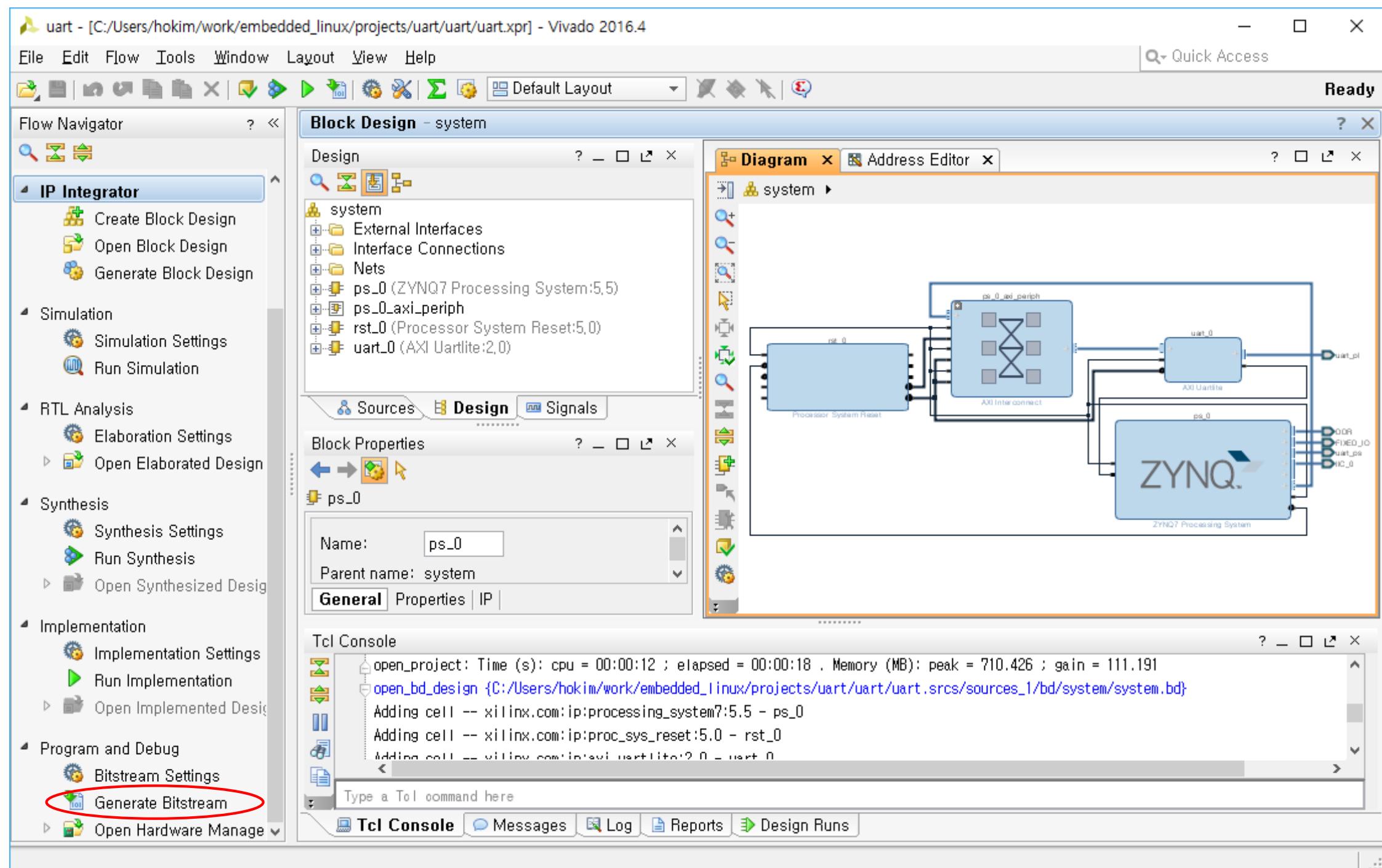
Project for UART



Address Editor

Cell	Slave Interface	Base Name	Offset Address	Range	High Address
ps_0 Data (32 address bits : 0x40000000 [1G]) uart_0	S_AXI	Reg	0x4000_0000	4K	0x4000_0FFF

Bit Generation for UART

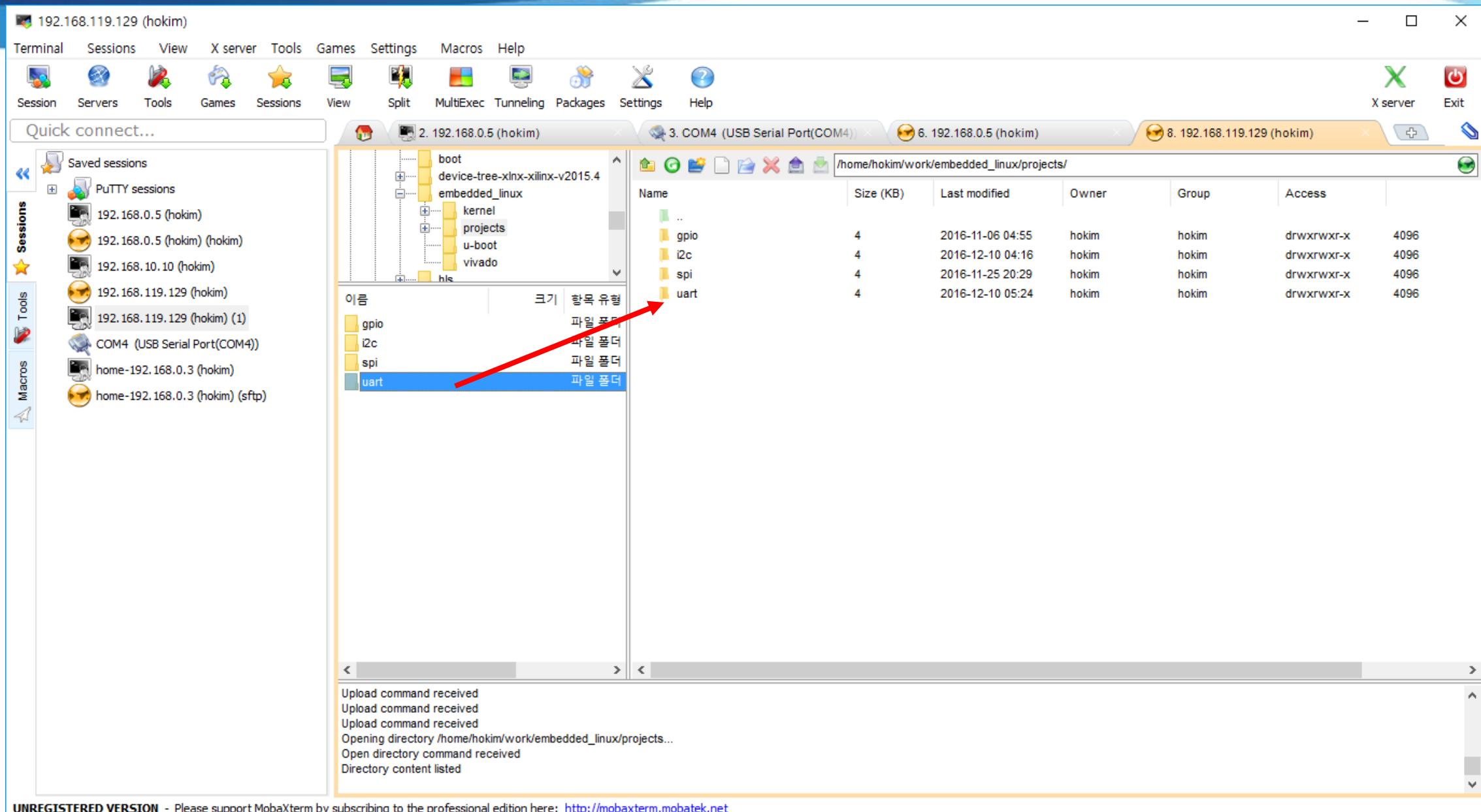


C:\Users\hokim\work\embedded_linux\projects\uart\all.bat

```
call vivado -nolog -nojournal -mode batch -source hwdef.tcl  
call hsi -nolog -nojournal -mode batch -source fsbl.tcl  
call tclsh bootbin.tcl  
  
call hsi -nolog -nojournal -mode batch -source devicetree.tcl
```

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\uart  
C:\> all
```

Device Tree Compile for UART



```
$ cd ~/work/embedded_linux/projects/uart
$ cp uart/uart.tree/system.dts system_uart.dts
$ nano system_uart.dts
```

Device Tree Compile for UART

system_uart.dts

```
/dts-v1/;  
/include/ "zynq-7000.dtsi"  
/include/ "pl.dtsi"  
.....  
.....  
&clkc {  
    fclk-enable = <0x1>;  
    ps-clk-frequency = <50000000>;  
};  
+&i2c0 {  
    eeprom@50 {  
        /* Microchip 24AA02E48 */  
        compatible = "microchip,24c02";  
        reg = <0x50>;  
        pagesize = <8>;  
    };  
};  
+/  
+/  
+    usb_phy0: phy0 {  
    compatible = "ulpi-phy";  
    #phy-cells = <0>;  
    reg = <0xe0002000 0x1000>;  
    view-port = <0x0170>;  
    drv-vbus;  
};  
+&usb0 {  
    usb-phy = <&usb_phy0>;  
};
```

```
+/  
+    aliases {  
+        serial0 = &uart1;  
+        serial1 = &uart0;  
+    };  
+};  
+&uart0 {  
    port-number = <1>;  
};  
+&uart1 {  
    port-number = <0>;  
};  
+&uart_0 {  
    port-number = <0>;  
};
```

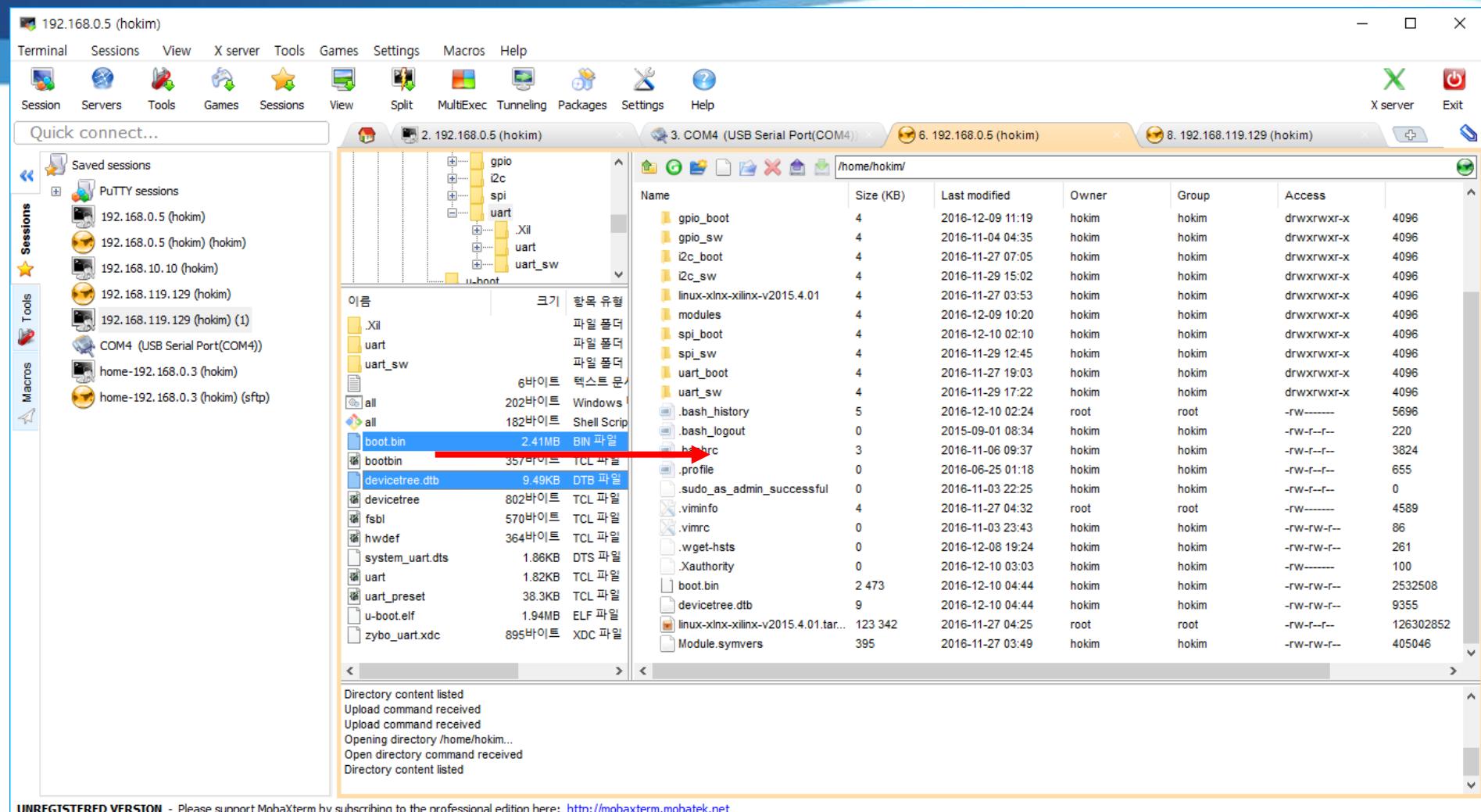
Device Tree Compile for UART

uart uart.tree/pl.dtsi

```
/ {  
    amba_pl: amba_pl {  
        #address-cells = <1>;  
        #size-cells = <1>;  
        compatible = "simple-bus";  
        ranges ;  
        uart_0: serial@40000000 {  
            clock-names = "ref_clk";  
            clocks = <&clkc 0>;  
            compatible = "xlnx,xps-uartlite-1.00.a";  
            current-speed = <115200>;  
            device_type = "serial";  
            interrupt-parent = <&intc>;  
            interrupts = <0 29 1>;  
            port-number = <2>;  
            reg = <0x40000000 0x1000>;  
            xlnx,baudrate = <0x2580>;  
            xlnx,data-bits = <0x8>;  
            xlnx,odd-parity = <0x0>;  
            xlnx,s-axi-aclk-freq-hz-d = "100.0";  
            xlnx,use-parity = <0x0>;  
        };  
    };  
};
```

```
$ dtc -O dtb -I dts -i uart uart.tree/ -o devicetree.dtb system_uart.dts
```

Update boot.bin, devicetree.dtb for UART



login into zybo

```
$ sudo -s
# cd /boot
# rm boot.bin devicetree.dtb
# mv ~hokim/boot.bin .
# mv ~hokim/devicetree.dtb
# sync
# reboot
```

```
hokim@zybo:~$ ls /dev/ttyPS* /dev/ttyUL*
/dev/ttyPS0 /dev/ttyPS1 /dev/ttyUL0
hokim@zybo:~$ sudo cat /sys/class/tty/ttyPS0/iomem_base
0xE0001000
hokim@zybo:~$ sudo cat /sys/class/tty/ttyPS1/iomem_base
0xE0000000
hokim@zybo:~$ sudo cat /sys/class/tty/ttyUL0/iomem_base
0x40000000
```

```
hokim@zybo:~$ cd uart_sw/
hokim@zybo:~/uart_sw$ ls
CMakeLists.txt PmodCLS.c PmodCLS.h main.c uart.c uart.h
hokim@zybo:~/uart_sw$ mkdir build
hokim@zybo:~/uart_sw$ cd build
hokim@zybo:~/uart_sw/build$ cmake ..
hokim@zybo:~/uart_sw/build$ make
hokim@zybo:~/uart_sw/build$ sudo ./uart_test
```

```
hokim@zybo:~$ cd uart_sw/python
hokim@zybo:~/uart_sw/python$ ls
pmodcls_uart.py uart_test.py
hokim@zybo:~/uart_sw/python$ sudo apt install python-serial
hokim@zybo:~/uart_sw/python$ sudo python uart_test.py
```



- **The Linux kernel provides a framework for doing user space drivers called UIO**
- **The framework is a character mode kernel driver (in drivers/uio) which runs as a layer under a user space driver**
- **UIO helps to offload some of the work to develop a driver**
- **UIO handles simple device drivers really well**

Simple driver: Device access and interrupt processing with no need to access kernel frameworks



■ Advantages

Runs in kernel space in the highest privilege mode to allow access to interrupts and hardware resources

There are a lot of kernel services such that kernel space drivers can be designed for complex devices

The kernel provides an API to user space which allows multiple applications to access a kernel space driver simultaneously

- Larger and more scalable software systems can be architected

Many drivers tend to be kernel space

- Asking questions in the open source community is going to be easier
- Pusing drivers to the open source community is likely easier



■ Disadvantages

System call overhead to access drivers

- A switch from user space to kernel space (and back) is required
- Overhead can be non-deterministic having impact on real time applications

Challenging learning curve for developers

- The kernel API is different from the application level API such that it takes time to become productive

Bugs can be fatal causing a kernel crash

Challenging to debug

- Kernel code is highly optimized and there are different debug tools

Frequent kernel API changes

- Kernel drivers built for one kernel version may not build for another



■ Advantages

Less challenging to debug as debug tools are more readily available and common to normal application development

User space services such as floating point are available

Device access is very efficient as there is no system call required

The application API of Linux is very stable

The driver can be written in any language, not just “C”



■ Disadvantages

No access to the kernel frameworks and services

- Contiguous memory allocation, direct cache control, and DMA are not available
- May have to duplicate kernel code or use a kernel driver to supplement

Interrupt handling cannot be done in user space

- It must be handled by a kernel driver which notifies user space causing some delay

There is no predefined API to allow applications to access the device driver

- Concurrency must also be considered if multiple applications access a driver



- **There are two distinct UIO device drivers provided by Linux in drivers/uio**
- **UIO Driver (drivers/uio.c)**

For more advanced users as a minimal kernel space driver is required to setup the UIO framework

This is the most universal and likely to handle all situations since the kernel space driver can be very custom

The majority of work can be accomplished in the user space driver

- **UIO Platform Device Driver (drivers/uio_pdev_irqgen.c)**

This driver augments the UIO driver such that no kernel space driver is required

- It provides the required kernel space driver for uio.c

It works with device tree making it easy to use

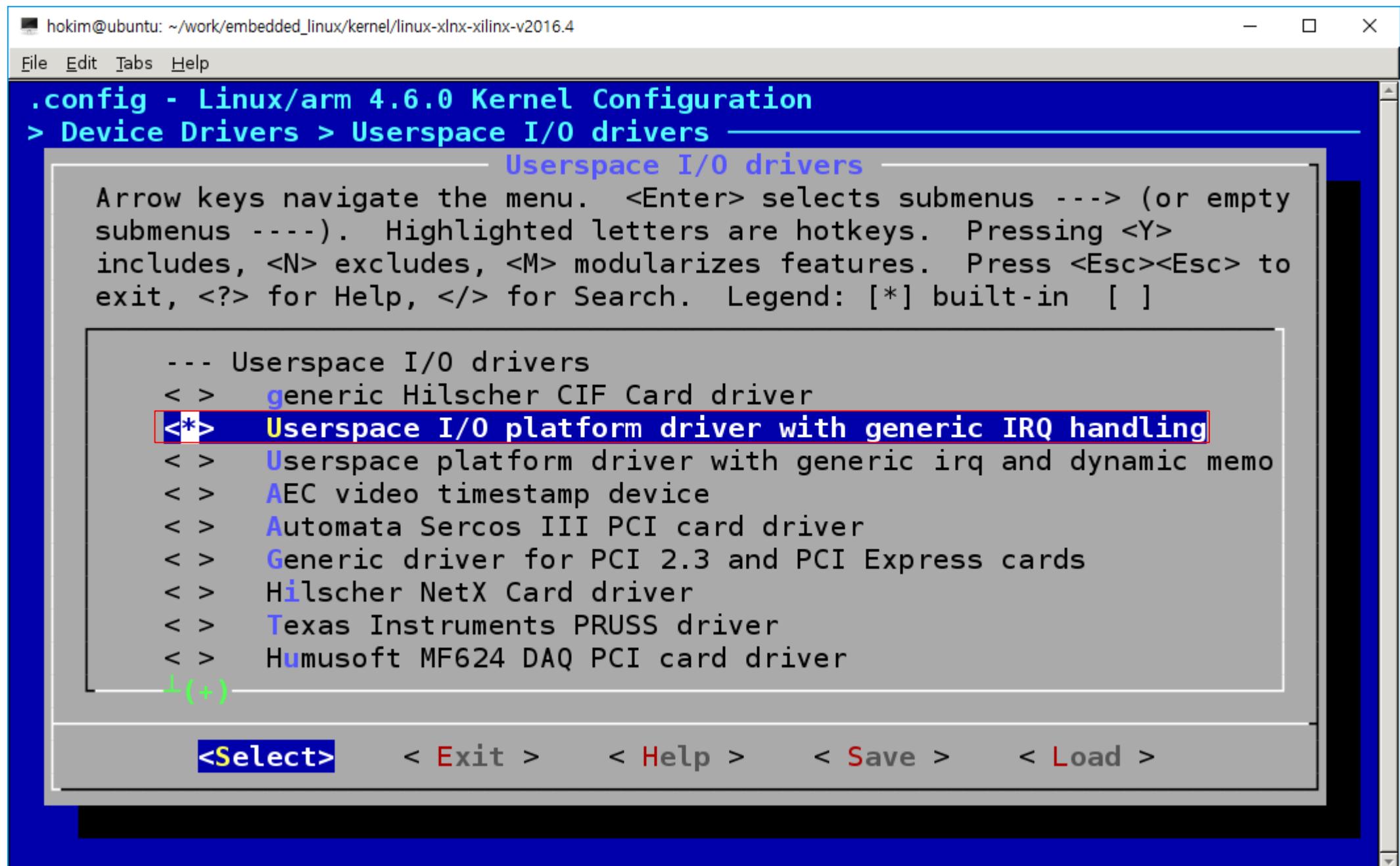
- The device tree node for the device needs to use “generic-uio” in it’s compatible property

Best starting point since no kernel space code is needed

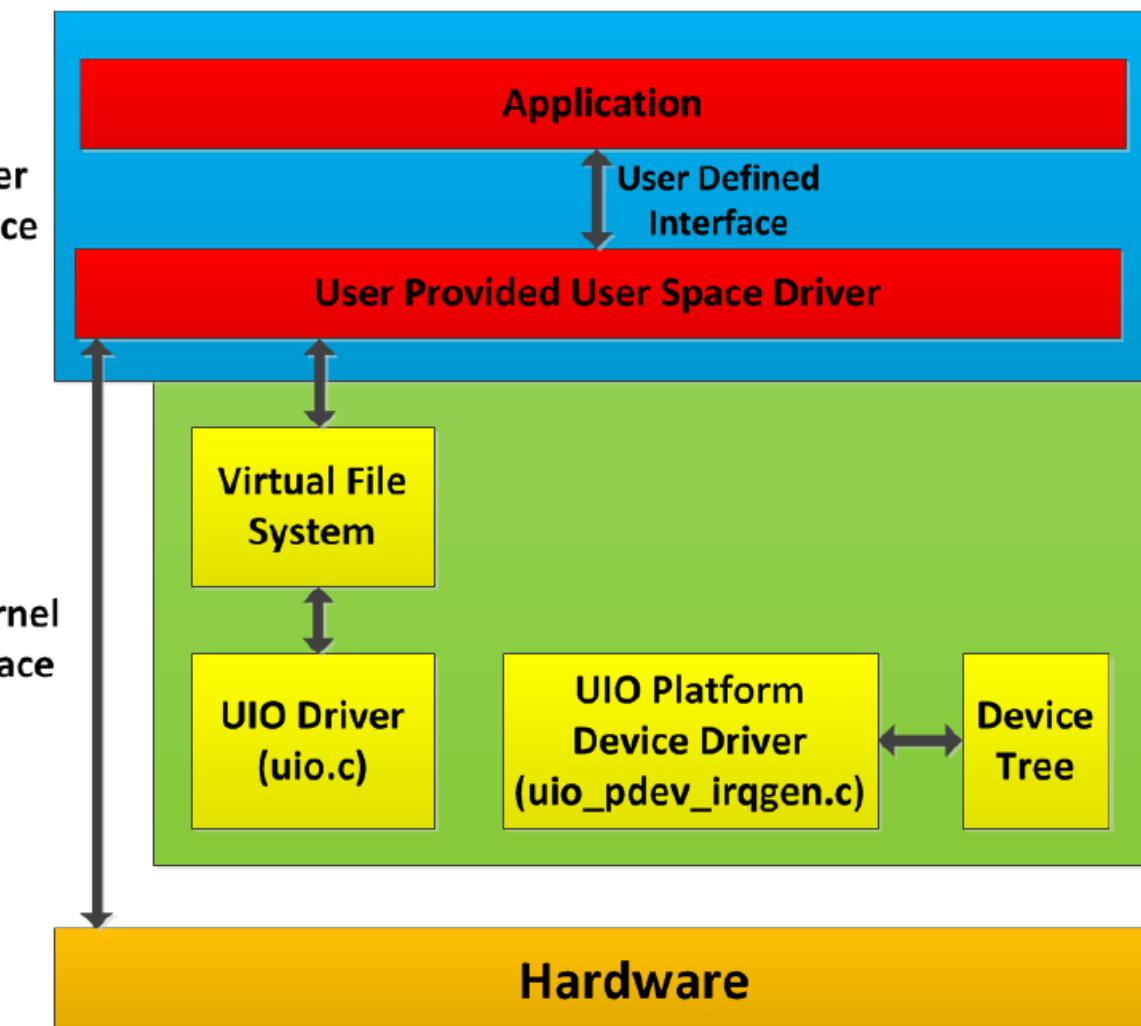
- It is the focus of this presentation



UIO Driver Kernel Configuration



UIO Platform Device Driver Details



- The user provides only a user space driver
- The UIO platform device driver configures from the device tree and registers a UIO device
- The user space driver has direct access to the hardware
- The user space driver gets notified of an interrupt by reading the UIO device file descriptor

- The UIO driver in the kernel creates file attributes in the sys filesystem describing the UIO device
- /sys/class/uio is the root directory for all the file attributes
- A separate numbered directory structure is created under /sys/class/uio for each UIO device

First UIO device: /sys/class/uio/uio0

/sys/class/uio/uio0/name contains the name of the devices which correlates to the name in the uio_info structure

/sys/class/uio/uio0/maps is a directory that has all the memory ranges for the device

Each numbered map directory has attributes to describe the device memory including the address, name, offset and size

- /sys/class/uio/uio0/maps/map0



User Space Driver Flow

- The kernel space UIO device driver(s) must be loaded before the user space driver is started (if using modules)
- The user space application is started and the UIO device file is opened (`/dev/uioX` where X is 0, 1, 2...)

From user space, the UIO device is a device node in the file system just like any other device

- The device memory address information is found from the relevant sysfs directory, only the size is needed
- The device memory is mapped into the process address space by calling the `mmap()` function of the UIO driver
- The application accesses the device hardware to control the device
- The device memory is unmapped by calling `munmap()`
- The UIO device file is closed



1. Login into zybo
2. Based on devicetree for gpio project

(Assume devicetree.dtb and boot.bin are saved in ~hokim/gpio_boot directory)

```
$ cd ~hokim/gpio_boot  
$ ls  
boot.bin devicetree.dtb
```

3. Convert devicetree.dtb into devicetree_gpio-uo.dts for uio using dtc command

```
$ dtc -I dtb -O dts -o devicetree_gpio-uo.dts devicetree.dtb  
$ ls  
boot.bin devicetree.dtb devicetree_gpio-uo.dts
```

4. Edit devicetree_gpio-uo.dts for UIO

```
$ nano devicetree_gpio-uo.dts
```



devicetree_gpio-uio.dts

```
/dts-v1/;

/ {
    #address-cells = <0x1>;
    #size-cells = <0x1>;
    compatible = "xlnx,zynq-7000";

    chosen {
        - bootargs = "console=ttyPS0,115200 root=/dev/mmcblk0p2 ro
rootfstype=ext4 earlyprintk rootwait";
        + bootargs = "console=ttyPS0,115200 root=/dev/mmcblk0p2 ro
rootfstype=ext4 earlyprintk rootwait uio_pdrv_genirq.of_id=generic-
uio";
    };
    .....
    .....
    /*

        gpio@40000000 {
            #gpio-cells = <0x2>;
            #interrupt-cells = <0x2>;
            compatible = "xlnx,xps-gpio-1.00.a";
            gpio-controller;
            interrupt-controller;
            interrupt-parent = <0x3>;
            interrupts = <0x0 0x1f 0x4>;
            reg = <0x40000000 0x1000>;
        };
        .....
        .....
    */
}
```

```
+    leds @40000000 {
+        compatible = "generic-uio";
+        interrupt-parent = <0x3>;
+        interrupts = <0x0 0x1f 0x4>;
+        reg = <0x40000000 0x1000>;
+    };
+/*
+    gpio@40002000 {
+        #gpio-cells = <0x2>;
+        #interrupt-cells = <0x2>;
+        compatible = "xlnx,xps-gpio-1.00.a";
+        gpio-controller;
+        interrupt-controller;
+        interrupt-parent = <0x3>;
+        interrupts = <0x0 0x1d 0x4>;
+
+        .....
+        .....
+    };
+/*
+    sws@40002000 {
+        compatible = "generic-uio";
+        interrupt-parent = <0x3>;
+        interrupts = <0x0 0x1d 0x4>;
+        reg = <0x40002000 0x1000>;
+    };
+*
```

5. Convert devicetree_gpio-ui0.dts into devicetree_gpio-ui0.dtb

```
$ dtc -I dts -O dtb -o devicetree_gpio-ui0.dtb devicetree_gpio-ui0.dts  
$ ls  
boot.bin devicetree.dtb devicetree_gpio-ui0.dts devicetree_gpio-ui0.dtb
```

6. Copy boot.bin, devicetree_gpio-ui0.dtb to /boot directory and reboot

```
$ sudo -s  
# cp boot.bin /boot  
# cp devicetree_gpio-ui0.dtb /boot/devicetree.dtb  
# halt
```

uio_test.c

```
#include <stdio.h>
#include <stdint.h>
#include <stdlib.h>
#include <unistd.h>
#include <sys/mman.h>
#include <fcntl.h>

#define GPIO_DATA_OFFSET 0x0 /* Data register for 1st
channel */
#define GPIO_TRI_OFFSET 0x4 /* I/O direction reg for 1st
channel */
#define GPIO_DATA2_OFFSET 0x8 /* Data register for 2nd
channel */
#define GPIO_TRI2_OFFSET 0xC /* I/O direction reg for 2nd
channel */
#define GPIO_GIE_OFFSET 0x11C /* Global interrupt enable
register */
#define GPIO_ISR_OFFSET 0x120 /* Interrupt status register */
#define GPIO_IER_OFFSET 0x128 /* Interrupt enable register
*/
void gpio_write(void *gpio_base, uint32_t offset, uint32_t value)
{
    *((volatile unsigned *)(gpio_base + offset)) = value;
}

uint32_t gpio_read(void *gpio_base, uint32_t offset)
{
    return *((volatile unsigned *)(gpio_base + offset));
}

int32_t get_memory_size(char *sysfs_path_file)
{
    FILE *size_fp;
    uint32_t size;
```

```
// open the file that describes the memory range size that is based
on the
// reg property of the node in the device tree
size_fp = fopen(sysfs_path_file, "r");
int32_t get_memory_size(char *sysfs_path_file)
{
    FILE *size_fp;
    uint32_t size;

    // open the file that describes the memory range size that is
based on the
    // reg property of the node in the device tree
    size_fp = fopen(sysfs_path_file, "r");

    if (!size_fp) {
        printf("unable to open the uio size file\n");
        exit(-1);
    }

    // get the size which is an ASCII string such as 0XXXXXXXXX
and then be stop
    // using the file
    fscanf(size_fp, "0x%08X", &size);
    fclose(size_fp);

    return size;
}
void wait_for_interrupt(int fd, void *gpio_ptr)
{
    int pending = 0;
    int reenable = 1;
    uint32_t reg;

    // block on the file waiting for an interrupt
    read(fd, (void *)&pending, sizeof(int));
    //printf("Interrupt!\n");
```

UIO Test

uio_test.c

```
// the interrupt occurred for the 1st GPIO channel so clear it
reg = gpio_read(gpio_ptr, GPIO_ISR_OFFSET);
if (reg) gpio_write(gpio_ptr, GPIO_ISR_OFFSET, 1);

// re-enable the interrupt in the interrupt controller thru
// the UIO subsystem now that it's been handled

write(fd, (void *)&reenable, sizeof(int));
}

int main()
{
    int uio0_fd, uio1_fd;
    void *ptr0;
    void *ptr1;
    uint32_t gpio_size0, gpio_size1;
    int reenable = 1;
    uint32_t value;

    if ((uio0_fd = open("/dev/uio0", O_RDWR)) < 0) {
        perror("open uio0");
    }
    if ((uio1_fd = open("/dev/uio1", O_RDWR)) < 0) {
        perror("open uio1");
    }

    gpio_size0 =
get_memory_size("/sys/class/uio/uio0/maps/map0/size");
    gpio_size1 =
get_memory_size("/sys/class/uio/uio1/maps/map0/size");

    ptr0 = mmap(NULL, gpio_size0, PROT_READ|PROT_WRITE,
MAP_SHARED, uio0_fd, 0);
```

```
if (ptr0 == MAP_FAILED) {
    perror("uio0 mmap call failure\n");
    return -1;
}

ptr1 = mmap(NULL, gpio_size1, PROT_READ|PROT_WRITE,
MAP_SHARED, uio1_fd, 0);

if (ptr1 == MAP_FAILED) {
    perror("uio1 mmap call failure\n");
    return -1;
}

gpio_write(ptr0, GPIO_TRI_OFFSET, 0x0); // GPIO Channel 1
input

gpio_write(ptr1, GPIO_TRI_OFFSET, 0xF); // GPIO Channel 1
input
gpio_write(ptr1, GPIO_GIE_OFFSET, 0x80000000); // GIER,
31st Bit
gpio_write(ptr1, GPIO_IER_OFFSET, 1); // interrupt enable

write(uio1_fd, (void*)&reenable, sizeof(int));
while (1)
{
    wait_for_interrupt(uio1_fd, ptr1);
    value = gpio_read(ptr1, GPIO_DATA_OFFSET);
    //printf("sws = 0x%X\n", value);
    gpio_write(ptr0, GPIO_DATA_OFFSET, value);
}

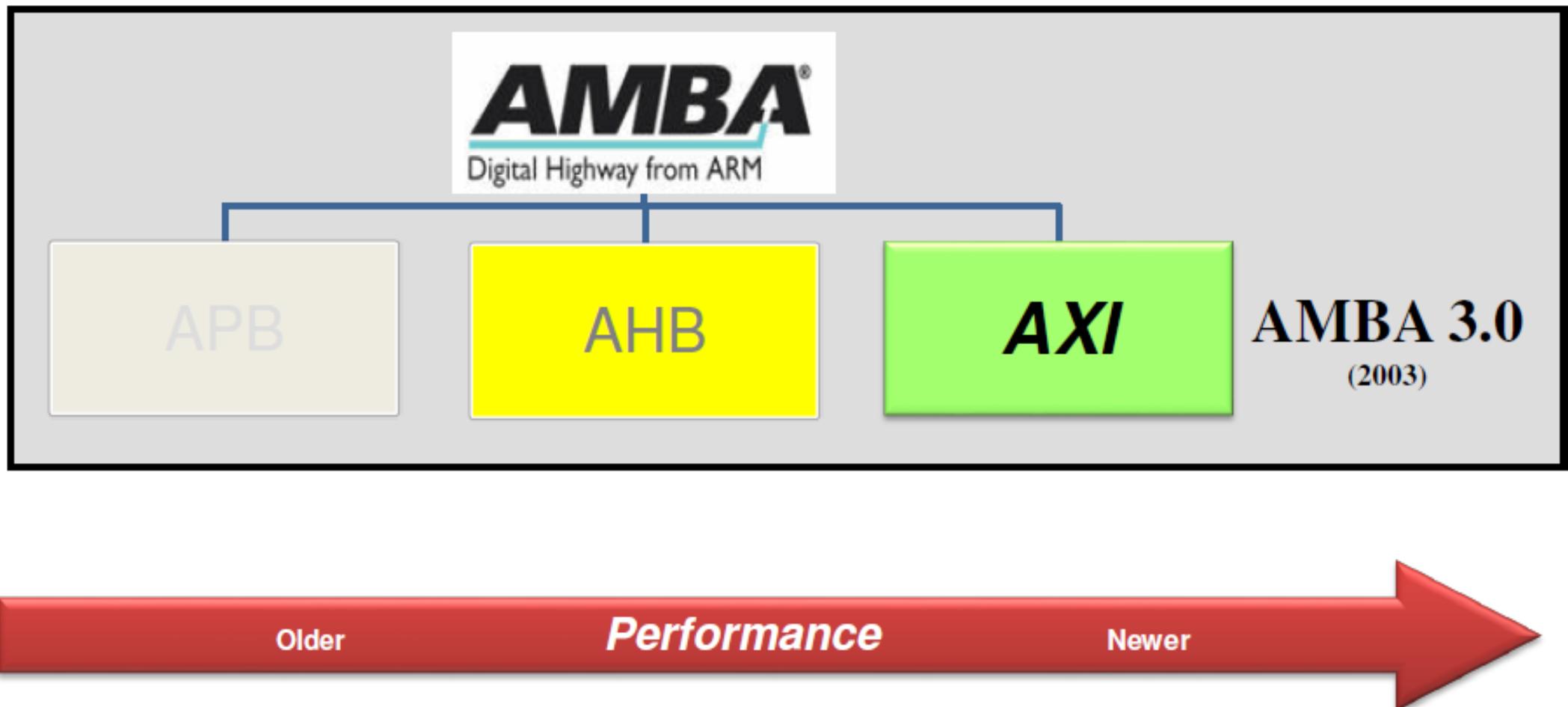
munmap(ptr0, gpio_size0);
munmap(ptr1, gpio_size1);

return 0;
}
```

```
$ cd ~/uiosw  
$ ls  
$ CMakeLists.txt uio_test.c  
$ mkdir build  
$ cd build  
$ cmake  
$ make  
$ sudo ./uio_test
```

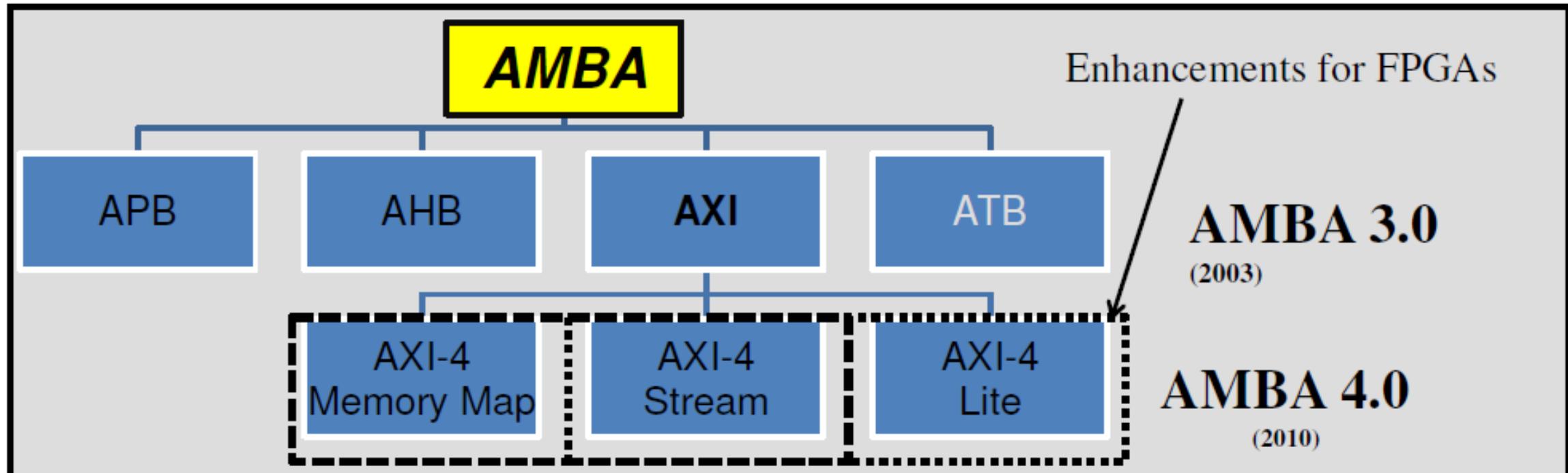


AXI is Part's of ARM's AMBA



AMBA: Advanced Microcontroller Bus Architecture
AXI: Advanced Extensible Interface

AXI-4 (Full, Lite and Stream)



Interface	Features	Similar to
Memory Map / Full (AXI4)	Traditional Address/Data Burst (single address, multiple data)	PLBv46, PCI
Streaming (AXI4-Stream)	Data-Only, Burst	Local Link / DSP Interfaces / FIFO / FSL
Lite (AXI4-Lite)	Traditional Address/Data—No Burst (single address, single data)	PLBv46-single OPB

- **AXI4 (a.k.a AXI4-full)**

- For high-performance memory-mapped requirements

- **AXI4-Lite**

- For simple, low-throughput memory-mapped communication (for example, to and from control and status registers)

- **AXI4-Stream**

- For high-speed streaming data



- **Memory Mapped Protocol : AXI3, AXI4, AXI4-Lite**

All transactions involve the concept of a target address within a system memory space and data to be transferred

Example : A typical peripheral or memory bank

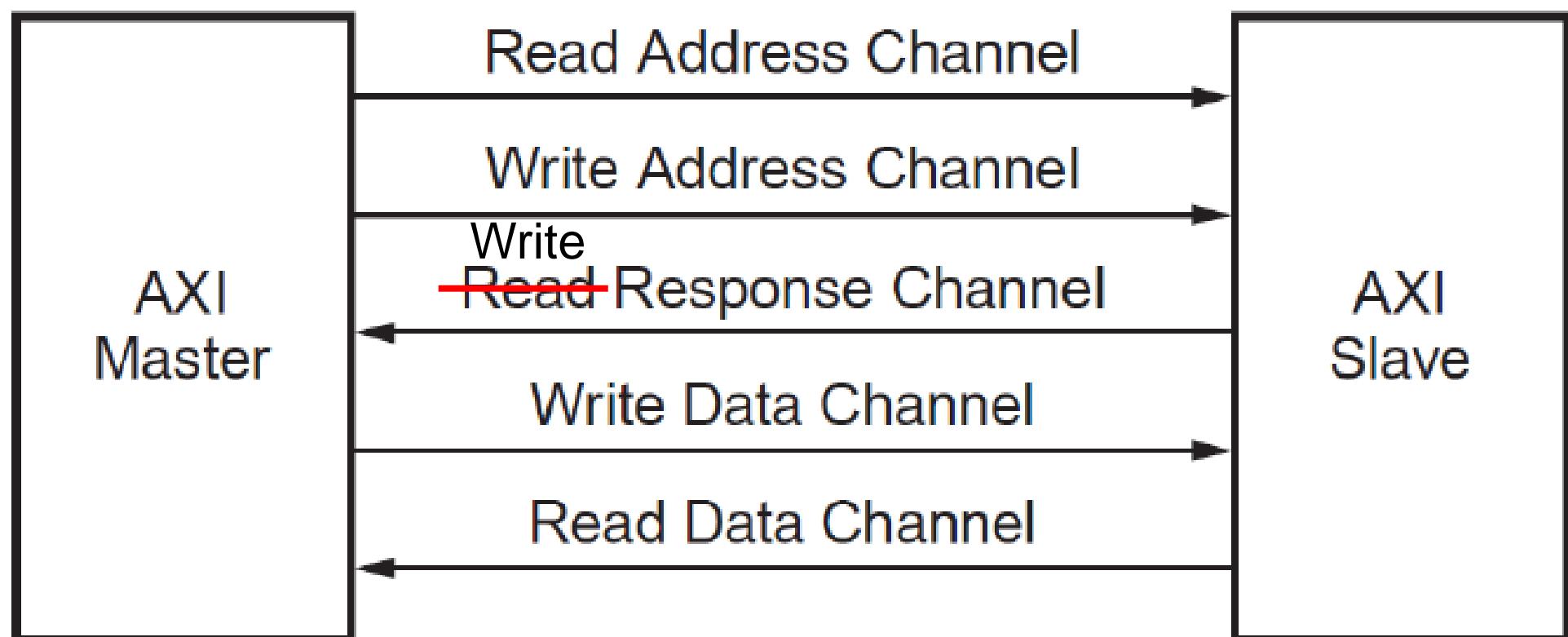
- **Stream Protocol : AXI4-Stream**

It's used for applications that typically focus on data-centric and data-flow paradigm where the concept of an address is not present or not required

Example : data coming from an Ethernet controller



- A typical MM master-slave connections

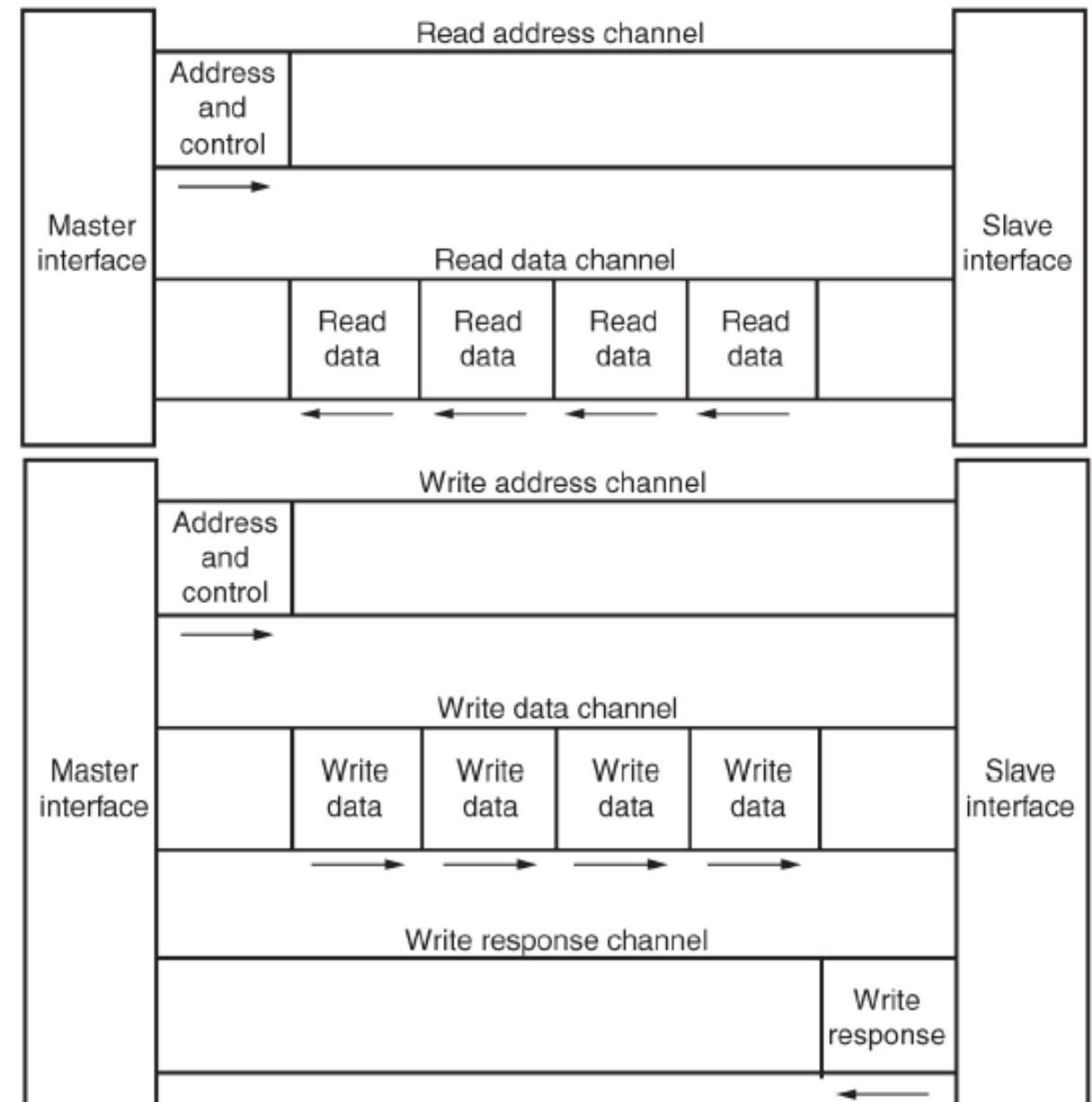


- **Read address channel**
- **Read data channel**

- **Write address channel**
- **Write data channel**
- **Write response channel**

Non-posted write model

There will always will be a
“write response”



AXI : Channel handshaking

- All AXI channels use a basic VALID/READY handshaking:

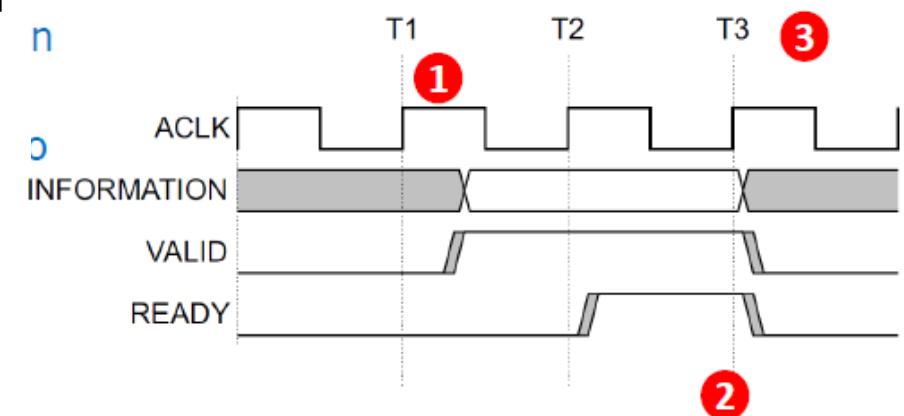
SOURCE asserts and holds VALID when DATA is available

DESTINATION asserts READY if able to accept DATA

DATA transferred when VALID and READY = 1

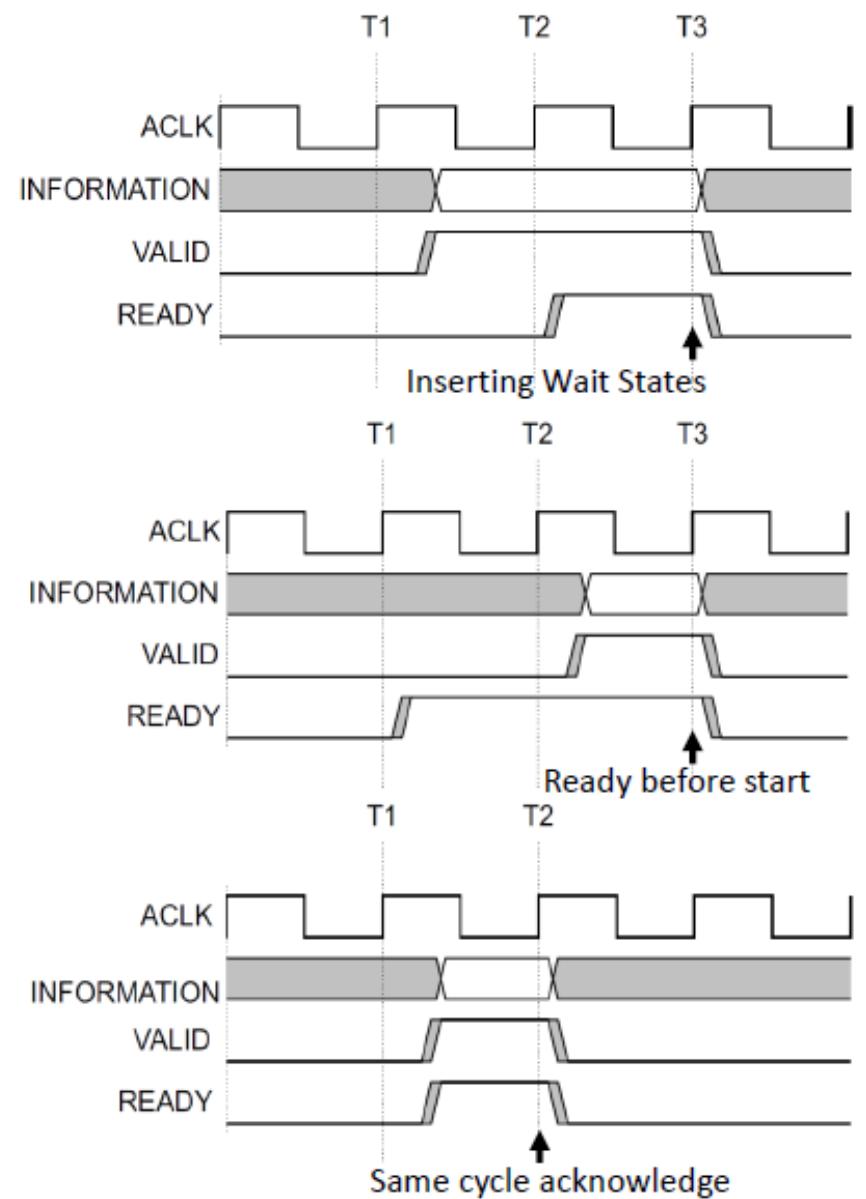
SOURCE sends next DATA(if an actual data channel) or deasserts VALID

DESTINATION deasserts READY if no longer able to accept DATA



AXI : Channel handshaking

- AXI uses a valid/ready handshake acknowledge
- Each channel has its own valid/ready
 - Address (read/write)
 - Data (read/write)
 - Response (read only)
- Flexible signaling functionality
 - Inserting wait states
 - Always ready
 - Same cycle acknowledge



AXI MM signals

Gbl	AXI4	AXI4-Lite
	ACLK	
	ARESETN	
Write Address	AWID	
	AWADDR	
	AWLEN	
	AWSIZE	
	AWBURST	
	AWLOCK	
	AWCACHE	
	AWPROT	
	AWQOS	
	AWSIZE	
	AWREGION	
	AWLOCK	
	AWUSER	
	AWVALID	
	AWREADY	

Read Address	AXI4	AXI4-Lite
	ARID	
	ARADDR	
	ARLEN	
	ARSIZE	
	ARBURST	
	ARLOCK	
	ARCACHE	ARCACHE
	ARPROT	ARPROT
	ARQOS	
	ARREGION	
	ARUSER	
	ARVALID	
	ARREADY	

Write Data	AXI4	AXI4-Lite
	WDATA	WDATA
	WSTRB	WSTRB
	WLAST	
	WUSER	
	WVALID	
	WREADY	
Write Resp.	BID	
	BRESP	BRESP
	BUSER	
	BVALID	
	BREADY	

Read Data	AXI4	AXI4-Lite
	RID	
	RDATA	RDATA
	RRESP	RRESP
	RLAST	
	RUSER	
	RVALID	
	WREADY	



- **AWADDR (ARADDR): Write (read) address**

The write (read) address gives the address of the first transfer in a write (read) burst transaction

- **AWVALID (ARVALID): Write (read) address valid**

This signal indicates that the channel is signaling valid write (read) address and control information

- **AWREADY (ARREADY): Write (read) address ready**

This signal indicates that the slave is ready to accept an address and associated control signals



- **AWID (ARID): Write (read) address ID**

This signal is the identification tag for the write address group of signals

- **AWLEN (ARLEN): Burst length**

This burst length gives the exact number of transfer in a burst (number of transfers) ; length = N + 1

- **AWSIZE (ARSIZE): Burst size**

This signal indicates the size of each transfer in the burst(size= 2^N)

- **AWBURST (ARBURST): Burst type**

The burst type and the size information, determine how the address for each transfer within the burst is calculated. FIXED, INCR, WRAP

- **AWLOCK (ARLOCK): Lock type**

Provides additional information about the atomic characteristics of the transfer

- **AWPROT (ARPROT): Protection type**

This signal indicates the privilege and security level of the transaction, and whether the transaction is a data access or an instruction access



- **AWCACHE (ARCACHE): Memory type**

The signal indicates how transactions are required to progress through a system

- **AWQOS (ARQOS): Quality of Service, QoS**

This QoS identifier sent for each write transaction

- **AWREGION (ARREGION): Region identifier**

Permits a single physical interface on a slave to be used for multiple logical interfaces

- **AWUSER (ARUSER): User signal**

Optional User-defined signal in the write address channel



- **WID: Write ID tag**

This signal is the ID tag of the write data transfer

- **WDATA: Write data**

- **WSTRB: Write strobes**

This signal indicates which byte lanes hold valid data. There is one write strobe bit for each eight bits of the write data bus

- **WLAST: Write last**

The signal indicates the last transfer in a write burst

- **WUSER: User signal**

Optional User-defined signal in the write data channel

- **WVALID: Write valid**

This signal indicates that valid write data and strobes are available

- **WREADY: Write ready**

This signal indicates that the slave can accept the write data



- **BID: Response ID tag**

This signal is the ID tag of the write response

- **BRESP: Write response**

This signal indicates the status of the write transaction

OKAY, EXOKAY, SLVERR, DECERR

- **BUSER: User signal**

Optional User-defined signal in the write response channel

- **BVALID: Write response valid**

This signal indicates that the channel is signaling a valid write response

- **BREADY: Response ready**

This signal indicates that the master can accept a write response



- **RID: Read ID tag**

This signal is the identification tag for the read data group of signals generated by the slave

- **RDATA: Read data**

- **RRESP: Read response**

This signal indicates the status of the read transaction

OKAY, EXOKAY, SLVERR, DECERR

- **RLAST: Read last**

This signal indicates the last transfer in a read burst

- **BUSER: User signal**

Optional User-defined signal in the read data channel

- **BVALID: Read valid**

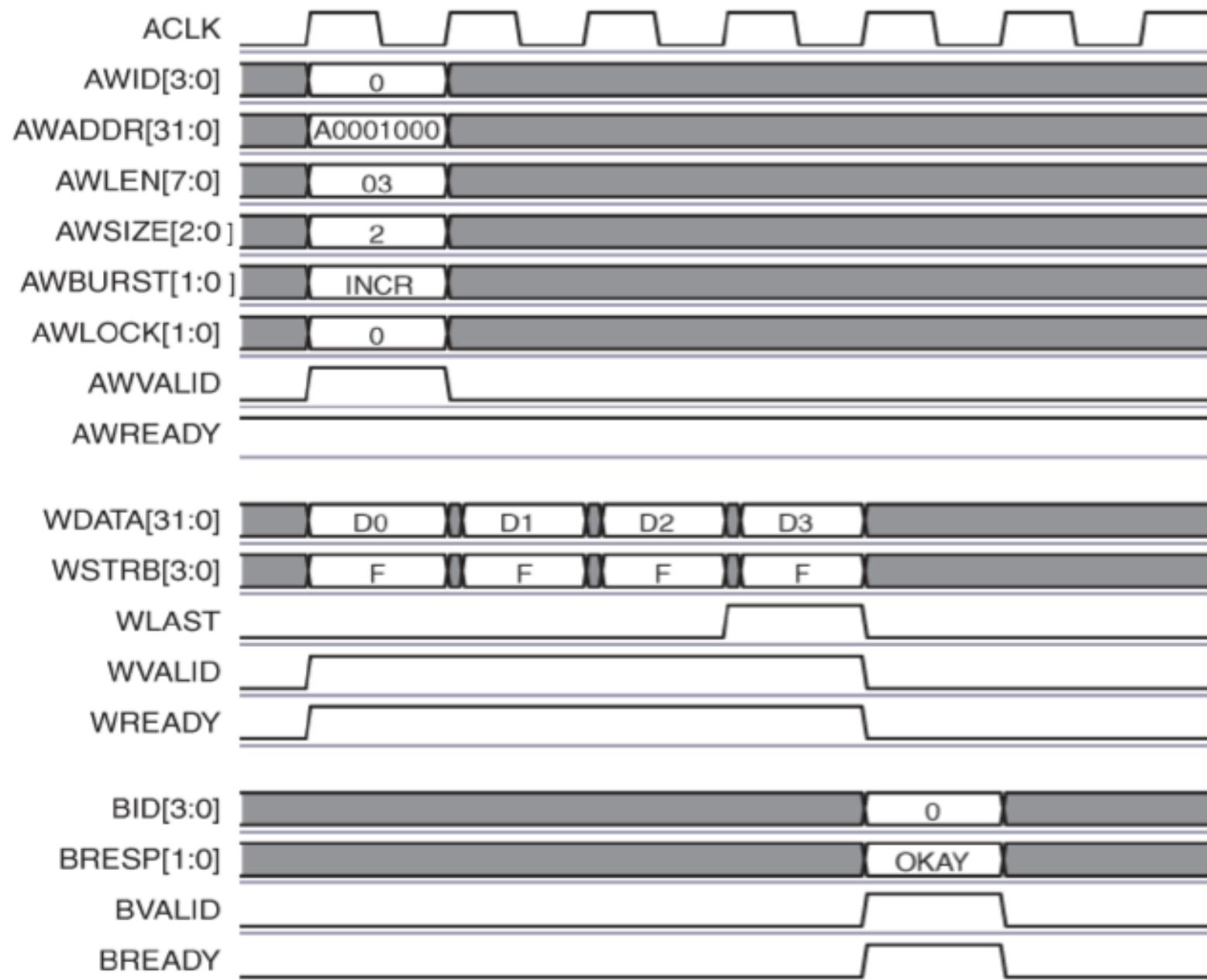
This signal indicates that the channel is signaling the required read data

- **RREADY: Read ready**

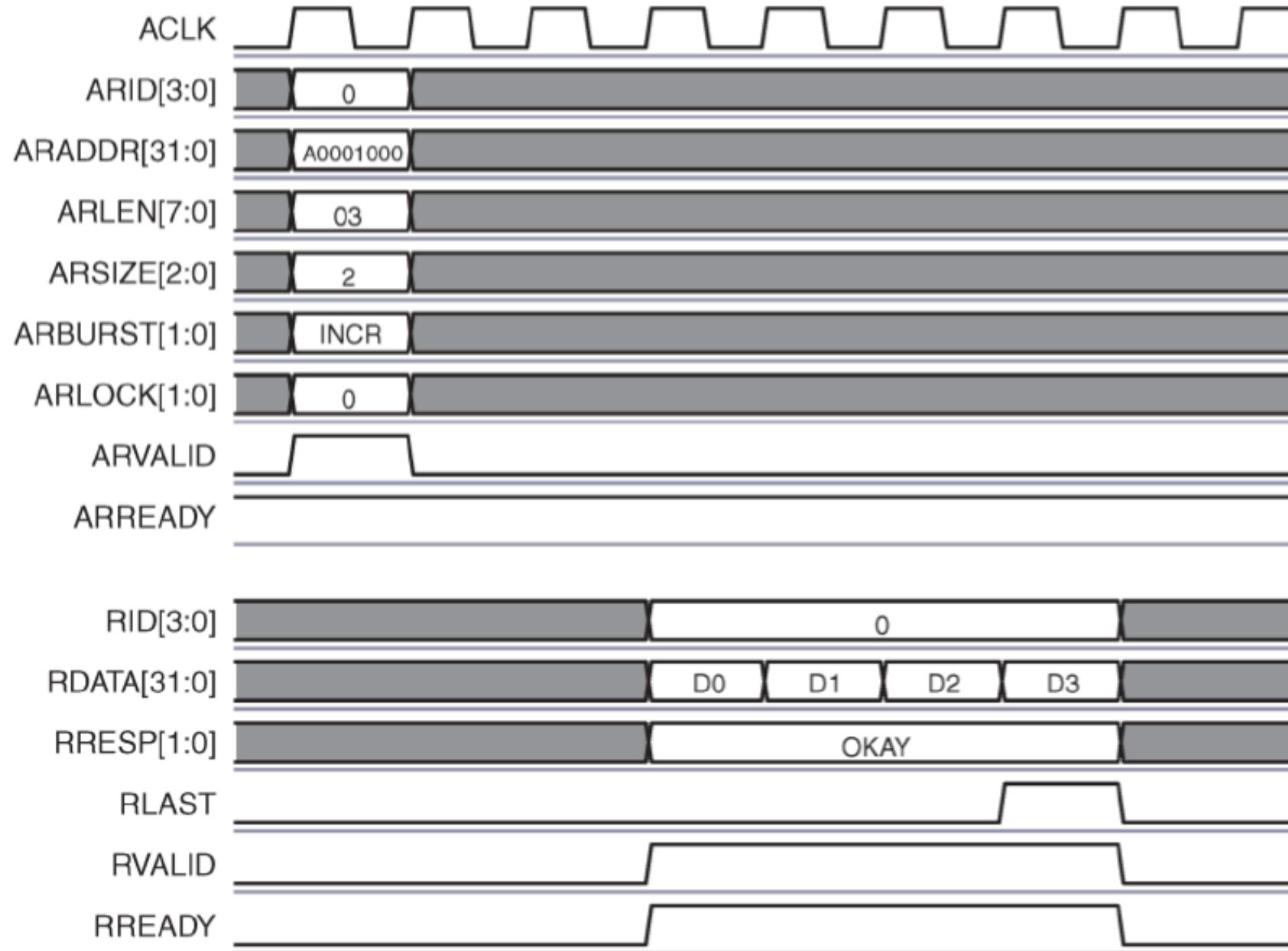
This signal indicates that the master can accept the read data and response information



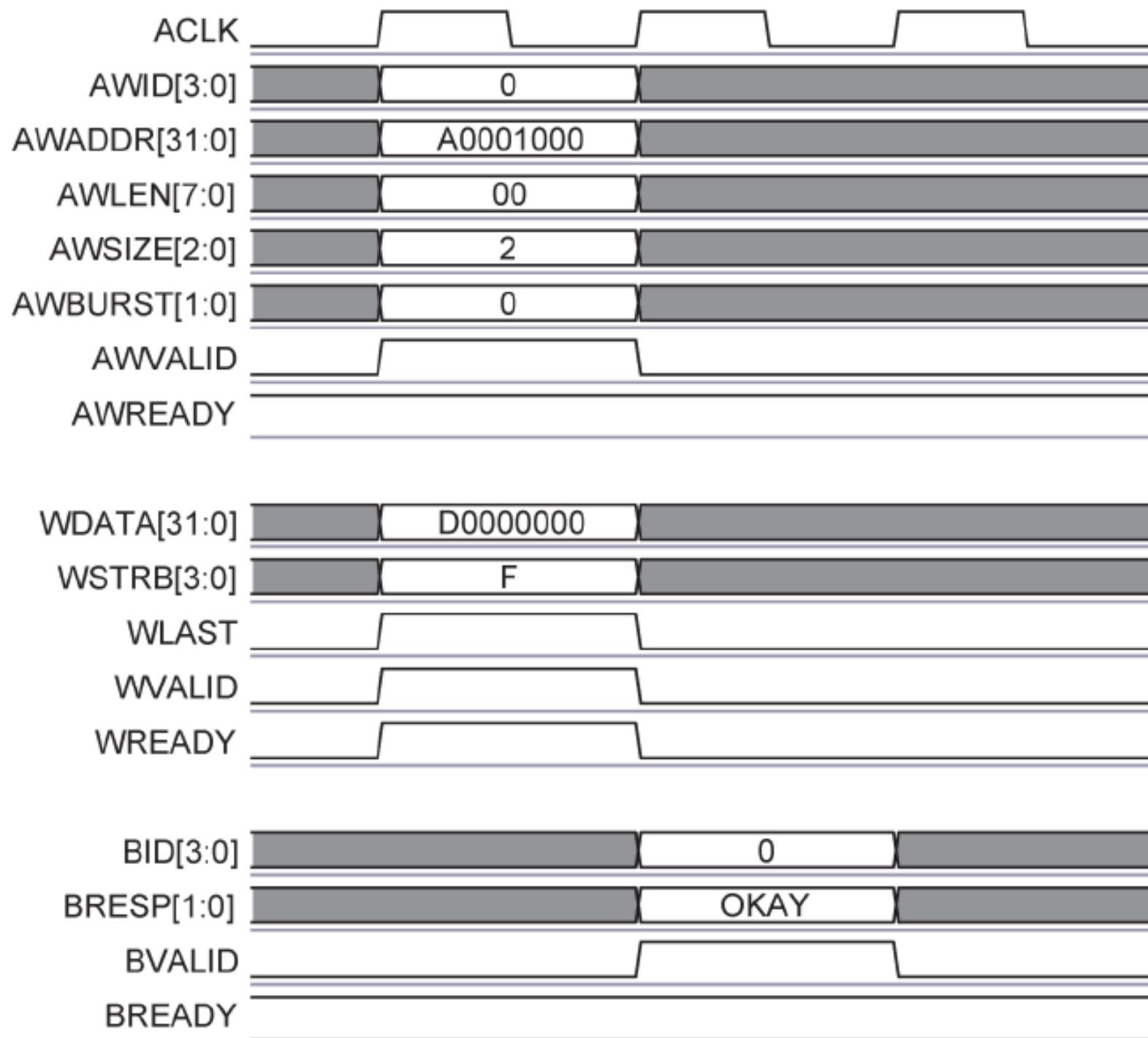
AXI4 Burst Write transaction



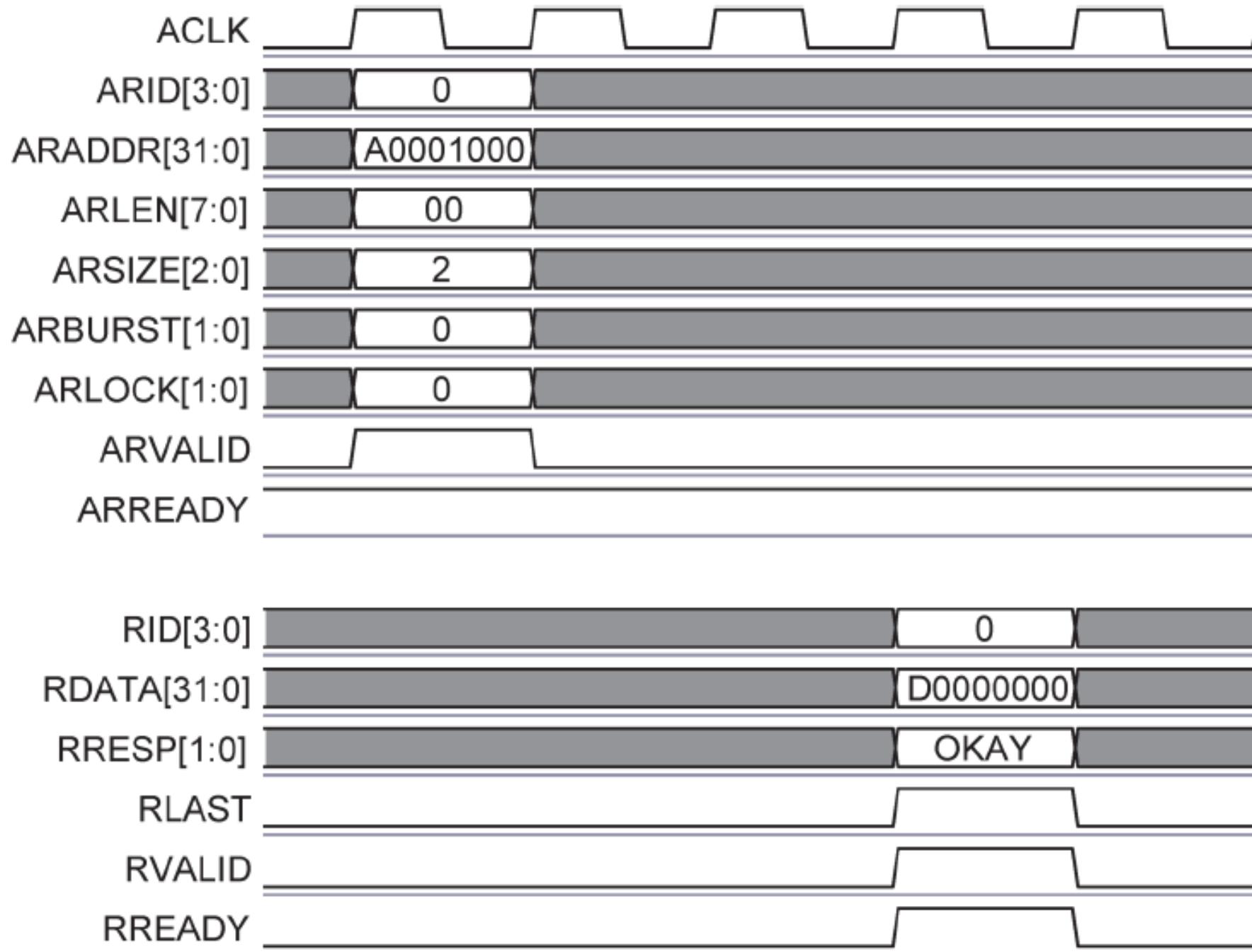
AXI4 Burst Read transaction



AXI4 Single Write transaction



AXI4 Single Read transaction



- **AXI-lite is subset of AXI4 for communication with simpler control register style interfaces within components**

- all transactions are of burst length 1

- all data accesses use the full width of the data bus

- AXI4-Lite supports a data bus width of 32-bit or 64-bit

- all accesses are Non-modifiable, Non-bufferable

- Exclusive accesses are not supported



Global	Write address channel	Write data channel	Write response channel	Read address channel	Read data channel
ACLK	AWVALID	WVALID	BVALID	ARVALID	RVALID
ARESETn	AWREADY	WREADY	BREADY	ARREADY	RREADY
-	AWADDR	WDATA	BRESP	ARADDR	RDATA
-	AWPROT	WSTRB	-	ARPROT	RRESP



- **AWLEN, ARLEN**

- This burst length is defined to be 1, equivalent to an AxLEN value of zero

- **AWSIZE, ARSIZE**

- All accesses are defined to be the width of the data bus

- AXI4-Lite requires a fixed data bus width of either 32-bits or 64-bits

- **AWBURST, ARBURST**

- This burst type has no meaning because the burst length is 1

- **AWLOCK, ARLOCK**

- All accesses are defined as Normal accesses, equivalent to an AxLOCK=0

- **AWCACHE, ARCACHE**

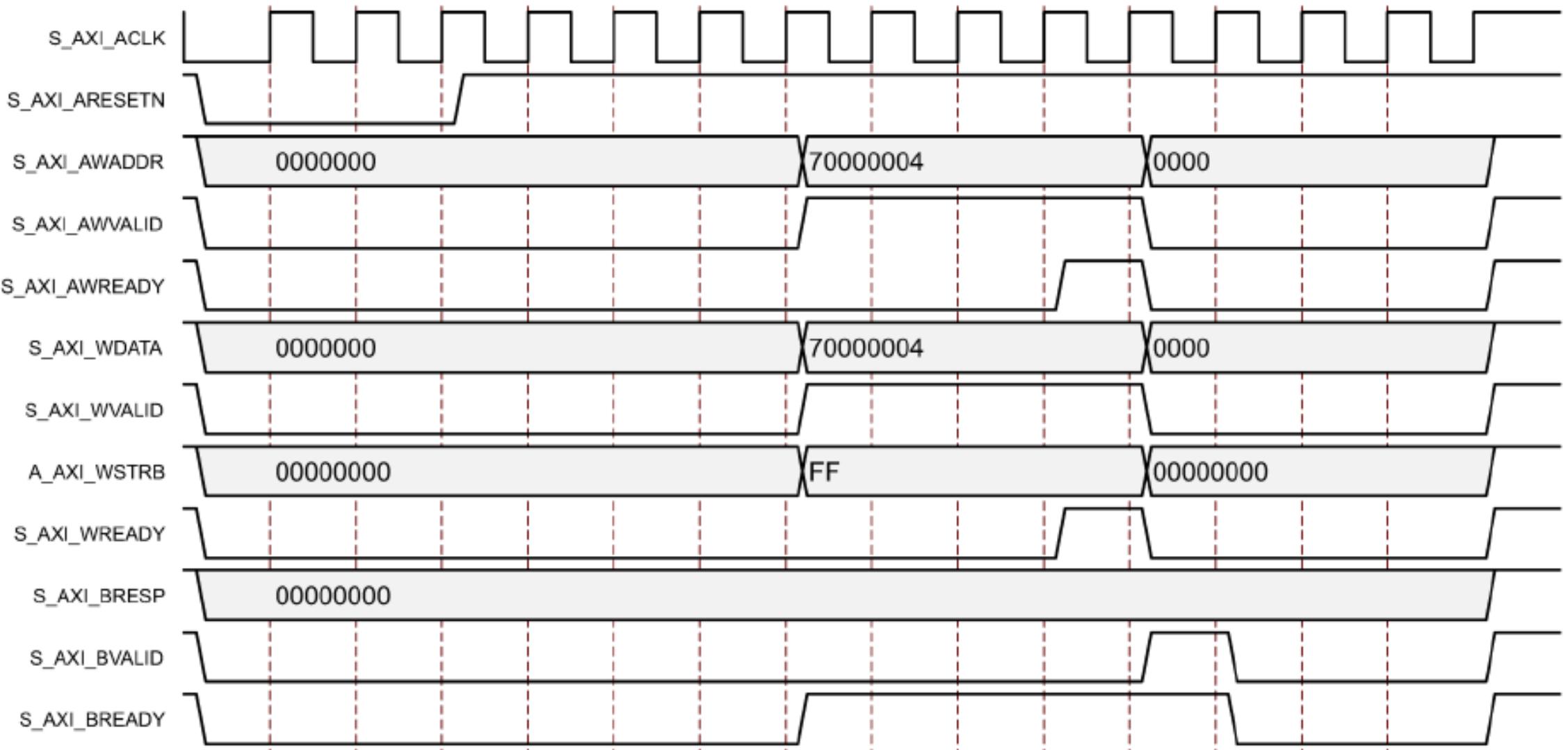
- All accesses are defined as Non-modifiable, Non-bufferable, equivalent to an AxCACHE=0b0000

- **WLAST, RLAST**

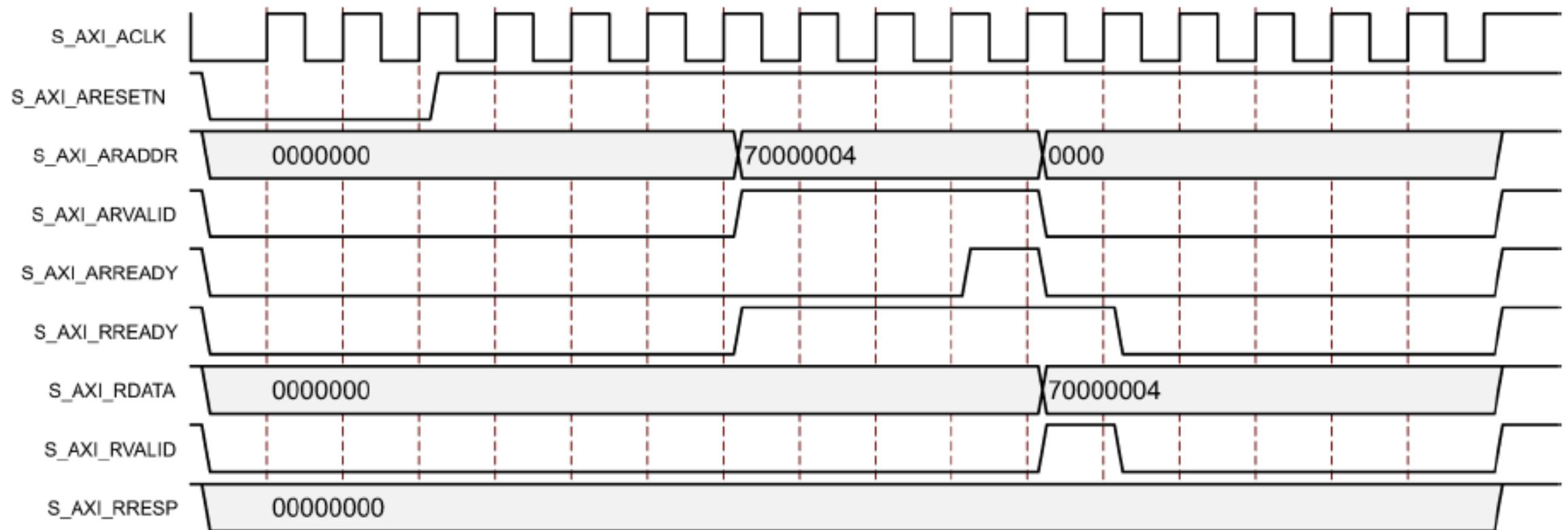
- All bursts are defined to be of length 1, equivalent to a WLAST or RLAST value of 1



AXI LITE : Single Write transfer



AXI LITE : Single Read transfer



- **Data moves in a single direction from a master to a slave**

Simplex communication

Dual direction would be dual simplex
(individual channels in each direction)

- **Data only**

No address bus

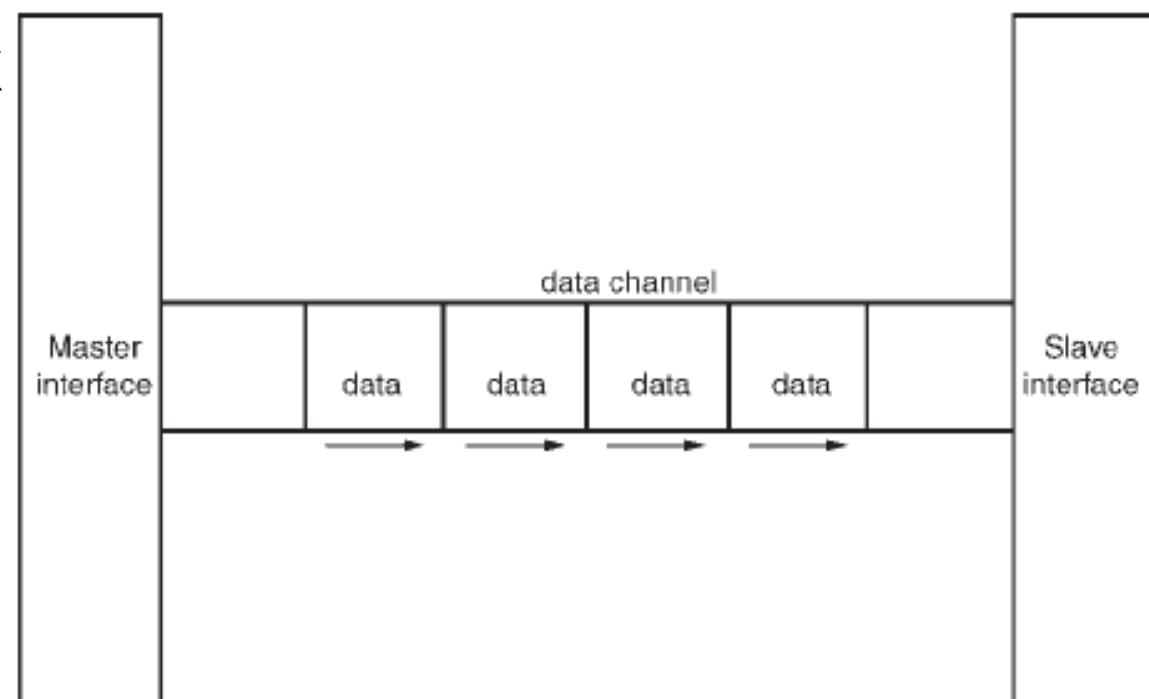
Minimum control bus

- **Data interpretation**

Packet or no packet

Master and slave must have prior knowledge of data format

Optional use of hardware signaling



- More signals defined than typically required
- Required signals

ACLK

TDATA

- Special, user-defined sideband signals consist of TUSER
- Other popular and useful signals are

TVALID

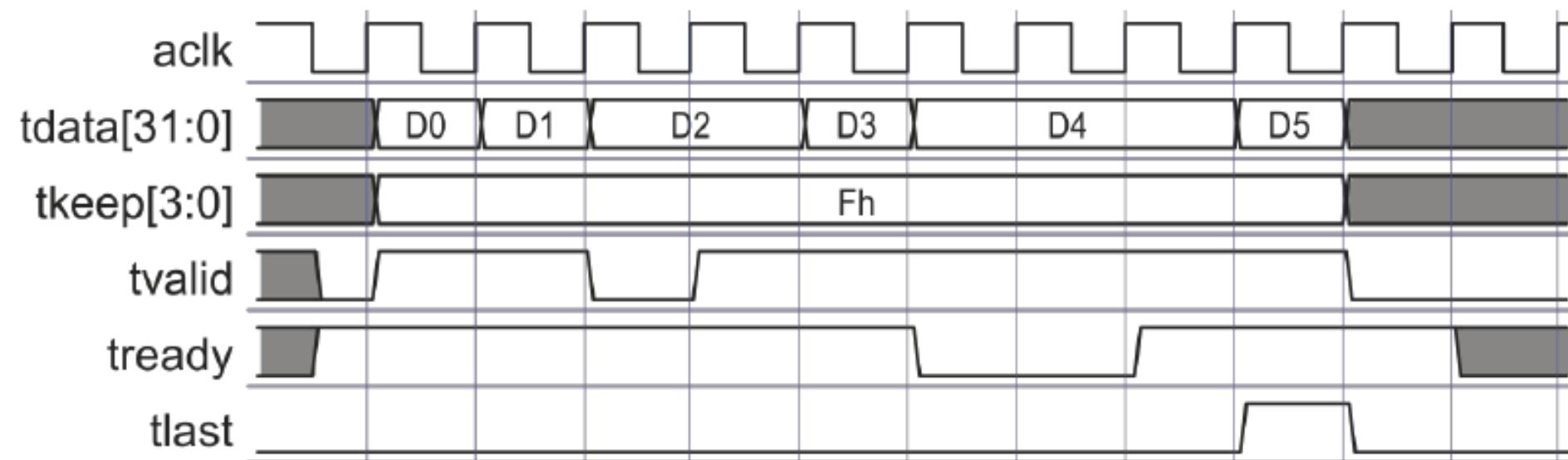
TREADY

TLAST

Signal	Source	Description
ACLK	Clock source	The global clock signal. All signals are sampled on the rising edge of ACLK.
ARESETn	Reset source	The global reset signal. ARESETn is active-LOW.
TVALID	Master	TVALID indicates that the master is driving a valid transfer. A transfer takes place when both TVALID and TREADY are asserted.
TREADY	Slave	TREADY indicates that the slave can accept a transfer in the current cycle.
TDATA[(8n-1):0]	Master	TDATA is the primary payload that is used to provide the data that is passing across the interface. The width of the data payload is an integer number of bytes.
TSTRB (n-1):0	Master	TSTRB is the byte qualifier that indicates whether the content of the associated byte of TDATA is processed as a data byte or a position byte.
TKEEP (n-1):0	Master	TKEEP is the byte qualifier that indicates whether the content of the associated byte of TDATA is processed as part of the data stream. Associated bytes that have the TKEEP byte qualifier deasserted are null bytes and can be removed from the data stream.
TLAST	Master	TLAST indicates the boundary of a packet.
TID (i-1):0	Master	TID is the data stream identifier that indicates different streams of data.
TDEST (d-1):0	Master	TDEST provides routing information for the data stream.
TUSER (u-1):0	Master	TUSER is user defined sideband information that can be transmitted alongside the data stream.



AXI STREAM : Basic protocol



Zynq7 PS Re-customize IP for AXI4 Lite

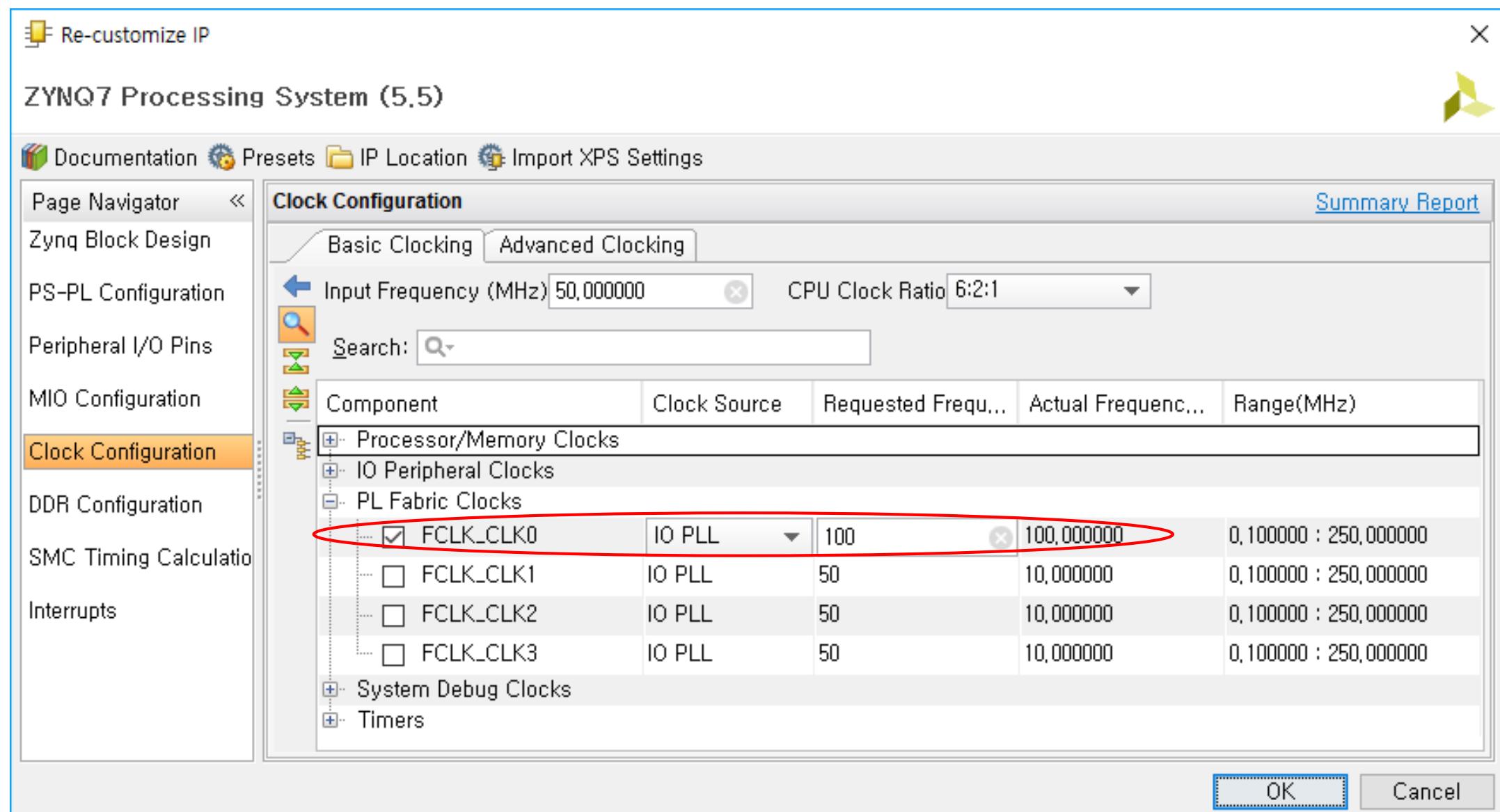


Based on Zynq7 PS Re-customize IP of embedded_linux project

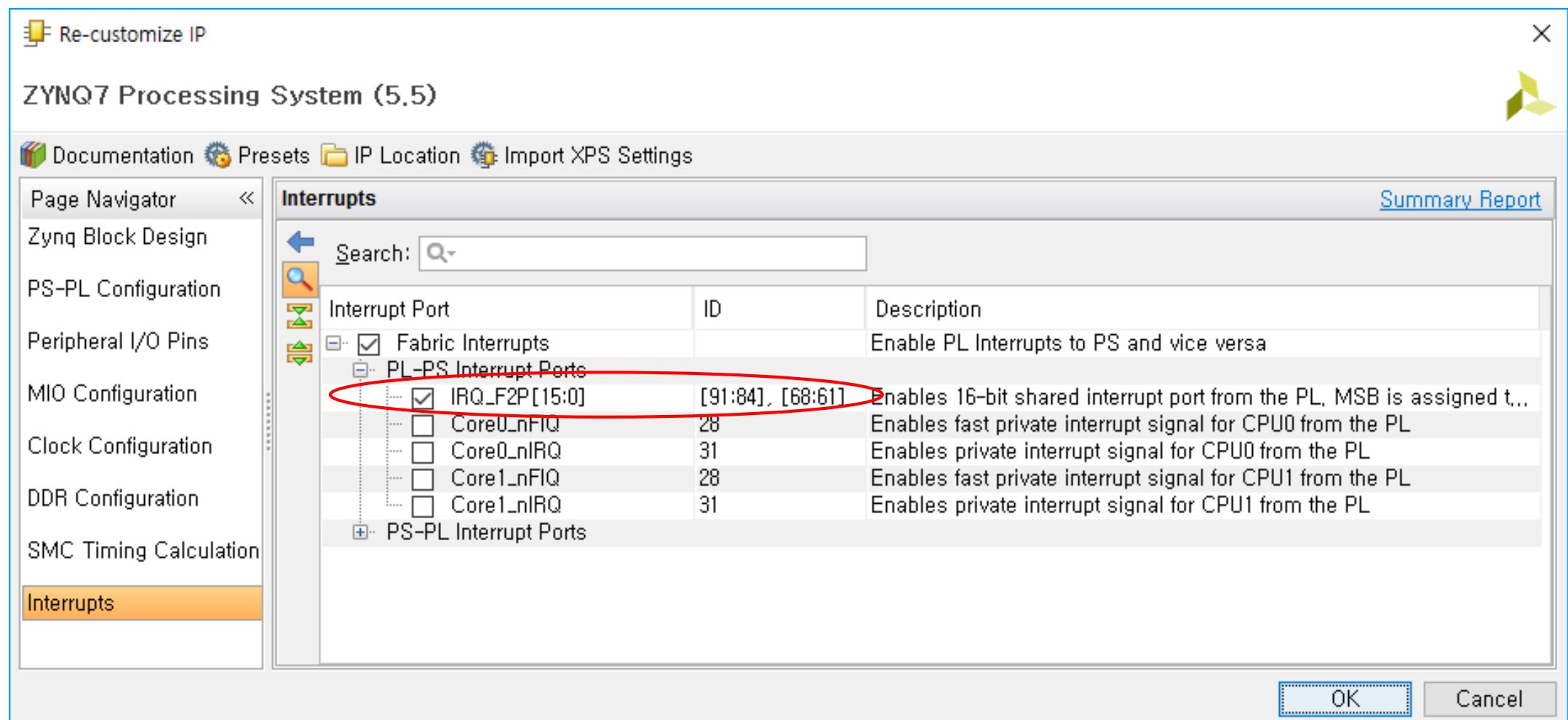
The screenshot shows the Xilinx Vivado IP Re-customization tool interface. The main window title is "Re-customize IP" and the sub-section is "ZYNQ7 Processing System (5.5)". The left sidebar lists various configuration tabs: Page Navigator, Zynq Block Design, PS-PL Configuration (which is selected and highlighted in orange), Peripheral I/O Pins, MIO Configuration, Clock Configuration, DDR Configuration, SMC Timing Calculation, and Interrupts. The central area is titled "PS-PL Configuration" and contains a table with columns for "Name", "Select", and "Description". The "General" section includes settings for UART0/1 Baud Rates, PL AXI idle Port, DDR ARB bypass Port, PS-PL Debug interface, FTM Trace data interface, FTM Trace buffer, FTM Data edge detector, FTM Trace buffer FIFO size, FTM Trace buffer clock delay, Include ACP transaction checker, Trace data/control signal pipeline width, Power-on reset(POR) 4k timer, and Processor event interface. The "Enable Clock Resets" section has four entries: FCLK_RESET0_N (checked), FCLK_RESET1_N, FCLK_RESET2_N, and FCLK_RESET3_N. The "AXI Non Secure Enablement" section includes settings for GP Master AXI Interface (M AXI GP0 interface checked) and GP Slave AXI Interface. The bottom right of the window has "OK" and "Cancel" buttons.

Name	Select	Description
UART0 Baud Rate	115200	Baud rate is generated with internally fixed UART Ref Clock Freq=10...
UART1 Baud Rate	115200	Baud rate is generated with internally fixed UART Ref Clock Freq=10...
PL AXI idle Port	<input type="checkbox"/>	Enables idle AXI signal to the PS used to indicate that there are no ...
DDR ARB bypass Port	<input type="checkbox"/>	Enables DDR urgent/arbitration signal used to signal a critical memory sta...
PS-PL Debug interface	<input type="checkbox"/>	Enables PL debug signals to PS and vice-versa
FTM Trace data interface	<input type="checkbox"/>	Enables FTM Trace AXI stream interface used to capture data from PL ... to PS debug system
FTM Trace buffer	0	Stores trace data in the FIFO when the data changes as marked by ...
FTM Data edge detector	0	FTM Trace buffer FIFO size
FTM Trace buffer FIFO size	128	Number of clock cycles interval for a trace data output from FIFO be...
FTM Trace buffer clock delay	12	Number of clock cycles interval for a trace data output from FIFO be...
Include ACP transaction checker	<input type="checkbox"/>	Enables ACP transaction checker.
Trace data/control signal pipeline width	8	Enables configurable number of pipeline stages on the TRACE DAT...
Power-on reset(POR) 4k timer	<input type="checkbox"/>	Enables power-on reset(POR) 4k timer. By default, 64k timer is used.
Processor event interface	<input type="checkbox"/>	Enables event bus which provides a low-latency and direct mecha...
Address Editor		
Enable Clock Triggers		
Enable Clock Resets		
FCLK_RESET0_N	<input checked="" type="checkbox"/>	Enables general purpose reset signal 0 for PL logic
FCLK_RESET1_N	<input type="checkbox"/>	Enables general purpose reset signal 1 for PL logic
FCLK_RESET2_N	<input type="checkbox"/>	Enables general purpose reset signal 2 for PL logic
FCLK_RESET3_N	<input type="checkbox"/>	Enables general purpose reset signal 3 for PL logic
AXI Non Secure Enablement		
GP Master AXI Interface		
M AXI GP0 interface	<input checked="" type="checkbox"/>	Enables General purpose AXI master interface 0
M AXI GP1 interface	<input type="checkbox"/>	Enables General purpose AXI master interface 1
GP Slave AXI Interface		

Based on Zynq7 PS Re-customize IP of embedded_linux project



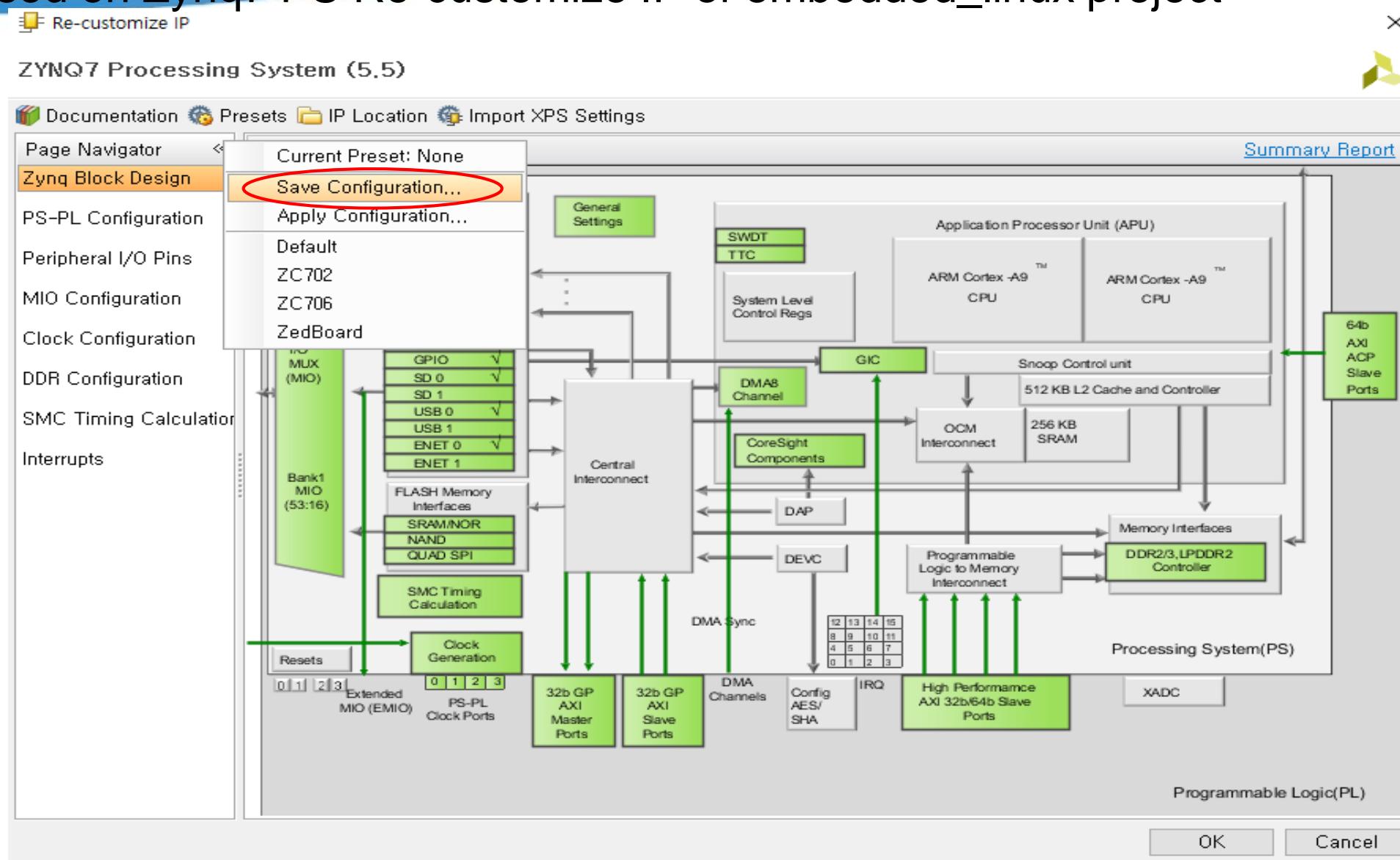
Based on Zynq7 PS Re-customize IP of embedded_linux project



Zynq7 PS Re-customize IP for AXI4 Lite



Based on Zynq7 PS Re-customize IP of embedded_linux project



Save Current Configuration...

Save the current configuration to a file on disk.

Preset Name:

File name:

OK Cancel

https://github.com/inipro/embedded_linux/projects/axi4_lite

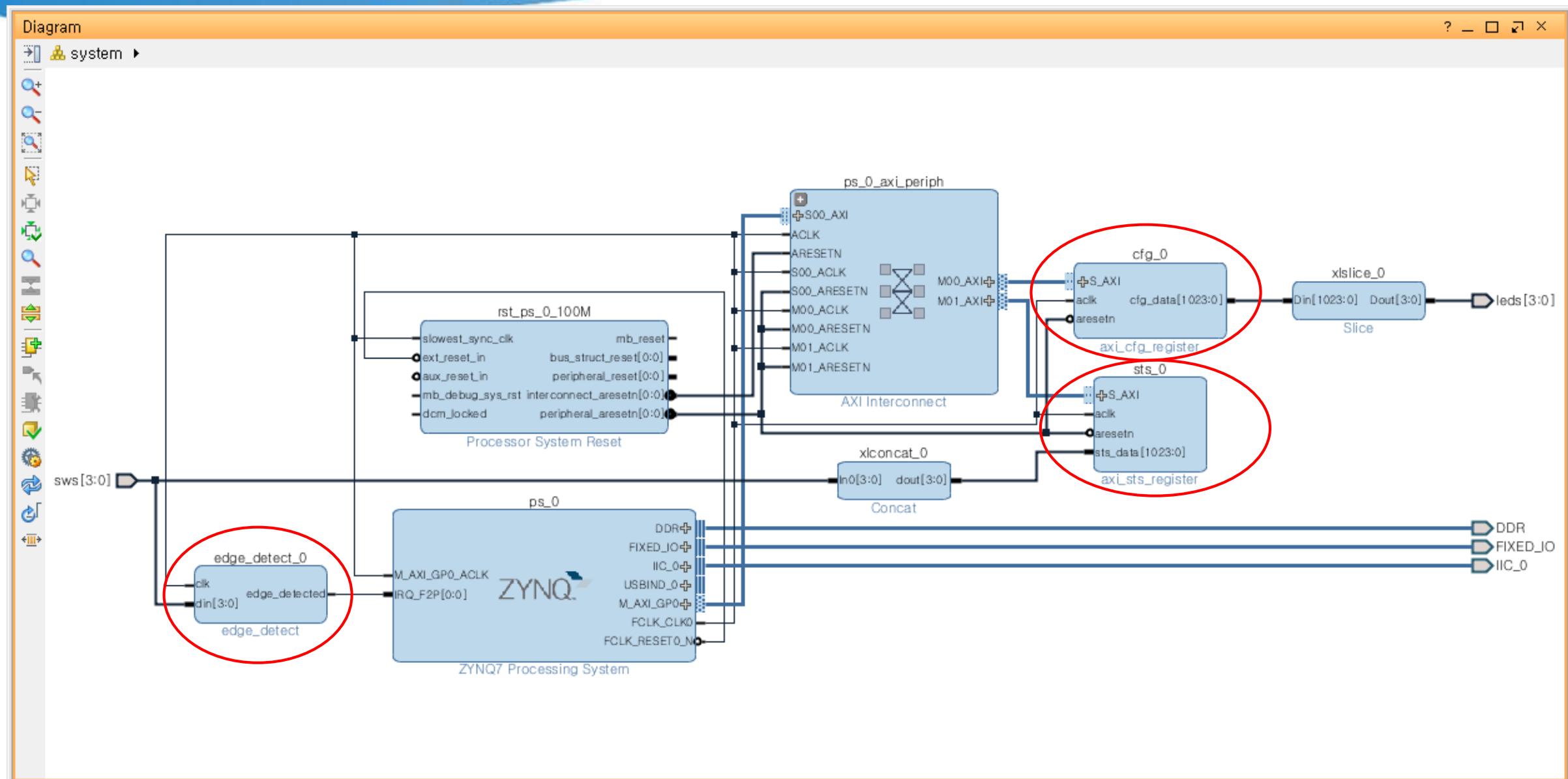
In cmd window for Vivado

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\axi4_lite  
C:\> vivado -nolog -nojournal -mode batch -source axi4_lite.tcl
```

output : axi4_lite\axi4_lite.xpr...



Project for AXI4_Lite



Address Editor

Cell	Slave Interface	Base Name	Offset Address	Range	High Address
ps_0					
Data (32 address bits : 0x40000000 [1G])					
cfg_0	S_AXI	reg0	0x4000_0000	64K	0x4000_FFFF
sts_0	S_AXI	reg0	0x4001_0000	64K	0x4001_FFFF

IP for AXI4_Lite Project

C:\Users\hokim\work\embedded_linux\projects\axi4_lite\ip\edge_dectector_v1_0

→ Non AXI IP for interrupt detection from 4-bit switches

edge_detector.tcl

hdl\edge_detector.v

```
`timescale 1ns / 1ps

module edge_detect
#(
    parameter N = 8
)
(
    input          clk,
    input [N-1:0]  din,
    output         edge_detected
);

reg [N-1:0]      tmp= 0;
reg              edge_detected_i = 0;

assign edge_detected = edge_detected_i;

always @ (posedge clk)
begin
    tmp <= din;
    if (tmp != din)
        edge_detected_i <= 1'b1;
    else
        edge_detected_i <= 1'b0;
end
endmodule
```

```
set ip_name "edge_detect"
file delete -force component.xml xgui

# Collect the names of the HDL source files that are used by this
# IP here.
set file_list [list "hdl/edge_detect.v"]

# Create a new Vivado project for this IP and add the source
# files.
create_project $ip_name . -force
set proj_dir [get_property directory [current_project]]
set proj_name [get_projects $ip_name]
set proj_fileset [get_filesets sources_1]
add_files -norecurse -scan_for_includes -fileset $proj_fileset
$file_list
set_property "top" "$ip_name" $proj_fileset
ipx::package_project -root_dir .

# Set the IP core information properties.
set core [ipx::current_core]
set_property vendor {hokim} $core
set_property library {ip} $core
set_property version {1.0} $core
set_property vendor_display_name {Hyunok Kim} $core
set_property company_url {https://github.com/hokim72} $core
set_property supported_families {{zynq} {Production}} $core
set_property name $ip_name $core
set_property display_name $ip_name $core
set_property description $ip_name $core

# Generate the XGUI files to accompany this IP core.
ipx::create_xgui_files $core
```

IP for AXI4_Lite Project

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\axi4_lite\ip\edge_detector_v1_0  
C:\> vivado -nolog -nojournal -mode batch -source edge_detector.tcl
```

C:\Users\hokim\work\embedded_linux\projects\axi4_lite\ip\xci_cfg_register_v1_0
→ AXI4-Lite IP for control register which are used for 4-bit leds here

hdl\xci_cfg_register.v

```
`timescale 1 ns / 1 ps

module axi_cfg_register #
(
    parameter integer CFG_DATA_WIDTH = 1024,
    parameter integer AXI_DATA_WIDTH = 32,
    parameter integer AXI_ADDR_WIDTH = 32
)
(
// System signals
    input wire                  aclk,
    input wire                  aresetn,
// Configuration bits
    output wire [CFG_DATA_WIDTH-1:0] cfg_data,
// Slave side
    input wire [AXI_ADDR_WIDTH-1:0] s_axi_awaddr, // AXI4-Lite slave: Write address
    input wire                   s_axi_awvalid, // AXI4-Lite slave: Write address valid
    output wire                  s_axi_awready, // AXI4-Lite slave: Write address ready
    input wire [AXI_DATA_WIDTH-1:0] s_axi_wdata, // AXI4-Lite slave: Write data
    input wire [AXI_DATA_WIDTH/8-1:0] s_axi_wstrb, // AXI4-Lite slave: Write strobe
    input wire                   s_axi_wvalid, // AXI4-Lite slave: Write data valid
```

hdl\axi_cfg_register.v

```
output wire          s_axi_wready, // AXI4-Lite slave: Write data ready
output wire [1:0]    s_axi_bresp, // AXI4-Lite slave: Write response
output wire          s_axi_bvalid, // AXI4-Lite slave: Write response valid
input  wire          s_axi_bready, // AXI4-Lite slave: Write response ready
input  wire [AXI_ADDR_WIDTH-1:0] s_axi_araddr, // AXI4-Lite slave: Read address
input  wire          s_axi_arvalid, // AXI4-Lite slave: Read address valid
output wire          s_axi_arready, // AXI4-Lite slave: Read address ready
output wire [AXI_DATA_WIDTH-1:0] s_axi_rdata, // AXI4-Lite slave: Read data
output wire [1:0]      s_axi_rresp, // AXI4-Lite slave: Read data response
output wire          s_axi_rvalid, // AXI4-Lite slave: Read data valid
input  wire          s_axi_rready // AXI4-Lite slave: Read data ready
);

function integer clogb2 (input integer value);
    for(clogb2 = 0; value > 0; clogb2 = clogb2 + 1) value = value >> 1;
endfunction

localparam integer ADDR_LSB = clogb2(AXI_DATA_WIDTH/8 - 1);
localparam integer CFG_SIZE = CFG_DATA_WIDTH/AXI_DATA_WIDTH;
localparam integer CFG_WIDTH = CFG_SIZE > 1 ? clogb2(CFG_SIZE-1) : 1;

reg int_bvalid_reg, int_bvalid_next;

reg int_rvalid_reg, int_rvalid_next;
reg [AXI_DATA_WIDTH-1:0] int_rdata_reg, int_rdata_next;

wire [AXI_DATA_WIDTH-1:0] int_data_mux [CFG_SIZE-1:0];
wire [CFG_DATA_WIDTH-1:0] int_data_wire;
wire [CFG_SIZE-1:0] int_ce_wire;
wire int_wvalid_wire;

genvar j, k;

assign int_wvalid_wire = s_axi_awvalid & s_axi_wvalid;
```

hdl\axi_cfg_register.v

```
generate
  for(j = 0; j < CFG_SIZE; j = j + 1)
    begin : WORDS
      assign int_data_mux[j] = int_data_wire[j*AXI_DATA_WIDTH+AXI_DATA_WIDTH-
1:j*AXI_DATA_WIDTH];
      assign int_ce_wire[j] = int_wvalid_wire & (s_axi_awaddr[ADDR_LSB+CFG_WIDTH-
1:ADDR_LSB] == j);
      for(k = 0; k < AXI_DATA_WIDTH; k = k + 1)
        begin : BITS
          FDRE #(
            .INIT(1'b0)
          ) FDRE_inst (
            .CE(int_ce_wire[j] & s_axi_wstrb[k/8]),
            .C(aclk),
            .R(~aresetn),
            .D(s_axi_wdata[k]),
            .Q(int_data_wire[j*AXI_DATA_WIDTH + k])
          );
        end
      end
    endgenerate

  always @(posedge aclk)
  begin
    if(~aresetn)
      begin
        int_bvalid_reg <= 1'b0;
        int_rvalid_reg <= 1'b0;
        int_rdata_reg <= {(AXI_DATA_WIDTH){1'b0}};
      end
    else
      begin
        int_bvalid_reg <= int_bvalid_next;
        int_rvalid_reg <= int_rvalid_next;
        int_rdata_reg <= int_rdata_next;
      end
  end
end
```

hdl\axi_cfg_register.v

```
always @*
begin
    int_bvalid_next = int_bvalid_reg;

    if(int_wvalid_wire)
        begin
            int_bvalid_next = 1'b1;
        end

    if(s_axi_bready & int_bvalid_reg)
        begin
            int_bvalid_next = 1'b0;
        end
    end

always @*
begin
    int_rvalid_next = int_rvalid_reg;
    int_rdata_next = int_rdata_reg;

    if(s_axi_arvalid)
        begin
            int_rvalid_next = 1'b1;
            int_rdata_next = int_data_mux[s_axi_araddr[ADDR_LSB+CFG_WIDTH-1:ADDR_LSB]];
        end

    if(s_axi_rready & int_rvalid_reg)
        begin
            int_rvalid_next = 1'b0;
        end
    end
```

hdl\axi_cfg_register.v

```
assign cfg_data = int_data_wire;  
  
assign s_axi_bresp = 2'd0;  
assign s_axi_rresp = 2'd0;  
  
assign s_axi_awready = int_wvalid_wire;  
assign s_axi_wready = int_wvalid_wire;  
assign s_axi_bvalid = int_bvalid_reg;  
assign s_axi_arready = 1'b1;  
assign s_axi_rdata = int_rdata_reg;  
assign s_axi_rvalid = int_rvalid_reg;  
  
endmodule
```

hdl\axi_cfg_register.tcl

```
set ip_name "axi_cfg_register"  
file delete -force component.xml xgui  
  
# Collect the names of the HDL source files that are used by this IP here.  
set file_list [list "hdl\axi_cfg_register.v"]  
  
# Create a new Vivado project for this IP and add the source files.  
create_project $ip_name . -force  
set proj_dir [get_property directory [current_project]]  
set proj_name [get_projects $ip_name]  
set proj_fileset [get_filesets sources_1]  
add_files -norecurse -scan_for_includes -fileset $proj_fileset $file_list  
set_property "top" "$ip_name" $proj_fileset  
ipx::package_project -root_dir .
```

hdl\axi_cfg_register.tcl

```
# Set the IP core information properties.  
set core [ipx::current_core]  
set_property vendor {hokim} $core  
set_property library {ip} $core  
set_property version {1.0} $core  
set_property vendor_display_name {Hyunok Kim} $core  
set_property company_url {https://github.com/hokim72} $core  
set_property supported_families {{zynq} {Production}} $core  
set_property name $ip_name $core  
set_property display_name $ip_name $core  
set_property description $ip_name $core  
  
set parameter [ipx::get_user_parameters AXI_DATA_WIDTH -of_objects $core]  
set_property DISPLAY_NAME {AXI DATA WIDTH} $parameter  
set_property DESCRIPTION {Width of the AXI data bus.} $parameter  
  
set parameter [ipgui::get_guibparamspec -name AXI_DATA_WIDTH -component $core]  
set_property DISPLAY_NAME {AXI DATA WIDTH} $parameter  
set_property TOOLTIP {Width of the AXI data bus.} $parameter  
  
set parameter [ipx::get_user_parameters AXI_ADDR_WIDTH -of_objects $core]  
set_property DISPLAY_NAME {AXI ADDR WIDTH} $parameter  
set_property DESCRIPTION {Width of the AXI address bus.} $parameter  
  
set parameter [ipgui::get_guibparamspec -name AXI_ADDR_WIDTH -component $core]  
set_property DISPLAY_NAME {AXI ADDR WIDTH} $parameter  
set_property TOOLTIP {Width of the AXI address bus.} $parameter  
  
set parameter [ipx::get_user_parameters CFG_DATA_WIDTH -of_objects $core]  
set_property DISPLAY_NAME {CFG DATA WIDTH} $parameter  
set_property DESCRIPTION {Width of the configuration data.} $parameter  
  
set parameter [ipgui::get_guibparamspec -name CFG_DATA_WIDTH -component $core]  
set_property DISPLAY_NAME {CFG DATA WIDTH} $parameter  
set_property TOOLTIP {Width of the configuration data.} $parameter
```

hdl\axi_cfg_register.tcl

```
set bus [ipx::get_bus_interfaces -of_objects $core s_axi]
set_property NAME S_AXI $bus
set_property INTERFACE_MODE slave $bus

set bus [ipx::get_bus_interfaces aclk]
set parameter [ipx::get_bus_parameters -of_objects $bus ASSOCIATED_BUSIF]
set_property VALUE S_AXI $parameter

# Generate the XGUI files to accompany this IP core.
ipx::create_xgui_files $core

# Save the IP core.
ipx::save_core $core

# Close the current project.
close_project

file delete -force $ip_name.cache $ip_name.hw $ip_name.ip_user_files $ip_name.xpr
```

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\axi4_lite\ip\axi_cfg_register_v1_0
C:\> vivado -nolog -nojournal -mode batch -source axi_cfg_register.tcl
```

C:\Users\hokim\work\embedded_linux\projects\axi4_lite\ip\xaxi_sts_register_v1_0
→ AXI4-Lite IP for status register which are used for 4-bit switches here

hdl\xaxi_sts_register.v

```
`timescale 1 ns / 1 ps

module axi_sts_register #
(
    parameter integer STS_DATA_WIDTH = 1024,
    parameter integer AXI_DATA_WIDTH = 32,
    parameter integer AXI_ADDR_WIDTH = 32
)
(
    // System signals
    input wire                  aclk,
    input wire                  aresetn,

    // Status bits
    input wire [STS_DATA_WIDTH-1:0] sts_data,

    // Slave side
    input wire [AXI_ADDR_WIDTH-1:0] s_axi_araddr, // AXI4-Lite slave: Read address
    input wire                  s_axi_arvalid, // AXI4-Lite slave: Read address valid
    output wire                 s_axi_arready, // AXI4-Lite slave: Read address ready
    output wire [AXI_DATA_WIDTH-1:0] s_axi_rdata, // AXI4-Lite slave: Read data
    output wire [1:0]              s_axi_rresp, // AXI4-Lite slave: Read data response
    output wire                 s_axi_rvalid, // AXI4-Lite slave: Read data valid
    input wire                  s_axi_rready // AXI4-Lite slave: Read data ready
);

function integer clogb2 (input integer value);
    for(clogb2 = 0; value > 0; clogb2 = clogb2 + 1) value = value >> 1;
endfunction
```

hdl\axi_sts_register.v

```
localparam integer ADDR_LSB = clogb2(AXI_DATA_WIDTH/8 - 1);
localparam integer STS_SIZE = STS_DATA_WIDTH/AXI_DATA_WIDTH;
localparam integer STS_WIDTH = STS_SIZE > 1 ? clogb2(STS_SIZE-1) : 1;

reg int_rvalid_reg, int_rvalid_next;
reg [AXI_DATA_WIDTH-1:0] int_rdata_reg, int_rdata_next;

wire [AXI_DATA_WIDTH-1:0] int_data_mux [STS_SIZE-1:0];

genvar j, k;

generate
    for(j = 0; j < STS_SIZE; j = j + 1)
        begin : WORDS
            assign int_data_mux[j] = sts_data[j]*AXI_DATA_WIDTH+AXI_DATA_WIDTH-
1:j*AXI_DATA_WIDTH];
        end
    endgenerate

always @(posedge aclk)
begin
    if(~aresetn)
    begin
        int_rvalid_reg <= 1'b0;
        int_rdata_reg <= {(AXI_DATA_WIDTH){1'b0}};
    end
    else
    begin
        int_rvalid_reg <= int_rvalid_next;
        int_rdata_reg <= int_rdata_next;
    end
end
```

hdl\axi_sts_register.v

```
always @*
begin
    int_rvalid_next = int_rvalid_reg;
    int_rdata_next = int_rdata_reg;

    if(s_axi_arvalid)
        begin
            int_rvalid_next = 1'b1;
            int_rdata_next = int_data_mux[s_axi_araddr[ADDR_LSB+STS_WIDTH-1:ADDR_LSB]];
        end

    if(s_axi_rready & int_rvalid_reg)
        begin
            int_rvalid_next = 1'b0;
        end
    end

    assign s_axi_rresp = 2'd0;

    assign s_axi_arready = 1'b1;
    assign s_axi_rdata = int_rdata_reg;
    assign s_axi_rvalid = int_rvalid_reg;

endmodule
```

axi_sts_register.tcl

```
set ip_name "axi_sts_register"
file delete -force component.xml xgui

# Collect the names of the HDL source files that are used by this IP here.
set file_list [list "hdl/axi_sts_register.v"]

# Create a new Vivado project for this IP and add the source files.
create_project $ip_name . -force
set proj_dir [get_property directory [current_project]]
set proj_name [get_projects $ip_name]
set proj_fileset [get_filesets sources_1]
add_files -norecurse -scan_for_includes -fileset $proj_fileset $file_list
set_property "top" "$ip_name" $proj_fileset
ipx::package_project -root_dir .

# Set the IP core information properties.
set core [ipx::current_core]
set_property vendor {hokim} $core
set_property library {ip} $core
set_property version {1.0} $core
set_property vendor_display_name {Hyunok Kim} $core
set_property company_url {https://github.com/hokim72} $core
set_property supported_families {{zynq} {Production}} $core
set_property name $ip_name $core
set_property display_name $ip_name $core
set_property description $ip_name $core
```

axi_sts_register.tcl

```
set parameter [ipx::get_user_parameters AXI_DATA_WIDTH -of_objects $core]
set_property DISPLAY_NAME {AXI DATA WIDTH} $parameter
set_property DESCRIPTION {Width of the AXI data bus.} $parameter

set parameter [ipgui::get_guibparamspec -name AXI_DATA_WIDTH -component $core]
set_property DISPLAY_NAME {AXI DATA WIDTH} $parameter
set_property TOOLTIP {Width of the AXI data bus.} $parameter

set parameter [ipx::get_user_parameters AXI_ADDR_WIDTH -of_objects $core]
set_property DISPLAY_NAME {AXI ADDR WIDTH} $parameter
set_property DESCRIPTION {Width of the AXI address bus.} $parameter

set parameter [ipgui::get_guibparamspec -name AXI_ADDR_WIDTH -component $core]
set_property DISPLAY_NAME {AXI ADDR WIDTH} $parameter
set_property TOOLTIP {Width of the AXI address bus.} $parameter

set parameter [ipx::get_user_parameters STS_DATA_WIDTH -of_objects $core]
set_property DISPLAY_NAME {STS DATA WIDTH} $parameter
set_property DESCRIPTION {Width of the status data.} $parameter

set parameter [ipgui::get_guibparamspec -name STS_DATA_WIDTH -component $core]
set_property DISPLAY_NAME {STS DATA WIDTH} $parameter
set_property TOOLTIP {Width of the status data.} $parameter
```

axi_sts_register.tcl

```
set bus [ipx::get_bus_interfaces -of_objects $core s_axi]
set_property NAME S_AXI $bus
set_property INTERFACE_MODE slave $bus

set bus [ipx::get_bus_interfaces aclk]
set parameter [ipx::get_bus_parameters -of_objects $bus ASSOCIATED_BUSIF]
set_property VALUE S_AXI $parameter

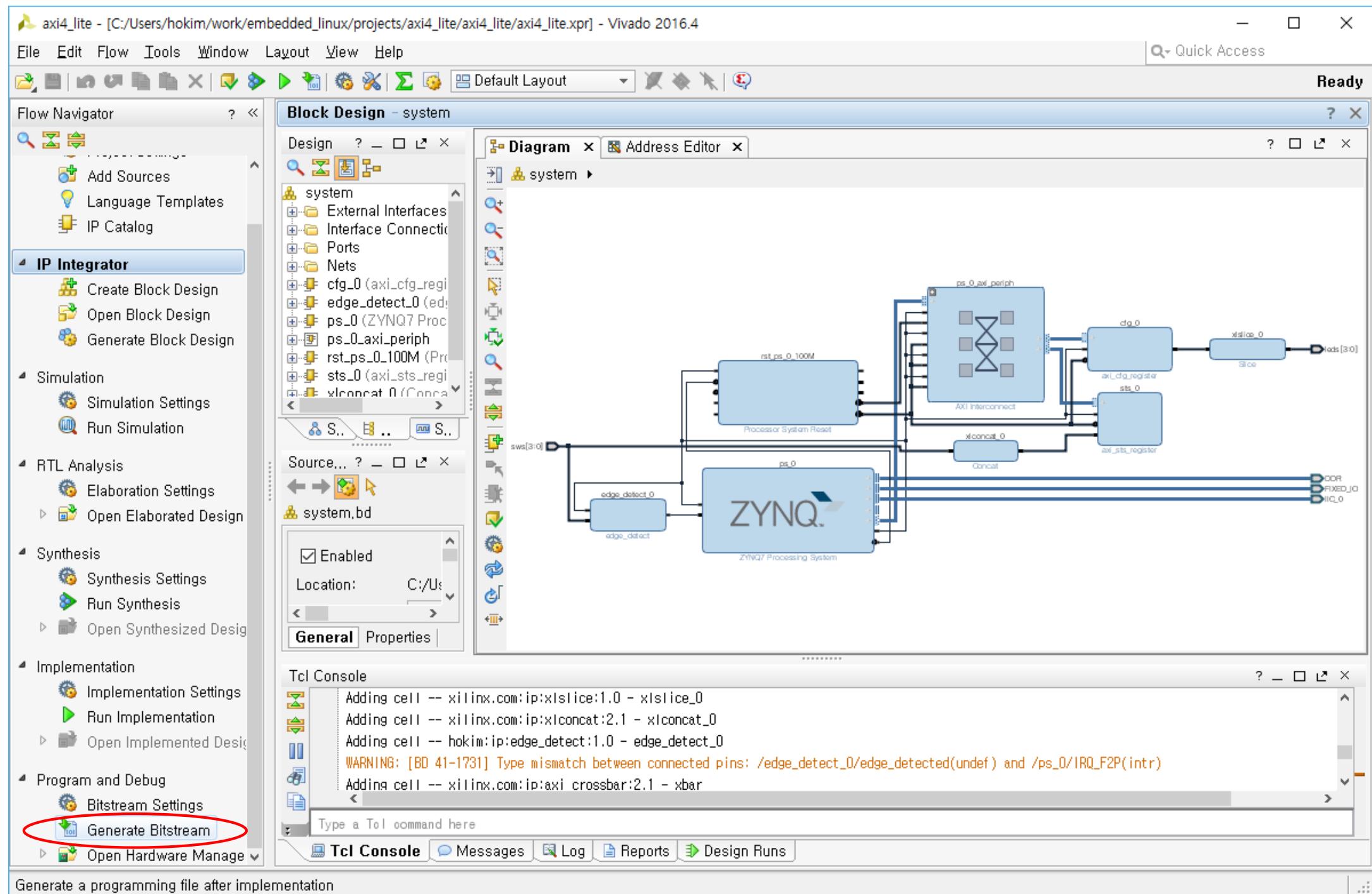
# Generate the XGUI files to accompany this IP core.
ipx::create_xgui_files $core

# Save the IP core.
ipx::save_core $core

# Close the current project.
close_project
```

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\axi4_lite\ip\axi_sts_register_v1_0
C:\> vivado -nolog -nojournal -mode batch -source axi_sts_register.tcl
```

Bit Generation for AXI4_Lite

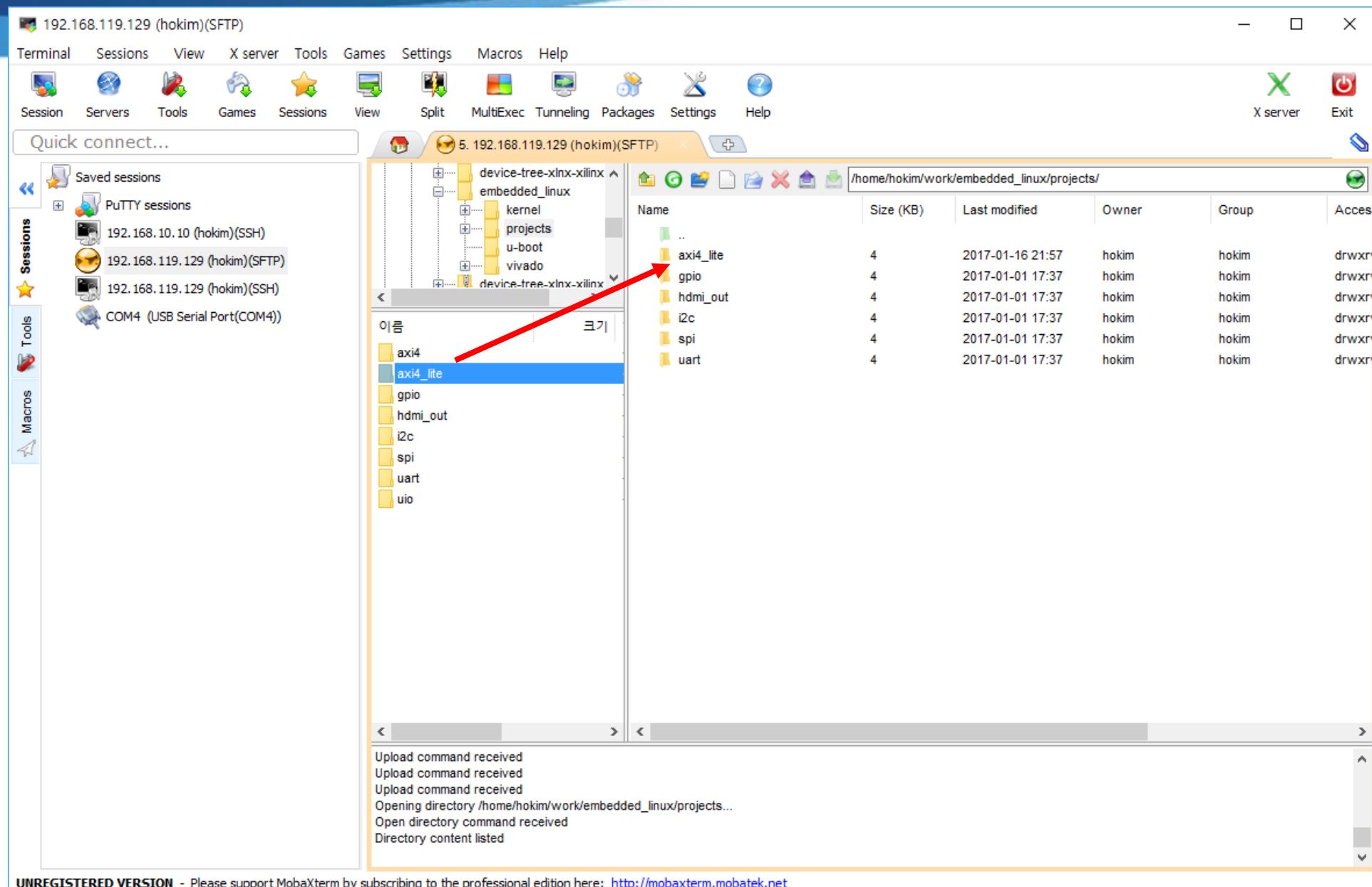


C:\Users\hokim\work\embedded_linux\projects\axi4_lite\all.bat

```
call vivado -nolog -nojournal -mode batch -source hwdef.tcl  
call hsi -nolog -nojournal -mode batch -source fsbl.tcl  
call tclsh bootbin.tcl  
  
call hsi -nolog -nojournal -mode batch -source devicetree.tcl
```

```
C:\> cd C:\Users\hokim\work\embedded_linux\projects\axi4_lite  
C:\> all
```

Device Tree Compile for UART



```
$ cd ~/work/embedded_linux/projects/axi4_lite
$ cp axi4_lite/uart.tree/system.dts system_axi4_lite.dts
$ nano system_axi4_lite.dts
```

Device Tree Compile for AXI4_Lite

system_axi4_lite.dts

```
/dts-v1/;  
/include/ "zynq-7000.dtsi"  
/include/ "pl.dtsi"  
.....  
chosen {  
-  bootargs = "console=ttyPS0,115200  
root=/dev/mmcblk0p2 ro rootfstype=ext4 earlyprintk rootwait";  
+  bootargs = "console=ttyPS0,115200  
root=/dev/mmcblk0p2 ro rootfstype=ext4 earlyprintk rootwait  
uio_pdrv_genirq.of_id=generic-uio";  
};  
.....  
&clkc {  
    fclk-enable = <0x1>;  
    ps-clk-frequency = <50000000>;  
};  
+&i2c0 {  
+  eeprom@50 {  
+    /* Microchip 24AA02E48 */  
+    compatible = "microchip,24c02";  
+    reg = <0x50>;  
+    pagesize = <8>;  
+  };  
+};  
+/  
+  usb_phy0: phy0 {  
+    compatible = "ulpi-phy";  
+    #phy-cells = <0>;  
+    reg = <0xe0002000 0x1000>;  
+    view-port = <0x0170>;  
+    drv-vbus;  
+  };  
+};
```

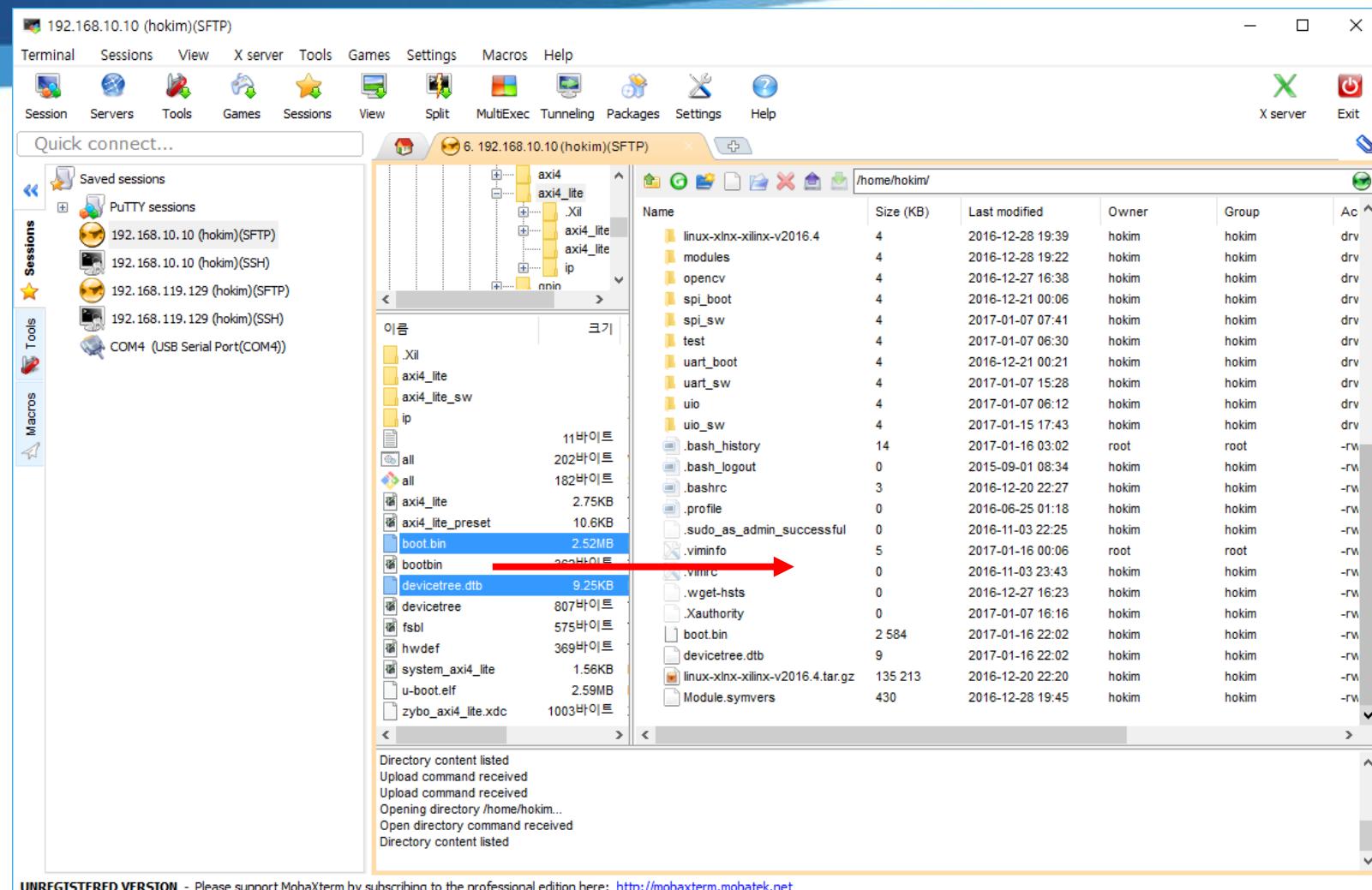
```
+&usb0 {  
+  usb-phy = <&usb_phy0>;  
+};  
+&cfg_0 {  
+  compatible = "generic-uio";  
+};  
+&sts_0 {  
+  compatible = "generic-uio";  
+  interrupt-parent = <&intc>;  
+  interrupts = <0x0 0x1d 0x1>;  
+};
```

axi4_lite/axi4_lite.tree/pl.dtsi

```
/ {  
    amba_pl: amba_pl {  
        #address-cells = <1>;  
        #size-cells = <1>;  
        compatible = "simple-bus";  
        ranges ;  
        cfg_0: axi_cfg_register@40000000 {  
            compatible = "xlnx,axi-cfg-register-1.0";  
            reg = <0x40000000 0x10000>;  
        };  
        sts_0: axi_sts_register@40010000 {  
            compatible = "xlnx,axi-sts-register-1.0";  
            reg = <0x40010000 0x10000>;  
        };  
    };  
};
```

```
$ dtc -O dtb -l dts -i axi4_lite/axi4_lite.tree/ -o devicetree.dtb system_axi4_lite.dts
```

Update boot.bin, devicetree.dtb for UART



login into zybo

```
$ sudo -s
# cd /boot
# rm boot.bin devicetree.dtb
# mv ~hokim/boot.bin .
# mv ~hokim/devicetree.dtb
# sync
# reboot
```

```
hokim@zybo:~$ ls /sys/class/uio  
uio0 uio1  
hokim@zybo:~$ cat /sys/class/uio/uio0/name  
axi_cfg_register  
hokim@zybo:~$ cat /sys/class/uio/uio1/name  
axi_sts_register
```

axi4_lite_test.c

```
#include <stdio.h>  
#include <stdint.h>  
#include <stdlib.h>  
#include <unistd.h>  
#include <sys/mman.h>  
#include <fcntl.h>  
  
#define DATA_OFFSET 0x0 /* Data register for  
cfg and sts */  
  
void uio_write(void *uio_base, uint32_t offset, uint32_t value)  
{  
    *((volatile uint32_t *) (uio_base + offset)) = value;  
}  
  
uint32_t uio_read(void *uio_base, uint32_t offset)  
{  
    return *((volatile uint32_t *) (uio_base + offset));  
}  
  
uint32_t get_memory_size(char *sysfs_path_file)  
{  
    FILE *size_fp;  
    uint32_t size;  
  
    // open the file that describes the memory range size that is based  
    on the  
    // reg property of the node in the device tree  
    size_fp = fopen(sysfs_path_file, "r");  
  
    if (!size_fp) {  
        printf("unable to open the uio size file\n");  
        exit(-1);  
    }
```

axi4_lite_test.c

```
// get the size which is an ASCII string such as 0xFFFFFFFF and  
then be stop  
    // using the file  
    fscanf(size_fp, "0x%08X", &size);  
    fclose(size_fp);  
  
    return size;  
}  
  
void wait_for_interrupt(int fd)  
{  
    int pending = 0;  
    int reenable = 1;  
    uint32_t reg;  
  
    // block on the file waiting for an interrupt  
    read(fd, (void *)&pending, sizeof(int));  
    //printf("Interrupt!\n");  
  
    // re-enable the interrupt in the interrupt controller thru  
    // the UIO subsystem now that it's been handled  
  
    write(fd, (void *)&reenable, sizeof(int));  
}  
  
int main()  
{  
    int cfg0_fd, sts0_fd;  
    void *cfg0;  
    void *sts0;  
    uint32_t cfg0_size, sts0_size;  
    int reenable = 1;  
    uint32_t value;
```



axi4_lite_test.c

```
if ((cfg0_fd = open("/dev/uio0", O_RDWR)) < 0) {
    perror("open cfg0");
    return -1;
}

if ((sts0_fd = open("/dev/uio1", O_RDWR)) < 0) {
    perror("open sts0");
    return -1;
}

cfg0_size =
get_memory_size("/sys/class/uio/uio0/maps/map0/size");
sts0_size =
get_memory_size("/sys/class/uio/uio1/maps/map0/size");

cfg0 = mmap(NULL, cfg0_size, PROT_READ|PROT_WRITE,
MAP_SHARED, cfg0_fd, 0);

if (cfg0 == MAP_FAILED) {
    perror("cfg0 mmap call failure");
    return -1;
}

sts0 = mmap(NULL, sts0_size, PROT_READ|PROT_WRITE,
MAP_SHARED, sts0_fd, 0);

if (sts0 == MAP_FAILED) {
    perror("sts0 mmap call failure");
    return -1;
}

write(sts0_fd, (void *)&reenable, sizeof(int));
```



axi4_lite_test.c

```
while (1)
{
    wait_for_interrupt(sts0_fd);
    value = uio_read(sts0, DATA_OFFSET);
    printf("sws = 0x%0X\n", value);
    uio_write(cfg0, DATA_OFFSET, value);
}

munmap(cfg0, cfg0_size);
munmap(sts0, sts0_size);

return 0;
}
```

```
$ cd ~/axi4_lite_sw
$ ls
$ CMakeLists.txt axi4_lite_test.c
$ mkdir build
$ cd build
$ cmake
$ make
$ sudo ./axi4_lite_test
```