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μC/OS-II

and

ARM Cortex-M3 Processors

Application Note

AN-1018

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Table of Contents

1.00	Introduction	4
2.00	The ARM Cortex-M3 programmer's model	6
3.00	μC/OS-II Port for the ARM Cortex-M3 processors	9
3.01	Directories and Files	10
3.02	OS_CPU.H	11
3.02.01	OS_CPU.H, macros for 'externals'	11
3.02.02	OS_CPU.H, Data Types	11
3.02.03	OS_CPU.H, Critical Sections	12
3.02.04	OS_CPU.H, Stack growth	12
3.02.05	OS_CPU.H, Task Level Context Switch.....	13
3.02.06	OS_CPU.H, Function Prototypes	13
3.03	OS_CPU_C.C	14
3.03.01	OS_CPU_C.C, OSInitHookBegin()	14
3.03.02	OS_CPU_C.C, OSTaskCreateHook()	15
3.03.03	OS_CPU_C.C, OSTaskStkInit()	16
3.03.04	OS_CPU_C.C, OSTaskSwHook()	18
3.03.05	OS_CPU_C.C, OSTimeTickHook()	18
3.04	OS_CPU_A.ASM	19
3.04.01	OS_CPU_A.ASM, OS_CPU_SR_Save()	19
3.04.02	OS_CPU_A.ASM, OS_CPU_SR_Restore()	19
3.04.03	OS_CPU_A.ASM, OSStartHighRdy()	20
3.04.04	OS_CPU_A.ASM, OSCtxSw()	21
3.04.05	OS_CPU_A.ASM, OSIntCtxSw()	22
3.04.06	OS_CPU_A.ASM, OSPendSV()	22
3.05	OS_DBG.C	26
4.00	Exception Vector Table	27
4.01	Exception / Interrupt Handling Sequence	29
4.02	Interrupt Controllers	29
4.03	Interrupt Service Routines.....	29
5.00	Application Code	30
5.01	APP.C, APP.H and APP_CFG.H	31
5.02	INCLUDES.H	34

6.00	BSP (Board Support Package).....	35
6.01	BSP (Board Support Package) – LED Management.....	35
6.02	BSP (Board Support Package) – Clock Tick	36
7.00	Conclusion	37
	Licensing.....	38
	References.....	38
	Contacts.....	38
	Notes.....	39

1.00 Introduction

ARM has been working on a new architecture called the Cortex for a number of years. During development, μC/OS-II was used to validate some of the design aspects and was used as a source of ideas to create new capabilities to support RTOSs. In other words, μC/OS-II was the first RTOS ported to the Cortex.

This application note describes the 'official' Micrium port for μC/OS-II on the Cortex-M3 processor. Figure 1-1 shows a block diagram showing the relationship between your application, μC/OS-II, the port code and the BSP (Board Support Package). Relevant sections of this application note are referenced on the figure.

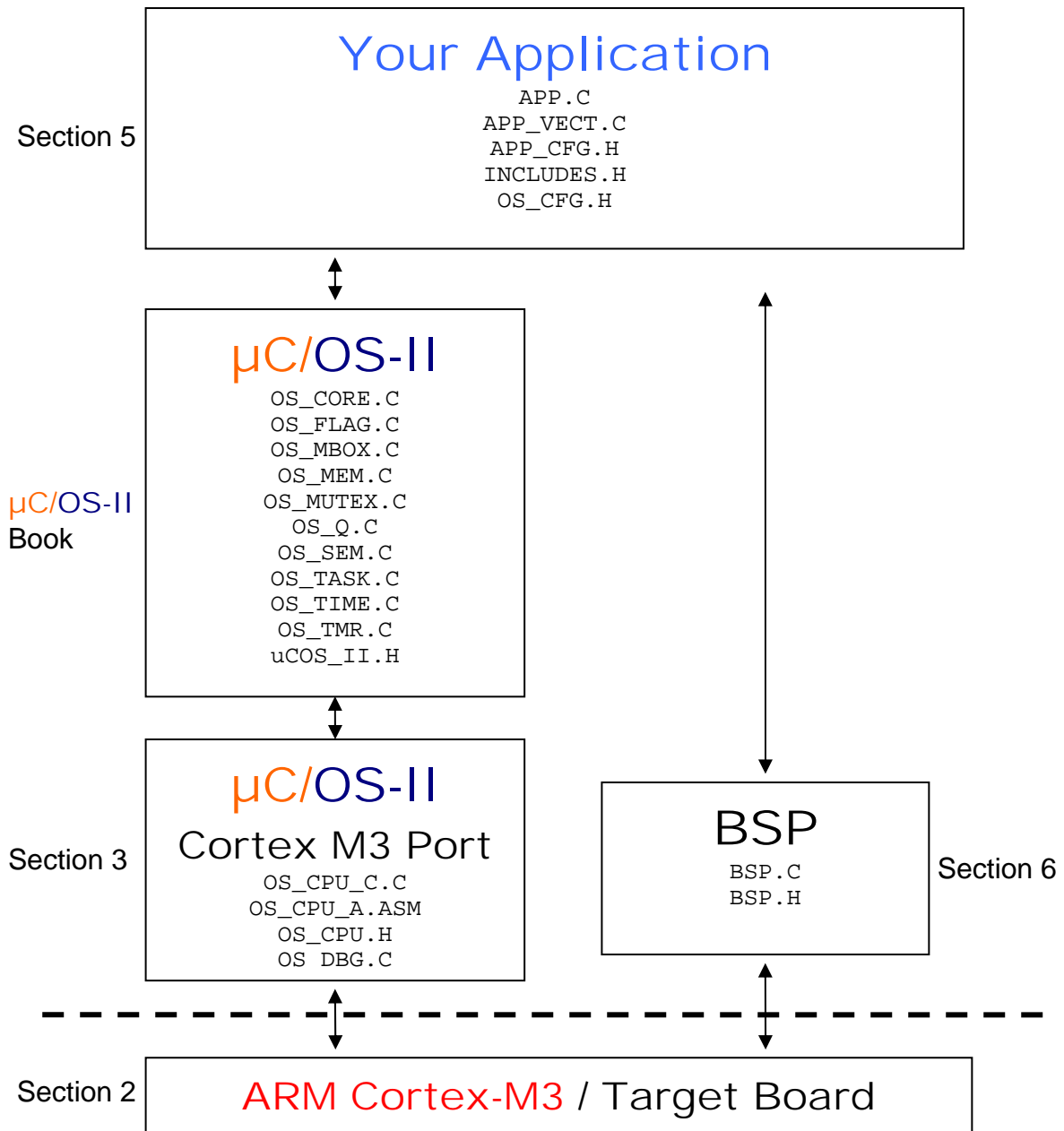


Figure 1-1, Relationship between modules.

2.00 The ARM Cortex-M3 programmer's model

The visible registers in an ARM Cortex-M3 processor are shown in Figure 2-1. The ARM Cortex-M3 has a total of 20 registers. Each register is 32 bits wide.

- | | |
|--------|---|
| R0-R12 | R0 through R12 are general purpose registers that can be used to hold data as well as pointers. |
| R13 | Is generally designated as the stack pointer (also called the <i>SP</i>) but could be the recipient of arithmetic operations. There are actually two stack pointers (<i>SP_process</i> and <i>SP_main</i>) but only one is visible at any given time. <i>SP_process</i> is used for task level code and <i>SP_main</i> is used for exception processing. |
| R14 | Is called the Link Register (<i>LR</i>) and is used to store the contents of the <i>PC</i> when a Branch and Link (<i>BL</i>) instruction is executed. The <i>LR</i> allows you to return to the caller. |
| R15 | Is dedicated to be used as the Program Counter (<i>PC</i>) and points to the current instruction being executed. As instructions are executed, the <i>PC</i> is incremented by either 2 or 4 depending on the instruction. |

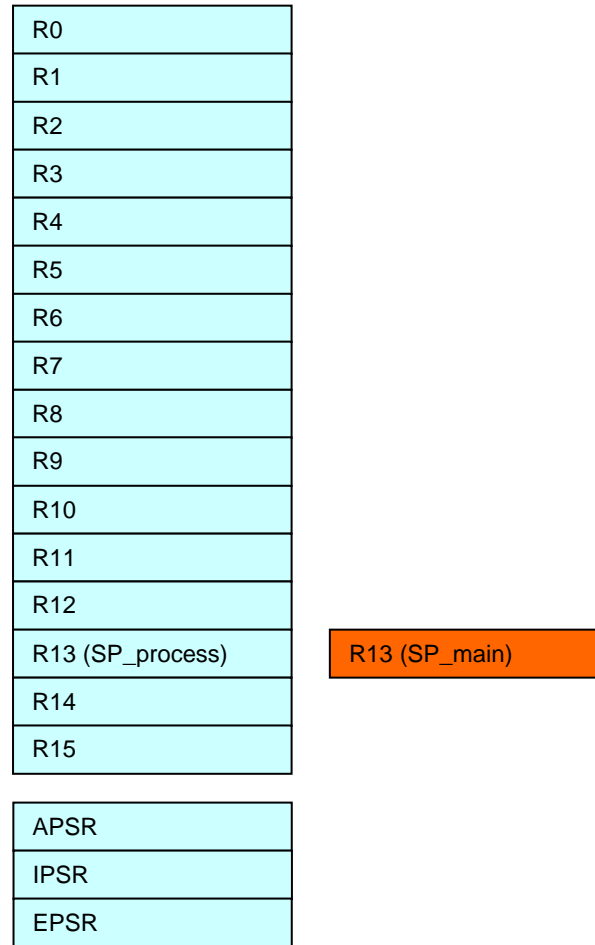


Figure 2-1, ARM Cortex-M3 Register Model.

xPSR

There are three separate registers to hold the state of the CPU: APSR, IPSR and EPSR. The **APSR** contains application status such as shown in Figure 2-2.



Figure 2-2, The APSR Register.

3.00 μC/OS-II Port for the ARM Cortex-M3 processors

We used the IAR EWARM V4.40A (Embedded Workbench for the ARM) to test the port. The EWARM contains an editor, a C/EC++ compiler, an assembler, a linker/locator and the C-Spy debugger. The C-Spy debugger actually contains an ARM Cortex-M3 simulator which allows you to test code prior to run it on actual hardware. We tested the ARM Cortex-M3 port on a Luminary Micro DK-LM3Sxxx development board as shown in Figure 3-1.

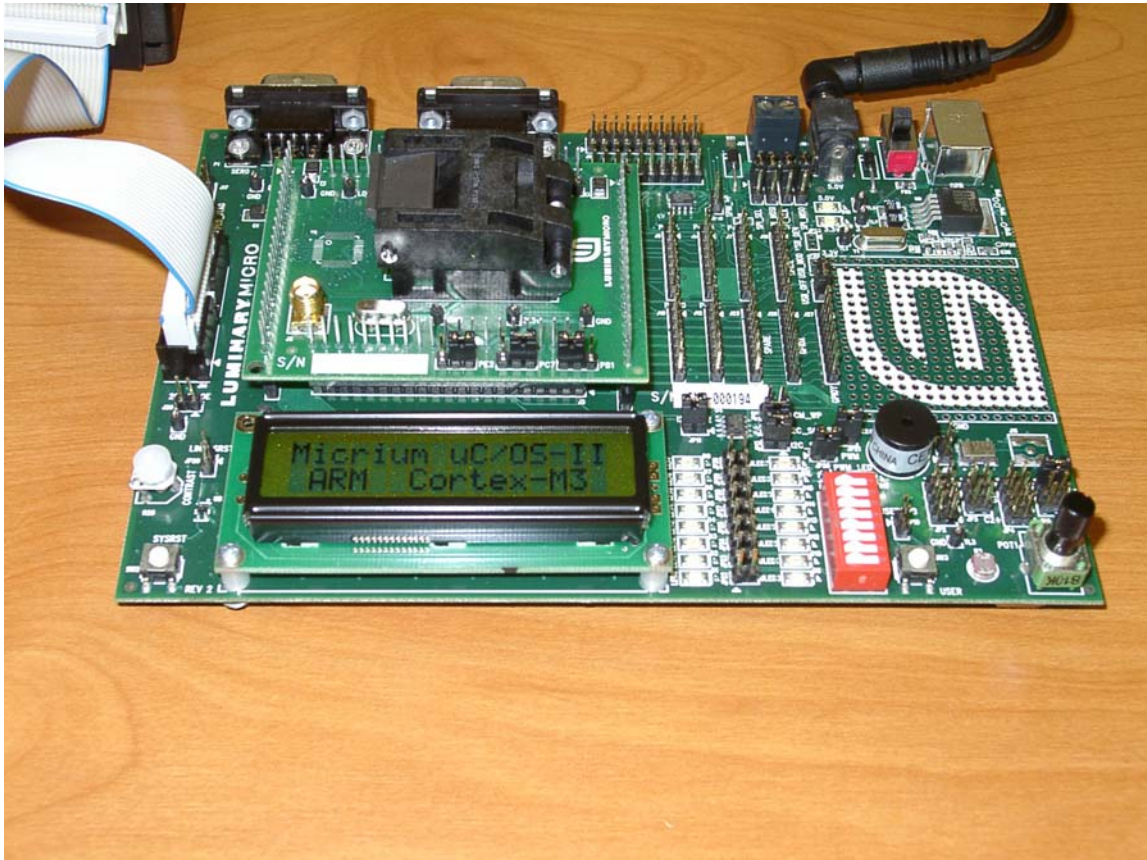


Figure 3-1, Luminary Micro DK-LM3Sxxx Development Kit (LM3S102 chip)

You can adapt the port provided in this application note to other ARM Cortex-M3 based compilers. The instructions (i.e. the code) should be identical and all you have to do is adapt the port to your compiler specifics. We will describe some of these when we cover the contents of the different files.

The port assumes that you are using μC/OS-II V2.83 or higher.

3.01 Directories and Files

The software that accompanies this application note is assumed to be placed in the following directory:

```
\Micrium\Software\uCOS-II\ARM-Cortex-M3\Generic\IAR
```

Like all μC/OS-II ports, the source code for the port is found in the following files:

```
OS_CPU.H  
OS_CPU_C.C  
OS_CPU_A.ASM  
OS_DBG.C
```

Test code and configuration files are found in their appropriate directories and are described later.

3.02 OS_CPU.H

OS_CPU.H contains processor- and implementation-specific `#defines` constants, macros, and typedefs.

3.02.01 OS_CPU.H, macros for ‘externals’

OS_CPU_GLOBALS and OS_CPU_EXT allows us to declare global variables that are specific to this port (described later).

Listing 3-1, OS_CPU.H, Globals and Externs

```
#ifdef OS_CPU_GLOBALS
#define OS_CPU_EXT
#else
#define OS_CPU_EXT extern
#endif
```

3.02.02 OS_CPU.H, Data Types

Listing 3-2, OS_CPU.H, Data Types

```
typedef unsigned char  BOOLEAN;
typedef unsigned char  INT8U;
typedef signed  char   INT8S;
typedef unsigned short INT16U;           // (1)
typedef signed  short  INT16S;
typedef unsigned int   INT32U;
typedef signed  int    INT32S;
typedef float          FP32;             // (2)
typedef double         FP64;

typedef unsigned int   OS_STK;           // (3)
typedef unsigned int   OS_CPU_SR;       // (4)
```

- L3-2(1) If you were to consult the IAR compiler documentation, you would find that an `short` is 16 bits and an `int` is 32 bits. Most ARM compilers should have the same definitions.
- L3-2(2) Floating-point data types are included even though µC/OS-II doesn't make use of floating-point numbers.
- L3-2(3) A stack entry for the ARM processor is always 32 bits wide; thus, `OS_STK` is declared accordingly. All task stacks must be declared using `OS_STK` as its data type.
- L3-2(4) The status register (the `xPSR`) on the ARM processor is 32 bits wide. The `OS_CPU_SR` data type is used when `OS_CRITICAL_METHOD #3` is used (described below). In fact, this port only supports `OS_CRITICAL_METHOD #3` because it's the preferred method for µC/OS-II ports.

3.02.03 OS_CPU.H, Critical Sections

μC/OS-II, as with all real-time kernels, needs to disable interrupts in order to access critical sections of code and re-enable interrupts when done. μC/OS-II defines two macros to disable and enable interrupts: `OS_ENTER_CRITICAL()` and `OS_EXIT_CRITICAL()`, respectively. μC/OS-II defines three ways to disable interrupts but, you only need to use one of the three methods for disabling and enabling interrupts. The book (MicroC/OS-II, The Real-Time Kernel) describes the three different methods. The one to choose depends on the processor and compiler. In most cases, the preferred method is `OS_CRITICAL_METHOD #3`.

`OS_CRITICAL_METHOD #3` implements `OS_ENTER_CRITICAL()` by writing a function that will save the status register of the CPU in a variable. `OS_EXIT_CRITICAL()` invokes another function to restore the status register from the variable. In the book, Mr. Labrosse recommends that you call the functions expected in `OS_ENTER_CRITICAL()` and `OS_EXIT_CRITICAL()`: `OS_CPU_SR_Save()` and `OS_CPU_SR_Restore()`, respectively. The code for these two functions is declared in `OS_CPU_A.S` (described later).

Listing 3-3, OS_CPU.H, OS_ENTER_CRITICAL() and OS_EXIT_CRITICAL()

```
#define OS_CRITICAL_METHOD    3

#define OS_ENTER_CRITICAL()  {cpu_sr = OS_CPU_SR_Save();}
#define OS_EXIT_CRITICAL()   {OS_CPU_SR_Restore(cpu_sr);}
```

Note that if your application code uses these macros, you MUST allocate a local variable called 'cpu_sr' and initialize it to 0, as shown below:

```
OS_CPU_SR  cpu_sr = 0;
```

3.02.04 OS_CPU.H, Stack growth

The stacks on the ARM Cortex-M3 grows from high memory to low memory and thus, `OS_STK_GROWTH` is set to 1 to indicate this to μC/OS-II.

Listing 3-4, OS_CPU.H, Stack Growth

```
#define OS_STK_GROWTH        1
```

3.02.05 OS_CPU.H, Task Level Context Switch

Task level context switches are performed when μC/OS-II invokes the macro `OS_TASK_SW()`. Because context switching is processor specific, `OS_TASK_SW()` needs to execute an assembly language function. In this case, `OSCtxSw()` which is declared in `OS_CPU_A.ASM` (described later).

Listing 3-5, OS_CPU.H, Task Level Context Switch

```
#define OS_TASK_SW()          OSCtxSw()
```

3.02.06 OS_CPU.H, Function Prototypes

The prototypes in Listing 3-6 are for the functions used to disable and re-enable interrupts using `OS_CRITICAL_METHOD #3` and are described later. You should note that these prototypes are prefixed with the special keyword `__arm`. This is an IAR keyword that indicates that these functions will run in ARM mode and thus, when called, the compiler will generate the appropriate instructions.

Listing 3-6, OS_CPU.H, Function Prototypes

```
#if OS_CRITICAL_METHOD == 3
OS_CPU_SR OS_CPU_SR_Save(void);
void      OS_CPU_SR_Restore(OS_CPU_SR cpu_sr);
#endif
```

As of V2.77, the prototypes for `OSCtxSw()`, `OSIntCtxSw()` and `OSStartHighRdy()` need to be placed in `OS_CPU.H`. In fact, it makes sense to do this since these are all port specific files.

Listing 3-7, OS_CPU.H, Function Prototypes

```
void      OSCtxSw(void);
void      OSIntCtxSw(void);
void      OSStartHighRdy(void);

void      OSPendSV(void);
```

3.03 OS_CPU_C.C

A μC/OS-II port requires that you write ten fairly simple C functions:

```
OSInitHookBegin()  
OSInitHookEnd()  
OSTaskCreateHook()  
OSTaskDelHook()  
OSTaskIdleHook()  
OSTaskStatHook()  
OSTaskStkInit()  
OSTaskSwHook()  
OSTCBInitHook()  
OSTimeTickHook()
```

Typically, μC/OS-II only requires OSTaskStkInit(). The other functions allow you to extend the functionality of the OS with your own functions. The functions that are highlighted will be discussed in this section.

Note that you will also need to set the #define constant OS_CPU_HOOKS_EN to 1 in OS_CFG.H in order for the compiler to use the functions declared in this file.

3.03.01 OS_CPU_C.C, OSInitHookBegin()

This function is called by μC/OS-II's OSInit() at the very beginning of OSInit(). It gives the opportunity to add additional initialization code specific to the port. In this case, we initialize the global variable (global to OS_CPU_C.C) OSTmrCtr (which is used by the OS_TMR.C module (if OS_TMR_EN is set to 1)).

Listing 3-8, OS_CPU_C.C, OSInitHookEnd()

```
void OSInitHookBegin (void)  
{  
    #if OS_TMR_EN > 0  
        OSTmrCtr = 0;  
    #endif  
}
```

3.03.02 OS_CPU_C.C, OSTaskCreateHook()

This function is called by μC/OS-II's OSTaskCreate() or OSTaskCreateExt() when a task is created. OSTaskCreateHook() gives the opportunity to add code specific to the port when a task is created. In our case, we call the initialization function of μC/OS-View (an optional module available for μC/OS-II which performs task profiling at run-time, See www.micrium.com for details).

Note that for OSView_TaskCreateHook() to be called, the target resident code for μC/OS-View must be included as part of your build. In this case, you need to add a #define OS_VIEW_MODULE 1 in OS_CFG.H of your application.

Note that if OS_VIEW_MODULE is 0, we simply tell the compiler that ptcb is not actually used (i.e. (void)ptcb)) and thus avoid a compiler warning.

Listing 3-9, OS_CPU_C.C, osInitHookEnd()

```
void OSTaskCreateHook (OS_TCB *ptcb)
{
    #if OS_VIEW_MODULE > 0
        OSView_TaskCreateHook(ptcb);
    #else
        (void)ptcb;
    #endif
}
```

3.03.03 OS_CPU_C.C, OSTaskStkInit()

It is typical for ARM compilers (the Cortex-M3 also) to pass the first argument of a function into the R0 register. Recall that a task is declared as shown in listing 3-10.

Listing 3-10, µC/OS-II Task

```
void MyTask (void *p_arg)
{
    /* Do something with 'p_arg', optional */
    while (1) {
        /* Task body */
    }
}
```

The code in Listing 3-11 initializes the stack frame for the task being created. The task received an optional argument 'p_arg'. That's why 'p_arg' is passed in R0 when the task is created. The initial value of most of the CPU registers is not important so, we decided to initialize them to values corresponding to their register number. This makes it convenient when debugging and examining stacks in RAM. The initial values are thus useful when the task is first created but, of course, the register values will most likely change as the task code is executed.

Listing 3-11, OS_CPU_C.C, OSTaskStkInit()

```
OS_STK *OSTaskStkInit (void (*task)(void *pd), void *p_arg, OS_STK *ptos, INT16U opt)
{
    OS_STK *stk;

    (void)opt; /* 'opt' is not used, prevent warning */
    stk = ptos; /* Load stack pointer */

    /* Registers stacked as if saved on exception */
    *(stk) = (INT32U)0x01000000L; /* xPSR */
    *(--stk) = (INT32U)task; /* Entry Point */
    *(--stk) = (INT32U)0xFFFFFFFFL; /* R14 (LR) */
    *(--stk) = (INT32U)0x12121212L; /* R12 */
    *(--stk) = (INT32U)0x03030303L; /* R3 */
    *(--stk) = (INT32U)0x02020202L; /* R2 */
    *(--stk) = (INT32U)0x01010101L; /* R1 */
    *(--stk) = (INT32U)p_arg; /* R0 : argument */

    /* Remaining registers saved on process stack */
    *(--stk) = (INT32U)0x11111111L; /* R11 */
    *(--stk) = (INT32U)0x10101010L; /* R10 */
    *(--stk) = (INT32U)0x09090909L; /* R9 */
    *(--stk) = (INT32U)0x08080808L; /* R8 */
    *(--stk) = (INT32U)0x07070707L; /* R7 */
    *(--stk) = (INT32U)0x06060606L; /* R6 */
    *(--stk) = (INT32U)0x05050505L; /* R5 */
    *(--stk) = (INT32U)0x04040404L; /* R4 */

    return (stk);
}
```

Figure 3-2 shows how the stack frame is initialized for each task when it's created.

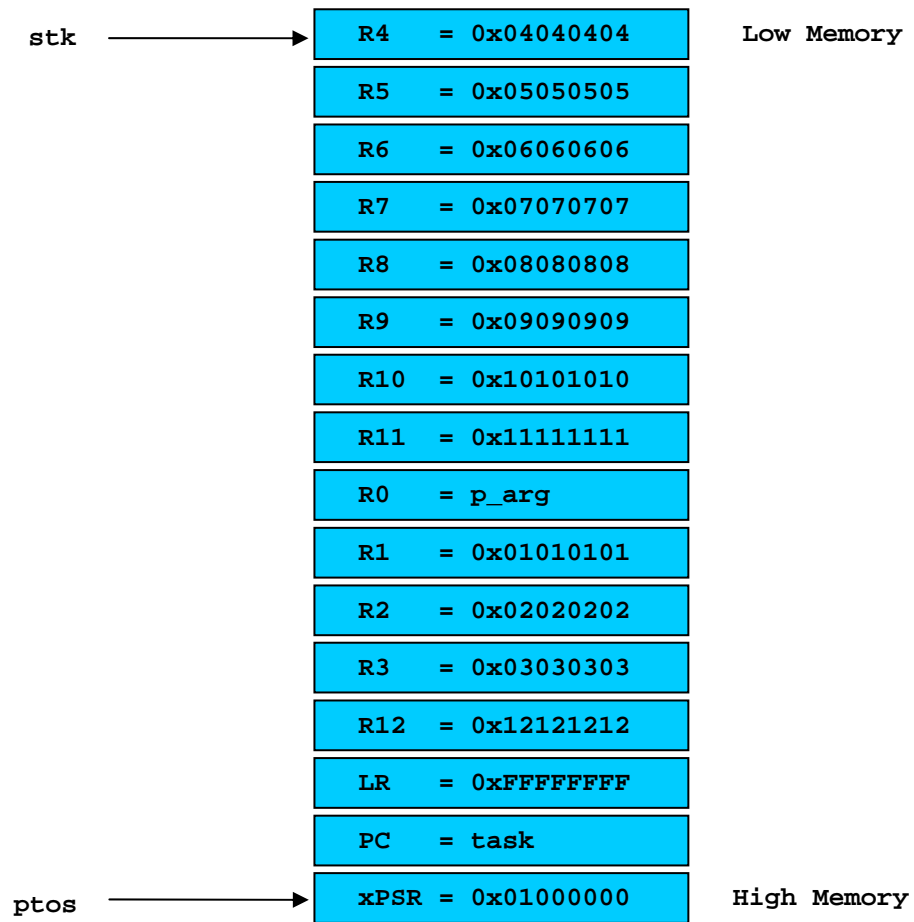


Figure 3-2, The Stack Frame for each Task for ARM Cortex-M3 port.

When the task is created, the final value of `stk` is placed in the `OS_TCB` of that task by the μC/OS-II function that calls `OSTaskStkInit()` (i.e. `OSTaskCreate()` or `OSTaskCreateExt()`).

3.03.04 OS_CPU_C.C, OSTaskSwHook()

OSTaskSwHook() is called when a context switch occurs. This function allows the port code to be extended and do things such as measuring the execution time of a task, output a pulse on a port pin when a context switch occurs, etc. In this case, we call the µC/OS-View task switch hook called OSView_TaskSwHook(). This assumes that you have µC/OS-View as part of your build and that you set OS_VIEW_MODULE to 1 in OS_CFG.H.

Listing 3-12, OS_CPU_C.C, OSTaskSwHook()

```
void OSTaskSwHook (void)
{
    #if OS_VIEW_MODULE > 0
        OSView_TaskSwHook();
    #endif
}
```

3.03.05 OS_CPU_C.C, OSTimeTickHook()

OSTimeTickHook() is called at the very beginning of OSTimeTick(). This function allows the port code to be extended and, in our case, we call the µC/OS-View function OSView_TickHook(). Again, this assumes that you have µC/OS-View as part of your build and that you set OS_VIEW_MODULE to 1 in OS_CFG.H.

OSTimeTickHook() also determines whether it's time to update the µC/OS-II timers. This is done by signaling the timer task.

Listing 3-13, OS_CPU_C.C, OSTimeTickHook()

```
void OSTimeTickHook (void)
{
    #if OS_VIEW_MODULE > 0
        OSView_TickHook();
    #endif

    #if OS_TMR_EN > 0
        OSTmrCtr++;
        if (OSTmrCtr >= (OS_TICKS_PER_SEC / OS_TMR_CFG_TICKS_PER_SEC)) {
            OSTmrCtr = 0;
            OSTmrSignal();
        }
    #endif
}
```

3.04 OS_CPU_A.ASM

A μC/OS-II port requires that you write five fairly simple assembly language functions. These functions are needed because you normally cannot save/restore registers from C functions. The five functions are:

```
OS_CPU_SR_Save( )
OS_CPU_SR_Restore( )
OSStartHighRdy( )
OSCtxSw( )
OSIntCtxSw( )
```

The ARM Cortex-M3 uses a clever way to perform a context switch. This is done via a special exception handler which needs to be defined (it will be described later). The handler is:

```
OSPendSV( )
```

3.04.01 OS_CPU_A.ASM, OS_CPU_SR_Save()

The code in listing 3-14 implements the saving of the interrupt mask register and then disabling interrupts to implement OS_CRITICAL_METHOD #3. This function is invoked by the OS_ENTER_CRITICAL() macro.

When this function returns, R0 contains the state of the PRIMASK register which contains the global interrupt mask prior to disabling interrupts.

Listing 3-14, OS_CPU_SR_Save()

```
OS_CPU_SR_Save
    MRS    R0, PRIMASK        ; set prio int mask to mask all (except faults)
    CPSID  I
    BX     LR
```

3.04.02 OS_CPU_A.ASM, OS_CPU_SR_Restore()

The code in the listing below implements the function to restore the interrupt disable mask to its original value prior to calling OS_ENTER_CRITICAL() (see previous section). In other words, if interrupts were disabled prior to calling OS_ENTER_CRITICAL(), they would be disabled after calling OS_EXIT_CRITICAL().

Listing 3-15, OS_CPU_SR_Restore()

```
OS_CPU_SR_Restore
    MSR    PRIMASK,R0
    BX     LR
```

3.04.03 OS_CPU_A.ASM, OSStartHighRdy()

OSStartHighRdy() is called by OSStart() to start running the highest priority task that was created before calling OSStart(). OSStart() sets OSTCBHighRdy to point to the OS_TCB of the highest priority task.

Listing 3-16, OSStartHighRdy()

OSStartHighRdy

```

LDR    R4, =NVIC_SYSPRI2      ; (1) Set the PendSV exception priority
LDR    R5, =NVIC_PENDSV_PRI
STR    R5, [R4]

MOV    R4, #0                  ; (2) Set PSP to 0 for initial context switch call
MSR    PSP, R4

LDR    R4, __OS_Running        ; (3) OSRunning = TRUE
MOV    R5, #1
STRB   R5, [R4]

LDR    R4, =NVIC_INT_CTRL      ; (4) Trigger the PendSV exception
LDR    R5, =NVIC_PENDSVSET
STR    R5, [R4]

CPSIE  I                       ; (5) Enable interrupts at processor level

```

- L3-16(1) The ARM Cortex-M3 provides a special mechanism to perform a context switch. Specifically, the ARM Cortex-M3 provides a special exception handler called the PendSV (Pend Service call). The PendSV is basically an interrupt mechanism that is triggered s called by software. It's like a software interrupt except that the interrupt is not taken until interrupts are enabled. This step sets up the PendSV interrupt priority which, is typically set lower than hardware interrupts. Note that the PendSV is set to be un-interruptable so that the PendSV call can perform a context switch atomically.

- L3-16(2) Here we setup the SP_process stack pointer to run the very first task but by the PendSV handler. This is done by setting the SP_process to 0 to inform the PendSV handler to not save the context of the task (because there is no task to save the context for since it will be the first task to run). It is assumed that OSTCBHighRdy contains the pointer to the OS_TCB of the task to start.

- L3-16(3) Here we set OSRunning to TRUE to indicate that multitasking will start.

- L3-16(4) We are ready to trigger the PendSV handler which will be starting the first task. The PendSV handler will run only when interrupts are enabled (see next step).

- L3-16(5) Once interrupts are enabled the ARM Cortex-M3 processor will branch to the PendSV handler (described later).

3.04.04 OS_CPU_A.ASM, OSCtxSw()

When a task gives up control of the CPU, the `OS_TASK_SW()` macro is invoked (see `OS_CPU.H`) which is translated to a call to `OSCtxSw()`. Normally, `OSCtxSw()` performs a task level context switch but, on the ARM Cortex-M3, all context switching is deferred to the PendSV handler. `OSCtxSw()` thus simply triggers the PendSV handler and returns to the caller. The PendSV handler does not execute immediately because `OS_TASK_SW()` (and thus `OSCtxSw()`) is invoked with interrupts disabled. The PendSV handler will only execute when interrupts are re-enabled.

`OS_TASK_SW()` is always called from `OS_Sched()` (see `OS_CORE.C`). The current version of `OS_Sched()` is shown in Listing 3-17.

Listing 3-17, `OS_Sched()`

```
void OS_Sched (void)
{
    #if OS_CRITICAL_METHOD == 3
        OS_CPU_SR cpu_sr = 0;
    #endif

    OS_ENTER_CRITICAL();
    if (OSIntNesting == 0) {
        if (OSLockNesting == 0) {
            OS_SchedNew();
            if (OSPrioHighRdy != OSPrioCur) {
                OSTCBHighRdy = OSTCBPrioTbl[OSPrioHighRdy];
            #if OS_TASK_PROFILE_EN > 0
                OSTCBHighRdy->OSTCBCtxSwCtr++;
            #endif

            OSCtxSwCtr++;
            OS_TASK_SW();
        }
    }
    OS_EXIT_CRITICAL();
}
```

Trigger the PendSV handler

PendSV handler will run when interrupts are re-enabled

The code for `OSCtxSw()` is shown in Listing 3-18. Again, all we do here is trigger the PendSV handler. Note that `OS_Sched()` sets `OSTCBHighRdy` to point to the `OS_TCB` of the task we wish to switch to.

Listing 3-18, `OSCtxSw()`

```
OSCtxSw
LDR    R4, =NVIC_INT_CTRL      ; trigger the PendSV exception
LDR    R5, =NVIC_PENDSVSET
STR    R5, [R4]
BX     LR
```

3.04.05 OS_CPU_A.ASM, OSIntCtxSw()

When an ISR completes, `OSIntExit()` is called to determine whether a more important task than the interrupted task needs to execute. If that's the case, `OSIntExit()` determines which task to run next and calls `OSIntCtxSw()`. However, unlike other μC/OS-II ports where `OSIntCtxSw()` actually performs the context switch, `OSIntCtxSw()` for the ARM Cortex-M3 simply triggers the PendSV handler and returns as shown in Listing 3-19.

Listing 3-19, OSIntCtxSw()

```
OSCtxSw
    LDR    R4, =NVIC_INT_CTRL      ; trigger the PendSV exception
    LDR    R5, =NVIC_PENDSVSET
    STR    R5, [R4]
    BX     LR
```

3.04.06 OS_CPU_A.ASM, OSPendSV()

`OSPendSV()` is the PendSV handler which handles all context switching for μC/OS-II. This is a recommended method for performing context switches with the ARM Cortex-M3. This is because the ARM Cortex-M3 auto-saves half of the processor context on any exception, and restores those same registers upon return from exception. The PendSV handler thus only needs to save R4-R11 and fix up the stack pointers. Using the PendSV exception this way means that context saving and restoring uses an identical method whether it's initiated from a task or occurs due to an interrupt or exception.

Note that you must place a pointer to `OSPendSV()` in the exception vector table at vector location 14 (based of the vector table + 4 * 14 or, offset 56).

The pseudo-code for the PendSV handler is:

Listing 3-20, OSPendSV()

```
OSPendSV:
    if (PSP != NULL) {
        Save R4-R11 onto task stack;      (2)
        OSTCBCur->OSTCBStkPtr = SP;      (3)
    }
    OSTaskSwHook();                       (4)
    OSPrioCur = OSPrioHighRdy;           (5)
    OSTCBCur = OSTCBHighRdy;             (6)
    PSP = OSTCBHighRdy->OSTCBStkPtr;      (7)
    Restore R4-R11 from new task stack;    (8)
    Return from exception;                 (9)
```

- L3-20(0) Note that when `OSPendSV()` is started by the CPU, the CPU automatically saves the `xPSR`, `PC`, `LR`, `R12` and `R0-R3` registers onto the task stack. After saving half the CPU registers onto the task's stack, the CPU switches stack pointer to use `SP_main` to process the remainder of the handler.
- L3-20(1) Here we check to see if this is the `SP_process` stack pointer is set to `NULL` or not. Recall that `OSStartHighRdy()` sets `SP_process` to `NULL` to avoid saving the task's context when we start the first task.
- L3-20(2) If `OSPendSV()` is actually triggered to perform a full task switch then we simply save the remaining registers (`R4-R11`).
- L3-20(3) Once the context of the task being switched out is saved, we simply save the task stack pointer (`SP_process`) into that task's `OS_TCB`.
- L3-20(4) We then call the µC/OS-II context switch hook (see `OS_CPU_C.C`).
- L3-20(5) As with all µC/OS-II ports, we need to copy the new high priority into the current priority.
- L3-20(6) Similarly, we need to copy `OSTCBHighRdy` into `OSTCBCur`.
- L3-20(7) We then retrieve the current top-of-stack pointer of the task we now want to switch to. Recall that the top-of-stack pointer is saved in `OSTCBHighRdy->OSTCBStkPtr`. For convenience, µC/OS-II always places `.OSTCBStkPtr` at the beginning of the `OS_TCB` and thus there is no need to find what offset the store `SP` is, it's always at offset 0.
- L3-20(8) We restore the context of the task to execute (i.e. it's register values) from the task's stack frame.
- L3-20(9) We then perform a return from exception which causes the ARM Cortex-M3 to restore `R3-R0`, `R12`, `LR`, `PC` and `xPSR` registers from the task's stack frame. At this point, we are running the new task.

The actual code for the `OSPendSV()` handler is shown in Listing 3-21. Note that the reference numbers in the comments correspond to the same elements in the pseudo-code of Listing 3-20.

Figure 3-3 shows the context switch graphically (again with the corresponding references).

You should note that the `PendSV` handler is non-preemptable and non-interruptable to ensure that the context switch is performed atomically. If an interrupt occurs while we perform the context switch, it will be serviced once the new task is restored.

Listing 3-21, OSPendSV()

```

OSPendSV                                     ; (0) CPU saved xPSR, PC, LR, R12, R0-R3

    MRS    R0, PSP                           ; (1) PSP is process stack pointer
    CBZ    R0, OSPendSV_nosave               ; skip register save the first time

    SUB    R0, R0, #0x20                     ; (2) save remaining regs r4-11 on process stack
    STM    R0, {R4-R11}

    LDR    R4, __OS_TCBCur                   ; (3) OSTCBCur->OSTCBStkPtr = SP;
    LDR    R4, [R4]
    STR    R0, [R4]                           ; R0 is SP of process being switched out

OSPendSV_nosave

    PUSH    {R14}                            ; (4) OSTaskSwHook();
    LDR    R0, __OS_TaskSwHook
    BLX    R0
    POP     {R14}

    LDR    R4, __OS_PrioCur                   ; (5) OSPrioCur = OSPrioHighRdy
    LDR    R5, __OS_PrioHighRdy
    LDRB   R6, [R5]
    STRB   R6, [R4]

    LDR    R4, __OS_TCBCur                   ; (6) OSTCBCur = OSTCBHighRdy;
    LDR    R6, __OS_TCBHighRdy
    LDR    R6, [R6]
    STR    R6, [R4]

    LDR    R0, [R6]                           ; (7) R0 is new task SP
                                           ; SP = OSTCBHighRdy->OSTCBStkPtr;

    LDM    R0, {R4-R11}                       ; (8) restore R4-R11 from new task stack
    ADD    R0, R0, #0x20
    MSR    PSP, R0                           ; load PSP with new task SP
    ORR    LR, LR, #0x04                     ; ensure exception return uses process stack
    BX     LR                               ; (9) exception return

```

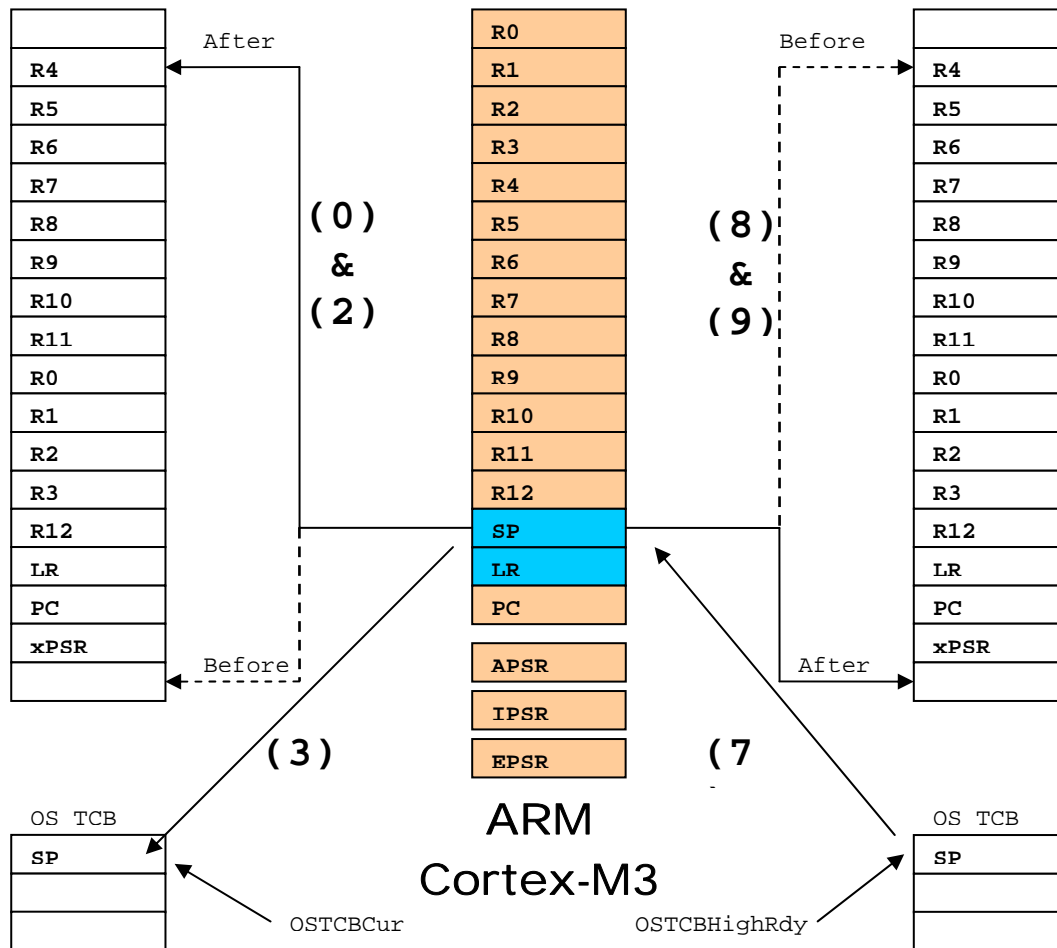



Figure 3-3, ARM Cortex-M3 Context Switch.

3.05 OS_DBG.C

OS_DBG.C is a file that has been added in V2.62 to provide Kernel Aware debugger to extract information about μC/OS-II and its configuration. Specifically, OS_DBG.C contains a number of constants that are placed in ROM (code space) which the debugger can read and display. Because you may not be using a debugger that needs that file, you may omit it in your build.

For IAR's C-Spy debugger, Micrium has introduced a Windows-based 'Plug-In' module that makes use of this file and thus needs to be included if you use C-Spy.

4.00 Exception Vector Table

The ARM Cortex-M3 contains an exception vector table (also called the interrupt vector table) starting at address 0x00000000. The table can contain up to 256 entries (can be up to 1 Kbytes since each entry is a 32-bit pointer). Each entry in the table is a pointer to the corresponding exception or interrupt handler.

The instruction placed in this table is generally a branch instruction with a signed 26-bit destination address. In other words, the ARM can branch to an address that is roughly +/- 0x0200000 from the vector location. The code that you branch to has to determine the interrupt source because there is only one address for all devices that can interrupt the ARM.

The exception vector table for the ARM Cortex-M3 is shown in table 4-1:

Position	Exception / Interrupt	Priority	Vector Address
0		-	0x00000000
1	Reset	-3 (highest)	0x00000004
2	Non-maskable Interrupt	-2	0x00000008
3	Hard Fault	-1	0x0000000C
4	Memory Management	settable	0x00000010
5	Bus Fault	Settable	0x00000014
6	Usage Fault	Settable	0x00000018
7	Reserved	-	0x0000001C
8	Reserved	-	0x00000020
9	Reserved	-	0x00000024
10	Reserved	-	0x00000028
11	SVCALL	Settable	0x0000002C
12	Debug Monitor	Settable	0x00000030
13	Reserved	-	0x00000034
14	PendSV	Settable	0x00000038
15	SysTick	Settable	0x0000003C
16	INTSIR[239]	Settable	0x00000040
17	INTISR[238]	Settable	0x00000044
:	:	Settable	:
:	:	Settable	:
255	INTISR[0]	Settable	0x000003FC

Table 4-1, ARM Cortex-M3 Exception Vector Table

μC/OS-II uses the PendSV handler for context switching and the SysTick handler to process system ticks (i.e. clock ticks).

The PendSV handler is configured by `OSStartHighRdy()` to be un-interruptable so that the PendSV handler can execute atomically.

The ARM Cortex-M3 has a built-in timer which was designed specifically for RTOS use. The timer can be configured to run at just about any tick rate. The application's BSP should set this timer to `OS_TICKS_PER_SEC`.

Note that it's up to the application code to setup the Exception Vector Table. To help you with this task, we created a file called `APP_VECT.C` that you can edit for each project.

4.01 Exception / Interrupt Handling Sequence

When the CPU incokes and exception or interrupt handler, the CPU automatically pushes the xPSR, PC, LR, R12 and R0-R3 registers onto the SP_process stack.

The CPU then reads the vector table to extract the address of the exception/interrupt handler and updates the PC with this address. The old PC is placed in the LR to allow us to return to the original code. The CPU then switches to use the SP_main stack pointer.

4.02 Interrupt Controllers

The ARM Cortex-M3 also comes with an integrated Nestable Vectored Interrupt Controller (NVIC).

4.03 Interrupt Service Routines

Interrupt Service Routines (ISRs) that need to use μC/OS-II services should be written as shown in Listing 4-1 for the ARM Cortex-M3.

Listing 4-1, Interrupt Service Routines using μC/OS-II services.

```
void OS_CPU_IRQ_ISR_Handler (void)
{
    OS_CPU_SR  cpu_sr = 0;

    OS_ENTER_CRITICAL();    /* Tell uC/OS-II that we are starting an ISR      */
    OSIntNesting++;
    OS_EXIT_CRITICAL();

    /* Handle the Interrupt ... don't forget to clear the interrupt source    */

    OSIntExit();            /* Tell uC/OS-II that we are leaving the ISR      */
}
```

You should note that you MUST disable interrupts in order to increment OSIntNesting to ensure that the operation is performed atomically. We do this by calling the OS_ENTER_CRITICAL() and OS_EXIT_CRITICAL() macros.

It's possible that some ISRs don't need to signal a task. In those cases, your ISRs would not need to increment OSIntNesting nor call OSIntExit().

5.00 Application Code

Your application code can make use of the port presented in this application note as described in this section. Figure 5-1 shows a block diagram of the relationship between your application, μC/OS-II, the μC/OS-II port, the BSP (Board Support Package), the ARM Cortex-M3 CPU and the target hardware.

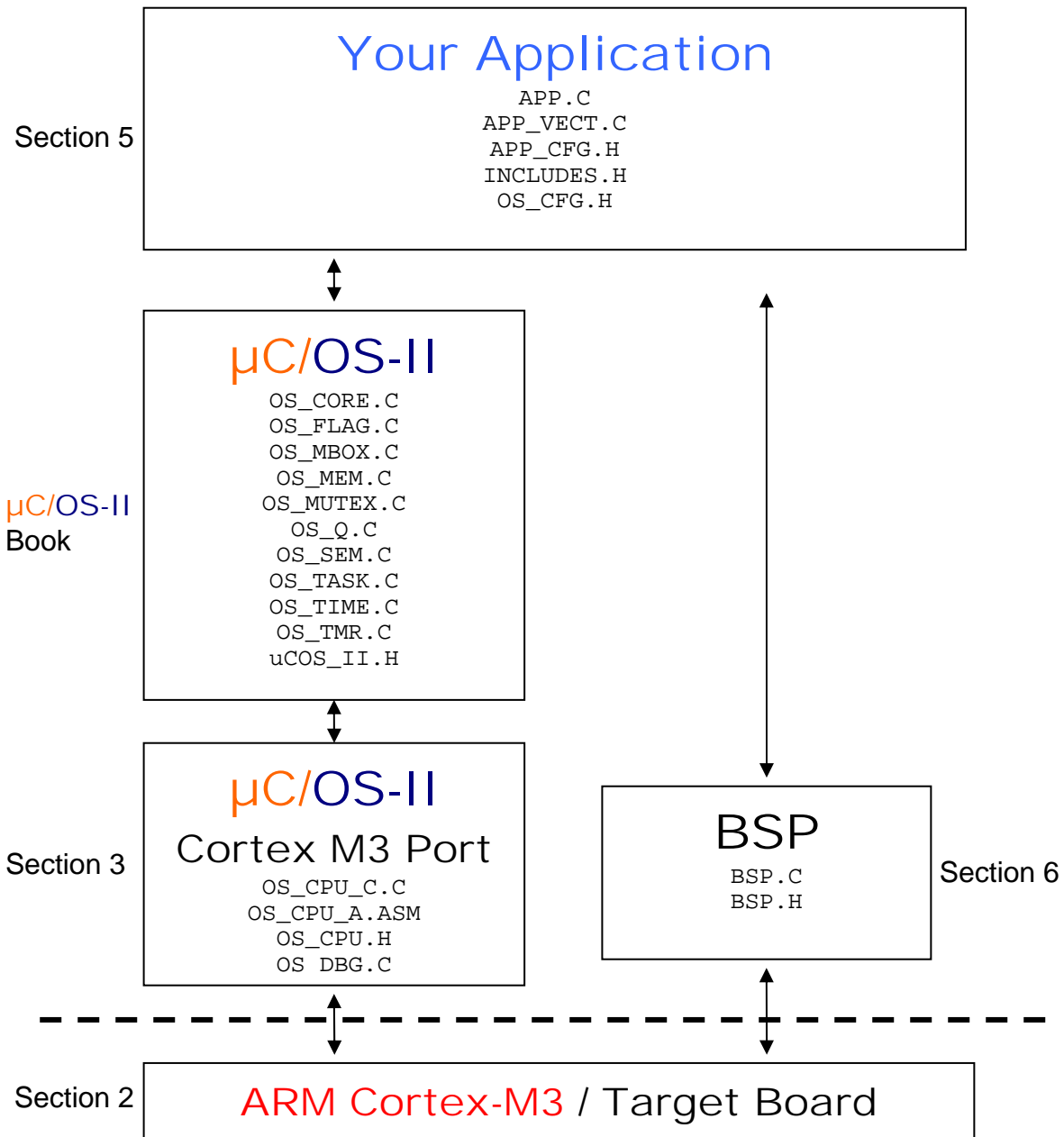


Figure 5-1, Relationship between modules.

5.01 APP.C, APP.H and APP_CFG.H

For sake of discussion, your application is placed in files called APP.C, APP.H and APP_CFG.H. Of course, your application (i.e. product) can contain many more files.

APP.C would be where you would place main() but, of course, you can place main() anywhere you want.

APP_VECT.C contains the exception / interrupt vector table for the application. You can edit this file to add your own interrupt handlers (or at least pointers to them). At vector 14, the vector table needs to point to OSPendSV() (see OS_CPU_A.ASM) and at vector 15, the vector table need to point to Tmr_TickISR_Handler() (see BSP.C).

APP_CFG.H contains #define constants to configure the application. We placed task stack sizes task priorities and other #defines in this file. This allows you to find task priorities and sizes in one place.

APP.C is a standard test file for µC/OS-II examples. The two important functions are main() (listing 5-1) and AppStartTask() (listing 5-2).

Listing 6-1, main()

```
void main (void)
{
    #if OS_TASK_NAME_SIZE > 13
        INT8U  err;
    #endif

    BSP_IntDisAll();                                (1)

    OSInit();                                        (2)

    OSTaskCreateExt(AppStartTask,                    (3)
        (void *)0,
        (OS_STK *)&AppStartTaskStk[APP_TASK_START_STK_SIZE-1],
        APP_TASK_START_PRIO,
        APP_TASK_START_PRIO,
        (OS_STK *)&AppStartTaskStk[0],
        APP_TASK_START_STK_SIZE,
        (void *)0,
        OS_TASK_OPT_STK_CHK | OS_TASK_OPT_STK_CLR);

    #if OS_TASK_NAME_SIZE > 11
        OSTaskNameSet(APP_TASK_START_PRIO, "Start Task", &err);    (4)
    #endif

    OSStart();                                        (5)
}
```

- L5-1(1) We need to disable interrupts to ensure we do not get interrupted until we complete the initialization sequence.
- L5-1(2) As with all μC/OS-II based applications, you need to initialize μC/OS-II by calling `OSInit()`.
- L5-1(3) You need to create at least one task. In this case, we created the task using the extended task create call. This allow μC/OS-II to have more information about your task. Specifically, with the IAR toolchain, the extra information allows the C-Spy debugger to display stack usage information when you use the μC/OS-II Kernel Awareness Plug-In.
- L5-1(4) We can now give names to tasks and those can be displayed by Kernel Aware debuggers such as IAR's C-Spy.
- L5-1(6) In order to start multitasking, you need to call `OSStart()`. Note that `OSStart()` will not return from this call.

Listing 5-2, `AppStartTask()`

```
static void AppStartTask (void *p_arg)
{
    (void)p_arg;

    BSP_Init();                                     (1)

    #if OS_TASK_STAT_EN > 0
        OSStatInit();                             (2)
    #endif

    #if OS_VIEW_MODULE > 0
        OSView_Init(38400);                       (3)
        OSView_TerminalRxSetCallback(AppTerminalRx);
    #endif

    AppTaskCreate();                               (4)

    while (TRUE) {
        /* Do something 'useful' in this task */   (5)
        LED_Toggle(1);                             (6)
        OSTimeDly(OS_TICKS_PER_SEC / 20);
    }
}
```


- L5-2(1) If you decided to implement a BSP (see section 6, Board Support Package) for your target board, you would initialize it here.
- L5-2(2) If you enabled the statistic task by setting `OS_TASK_STAT_EN` in `OS_CFG.H` to 1) then, you need to call it here. Please note that you need to make sure that you initialized and enabled the μC/OS-II clock tick because `OSStatInit()` assumes the presence of clock ticks. In other words, if the tick ISR is not active when you call `OSStatInit()`, your application will end up in μC/OS-II's idle task and not be able to run any other tasks.
- L5-2(3) If you purchase μC/OS-View (a product available from Micrium) you would be able to initialize it here. Note that for this to happen, you need to also include the μC/OS-View target resident files in your build.
- L5-2(4) At this point, you can create additional tasks. We decided to place all our task initialization in one function called `AppTaskCreate()` but, you are certainly welcome to use a different technique.
- L5-2(5) You can now perform whatever additional function you want for this task.
- L5-2(6) We decided to toggle an LED at a rate of 20 Hz (LED will blink at 10 Hz) when this task is running (see section 6, Board Support Package).

5.02 INCLUDES.H

INCLUDES.H is a master include file and is found at the top of all .C files. INCLUDES.H allows every .C file in your project to be written without concern about which header file is actually needed. The only drawbacks to having a master include file are that INCLUDES.H may include header files that are not pertinent to the actual .C file being compiled and the compilation process may take longer. These inconveniences are offset by code portability. You can edit INCLUDES.H to add your own header files, but your header files should be added at the end of the list.

6.00 BSP (Board Support Package)

It is often convenient to create a Board Support Package (BSP) for your target hardware. A BSP could allow you to encapsulate the following functionality:

- Timer initialization
- ISR Handlers
- LED control functions
- Reading switches
- Setting up the interrupt controller
- Setting up communication channels
- Etc.

A Micrium BSP consist of at least 2 files: `BSP.C` and `BSP.H`.

Each BSP should contain a BSP initialization function. We called ours `BSP_Init()` and should be called by your application code.

6.01 BSP (Board Support Package) – LED Management

A number of evaluation boards are equipped with LEDs, we decided to create LED control functions as follows:

```
void LED_Init(void);  
void LED_On(CPU_INT08U led_id);  
void LED_Off(CPU_INT08U led_id);  
void LED_Toggle(CPU_INT08U led_id);
```

In this case, LEDs are referenced 'logically' instead of physically. When you write the BSP, you determine which LED is LED #1, which is LED #2, etc. When you want to turn on LED #1, you simply call `LED_On(1)`. If you want to toggle LED #2, you simply call `LED_Toggle(2)`. In fact, you can (and should) associate names to your LEDs using `#defines`. You could thus specify `LED_Off(LED_PM)`.

6.02 BSP (Board Support Package) – Clock Tick

We decided to encapsulate the μC/OS-II clock tick handler in the BSP to be consistent with other μC/OS-II port. For the ARM Cortex-M3, the clock tick handler could have been part of the μC/OS-II port because all ARM Cortex-M3 implementations will contain the SysTick. The clock tick ISR handler is thus found in `BSP.C` and is called `Tmr_TickISR_Handler()`. An example of the clock tick handler is shown in Listing 6-1. You will notice that there is no need to write any ISR code in assembly language on the ARM Cortex-M3, an ISR is another C function.

Listing 6-1, `Tmr_TickISR_Handler()`

```
void Tmr_TickISR_Handler (void)
{
    OS_CPU_SR  cpu_sr;

    OS_ENTER_CRITICAL();          /* Tell uC/OS-II that we are starting an ISR      */
    OSIntNesting++;
    OS_EXIT_CRITICAL();

    OSTimeTick();                 /* Call uC/OS-II's OSTimeTick()          */

    OSIntExit();                  /* Tell uC/OS-II that we are leaving the ISR */
}
```

7.00 Conclusion

This application note presented a 'generic' port ARM Cortex-M3 processors. The port should be easily adapted to different compilers (the code itself should be identical). Of course, if you use μC/OS-II and use the port on actual hardware, you will need to initialize and properly handle hardware interrupts.

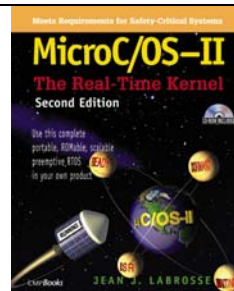
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References

MicroC/OS-II, The Real-Time Kernel, 2nd Edition

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Contacts

CMP Books, Inc.

1601 W. 23rd St., Suite 200
Lawrence, KS 66046-9950
USA
+1 785 841 1631
+1 785 841 2624 (FAX)
WEB: <http://www.rdbooks.com>
e-mail: rdorders@rdbooks.com

IAR Systems, Inc.

Century Plaza
1065 E. Hillsdale Blvd
Foster City, CA 94404
USA
+1 650 287 4250
+1 650 287 4253 (FAX)
WEB: <http://www.IAR.com>
e-mail: info@IAR.com

Luminary Micro

2499 South Capital of Texas Highway, Suite A-100
Austin, TX 78746
USA
+1 512 279 8800
+1 512 279 8879 (FAX)
e-mail: Sales@LuminaryMicro.com
WEB: <http://www.LuminaryMicro.com>

Micrium

949 Crestview Circle
Weston, FL 33327
USA
+1 954 217 2036
+1 954 217 2037 (FAX)
e-mail: Licensing@Micrium.com
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400 West Cesar Chavez
Austin, TX 78701
USA

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