

BeagleBone Black project

Bc. et Bc. Jaroslav Svoboda,
Andrea Vallejo, Diallo Elhadj Sadou

Advanced Digital Architectures

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Tasks

- Compile embedded Linux for BeagleBone Black
- Develop C application which uses
 - TCS34725 RGB colour sensor
 - L3GD20H 3-axis gyroscope

Compiling Linux

■ Buildroot

- custom Linux kernel 3.12 with patches for Texas Instruments SoCs
- U-Boot 2016.03
- gdbserver for remote debugging
- openssh for remote connection
- set of elementary programs BusyBox

Files

- FAT32 boot partition
 - X-Loader - MLO
 - U-boot binary - u-boot.bin
 - Linux kernel - zImage
- Linux partition
 - filesystem - rootfs.ext2

Configuration

- Allowed remote login for root user using password
 - /etc/ssh/sshd_config
 - PermitRootLogin yes
 - otherwise turn off!!!
- Set static IP address
 - /etc/network/interfaces
 - iface eth0 inet static
address 192.168.1.2
netmask 255.255.255.0

Development

- IDE Eclipse Oxygen from October 2017
- remote debugging
- both devices in 192.168.1.0 subnet
- root user

Cross-Compilation Configuration

- Adding a line for cross-compiling tools to the PATH variable in the file “.profile”:

```
PATH="/home/jaroslav/buildroot-2016-  
05/buildroot/output/host/usr/bin:$PATH"
```

- Creation of C/C++ project: gyroRGB
- Set the toolchain: Cross GCC
- Configuration: Debug [Activate]
- Prefix: arm-buildroot-linux-uclibcgnueabihf-
- Path: /home/jaroslav/buildroot-2016.05/output/host/usr/bin

The compiling process is made in Linux x86 machine and the execution in ARM architecture (BBB)!

Development III

Run **Debug Configuration**

Open a new **C/C++ Remote Application** and the code of the program to be debugged

- Project name
- Build Configuration: Use Active
- C/C++ Application: browse executable
- Remote Absolute File Path for C/C++ Application
- Commands to execute before application: chmod +x location path of the application
- **GDB Debugger:** Location path of the **gdb**
- **GDB Command:** Location path of the **.gdbinit** file
- **Debugger Options:** Gdbserver Settings / Port number

Sensors



(a) TCS34725 RGB colour sensor

GND → 1&2
3.3 V → 3&4
Clock → 17&19
Data → 18&20



(b) L3GD20H 3-axis gyroscope

Soldering

Figure: BeagleBone Black with HAT with sensors



Implementation - I²C Interface

```
#include <stdio.h>
#include <stdlib.h>
#include <linux/i2c-dev.h>
#include <sys/ioctl.h>
#include <fcntl.h>

int main()
{
// Create I2C bus
int file;
int file2;
char *bus = "/dev/i2c-1";
char *bus2 = "/dev/i2c-2";

if ((file = open(bus, O_RDWR)) < 0)
{
printf("Failed to open the bus.\n");
exit(1);
}
else
{ //the bus of RGB sensor was successfully opened
printf("It's alive!\n");

// Get I2C device , TCS34725 I2C address is 0x29(41)
ioctl(file , I2C_SLAVE, 0x29);
```

Implementation - RGB sensor

- First check in the datasheet of the sensor for address of the I2C device.

Available Options

DEVICE	ADDRESS	PACKAGE - LEADS	INTERFACE DESCRIPTION	ORDERING NUMBER
TCS34721 [†]	0x39	FN-6	I ² C Vbus = V _{DD} Interface	TCS34721FN
TCS34723 [†]	0x39	FN-6	I ² C Vbus = 1.8 V Interface	TCS34723FN
TCS34725	0x29	FN-6	I ² C Vbus = V _{DD} Interface	TCS34725FN
TCS34727	0x29	FN-6	I ² C Vbus = 1.8 V Interface	TCS34727FN

[†] Contact TAOS for availability.

- Example of configuration used in the code

```
// Select enable register(0x80)
// Power ON, RGBC enable, wait time disable(0x03)
char config[2] = {0};
config[0] = 0x80;
config[1] = 0x03;
write(file, config, 2);
```

Implementation - RGB sensor

■ Command Register

Table 4. Command Register

COMMAND	CMD	TYPE	ADDR/SF	--

`config[0] = 0x80;`

■ Time Register

Wait Time Register (0x03)

Wait time is set 2.4 ms increments unless the WLONG bit is asserted, in which case the wait times are 12× longer. WTIME is programmed as a 2's complement number.

Table 7. Wait Time Register

FIELD	BITS	DESCRIPTION			
		REGISTER VALUE	WAIT TIME	TIME (WLONG = 0)	TIME (WLONG = 1)
WTIME	7:0	0xFF	1	2.4 ms	0.029 sec
		0xAB	85	204 ms	2.45 sec
		0x00	256	614 ms	7.4 sec

`config[1] = 0x03;`

Implementation - Gyroscope

- First check in the datasheet of the sensor for address of the I²C device.

The Slave Address (SAD) associated to the L3GD20H is 110101xb. SDO/SA0 pin can be used to modify less significant bit of the device address. If SDO/SA0 pin is connected to voltage supply LSb is '1' (address 1101011b) else if SDO/SA0 pin is connected to ground LSb value is '0' (address 1101010b). This solution permits to connect and address two different gyroscopes to the same I²C bus.

- Example of configuration used in the code

```
// Enable X, Y, Z-Axis and disable Power down mode(0x0F)
char config[2] = {0};
config[0] = 0x20;
config[1] = 0x0F;
```

Implementation - Gyroscope

■ Axis control register

Table 19. CTRL1 register⁽¹⁾

DR1	DR0	BW1	BW0	PD	Zen	Xen	Yen
-----	-----	-----	-----	----	-----	-----	-----

1. Xen, Yen, Zen enable X, Y or Z register in level sensitive trigger mode. Once LVLEN bit = 1, DEN level replaces the LSB of X, Y or Z axes and all axis are available for reading.

■ Axis control register possible combination of value

Table 20. CTRL1 description

DR1-DR0	Output data rate selection. Refer to Table 21
BW1-BW0	Bandwidth selection. Refer to Table 21
PD	Power mode. Default value: 0. Refer to Table 0= Power Down 1= Normal Mode (For Sleep Mode set {PD:Zen:Yen:Xen} to {1000})
Zen	Z axis enable. Default value: 1 (0: Z axis disabled; 1: Z axis enabled)
Yen	Y axis enable. Default value: 1 (0: Y axis disabled; 1: Y axis enabled)
Xen	X axis enable. Default value: 1 (0: X axis disabled; 1: X axis enabled)

DR<1:0> is used to set ODR selection. **BW <1:0>** is used to set bandwidth selection.