



LUMINARY MICRO®

Stellaris® Peripheral Driver Library

USER'S GUIDE

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1 Introduction

The Luminary Micro® Stellaris® Peripheral Driver Library is a set of drivers for accessing the peripherals found on the Stellaris family of ARM® Cortex™-M3 based microcontrollers. While they are not drivers in the pure operating system sense (that is, they do not have a common interface and do not connect into a global device driver infrastructure), they do provide a mechanism that makes it easy to use the device's peripherals.

The capabilities and organization of the drivers are governed by the following design goals:

- They are written entirely in C except where absolutely not possible.
- They demonstrate how to use the peripheral in its common mode of operation.
- They are easy to understand.
- They are reasonably efficient in terms of memory and processor usage.
- They are as self-contained as possible.
- Where possible, computations that can be performed at compile time are done there instead of at run time.
- They can be built with more than one tool chain.

Some consequences of these design goals are:

- The drivers are not necessarily as efficient as they could be (from a code size and/or execution speed point of view). While the most efficient piece of code for operating a peripheral would be written in assembly and custom tailored to the specific requirements of the application, further size optimizations of the drivers would make them more difficult to understand.
- The drivers do not support the full capabilities of the hardware. Some of the peripherals provide complex capabilities which can not be utilized by the drivers in this library, though the existing code can be used as a reference upon which to add support for the additional capabilities.
- The APIs have a means of removing all error checking code. Since the error checking is usually only useful during initial program development, it can be removed to improve code size and speed.

For many applications, the drivers can be used as is. But in some cases, the drivers will have to be enhanced or rewritten in order to meet the functionality, memory, or processing requirements of the application. If so, the existing driver can be used as a reference on how to operate the peripheral.

The following tool chains are supported:

- Keil™ RealView® Microcontroller Development Kit
- CodeSourcery Sourcery G++ for Stellaris EABI
- IAR Embedded Workbench®

Source Code Overview

The following is an overview of the organization of the peripheral driver library source code, along with references to where each portion is described in detail.

<code>EULA.txt</code>	The full text of the End User License Agreement that covers the use of this software package.
<code>Makefile</code>	The rules for building the peripheral driver library. The contents of this file are described in chapter 2.
<code>asmdefs.h</code>	A set of macros used by assembly language source files. The contents of this file are described in chapter 27.
<code>boards/</code>	This directory contains the source code for the example applications that run on the various Luminary Micro development and evaluation boards. These applications are described in chapter 28 through 43.
<code>boot_loader/</code>	This directory contains the source code for the boot loader. This code is described in chapter 26.
<code>ewarm/</code>	This directory contains the source files that are specific to the IAR Embedded Workbench tool chain. The contents of this directory are described in chapters 3 and 27.
<code>gcc/</code>	This directory contains the source files that are specific to the GNU tool chain. The contents of this directory are described in chapters 3 and 27.
<code>hw_*.h</code>	Header files, one per peripheral, that describe all the registers and the bit fields within those registers for each peripheral. These header files are used by the drivers to directly access a peripheral, and can be used by application code to bypass the peripheral driver library API.
<code>inc/</code>	This directory holds the part specific header files used for the direct register access programming model, which is described in chapter 4.
<code>makedefs</code>	A set of definitions used by make files. The contents of this file are described in chapter 27.
<code>rvmdk/</code>	This directory contains the source files that are specific to the Keil RealView Microcontroller Development Kit. The contents of this directory are described in chapters 3 and 27.
<code>src/</code>	This directory contains the source code for the drivers, which are each described in chapters 5 through 23.
<code>third_party/</code>	This directory contains third party software packages that have been ported to the Stellaris microcontroller family. Each package has its own documentation describing its functionality.
<code>utils/</code>	This directory contains a set of utility functions for use by the example applications. The contents of this directory are described in chapter 24.

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2.1 Required Software

In order to build the code in the peripheral driver library, the following software is needed.

- One of the following tool chains:
 - Keil RealView Microcontroller Development Kit
 - CodeSourcery's Sourcery G++ for ARM EABI
 - IAR Embedded Workbench
- If building from the command line, some form of Unix environment for Windows®.

Follow the directions provided with the tool chain of choice to install the compiler and debugger (there are also Quickstart guides provided by Luminary Micro that describe installing each of these tool chains); this will also add the compiler to the search path so that it can be executed.

Once the required software is installed, the peripheral driver library source must be extracted from its ZIP file using the archiver of your choice (such as WinZip® or the built-in utilities in Windows XP). For the remainder of these directions, it will be assumed that the source is extracted to `c:/DriverLib`.

2.2 Building With Keil uVision

The peripheral driver library and each example application has a uVision project (with a `.Uv2` file name extension) that can be used to build from within uVision. Simply load the project file into uVision and click on the “Build target” or “Rebuild all target files” buttons. Note that the peripheral driver library (`c:/DriverLib/src/driverlib.Uv2`) project must be built before any of the example applications can be built.

There is a multi-project workspace file (with a `.mpw` file name extension) that includes all the projects for a particular board in each board directory. For example, in the `boards/dk-lm3s101` directory, there is a `dk-lm3s101.mpw` file that contains the project for the peripheral driver library along with the projects for all of the board examples for the DK-LM3S101 board.

See the “RealView Quickstart” for details about using uVision.

2.3 Building with IAR Embedded Workbench

The peripheral driver library and each example application has an Embedded Workbench project (with a `.ewp` file name extension) that can be used to build from within Embedded Workbench.

Simply load the project file into Embedded Workbench and select “Make” or “Rebuild All” from the “Project” menu. Note that the peripheral driver library (`c:/DriverLib/src/driverlib.ewp`) project must be built before any of the examples applications can be built.

There is a workspace file (with a `.eww` file name extension) that includes all the projects for a particular board in each board directory. For example, in the `boards/dk-lm3s101` directory, there is a `dk-lm3s101.eww` file that contains the project for the peripheral driver library along with the projects for all of the board examples for the DK-LM3S101 board.

See the “IAR KickStart Quickstart” for details about using Embedded Workbench.

2.4 Building with CodeSourcery Sourcery G++

The peripheral driver library and each example application can be built utilizing the CodeSourcery Common Startup Code Sequence (CS3). By setting the **COMPILER** environment variable to “sourcerygxx”, CS3 will be used to build the application. The advantage of using CS3 is the ability to easily use the C library provided by CodeSourcery for things such as `printf()`.

See the CodeSourcery Getting Started document for details on CS3 and how to use it in your application. See the following section for details on how to build the code using CS3.

2.5 Building From The Command Line

In order to build from the command line, some form of Unix environment for Windows is required. The recommended solution is the Unix Utilities from SourceForge (<http://unxutils.sourceforge.net>); alternatives are Cygwin (<http://www.cygwin.com>) and MinGW (<http://www.mingw.org>). The Unix Utilities and Cygwin have both been tested and work with this library; MinGW should work as well, though it has not been tested.

See the “GNU Quickstart” for details about installing and setting up the Unix Utilities.

The makefiles will not work with the `make` utilities normally available on Windows (such as the one provided with RealView); the “Unix” version must appear in the search path before any other version of `make`. Of course, if using CodeSourcery’s compiler on Linux, the normal Posix shell environment that exists is more than adequate for building the code.

The Unix utilities from SourceForge are in a ZIP file that must be unpacked; for the remainder of these directions, it will be assumed that the Unix utilities are extracted to `c:/`.

The search path must be manually updated to include both the `c:/bin` directory and the `c:/usr/local/wbin` directory, preferably at the beginning of the search path (so that `make` from `c:/usr/local/wbin` is used in preference to other versions of `make`).

The remainder of these directions assume that the shell in `c:/bin/sh` is being used in preference to the command shell provided by Windows XP; if not using this shell, the commands may have to be modified to be compatible with the Windows XP shell.

A couple of quick tests will determine if the search path is set up correctly. First, type:

```
make --version
```

It should report back that some version of GNU Make was invoked; if not, then the wrong `make` utility is being found and the search path needs to be corrected. Next, type:

```
type sh
```

It should specify the path where `sh.exe` from the Unix utilities was extracted; if not, then the `make` utility will not be able to find the shell (meaning that the build will fail) and the search path needs to be corrected.

If using the Keil RealView Microcontroller Development Kit, the following will verify that the compiler can be found (which means that all the other tool chain utilities will be found as well):

```
type armcc
```

If using CodeSourcery's Sourcery G++ for ARM EABI, the following will verify that the compiler can be found:

```
type arm-stellaris-eabi-gcc
```

If using IAR Embedded Workbench, the following will verify that the compiler can be found:

```
type iccarm  
type xlink
```

If any of the above checks fail then the build will probably fail as well. In each case, the search path would need to be updated so that the tools in question can be located by the shell.

Now, to build the library and example applications, type the following:

```
cd c:/DriverLib  
make
```

It will display short messages to indicate the build step being performed; the following extract is an example:

```
...  
CC    timer.c  
CC    uart.c  
CC    watchdog.c  
AR    gcc/libdriver.a  
...
```

This indicates that it is compiling `timer.c`, `uart.c`, `watchdog.c`, and then creating a library called `gcc/libdriver.a`. Displaying short messages like this makes it very easy to spot warnings and errors encountered during the build process.

There are several variables that control the build process. They can either appear as environment variables or they can be passed on the command line to `make`. The variables are:

- **COMPILER** specifies the tool chain to be used to build the source code. Currently, this can be **ewarm**, **gcc**, **rvmdk**, or **sourcerygxx**; the default value if not specified is **gcc**.
- **DEBUGGER** specifies the debugger that will be used to run the executables. This affects the version of the `Diag...()` functions that are used. Currently, this can be either **cspy**, **gdb**, or **uvision**; the default value if not specified depends on the value of **COMPILER** (**ewarm** results in **cspy**, **gcc** results in **gdb**, **rvmdk** results in **uvision**, and **sourcerygxx** results in **gdb**).

- **DEBUG** specifies that debugging information should be included in the object files that are built. This allows the debugger to perform source level debugging, and may add additional code that helps the development and debugging process (such as the ASSERT-based error checking). The value of this variable is not important; if it exists then debugging information will be included. If not specified, debugging information is not included.
- **VERBOSE** specifies that the actual compiler invocations should be displayed instead of the brief build steps. The value of this variable is not important; if it exists then verbose mode will be enabled. If not specified, verbose mode is disabled.

So, for example, to build using **rvmdk** with debugging enabled, type the following:

```
make COMPILER=rvmdk DEBUG=1
```

Alternatively, the following could be typed instead:

```
export COMPILER=rvmdk
export DEBUG=1
make
```

The advantage of the latter is subsequent builds require only invoking `make`, and is less prone to unexpected results from forgetting to add the variables to the command line each time (that is, from mixing and matching objects built with different definitions).

To remove all build products, use:

```
make clean
```

Note that this still depends upon the `COMPILER` environment variable; it will only remove the objects associated with the tool chain in use (that is, it can be used to clean out the `rvmdk` objects while leaving the `gcc` objects undisturbed).

3 Boot Code

The boot code contains the minimal set of code required to set up the vector table and get application code running after a system reset. There are multiple versions of the boot code, one per supported tool chain (some tool chain-specific constructs are used to find where the code, data, and bss segments reside in memory); the startup code is contained in `<toolchain>/startup.c`. Accompanying the startup code is the corresponding linker script that is used to link an application so that the vector table, code segment, data segment initializers, and data segments are placed in the appropriate locations in memory; this script is contained in `<toolchain>/standalone.ld` (`standalone.xcl` for IAR Embedded Workbench).

The boot code and its corresponding linker script utilize a typical memory layout for a flash-based system. The first portion of the flash is used for code and read-only data (this is referred to as the “code” segment). Immediately following are the initializers (if any) for the non-zero initialized data. The first portion of SRAM is used for the non-zero initialized data (referred to as the “data” segment), with the zero initialized data immediately following it (referred to as the “bss” segment).

The vector table of the Cortex-M3 microprocessor contains four required entries; they are the initial stack pointer, the reset handler address, the NMI handler address, and the hard fault handler address. Upon reset, the processor will load the initial stack pointer and then start executing the reset handler. The initial stack pointer is required since an NMI or hard fault can occur at any time; the stack is required to be able to take those interrupts since the processor will automatically push eight items onto the stack.

The `g_pfnVectors` array contains a full vector table. It contains the addresses of the all the handlers and the end of the initial stack. Tool chain-specific constructs are used to provide a hint to the linker that is used to make sure that this array is located at `0x0000.0000`, the default location of the vector table.

The `NmiISR` function contains the NMI handler. It simply enters an infinite loop, effectively halting the application if an NMI occurs; the application state is therefore preserved for examination by a debugger. If desired, the application can provide its own NMI handler via the interrupt driver.

The `FaultISR` function contains the hard fault handler. It also enters an infinite loop and can be replaced by the application.

The `ResetISR` function contains the reset handler. It copies the initializers from the end of the code segment in flash into the data segment in SRAM, zero fills the bss segment, and branches to the application-supplied entry point. This corresponds to the minimal set of things that must be done for C code to work properly when called; anything more complicated that is required by an application must be provided by that application.

The application must supply an entry point called `main` that takes no arguments and never returns. This function will be called by `ResetISR` after memory has been initialized. If `main` does return, `ResetISR` will also return, which will cause a hard fault to occur.

Each example application has its own copy of the boot code with the required interrupt handlers in place. This allows the interrupt handlers to be custom to each example and reside in flash.

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4.1 Introduction

The peripheral driver library provides support for two programming models: the direct register access model and the software driver model. Each model can be used independently, or combined, based on the needs of the application or the programming environment desired by the developer.

Each programming model has advantages and disadvantages. Use of the direct register access model will generally result in smaller and more efficient code than using the software driver model. However, the direct register access model does require detailed knowledge of the operation of each register, bit field, their interactions, and any sequencing required for proper operation of the peripheral; the developer is insulated from these details by the software driver model, generally requiring less time to develop applications.

4.2 Direct Register Access Model

In the direct register access model, the peripherals are programmed by the application by writing values directly into the peripheral's registers. A set of macros is provided that simplifies this process. These macros are stored in part-specific header files contained in the `inc` directory; the name of the header file matches the part number (for example, the header file for the LM3S6965 microcontroller is `inc/lm3s6965.h`). By including the header file that matches the part being used, macros are available for accessing all registers on that part, as well as all bit fields within those registers. No macros are available for registers that do not exist on the part in question, making it difficult to access registers that do not exist.

The defines used by the direct register access model follow a naming convention that makes it easier to know how to use a particular macro. The rules are as follows:

- Values that end in `_R` are used to access the value of a register. For example, `SSI0_CR0_R` is used to access the `CR0` register in the `SSI0` module.
- Values that end in `_M` represent the mask for a multi-bit field in a register. If the value placed in the multi-bit field is a number, there will be a macro with the same base name but ending with `_S` (for example, `SSI_CR0_SCR_M` and `SSI_CR0_SCR_S`). If the value placed into the multi-bit field is an enumeration, then there will be a set of macros with the same base name but ending with identifiers for the various enumeration values (for example, the `SSI_CR0_FRF_M` macro defines the bit field, and the `SSI_CR0_FRF_NMW`, `SSI_CR0_FRF_TI`, and `SSI_CR0_FRF_MOTO` macros provide the enumerations for the bit field).
- Values that end in `_S` represent the number of bits to shift a value in order to align it with a multi-bit field. These values will match the macro with the same base name but ending with `_M`.

- All other macros represent the value of a bit field.
- All register name macros start with the module name and instance number (for example, `SSI0` for the first SSI module) and are followed by the name of the register as it appears in the data sheet (for example, the `CR0` register in the data sheet results in `SSI0_CR0_R`).
- All register bit fields start with the module name, followed by the register name, and then followed by the bit field name as it appears in the data sheet. For example, the `SCR` bit field in the `CR0` register in the `SSI` module will be identified by `SSI_CR0_SCR`. . . . In the case where the bit field is a single bit, there will be nothing further (for example, `SSI_CR0_SPH` is a single bit in the `CR0` register). If the bit field is more than a single bit, there will be a mask value (`_M`) and either a shift (`_S`) if the bit field contains a number or a set of enumerations if not.

Given these definitions, the `CR0` register can be programmed as follows:

```
SSI0_CR0_R = ((5 << SSI_CR0_SCR_S) | SSI_CR0_SPH | SSI_CR0_SPO |  
              SSI_CR0_FRF_MOTO | SSI_CR0_DSS_8);
```

Alternatively, the following has the same effect (although it is not as easy to understand):

```
SSI0_CR0_R = 0x000005c7;
```

Extracting the value of the `SCR` field from the `CR0` register is as follows:

```
ulValue = (SSI0_CR0_R & SSI_CR0_SCR_M) >> SSI0_CR0_SCR_S;
```

The GPIO modules have many registers that do not have bit field definitions. For these registers, the register bits represent the individual GPIO pins; so bit zero in these registers corresponds to the **Px0** pin on the part (where **x** is replaced by a GPIO module letter), bit one corresponds to the **Px1** pin, and so on.

The `blinky` example for each board utilizes the direct register access model to blink the on-board LED.

Note:

The `hw_*.h` header files that are used by the drivers in the library contain many of the same definitions as the header files used for direct register access. As such, the two can not be included into the same source file without the compiler producing warnings about the redefinition of symbols.

4.3 Software Driver Model

In the software driver model, the API provided by the peripheral driver library is used by applications to control the peripherals. Since these drivers provide complete control of the peripherals in their normal mode of operation, it is possible to write an entire application without direct access to the hardware. This provides for rapid development of the application without requiring detailed knowledge of how to program the peripherals.

Corresponding to the direct register access model example, the following will also program the `CR0` register in the `SSI` module (though that fact is hidden by the API):


```
SSISConfigSetExpClk(SSI0_BASE, 50000000, SSI_FRF_MOTO_MODE_3,  
                    SSI_MODE_MASTER, 1000000, 8);
```

The resulting value in the `CR0` register might not be exactly the same since [SSISConfigSetExpClk\(\)](#) may compute a different value for the `SCR` bit field than what was used in the direct register access model example.

All example applications other than `blinky` utilize the software driver model.

The drivers in the peripheral driver library are described in chapters [5](#) through [23](#) . They combine to form the software driver model.

4.4 Combining The Models

The direct register access model and software driver model can be utilized together in a single application. This allows the most appropriate model to be used in any particular situation within the application; for example, the software driver model can be used to configure the peripherals (since this is not performance critical) and the direct register access model can be used for operation of the peripheral (which may be more performance critical). Or, the software driver model can be used for peripherals that are not performance critical (such as a UART used for data logging) and the direct register access model for performance critical peripherals (such as the ADC module used to capture real-time analog data).

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5.1 Introduction

The comparator API provides a set of functions for dealing with the analog comparators. A comparator can compare a test voltage against individual external reference voltage, a shared single external reference voltage, or a shared internal reference voltage. It can provide its output to a device pin, acting as a replacement for an analog comparator on the board, or it can be used to signal the application via interrupts or triggers to the ADC to cause it to start capturing a sample sequence. The interrupt generation and ADC triggering logic is separate, so that an interrupt can be generated on a rising edge and the ADC triggered on a falling edge (for example).

This driver is contained in `src/comp.c`, with `src/comp.h` containing the API definitions for use by applications.

5.2 API Functions

Functions

- void [ComparatorConfigure](#) (unsigned long ulBase, unsigned long ulComp, unsigned long ulConfig)
- void [ComparatorIntClear](#) (unsigned long ulBase, unsigned long ulComp)
- void [ComparatorIntDisable](#) (unsigned long ulBase, unsigned long ulComp)
- void [ComparatorIntEnable](#) (unsigned long ulBase, unsigned long ulComp)
- void [ComparatorIntRegister](#) (unsigned long ulBase, unsigned long ulComp, void (*pfnHandler)(void))
- tBoolean [ComparatorIntStatus](#) (unsigned long ulBase, unsigned long ulComp, tBoolean bMasked)
- void [ComparatorIntUnregister](#) (unsigned long ulBase, unsigned long ulComp)
- void [ComparatorRefSet](#) (unsigned long ulBase, unsigned long ulRef)
- tBoolean [ComparatorValueGet](#) (unsigned long ulBase, unsigned long ulComp)

5.2.1 Detailed Description

The comparator API is fairly simple, like the comparators themselves. There are functions for configuring a comparator and reading its output ([ComparatorConfigure\(\)](#), [ComparatorRefSet\(\)](#) and [ComparatorValueGet\(\)](#)) and functions for dealing with an interrupt handler for the comparator ([ComparatorIntRegister\(\)](#), [ComparatorIntUnregister\(\)](#), [ComparatorIntEnable\(\)](#), [ComparatorIntDisable\(\)](#), [ComparatorIntStatus\(\)](#), and [ComparatorIntClear\(\)](#)).

5.2.2 Function Documentation

5.2.2.1 ComparatorConfigure

Configures a comparator.

Prototype:

```
void  
ComparatorConfigure(unsigned long ulBase,  
                   unsigned long ulComp,  
                   unsigned long ulConfig)
```

Parameters:

ulBase is the base address of the comparator module.

ulComp is the index of the comparator to configure.

ulConfig is the configuration of the comparator.

Description:

This function will configure a comparator. The *ulConfig* parameter is the result of a logical OR operation between the **COMP_TRIG_xxx**, **COMP_INT_xxx**, **COMP_ASRC_P_xxx**, and **COMP_OUTPUT_xxx** values.

The **COMP_TRIG_xxx** term can take on the following values:

- **COMP_TRIG_NONE** to have no trigger to the ADC.
- **COMP_TRIG_HIGH** to trigger the ADC when the comparator output is high.
- **COMP_TRIG_LOW** to trigger the ADC when the comparator output is low.
- **COMP_TRIG_FALL** to trigger the ADC when the comparator output goes low.
- **COMP_TRIG_RISE** to trigger the ADC when the comparator output goes high.
- **COMP_TRIG_BOTH** to trigger the ADC when the comparator output goes low or high.

The **COMP_INT_xxx** term can take on the following values:

- **COMP_INT_HIGH** to generate an interrupt when the comparator output is high.
- **COMP_INT_LOW** to generate an interrupt when the comparator output is low.
- **COMP_INT_FALL** to generate an interrupt when the comparator output goes low.
- **COMP_INT_RISE** to generate an interrupt when the comparator output goes high.
- **COMP_INT_BOTH** to generate an interrupt when the comparator output goes low or high.

The **COMP_ASRC_P_xxx** term can take on the following values:

- **COMP_ASRC_P_PIN** to use the dedicated Comp+ pin as the reference voltage.
- **COMP_ASRC_P_PIN0** to use the Comp0+ pin as the reference voltage (this the same as **COMP_ASRC_P_PIN** for the comparator 0).
- **COMP_ASRC_P_REF** to use the internally generated voltage as the reference voltage.

The **COMP_OUTPUT_xxx** term can take on the following values:

- **COMP_OUTPUT_NORMAL** to enable a non-inverted output from the comparator to a device pin.
- **COMP_OUTPUT_INVERT** to enable an inverted output from the comparator to a device pin.

■ **COMP_OUTPUT_NONE** is deprecated and behaves the same as **COMP_OUTPUT_NORMAL**.

Returns:

None.

5.2.2.2 ComparatorIntClear

Clears a comparator interrupt.

Prototype:

```
void  
ComparatorIntClear(unsigned long ulBase,  
                   unsigned long ulComp)
```

Parameters:

ulBase is the base address of the comparator module.

ulComp is the index of the comparator.

Description:

The comparator interrupt is cleared, so that it no longer asserts. This must be done in the interrupt handler to keep it from being called again immediately upon exit. Note that for a level triggered interrupt, the interrupt cannot be cleared until it stops asserting.

Returns:

None.

5.2.2.3 ComparatorIntDisable

Disables the comparator interrupt.

Prototype:

```
void  
ComparatorIntDisable(unsigned long ulBase,  
                    unsigned long ulComp)
```

Parameters:

ulBase is the base address of the comparator module.

ulComp is the index of the comparator.

Description:

This function disables generation of an interrupt from the specified comparator. Only comparators whose interrupts are enabled can be reflected to the processor.

Returns:

None.

5.2.2.4 ComparatorIntEnable

Enables the comparator interrupt.

Prototype:

```
void  
ComparatorIntEnable(unsigned long ulBase,  
                    unsigned long ulComp)
```

Parameters:

ulBase is the base address of the comparator module.

ulComp is the index of the comparator.

Description:

This function enables generation of an interrupt from the specified comparator. Only comparators whose interrupts are enabled can be reflected to the processor.

Returns:

None.

5.2.2.5 ComparatorIntRegister

Registers an interrupt handler for the comparator interrupt.

Prototype:

```
void  
ComparatorIntRegister(unsigned long ulBase,  
                     unsigned long ulComp,  
                     void (*pfnHandler)(void))
```

Parameters:

ulBase is the base address of the comparator module.

ulComp is the index of the comparator.

pfnHandler is a pointer to the function to be called when the comparator interrupt occurs.

Description:

This sets the handler to be called when the comparator interrupt occurs. This will enable the interrupt in the interrupt controller; it is the interrupt-handler's responsibility to clear the interrupt source via [ComparatorIntClear\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

5.2.2.6 ComparatorIntStatus

Gets the current interrupt status.

Prototype:

```
tBoolean  
ComparatorIntStatus(unsigned long ulBase,  
                    unsigned long ulComp,  
                    tBoolean bMasked)
```

Parameters:

ulBase is the base address of the comparator module.

ulComp is the index of the comparator.

bMasked is **false** if the raw interrupt status is required and **true** if the masked interrupt status is required.

Description:

This returns the interrupt status for the comparator. Either the raw or the masked interrupt status can be returned.

Returns:

true if the interrupt is asserted and **false** if it is not asserted.

5.2.2.7 ComparatorIntUnregister

Unregisters an interrupt handler for a comparator interrupt.

Prototype:

```
void  
ComparatorIntUnregister(unsigned long ulBase,  
                       unsigned long ulComp)
```

Parameters:

ulBase is the base address of the comparator module.

ulComp is the index of the comparator.

Description:

This function will clear the handler to be called when a comparator interrupt occurs. This will also mask off the interrupt in the interrupt controller so that the interrupt handler no longer is called.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

5.2.2.8 ComparatorRefSet

Sets the internal reference voltage.

Prototype:

```
void  
ComparatorRefSet(unsigned long ulBase,  
                 unsigned long ulRef)
```

Parameters:

ulBase is the base address of the comparator module.

ulRef is the desired reference voltage.

Description:

This function will set the internal reference voltage value. The voltage is specified as one of the following values:

- **COMP_REF_OFF** to turn off the reference voltage
- **COMP_REF_0V** to set the reference voltage to 0 V
- **COMP_REF_0_1375V** to set the reference voltage to 0.1375 V
- **COMP_REF_0_275V** to set the reference voltage to 0.275 V
- **COMP_REF_0_4125V** to set the reference voltage to 0.4125 V
- **COMP_REF_0_55V** to set the reference voltage to 0.55 V
- **COMP_REF_0_6875V** to set the reference voltage to 0.6875 V
- **COMP_REF_0_825V** to set the reference voltage to 0.825 V
- **COMP_REF_0_928125V** to set the reference voltage to 0.928125 V
- **COMP_REF_0_9625V** to set the reference voltage to 0.9625 V
- **COMP_REF_1_03125V** to set the reference voltage to 1.03125 V
- **COMP_REF_1_134375V** to set the reference voltage to 1.134375 V
- **COMP_REF_1_1V** to set the reference voltage to 1.1 V
- **COMP_REF_1_2375V** to set the reference voltage to 1.2375 V
- **COMP_REF_1_340625V** to set the reference voltage to 1.340625 V
- **COMP_REF_1_375V** to set the reference voltage to 1.375 V
- **COMP_REF_1_44375V** to set the reference voltage to 1.44375 V
- **COMP_REF_1_5125V** to set the reference voltage to 1.5125 V
- **COMP_REF_1_546875V** to set the reference voltage to 1.546875 V
- **COMP_REF_1_65V** to set the reference voltage to 1.65 V
- **COMP_REF_1_753125V** to set the reference voltage to 1.753125 V
- **COMP_REF_1_7875V** to set the reference voltage to 1.7875 V
- **COMP_REF_1_85625V** to set the reference voltage to 1.85625 V
- **COMP_REF_1_925V** to set the reference voltage to 1.925 V
- **COMP_REF_1_959375V** to set the reference voltage to 1.959375 V
- **COMP_REF_2_0625V** to set the reference voltage to 2.0625 V
- **COMP_REF_2_165625V** to set the reference voltage to 2.165625 V
- **COMP_REF_2_26875V** to set the reference voltage to 2.26875 V
- **COMP_REF_2_371875V** to set the reference voltage to 2.371875 V

Returns:

None.

5.2.2.9 ComparatorValueGet

Gets the current comparator output value.

Prototype:

```
tBoolean  
ComparatorValueGet(unsigned long ulBase,  
                   unsigned long ulComp)
```


Parameters:

ulBase is the base address of the comparator module.

ulComp is the index of the comparator.

Description:

This function retrieves the current value of the comparator output.

Returns:

Returns **true** if the comparator output is high and **false** if the comparator output is low.

5.3 Programming Example

The following example shows how to use the comparator API to configure the comparator and read its value.

```
//  
// Configure the internal voltage reference.  
//  
ComparatorRefSet (COMP_BASE, COMP_REF_1_65V);  
  
//  
// Configure a comparator.  
//  
ComparatorConfigure (COMP_BASE, 0,  
                    (COMP_TRIG_NONE | COMP_INT_BOTH |  
                     COMP_ASRCF_REF | COMP_OUTPUT_NONE));  
  
//  
// Delay for some time...  
//  
  
//  
// Read the comparator output value.  
//  
ComparatorValueGet (COMP_BASE, 0);
```


6 Analog to Digital Converter (ADC)

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6.1 Introduction

The analog to digital converter (ADC) API provides a set of functions for dealing with the ADC. Functions are provided to configure the sample sequencers, read the captured data, register a sample sequence interrupt handler, and handle interrupt masking/clearing.

The ADC supports up to eight input channels plus an internal temperature sensor. Four sampling sequences, each with configurable trigger events, can be captured. The first sequence will capture up to eight samples, the second and third sequences will capture up to four samples, and the fourth sequence will capture a single sample. Each sample can be the same channel, different channels, or any combination in any order.

The sample sequences have configurable priorities that determine the order in which they are captured when multiple triggers occur simultaneously. The highest priority sequence that is currently triggered will be sampled. Care must be taken with triggers that occur frequently (such as the “always” trigger); if their priority is too high it is possible to starve the lower priority sequences.

Beginning with Rev C0 of the Stellaris microcontroller, hardware oversampling of the ADC data is available for improved accuracy. An oversampling factor of 2x, 4x, 8x, 16x, 32x, and 64x is supported, but reduces the throughput of the ADC by a corresponding factor. Hardware oversampling is applied uniformly across all sample sequences.

Software oversampling of the ADC data is also available (even when hardware oversampling is available). An oversampling factor of 2x, 4x, and 8x is supported, but reduces the depth of the sample sequences by a corresponding amount. For example, the first sample sequence will capture eight samples; in 4x oversampling mode it can only capture two samples since the first four samples are used over the first oversampled value and the second four samples are used for the second oversampled value. The amount of software oversampling is configured on a per sample sequence basis.

A more sophisticated software oversampling can be used to eliminate the reduction of the sample sequence depth. By increasing the ADC trigger rate by 4x (for example) and averaging four triggers worth of data, 4x oversampling is achieved without any loss of sample sequence capability. In this case, an increase in the number of ADC triggers (and presumably ADC interrupts) is the consequence. Since this requires adjustments outside of the ADC driver itself, this is not directly supported by the driver (though nothing in the driver prevents it). The software oversampling APIs should not be used in this case.

This driver is contained in `src/adc.c`, with `src/adc.h` containing the API definitions for use by applications.

6.2 API Functions

Functions

- void [ADCHardwareOversampleConfigure](#) (unsigned long ulBase, unsigned long ulFactor)
- void [ADCIntClear](#) (unsigned long ulBase, unsigned long ulSequenceNum)
- void [ADCIntDisable](#) (unsigned long ulBase, unsigned long ulSequenceNum)
- void [ADCIntEnable](#) (unsigned long ulBase, unsigned long ulSequenceNum)
- void [ADCIntRegister](#) (unsigned long ulBase, unsigned long ulSequenceNum, void (*pfnHandler)(void))
- unsigned long [ADCIntStatus](#) (unsigned long ulBase, unsigned long ulSequenceNum, tBoolean bMasked)
- void [ADCIntUnregister](#) (unsigned long ulBase, unsigned long ulSequenceNum)
- void [ADCProcessorTrigger](#) (unsigned long ulBase, unsigned long ulSequenceNum)
- void [ADCSequenceConfigure](#) (unsigned long ulBase, unsigned long ulSequenceNum, unsigned long ulTrigger, unsigned long ulPriority)
- long [ADCSequenceDataGet](#) (unsigned long ulBase, unsigned long ulSequenceNum, unsigned long *pulBuffer)
- void [ADCSequenceDisable](#) (unsigned long ulBase, unsigned long ulSequenceNum)
- void [ADCSequenceEnable](#) (unsigned long ulBase, unsigned long ulSequenceNum)
- long [ADCSequenceOverflow](#) (unsigned long ulBase, unsigned long ulSequenceNum)
- void [ADCSequenceOverflowClear](#) (unsigned long ulBase, unsigned long ulSequenceNum)
- void [ADCSequenceStepConfigure](#) (unsigned long ulBase, unsigned long ulSequenceNum, unsigned long ulStep, unsigned long ulConfig)
- long [ADCSequenceUnderflow](#) (unsigned long ulBase, unsigned long ulSequenceNum)
- void [ADCSequenceUnderflowClear](#) (unsigned long ulBase, unsigned long ulSequenceNum)
- void [ADCSoftwareOversampleConfigure](#) (unsigned long ulBase, unsigned long ulSequenceNum, unsigned long ulFactor)
- void [ADCSoftwareOversampleDataGet](#) (unsigned long ulBase, unsigned long ulSequenceNum, unsigned long *pulBuffer, unsigned long ulCount)
- void [ADCSoftwareOversampleStepConfigure](#) (unsigned long ulBase, unsigned long ulSequenceNum, unsigned long ulStep, unsigned long ulConfig)

6.2.1 Detailed Description

The analog to digital converter API is broken into three groups of functions: those that deal with the sample sequences, those that deal with the processor trigger, and those that deal with interrupt handling.

The sample sequences are configured with [ADCSequenceConfigure\(\)](#) and [ADCSequenceStepConfigure\(\)](#). They are enabled and disabled with [ADCSequenceEnable\(\)](#) and [ADCSequenceDisable\(\)](#). The captured data is obtained with [ADCSequenceDataGet\(\)](#). Sample sequence FIFO overflow and underflow is managed with [ADCSequenceOverflow\(\)](#), [ADCSequenceOverflowClear\(\)](#), [ADCSequenceUnderflow\(\)](#), and [ADCSequenceUnderflowClear\(\)](#).

Hardware oversampling of the ADC is controlled with [ADCHardwareOversampleConfigure\(\)](#). Software oversampling of the ADC is controlled with [ADCSoftwareOversampleConfigure\(\)](#), [ADCSoftwareOversampleStepConfigure\(\)](#), and [ADCSoftwareOversampleDataGet\(\)](#).

The processor trigger is generated with [ADCProcessorTrigger\(\)](#).

The interrupt handler for the ADC sample sequence interrupts are managed with [ADCIntRegister\(\)](#) and [ADCIntUnregister\(\)](#). The sample sequence interrupt sources are managed with [ADCIntDisable\(\)](#), [ADCIntEnable\(\)](#), [ADCIntStatus\(\)](#), and [ADCIntClear\(\)](#).

6.2.2 Function Documentation

6.2.2.1 ADCHardwareOversampleConfigure

Configures the hardware oversampling factor of the ADC.

Prototype:

```
void  
ADCHardwareOversampleConfigure(unsigned long ulBase,  
                                unsigned long ulFactor)
```

Parameters:

ulBase is the base address of the ADC module.

ulFactor is the number of samples to be averaged.

Description:

This function configures the hardware oversampling for the ADC, which can be used to provide better resolution on the sampled data. Oversampling is accomplished by averaging multiple samples from the same analog input. Six different oversampling rates are supported; 2x, 4x, 8x, 16x, 32x, and 64x. Specifying an oversampling factor of zero will disable hardware oversampling.

Hardware oversampling applies uniformly to all sample sequencers. It does not reduce the depth of the sample sequencers like the software oversampling APIs; each sample written into the sample sequence FIFO is a fully oversampled analog input reading.

Enabling hardware averaging increases the precision of the ADC at the cost of throughput. For example, enabling 4x oversampling reduces the throughput of a 250 Ksps ADC to 62.5 Ksps.

Note:

Hardware oversampling is available beginning with Rev C0 of the Stellaris microcontroller.

Returns:

None.

6.2.2.2 ADCIntClear

Clears sample sequence interrupt source.

Prototype:

```
void  
ADCIntClear(unsigned long ulBase,  
             unsigned long ulSequenceNum)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

Description:

The specified sample sequence interrupt is cleared, so that it no longer asserts. This must be done in the interrupt handler to keep it from being called again immediately upon exit.

Returns:

None.

6.2.2.3 ADCIntDisable

Disables a sample sequence interrupt.

Prototype:

```
void  
ADCIntDisable(unsigned long ulBase,  
               unsigned long ulSequenceNum)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

Description:

This function disables the requested sample sequence interrupt.

Returns:

None.

6.2.2.4 ADCIntEnable

Enables a sample sequence interrupt.

Prototype:

```
void  
ADCIntEnable(unsigned long ulBase,  
              unsigned long ulSequenceNum)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

Description:

This function enables the requested sample sequence interrupt. Any outstanding interrupts are cleared before enabling the sample sequence interrupt.

Returns:

None.

6.2.2.5 ADCIntRegister

Registers an interrupt handler for an ADC interrupt.

Prototype:

```
void  
ADCIntRegister(unsigned long ulBase,  
               unsigned long ulSequenceNum,  
               void (*pfnHandler)(void))
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

pfnHandler is a pointer to the function to be called when the ADC sample sequence interrupt occurs.

Description:

This function sets the handler to be called when a sample sequence interrupt occurs. This will enable the global interrupt in the interrupt controller; the sequence interrupt must be enabled with [ADCIntEnable\(\)](#). It is the interrupt handler's responsibility to clear the interrupt source via [ADCIntClear\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

6.2.2.6 ADCIntStatus

Gets the current interrupt status.

Prototype:

```
unsigned long  
ADCIntStatus(unsigned long ulBase,  
             unsigned long ulSequenceNum,  
             tBoolean bMasked)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

bMasked is false if the raw interrupt status is required and true if the masked interrupt status is required.

Description:

This returns the interrupt status for the specified sample sequence. Either the raw interrupt status or the status of interrupts that are allowed to reflect to the processor can be returned.

Returns:

The current raw or masked interrupt status.

6.2.2.7 ADCIntUnregister

Unregisters the interrupt handler for an ADC interrupt.

Prototype:

```
void  
ADCIntUnregister(unsigned long ulBase,  
                 unsigned long ulSequenceNum)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

Description:

This function unregisters the interrupt handler. This will disable the global interrupt in the interrupt controller; the sequence interrupt must be disabled via [ADCIntDisable\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

6.2.2.8 ADCProcessorTrigger

Causes a processor trigger for a sample sequence.

Prototype:

```
void  
ADCProcessorTrigger(unsigned long ulBase,  
                    unsigned long ulSequenceNum)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

Description:

This function triggers a processor-initiated sample sequence if the sample sequence trigger is configured to ADC_TRIGGER_PROCESSOR.

Returns:

None.

6.2.2.9 ADCSequenceConfigure

Configures the trigger source and priority of a sample sequence.

Prototype:

```
void  
ADCSequenceConfigure(unsigned long ulBase,
```



```
unsigned long ulSequenceNum,  
unsigned long ulTrigger,  
unsigned long ulPriority)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

ulTrigger is the trigger source that initiates the sample sequence; must be one of the **ADC_TRIGGER_*** values.

ulPriority is the relative priority of the sample sequence with respect to the other sample sequences.

Description:

This function configures the initiation criteria for a sample sequence. Valid sample sequences range from zero to three; sequence zero will capture up to eight samples, sequences one and two will capture up to four samples, and sequence three will capture a single sample. The trigger condition and priority (with respect to other sample sequence execution) is set.

The parameter **ulTrigger** can take on the following values:

- **ADC_TRIGGER_PROCESSOR** - A trigger generated by the processor, via the [ADCProcessorTrigger\(\)](#) function.
- **ADC_TRIGGER_COMP0** - A trigger generated by the first analog comparator; configured with [ComparatorConfigure\(\)](#).
- **ADC_TRIGGER_COMP1** - A trigger generated by the second analog comparator; configured with [ComparatorConfigure\(\)](#).
- **ADC_TRIGGER_COMP2** - A trigger generated by the third analog comparator; configured with [ComparatorConfigure\(\)](#).
- **ADC_TRIGGER_EXTERNAL** - A trigger generated by an input from the Port B4 pin.
- **ADC_TRIGGER_TIMER** - A trigger generated by a timer; configured with [TimerControlTrigger\(\)](#).
- **ADC_TRIGGER_PWM0** - A trigger generated by the first PWM generator; configured with [PWMDGenIntTrigEnable\(\)](#).
- **ADC_TRIGGER_PWM1** - A trigger generated by the second PWM generator; configured with [PWMDGenIntTrigEnable\(\)](#).
- **ADC_TRIGGER_PWM2** - A trigger generated by the third PWM generator; configured with [PWMDGenIntTrigEnable\(\)](#).
- **ADC_TRIGGER_ALWAYS** - A trigger that is always asserted, causing the sample sequence to capture repeatedly (so long as there is not a higher priority source active).

Note that not all trigger sources are available on all Stellaris family members; consult the data sheet for the device in question to determine the availability of triggers.

The parameter **ulPriority** is a value between 0 and 3, where 0 represents the highest priority and 3 the lowest. Note that when programming the priority among a set of sample sequences, each must have unique priority; it is up to the caller to guarantee the uniqueness of the priorities.

Returns:

None.

6.2.2.10 ADCSequenceDataGet

Gets the captured data for a sample sequence.

Prototype:

```
long  
ADCSequenceDataGet(unsigned long ulBase,  
                   unsigned long ulSequenceNum,  
                   unsigned long *pulBuffer)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

pulBuffer is the address where the data is stored.

Description:

This function copies data from the specified sample sequence output FIFO to a memory resident buffer. The number of samples available in the hardware FIFO are copied into the buffer, which is assumed to be large enough to hold that many samples. This will only return the samples that are presently available, which may not be the entire sample sequence if it is in the process of being executed.

Returns:

Returns the number of samples copied to the buffer.

6.2.2.11 ADCSequenceDisable

Disables a sample sequence.

Prototype:

```
void  
ADCSequenceDisable(unsigned long ulBase,  
                   unsigned long ulSequenceNum)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

Description:

Prevents the specified sample sequence from being captured when its trigger is detected. A sample sequence should be disabled before it is configured.

Returns:

None.

6.2.2.12 ADCSequenceEnable

Enables a sample sequence.

Prototype:

```
void  
ADCSequenceEnable(unsigned long ulBase,  
                  unsigned long ulSequenceNum)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

Description:

Allows the specified sample sequence to be captured when its trigger is detected. A sample sequence must be configured before it is enabled.

Returns:

None.

6.2.2.13 ADCSequenceOverflow

Determines if a sample sequence overflow occurred.

Prototype:

```
long  
ADCSequenceOverflow(unsigned long ulBase,  
                   unsigned long ulSequenceNum)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

Description:

This determines if a sample sequence overflow has occurred. This will happen if the captured samples are not read from the FIFO before the next trigger occurs.

Returns:

Returns zero if there was not an overflow, and non-zero if there was.

6.2.2.14 ADCSequenceOverflowClear

Clears the overflow condition on a sample sequence.

Prototype:

```
void  
ADCSequenceOverflowClear(unsigned long ulBase,  
                        unsigned long ulSequenceNum)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

Description:

This will clear an overflow condition on one of the sample sequences. The overflow condition must be cleared in order to detect a subsequent overflow condition (it otherwise causes no harm).

Returns:

None.

6.2.2.15 ADCSequenceStepConfigure

Configure a step of the sample sequencer.

Prototype:

```
void  
ADCSequenceStepConfigure(unsigned long ulBase,  
                          unsigned long ulSequenceNum,  
                          unsigned long ulStep,  
                          unsigned long ulConfig)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

ulStep is the step to be configured.

ulConfig is the configuration of this step; must be a logical OR of **ADC_CTL_TS**, **ADC_CTL_IE**, **ADC_CTL_END**, **ADC_CTL_D**, and one of the input channel selects (**ADC_CTL_CH0** through **ADC_CTL_CH7**).

Description:

This function will set the configuration of the ADC for one step of a sample sequence. The ADC can be configured for single-ended or differential operation (the **ADC_CTL_D** bit selects differential operation when set), the channel to be sampled can be chosen (the **ADC_CTL_CH0** through **ADC_CTL_CH7** values), and the internal temperature sensor can be selected (the **ADC_CTL_TS** bit). Additionally, this step can be defined as the last in the sequence (the **ADC_CTL_END** bit) and it can be configured to cause an interrupt when the step is complete (the **ADC_CTL_IE** bit). The configuration is used by the ADC at the appropriate time when the trigger for this sequence occurs.

The **ulStep** parameter determines the order in which the samples are captured by the ADC when the trigger occurs. It can range from zero to seven for the first sample sequence, from zero to three for the second and third sample sequence, and can only be zero for the fourth sample sequence.

Differential mode only works with adjacent channel pairs (for example, 0 and 1). The channel select must be the number of the channel pair to sample (for example, **ADC_CTL_CH0** for 0 and 1, or **ADC_CTL_CH1** for 2 and 3) or undefined results will be returned by the ADC. Additionally, if differential mode is selected when the temperature sensor is being sampled, undefined results will be returned by the ADC.

It is the responsibility of the caller to ensure that a valid configuration is specified; this function does not check the validity of the specified configuration.

Returns:

None.

6.2.2.16 ADCSequenceUnderflow

Determines if a sample sequence underflow occurred.

Prototype:

```
long  
ADCSequenceUnderflow(unsigned long ulBase,  
                     unsigned long ulSequenceNum)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

Description:

This determines if a sample sequence underflow has occurred. This will happen if too many samples are read from the FIFO.

Returns:

Returns zero if there was not an underflow, and non-zero if there was.

6.2.2.17 ADCSequenceUnderflowClear

Clears the underflow condition on a sample sequence.

Prototype:

```
void  
ADCSequenceUnderflowClear(unsigned long ulBase,  
                          unsigned long ulSequenceNum)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

Description:

This will clear an underflow condition on one of the sample sequences. The underflow condition must be cleared in order to detect a subsequent underflow condition (it otherwise causes no harm).

Returns:

None.

6.2.2.18 ADCSoftwareOversampleConfigure

Configures the software oversampling factor of the ADC.

Prototype:

```
void  
ADCSoftwareOversampleConfigure(unsigned long ulBase,  
                               unsigned long ulSequenceNum,  
                               unsigned long ulFactor)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

ulFactor is the number of samples to be averaged.

Description:

This function configures the software oversampling for the ADC, which can be used to provide better resolution on the sampled data. Oversampling is accomplished by averaging multiple samples from the same analog input. Three different oversampling rates are supported; 2x, 4x, and 8x.

Oversampling is only supported on the sample sequencers that are more than one sample in depth (that is, the fourth sample sequencer is not supported). Oversampling by 2x (for example) divides the depth of the sample sequencer by two; so 2x oversampling on the first sample sequencer can only provide four samples per trigger. This also means that 8x oversampling is only available on the first sample sequencer.

Returns:

None.

6.2.2.19 ADCSoftwareOversampleDataGet

Gets the captured data for a sample sequence using software oversampling.

Prototype:

```
void  
ADCSoftwareOversampleDataGet(unsigned long ulBase,  
                             unsigned long ulSequenceNum,  
                             unsigned long *pulBuffer,  
                             unsigned long ulCount)
```

Parameters:

ulBase is the base address of the ADC module.

ulSequenceNum is the sample sequence number.

pulBuffer is the address where the data is stored.

ulCount is the number of samples to be read.

Description:

This function copies data from the specified sample sequence output FIFO to a memory resident buffer with software oversampling applied. The requested number of samples are copied into the data buffer; if there are not enough samples in the hardware FIFO to satisfy this many oversampled data items then incorrect results will be returned. It is the caller's responsibility to read only the samples that are available and wait until enough data is available, for example as a result of receiving an interrupt.

Returns:

None.

6.2.2.20 ADCSoftwareOversampleStepConfigure

Configures a step of the software oversampled sequencer.

Prototype:

```
void
ADCSOFTWAREOVERSAMPLESTEPConfigure(unsigned long ulBase,
                                     unsigned long ulSequenceNum,
                                     unsigned long ulStep,
                                     unsigned long ulConfig)
```

Parameters:

ulBase is the base address of the ADC module.
ulSequenceNum is the sample sequence number.
ulStep is the step to be configured.
ulConfig is the configuration of this step.

Description:

This function configures a step of the sample sequencer when using the software oversampling feature. The number of steps available depends on the oversampling factor set by [ADCSoftwareOversampleConfigure\(\)](#). The value of *ulConfig* is the same as defined for [ADCSequenceStepConfigure\(\)](#).

Returns:

None.

6.3 Programming Example

The following example shows how to use the ADC API to initialize a sample sequence for processor triggering, trigger the sample sequence, and then read back the data when it is ready.

```
unsigned long ulValue;

//
// Enable the first sample sequence to capture the value of channel 0 when
// the processor trigger occurs.
//
ADCSequenceConfigure(ADC_BASE, 0, ADC_TRIGGER_PROCESSOR, 0);
ADCSequenceStepConfigure(ADC_BASE, 0, 0,
                         ADC_CTL_IE | ADC_CTL_END | ADC_CTL_CH0);
ADCSequenceEnable(ADC_BASE, 0);

//
// Trigger the sample sequence.
//
ADCProcessorTrigger(ADC_BASE, 0);

//
// Wait until the sample sequence has completed.
//
while(!ADCIntStatus(ADC_BASE, 0, false))
{
}

//
// Read the value from the ADC.
//
ADCSequenceDataGet(ADC_BASE, 0, &ulValue);
```


7 Controller Area Network (CAN)

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7.1 Introduction

The Controller Area Network (CAN) APIs provide a set of functions for accessing the Stellaris CAN modules. Functions are provided to configure the CAN controllers, configure message objects, and manage CAN interrupts.

The Stellaris CAN module provides hardware processing of the CAN data link layer. It can be configured with message filters and preloaded message data so that it can autonomously send and receive messages on the bus, and notify the application accordingly. It automatically handles generation and checking of CRCs, error processing, and retransmission of CAN messages.

The message objects are stored in the CAN controller and provide the main interface for the CAN module on the CAN bus. There are 32 message objects that can each be programmed to handle a separate message ID, or can be chained together for a sequence of frames with the same ID. The message identifier filters provide masking that can be programmed to match any or all of the message ID bits, and frame types.

This driver is contained in `src/can.c`, with `src/can.h` containing the API definitions for use by applications.

7.2 API Functions

Data Structures

- `tCANBitClkParms`
- `tCANMsgObject`

Defines

- `MSG_OBJ_STATUS_MASK`

Enumerations

- `tCANIntFlags`
- `tCANIntStsReg`
- `tCANObjFlags`
- `tCANStatusCtrl`
- `tCANStsReg`
- `tMsgObjType`

Functions

- void [CANDisable](#) (unsigned long ulBase)
- void [CANEnable](#) (unsigned long ulBase)
- tBoolean [CANErrCntGet](#) (unsigned long ulBase, unsigned long *pulRxCnt, unsigned long *pulTxCount)
- void [CANGetBitTiming](#) (unsigned long ulBase, [tCANBitClkParms](#) *pClkParms)
- long [CANGetIntNumber](#) (unsigned long ulBase)
- void [CANInit](#) (unsigned long ulBase)
- void [CANIntClear](#) (unsigned long ulBase, unsigned long ulIntClr)
- void [CANIntDisable](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [CANIntEnable](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [CANIntRegister](#) (unsigned long ulBase, void (*pfnHandler)(void))
- unsigned long [CANIntStatus](#) (unsigned long ulBase, [tCANIntStsReg](#) eIntStsReg)
- void [CANIntUnregister](#) (unsigned long ulBase)
- void [CANMessageClear](#) (unsigned long ulBase, unsigned long ulObjID)
- void [CANMessageGet](#) (unsigned long ulBase, unsigned long ulObjID, [tCANMsgObject](#) *pMsgObject, tBoolean bClrPendingInt)
- void [CANMessageSet](#) (unsigned long ulBase, unsigned long ulObjID, [tCANMsgObject](#) *pMsgObject, [tMsgObjType](#) eMsgType)
- void [CANReadDataReg](#) (unsigned char *pucData, unsigned long *pulRegister, int iSize)
- unsigned long [CANReadReg](#) (unsigned long ulRegAddress)
- tBoolean [CANRetryGet](#) (unsigned long ulBase)
- void [CANRetrySet](#) (unsigned long ulBase, tBoolean bAutoRetry)
- void [CANSetBitTiming](#) (unsigned long ulBase, [tCANBitClkParms](#) *pClkParms)
- unsigned long [CANStatusGet](#) (unsigned long ulBase, [tCANStsReg](#) eStatusReg)
- void [CANWriteDataReg](#) (unsigned char *pucData, unsigned long *pulRegister, int iSize)
- void [CANWriteReg](#) (unsigned long ulRegAddress, unsigned long ulRegValue)

7.2.1 Detailed Description

The CAN APIs provide all of the functions needed by the application to implement an interrupt-driven CAN stack. These functions may be used to control any of the available CAN ports on a Stellaris microcontroller, and can be used with one port without causing conflicts with the other port.

The CAN module is disabled by default, so the the [CANInit\(\)](#) function must be called before any other CAN functions are called. This call initializes the message objects to a safe state prior to enabling the controller on the CAN bus. Also, the bit timing values must be programmed prior to enabling the CAN controller. The [CANSetBitTiming\(\)](#) function should be called with the appropriate bit timing values for the CAN bus. Once these two functions have been called, a CAN controller can be enabled using the [CANEnable\(\)](#), and later disabled using [CANDisable\(\)](#) if needed. Calling [CANDisable\(\)](#) does not reinitialize a CAN controller, so it can be used to temporarily remove a CAN controller from the bus.

The CAN controller is highly configurable and contains 32 message objects that can be programmed to automatically transmit and receive CAN messages under certain conditions. Message objects allow the application to perform some actions automatically without interaction from the microcontroller. Some examples of these actions are the following:

- Send a data frame immediately
- Send a data frame when a matching remote frame is seen on the CAN bus
- Receive a specific data frame
- Receive data frames that match a certain identifier pattern

To configure message objects to perform any of these actions, the application must first set up one of the 32 message objects using [CANMessageSet\(\)](#). This function must be used to configure a message object to send data, or to configure a message object to receive data. Each message object can be configured to generate interrupts on transmission or reception of CAN messages.

When data is received from the CAN bus, the application can use the [CANMessageGet\(\)](#) function to read the received message. This function can also be used to read a message object that is already configured in order to populate a message structure prior to making changes to the configuration of a message object. Reading the message object using this function will also clear any pending interrupt on the message object.

Once a message object has been configured using [CANMessageSet\(\)](#), it has allocated the message object and will continue to perform its programmed function unless it is released with a call to [CANMessageClear\(\)](#). The application is not required to clear out a message object before setting it with a new configuration, because each time [CANMessageSet\(\)](#) is called, it will overwrite any previously programmed configuration.

The 32 message objects are identical except for priority. The lowest numbered message objects have the highest priority. Priority affects operation in two ways. First, if multiple actions are ready at the same time, the one with the highest priority message object will occur first. And second, when multiple message objects have interrupts pending, the highest priority will be presented first when reading the interrupt status. It is up to the application to manage the 32 message objects as a resource, and determine the best method for allocating and releasing them.

The CAN controller can generate interrupts on several conditions:

- When any message object transmits a message
- When any message object receives a message
- On warning conditions such as an error counter reaching a limit or occurrence of various bus errors
- On controller error conditions such as entering the bus-off state

An interrupt handler must be installed in order to process CAN interrupts. If dynamic interrupt configuration is desired, the [CANIntRegister\(\)](#) can be used to register the interrupt handler. This will place the vector in a RAM-based vector table. However, if the application uses a pre-loaded vector table in flash, then the CAN controller handler should be entered in the appropriate slot in the vector table. In this case, [CANIntRegister\(\)](#) is not needed, but the interrupt will need to be enabled on the host processor master interrupt controller using the [IntEnable\(\)](#) function. The CAN module interrupts are enabled using the [CANIntEnable\(\)](#) function. They can be disabled by using the [CANIntDisable\(\)](#) function.

Once CAN interrupts are enabled, the handler will be invoked whenever a CAN interrupt is triggered. The handler can determine which condition caused the interrupt by using the [CANIntStatus\(\)](#) function. Multiple conditions can be pending when an interrupt occurs, so the handler must be designed to process all pending interrupt conditions before exiting. Each interrupt condition must be cleared before exiting the handler. There are two ways to do this. The [CANIntClear\(\)](#) function will clear a specific interrupt condition without further action required by the handler. However, the handler can also clear the condition by performing certain actions. If the interrupt is a status interrupt,

the interrupt can be cleared by reading the status register with [CANStatusGet\(\)](#). If the interrupt is caused by one of the message objects, then it can be cleared by reading the message object using [CANMessageGet\(\)](#).

There are several status registers that can be used to help the application manage the controller. The status registers are read using the [CANStatusGet\(\)](#) function. There is a controller status register that provides general status information such as error or warning conditions. There are also several status registers that provide information about all of the message objects at once using a 32-bit bit map of the status, with one bit representing each message object. These status registers can be used to determine:

- Which message objects have unprocessed received data
- Which message objects have pending transmission requests
- Which message objects are allocated for use

7.2.2 Data Structure Documentation

7.2.2.1 tCANBitClkParms

Definition:

```
typedef struct
{
    unsigned int uSyncPropPhase1Seg;
    unsigned int uPhase2Seg;
    unsigned int uSJW;
    unsigned int uQuantumPrescaler;
}
tCANBitClkParms
```

Members:

uSyncPropPhase1Seg This value holds the sum of the Synchronization, Propagation, and Phase Buffer 1 segments, measured in time quanta. The valid values for this setting range from 2 to 16.

uPhase2Seg This value holds the Phase Buffer 2 segment in time quanta. The valid values for this setting range from 1 to 8.

uSJW This value holds the Resynchronization Jump Width in time quanta. The valid values for this setting range from 1 to 4.

uQuantumPrescaler This value holds the CAN_CLK divider used to determine time quanta. The valid values for this setting range from 1 to 1023.

Description:

This structure is used for encapsulating the values associated with setting up the bit timing for a CAN controller. The structure is used when calling the [CANGetBitTiming](#) and [CANSetBitTiming](#) functions.

7.2.2.2 tCANMsgObject

Definition:

```
typedef struct
{
```

```
    unsigned long ulMsgID;  
    unsigned long ulMsgIDMask;  
    unsigned long ulFlags;  
    unsigned long ulMsgLen;  
    unsigned char *pucMsgData;  
}  
tCANMsgObject
```

Members:

ulMsgID The CAN message identifier used for 11 or 29 bit identifiers.

ulMsgIDMask The message identifier mask used when identifier filtering is enabled.

ulFlags This value holds various status flags and settings specified by tCANObjFlags.

ulMsgLen This value is the number of bytes of data in the message object.

pucMsgData This is a pointer to the message object's data.

Description:

The structure used for encapsulating all the items associated with a CAN message object in the CAN controller.

7.2.3 Define Documentation

7.2.3.1 MSG_OBJ_STATUS_MASK

Definition:

```
#define MSG_OBJ_STATUS_MASK
```

Description:

This define is used with the [tCANObjFlags](#) enumerated values to allow checking only status flags and not configuration flags.

7.2.4 Enumeration Documentation

7.2.4.1 tCANIntFlags

Description:

These definitions are used to specify interrupt sources to [CANIntEnable\(\)](#) and [CANIntDisable\(\)](#).

Enumerators:

CAN_INT_ERROR This flag is used to allow a CAN controller to generate error interrupts.

CAN_INT_STATUS This flag is used to allow a CAN controller to generate status interrupts.

CAN_INT_MASTER This flag is used to allow a CAN controller to generate any CAN interrupts. If this is not set, then no interrupts will be generated by the CAN controller.

7.2.4.2 tCANIntStsReg

Description:

This data type is used to identify the interrupt status register. This is used when calling the [CANIntStatus\(\)](#) function.

Enumerators:

CAN_INT_STS_CAUSE Read the CAN interrupt status information.

CAN_INT_STS_OBJECT Read a message object's interrupt status.

7.2.4.3 tCANObjFlags

Description:

These are the flags used by the [tCANMsgObject](#) variable when calling the [CANMessageSet\(\)](#) and [CANMessageGet\(\)](#) functions.

Enumerators:

MSG_OBJ_TX_INT_ENABLE This indicates that transmit interrupts should be enabled, or are enabled.

MSG_OBJ_RX_INT_ENABLE This indicates that receive interrupts should be enabled, or are enabled.

MSG_OBJ_EXTENDED_ID This indicates that a message object will use or is using an extended identifier.

MSG_OBJ_USE_ID_FILTER This indicates that a message object will use or is using filtering based on the object's message identifier.

MSG_OBJ_NEW_DATA This indicates that new data was available in the message object.

MSG_OBJ_DATA_LOST This indicates that data was lost since this message object was last read.

MSG_OBJ_USE_DIR_FILTER This indicates that a message object will use or is using filtering based on the direction of the transfer. If the direction filtering is used, then ID filtering must also be enabled.

MSG_OBJ_USE_EXT_FILTER This indicates that a message object will use or is using message identifier filtering based on the extended identifier. If the extended identifier filtering is used, then ID filtering must also be enabled.

MSG_OBJ_REMOTE_FRAME This indicates that a message object is a remote frame.

MSG_OBJ_NO_FLAGS This indicates that a message object has no flags set.

7.2.4.4 tCANStatusCtrl

Description:

The following enumeration contains all error or status indicators that can be returned when calling the [CANStatusGet\(\)](#) function.

Enumerators:

CAN_STATUS_BUS_OFF CAN controller has entered a Bus Off state.

CAN_STATUS_EWARN CAN controller error level has reached warning level.

CAN_STATUS_EPASS CAN controller error level has reached error passive level.

CAN_STATUS_RXOK A message was received successfully since the last read of this status.

CAN_STATUS_TXOK A message was transmitted successfully since the last read of this status.

CAN_STATUS_LEC_MSK This is the mask for the last error code field.

CAN_STATUS_LEC_NONE There was no error.

CAN_STATUS_LEC_STUFF A bit stuffing error has occurred.

CAN_STATUS_LEC_FORM A formatting error has occurred.
CAN_STATUS_LEC_ACK An acknowledge error has occurred.
CAN_STATUS_LEC_BIT1 The bus remained a bit level of 1 for longer than is allowed.
CAN_STATUS_LEC_BIT0 The bus remained a bit level of 0 for longer than is allowed.
CAN_STATUS_LEC_CRC A CRC error has occurred.
CAN_STATUS_LEC_MASK This is the mask for the CAN Last Error Code (LEC).

7.2.4.5 tCANStsReg

Description:

This data type is used to identify which of several status registers to read when calling the [CANStatusGet\(\)](#) function.

Enumerators:

CAN_STS_CONTROL Read the full CAN controller status.
CAN_STS_TXREQUEST Read the full 32-bit mask of message objects with a transmit request set.
CAN_STS_NEWDAT Read the full 32-bit mask of message objects with new data available.
CAN_STS_MSGVAL Read the full 32-bit mask of message objects that are enabled.

7.2.4.6 tMsgObjType

Description:

This definition is used to determine the type of message object that will be set up via a call to the [CANMessageSet\(\)](#) API.

Enumerators:

MSG_OBJ_TYPE_TX Transmit message object.
MSG_OBJ_TYPE_TX_REMOTE Transmit remote request message object.
MSG_OBJ_TYPE_RX Receive message object.
MSG_OBJ_TYPE_RX_REMOTE Receive remote request message object.
MSG_OBJ_TYPE_RXTX_REMOTE Remote frame receive remote, with auto-transmit message object.

7.2.5 Function Documentation

7.2.5.1 CANDisable

Disables the CAN controller.

Prototype:

```
void  
CANDisable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the CAN controller to disable.

Description:

Disables the CAN controller for message processing. When disabled, the controller will no longer automatically process data on the CAN bus. The controller can be restarted by calling [CANEnable\(\)](#). The state of the CAN controller and the message objects in the controller are left as they were before this call was made.

Returns:

None.

7.2.5.2 CANEnable

Enables the CAN controller.

Prototype:

```
void  
CANEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the CAN controller to enable.

Description:

Enables the CAN controller for message processing. Once enabled, the controller will automatically transmit any pending frames, and process any received frames. The controller can be stopped by calling [CANDisable\(\)](#). Prior to calling [CANEnable\(\)](#), [CANInit\(\)](#) should have been called to initialize the controller and the CAN bus clock should be configured by calling [CANSetBitTiming\(\)](#).

Returns:

None.

7.2.5.3 CANErrCntGet

Reads the CAN controller error counter register.

Prototype:

```
tBoolean  
CANErrCntGet(unsigned long ulBase,  
             unsigned long *pulRxCount,  
             unsigned long *pulTxCount)
```

Parameters:

ulBase is the base address of the CAN controller.

pulRxCount is a pointer to storage for the receive error counter.

pulTxCount is a pointer to storage for the transmit error counter.

Description:

Reads the error counter register and returns the transmit and receive error counts to the caller along with a flag indicating if the controller receive counter has reached the error passive limit. The values of the receive and transmit error counters are returned through the pointers provided as parameters.

After this call, **pulRxCount* will hold the current receive error count and **pulTxCount* will hold the current transmit error count.

Returns:

Returns **true** if the receive error count has reached the error passive limit, and **false** if the error count is below the error passive limit.

7.2.5.4 CANGetBitTiming

Reads the current settings for the CAN controller bit timing.

Prototype:

```
void  
CANGetBitTiming(unsigned long ulBase,  
                 tCANBitClkParms *pClkParms)
```

Parameters:

ulBase is the base address of the CAN controller.

pClkParms is a pointer to a structure to hold the timing parameters.

Description:

This function reads the current configuration of the CAN controller bit clock timing, and stores the resulting information in the structure supplied by the caller. Refer to [CANSetBitTiming\(\)](#) for the meaning of the values that are returned in the structure pointed to by *pClkParms*.

Returns:

None.

7.2.5.5 CANGetIntNumber

Returns the CAN controller interrupt number.

Prototype:

```
long  
CANGetIntNumber(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the selected CAN controller

Description:

Given a CAN controller base address, returns the corresponding interrupt number.

Returns:

Returns a CAN interrupt number, or -1 if *ulPort* is invalid.

7.2.5.6 CANInit

Initializes the CAN controller after reset.

Prototype:

```
void  
CANInit(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the CAN controller.

Description:

After reset, the CAN controller is left in the disabled state. However, the memory used for message objects contains undefined values and must be cleared prior to enabling the CAN controller the first time. This prevents unwanted transmission or reception of data before the message objects are configured. This function must be called before enabling the controller the first time.

Returns:

None.

7.2.5.7 CANIntClear

Clears a CAN interrupt source.

Prototype:

```
void  
CANIntClear(unsigned long ulBase,  
             unsigned long ulIntClr)
```

Parameters:

ulBase is the base address of the CAN controller.

ulIntClr is a value indicating which interrupt source to clear.

Description:

This function can be used to clear a specific interrupt source. The *ulIntClr* parameter should be one of the following values:

- **CAN_INT_INTID_STATUS** - Clears a status interrupt.
- 1-32 - Clears the specified message object interrupt

It is not necessary to use this function to clear an interrupt. This should only be used if the application wants to clear an interrupt source without taking the normal interrupt action.

Normally, the status interrupt is cleared by reading the controller status using [CANStatusGet\(\)](#). A specific message object interrupt is normally cleared by reading the message object using [CANMessageGet\(\)](#).

Returns:

None.

7.2.5.8 CANIntDisable

Disables individual CAN controller interrupt sources.

Prototype:

```
void  
CANIntDisable(unsigned long ulBase,  
              unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the CAN controller.

ulIntFlags is the bit mask of the interrupt sources to be disabled.

Description:

Disables the specified CAN controller interrupt sources. Only enabled interrupt sources can cause a processor interrupt.

The *ulIntFlags* parameter has the same definition as in the [CANIntEnable\(\)](#) function.

Returns:

None.

7.2.5.9 CANIntEnable

Enables individual CAN controller interrupt sources.

Prototype:

```
void  
CANIntEnable(unsigned long ulBase,  
             unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the CAN controller.

ulIntFlags is the bit mask of the interrupt sources to be enabled.

Description:

Enables specific interrupt sources of the CAN controller. Only enabled sources will cause a processor interrupt.

The *ulIntFlags* parameter is the logical OR of any of the following:

- **CAN_INT_ERROR** - a controller error condition has occurred
- **CAN_INT_STATUS** - a message transfer has completed, or a bus error has been detected
- **CAN_INT_MASTER** - allow CAN controller to generate interrupts

In order to generate any interrupts, **CAN_INT_MASTER** must be enabled. Further, for any particular transaction from a message object to generate an interrupt, that message object must have interrupts enabled (see [CANMessageSet\(\)](#)). **CAN_INT_ERROR** will generate an interrupt if the controller enters the “bus off” condition, or if the error counters reach a limit. **CAN_INT_STATUS** will generate an interrupt under quite a few status conditions and may provide more interrupts than the application needs to handle. When an interrupt occurs, use [CANIntStatus\(\)](#) to determine the cause.

Returns:

None.

7.2.5.10 CANIntRegister

Registers an interrupt handler for the CAN controller.

Prototype:

```
void  
CANIntRegister(unsigned long ulBase,  
               void (*pfnHandler)(void))
```

Parameters:

ulBase is the base address of the CAN controller.

pfnHandler is a pointer to the function to be called when the enabled CAN interrupts occur.

Description:

This function registers the interrupt handler in the interrupt vector table, and enables CAN interrupts on the interrupt controller; specific CAN interrupt sources must be enabled using [CANIntEnable\(\)](#). The interrupt handler being registered must clear the source of the interrupt using [CANIntClear\(\)](#);

If the application is using a static interrupt vector table stored in flash, then it is not necessary to register the interrupt handler this way. Instead, [IntEnable\(\)](#) should be used to enable CAN interrupts on the interrupt controller.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

7.2.5.11 CANIntStatus

Returns the current CAN controller interrupt status.

Prototype:

```
unsigned long  
CANIntStatus(unsigned long ulBase,  
              tCANIntStsReg eIntStsReg)
```

Parameters:

ulBase is the base address of the CAN controller.

eIntStsReg indicates which interrupt status register to read

Description:

Returns the value of one of two interrupt status registers. The interrupt status register read is determined by the *eIntStsReg* parameter, which can have one of the following values:

- **CAN_INT_STS_CAUSE** - indicates the cause of the interrupt
- **CAN_INT_STS_OBJECT** - indicates pending interrupts of all message objects

CAN_INT_STS_CAUSE returns the value of the controller interrupt register and indicates the cause of the interrupt. It will be a value of **CAN_INT_INTID_STATUS** if the cause is a status interrupt. In this case, the status register should be read with the [CANStatusGet\(\)](#) function. Calling this function to read the status will also clear the status interrupt. If the value of the

interrupt register is in the range 1-32, then this indicates the number of the highest priority message object that has an interrupt pending. The message object interrupt can be cleared by using the [CANIntClear\(\)](#) function, or by reading the message using [CANMessageGet\(\)](#) in the case of a received message. The interrupt handler can read the interrupt status again to make sure all pending interrupts are cleared before returning from the interrupt.

CAN_INT_STS_OBJECT returns a bit mask indicating which message objects have pending interrupts. This can be used to discover all of the pending interrupts at once, as opposed to repeatedly reading the interrupt register by using **CAN_INT_STS_CAUSE**.

Returns:

Returns the value of one of the interrupt status registers.

7.2.5.12 CANIntUnregister

Unregisters an interrupt handler for the CAN controller.

Prototype:

```
void  
CANIntUnregister(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the controller.

Description:

This function unregisters the previously registered interrupt handler and disables the interrupt on the interrupt controller.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

7.2.5.13 CANMessageClear

Clears a message object so that it is no longer used.

Prototype:

```
void  
CANMessageClear(unsigned long ulBase,  
                 unsigned long ulObjID)
```

Parameters:

ulBase is the base address of the CAN controller.

ulObjID is the message object number to disable (1-32).

Description:

This function frees the specified message object from use. Once a message object has been "cleared," it will no longer automatically send or receive messages, or generate interrupts.

Returns:

None.

7.2.5.14 CANMessageGet

Reads a CAN message from one of the message object buffers.

Prototype:

```
void  
CANMessageGet (unsigned long ulBase,  
               unsigned long ulObjID,  
               tCANMsgObject *pMsgObject,  
               tBoolean bClrPendingInt)
```

Parameters:

ulBase is the base address of the CAN controller.

ulObjID is the object number to read (1-32).

pMsgObject points to a structure containing message object fields.

bClrPendingInt indicates whether an associated interrupt should be cleared.

Description:

This function is used to read the contents of one of the 32 message objects in the CAN controller, and return it to the caller. The data returned is stored in the fields of the caller-supplied structure pointed to by *pMsgObject*. The data consists of all of the parts of a CAN message, plus some control and status information.

Normally this is used to read a message object that has received and stored a CAN message with a certain identifier. However, this could also be used to read the contents of a message object in order to load the fields of the structure in case only part of the structure needs to be changed from a previous setting.

When using CANMessageGet, all of the same fields of the structure are populated in the same way as when the [CANMessageSet\(\)](#) function is used, with the following exceptions:

pMsgObject->ulFlags:

- **MSG_OBJ_NEW_DATA** indicates if this is new data since the last time it was read
- **MSG_OBJ_DATA_LOST** indicates that at least one message was received on this message object, and not read by the host before being overwritten.

Returns:

None.

7.2.5.15 CANMessageSet

Configures a message object in the CAN controller.

Prototype:

```
void  
CANMessageSet (unsigned long ulBase,  
               unsigned long ulObjID,  
               tCANMsgObject *pMsgObject,  
               tMsgObjType eMsgType)
```

Parameters:

ulBase is the base address of the CAN controller.

ulObjID is the object number to configure (1-32).

pMsgObject is a pointer to a structure containing message object settings.

eMsgType indicates the type of message for this object.

Description:

This function is used to configure any one of the 32 message objects in the CAN controller. A message object can be configured as any type of CAN message object as well as several options for automatic transmission and reception. This call also allows the message object to be configured to generate interrupts on completion of message receipt or transmission. The message object can also be configured with a filter/mask so that actions are only taken when a message that meets certain parameters is seen on the CAN bus.

The *eMsgType* parameter must be one of the following values:

- **MSG_OBJ_TYPE_TX** - CAN transmit message object.
- **MSG_OBJ_TYPE_TX_REMOTE** - CAN transmit remote request message object.
- **MSG_OBJ_TYPE_RX** - CAN receive message object.
- **MSG_OBJ_TYPE_RX_REMOTE** - CAN receive remote request message object.
- **MSG_OBJ_TYPE_RXTX_REMOTE** - CAN remote frame receive remote, then transmit message object.

The message object pointed to by *pMsgObject* must be populated by the caller, as follows:

- *ulMsgID* - contains the message ID, either 11 or 29 bits.
- *ulMsgIDMask* - mask of bits from *ulMsgID* that must match if identifier filtering is enabled.
- *ulFlags*
 - Set **MSG_OBJ_TX_INT_ENABLE** flag to enable interrupt on transmission.
 - Set **MSG_OBJ_RX_INT_ENABLE** flag to enable interrupt on receipt.
 - Set **MSG_OBJ_USE_ID_FILTER** flag to enable filtering based on the identifier mask specified by *ulMsgIDMask*.
- *ulMsgLen* - the number of bytes in the message data. This should be non-zero even for a remote frame; it should match the expected bytes of the data responding data frame.
- *pucMsgData* - points to a buffer containing up to 8 bytes of data for a data frame.

To send a data frame or remote frame directly, take the following steps:

1. Set *tMsgObjType* to **MSG_OBJ_TYPE_TX**.
2. Set *ulMsgID* to the message ID.
3. Set *ulFlags* Set **MSG_OBJ_TX_INT_ENABLE** to to get an interrupt when the message is sent. To disable filtering based on message identifiers, do not set **MSG_OBJ_USE_ID_FILTER**.
4. Set *ulMsgLen* to the number of bytes in the data frame.
5. Set *pucMsgData* to point to an array containing the bytes in the message (if a data frame, this is not applicable; if a remote frame, it is a good idea to set this to point to a valid buffer).
6. Call this function with *ulObjID* set to one of the 32 object buffers.

To receive a specific data frame, take the following steps:

1. Set *tMsgObjType* to **MSG_OBJ_TYPE_RX**.
2. Set *ulMsgID* to the full message ID, or a partial mask to use partial ID matching.
3. Set *ulMsgIDMask* bits that should be used for masking during comparison.
4. Set *ulFlags* as follows:

- Set **MSG_OBJ_TX_INT_ENABLE** flag to be interrupted when the data frame is received.
 - Set **MSG_OBJ_USE_ID_FILTER** flag to enable identifier based filtering.
5. Set *ulMsgLen* to the number of bytes in the expected data frame.
 6. The buffer pointed to by *pucMsgData* is not used for this call.
 7. Call this function with *ulObjID* set to one of the 32 object buffers.

If you specify a message object buffer that already contains a message definition, it will be overwritten.

Returns:

None.

7.2.5.16 CANReadDataReg

Copies data from a buffer to the CAN Data registers.

Prototype:

```
void  
CANReadDataReg(unsigned char *pucData,  
               unsigned long *pulRegister,  
               int iSize)
```

Parameters:

pucData is a pointer to the location to store the data read from the CAN controller's data registers.

pulRegister is an unsigned long pointer to the first register of the CAN controller's data registers. For example, in order to use the IF1 register set on CAN controller 1, the value would be: **CAN0_BASE + CAN_O_IF1DA1**.

iSize is the number of bytes to copy from the CAN controller.

Description:

This function takes the steps necessary to copy data to a contiguous buffer in memory from the non-contiguous data registers used by the CAN controller. This function is rarely used outside of the [CANMessageGet\(\)](#) function.

Returns:

None.

7.2.5.17 CANReadReg

Reads a CAN controller register.

Prototype:

```
unsigned long  
CANReadReg(unsigned long ulRegAddress)
```

Parameters:

ulRegAddress is the full address of the CAN register to be read.

Description:

This function performs the necessary synchronization to read from a CAN controller register.

Note:

This function provides the delay required to access CAN registers. This delay is required when accessing CAN registers directly.

Returns:

Returns the value read from the register.

7.2.5.18 CANRetryGet

Returns the current setting for automatic retransmission.

Prototype:

```
tBoolean  
CANRetryGet(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the CAN controller.

Description:

Reads the current setting for the automatic retransmission in the CAN controller and returns it to the caller.

Returns:

Returns **true** if automatic retransmission is enabled, **false** otherwise.

7.2.5.19 CANRetrySet

Sets the CAN controller automatic retransmission behavior.

Prototype:

```
void  
CANRetrySet(unsigned long ulBase,  
             tBoolean bAutoRetry)
```

Parameters:

ulBase is the base address of the CAN controller.

bAutoRetry enables automatic retransmission.

Description:

Enables or disables automatic retransmission of messages with detected errors. If *bAutoRetry* is **true**, then automatic retransmission is enabled, otherwise it is disabled.

Returns:

None.

7.2.5.20 CANSetBitTiming

Configures the CAN controller bit timing.

Prototype:

```
void  
CANSetBitTiming(unsigned long ulBase,  
                tCANBitClkParms *pClkParms)
```

Parameters:

ulBase is the base address of the CAN controller.
pClkParms points to the structure with the clock parameters.

Description:

Configures the various timing parameters for the CAN bus bit timing: Propagation segment, Phase Buffer 1 segment, Phase Buffer 2 segment, and the Synchronization Jump Width. The values for Propagation and Phase Buffer 1 segments are derived from the combination *pClkParms->uSyncPropPhase1Seg* parameter. Phase Buffer 2 is determined from the *pClkParms->uPhase2Seg* parameter. These two parameters, along with *pClkParms->uSJW* are based in units of bit time quanta. The actual quantum time is determined by the *pClkParms->uQuantumPrescaler* value, which specifies the divisor for the CAN module clock.

The total bit time, in quanta, will be the sum of the two Seg parameters, as follows:

$$\text{bit_time_q} = \text{uSyncPropPhase1Seg} + \text{uPhase2Seg} + 1$$

Note that the Sync_Seg is always one quantum in duration, and will be added to derive the correct duration of Prop_Seg and Phase1_Seg.

The equation to determine the actual bit rate is as follows:

$$\text{CAN Clock} / ((\text{uSyncPropPhase1Seg} + \text{uPhase2Seg} + 1) * (\text{uQuantumPrescaler}))$$

This means that with *uSyncPropPhase1Seg* = 4, *uPhase2Seg* = 1, *uQuantumPrescaler* = 2 and an 8 MHz CAN clock, that the bit rate will be (8 MHz) / ((5 + 2 + 1) * 2) or 500 Kbit/sec.

Returns:

None.

7.2.5.21 CANStatusGet

Reads one of the controller status registers.

Prototype:

```
unsigned long  
CANStatusGet(unsigned long ulBase,  
              tCANStsReg eStatusReg)
```

Parameters:

ulBase is the base address of the CAN controller.
eStatusReg is the status register to read.

Description:

Reads a status register of the CAN controller and returns it to the caller. The different status registers are:

- **CAN_STS_CONTROL** - the main controller status
- **CAN_STS_TXREQUEST** - bit mask of objects pending transmission
- **CAN_STS_NEWDAT** - bit mask of objects with new data
- **CAN_STS_MSGVAL** - bit mask of objects with valid configuration

When reading the main controller status register, a pending status interrupt will be cleared. This should be used in the interrupt handler for the CAN controller if the cause is a status interrupt. The controller status register fields are as follows:

- **CAN_STATUS_BUS_OFF** - controller is in bus-off condition
- **CAN_STATUS_EWARN** - an error counter has reached a limit of at least 96
- **CAN_STATUS_EPASS** - CAN controller is in the error passive state
- **CAN_STATUS_RXOK** - a message was received successfully (independent of any message filtering).
- **CAN_STATUS_TXOK** - a message was successfully transmitted
- **CAN_STATUS_LEC_MSK** - mask of last error code bits (3 bits)
- **CAN_STATUS_LEC_NONE** - no error
- **CAN_STATUS_LEC_STUFF** - stuffing error detected
- **CAN_STATUS_LEC_FORM** - a format error occurred in the fixed format part of a message
- **CAN_STATUS_LEC_ACK** - a transmitted message was not acknowledged
- **CAN_STATUS_LEC_BIT1** - dominant level detected when trying to send in recessive mode
- **CAN_STATUS_LEC_BIT0** - recessive level detected when trying to send in dominant mode
- **CAN_STATUS_LEC_CRC** - CRC error in received message

The remaining status registers are 32-bit bit maps to the message objects. They can be used to quickly obtain information about the status of all the message objects without needing to query each one. They contain the following information:

- **CAN_STS_TXREQUEST** - if a message object's TxRequest bit is set, that means that a transmission is pending on that object. The application can use this to determine which objects are still waiting to send a message.
- **CAN_STS_NEWDAT** - if a message object's NewDat bit is set, that means that a new message has been received in that object, and has not yet been picked up by the host application
- **CAN_STS_MSGVAL** - if a message object's MsgVal bit is set, that means it has a valid configuration programmed. The host application can use this to determine which message objects are empty/unused.

Returns:

Returns the value of the status register.

7.2.5.22 CANWriteDataReg

Copies data from a buffer to the CAN Data registers.

Prototype:

```
void  
CANWriteDataReg(unsigned char *pucData,
```

```
unsigned long *pulRegister,  
int iSize)
```

Parameters:

pucData is a pointer to the data to be written out to the CAN controller's data registers.

pulRegister is an unsigned long pointer to the first register of the CAN controller's data registers. For example, in order to use the IF1 register set on CAN controller 0, the value would be: **CAN0_BASE + CAN_O_IF1DA1**.

iSize is the number of bytes to copy into the CAN controller.

Description:

This function takes the steps necessary to copy data from a contiguous buffer in memory into the non-contiguous data registers used by the CAN controller. This function is rarely used outside of the [CANMessageSet\(\)](#) function.

Returns:

None.

7.2.5.23 CANWriteReg

Writes a CAN controller register.

Prototype:

```
void  
CANWriteReg(unsigned long ulRegAddress,  
             unsigned long ulRegValue)
```

Parameters:

ulRegAddress is the full address of the CAN register to be written.

ulRegValue is the value to write into the register specified by *ulRegAddress*.

Description:

This function takes care of the synchronization necessary to write to a CAN controller register.

Note:

The delays in this function are required when accessing CAN registers directly.

Returns:

None.

7.3 Programming Example

This example code will send out data from CAN controller 0 to be received by CAN controller 1. In order to actually receive the data, an external cable must be connected between the two ports. In this example, both controllers are configured for 1 Mbit operation.

```
tCANBitClkParms CANBitClk;  
tCANMsgObject sMsgObjectRx;  
tCANMsgObject sMsgObjectTx;  
unsigned char ucBufferIn[8];
```

```
unsigned char ucBufferOut[8];

//
// Reset the state of all the message objects and the state of the CAN
// module to a known state.
//
CANInit(CAN0_BASE);
CANInit(CAN1_BASE);

//
// Configure the controller for 1 Mbit operation.
//
CANBitClk.uSyncPropPhase1Seg = 5;
CANBitClk.uPhase2Seg = 2;
CANBitClk.uQuantumPrescaler = 1;
CANBitClk.uSJW = 2;
CANSetBitTiming(CAN0_BASE, &CANBitClk);
CANSetBitTiming(CAN1_BASE, &CANBitClk);

//
// Take the CAN0 device out of INIT state.
//
CANEnable(CAN0_BASE);
CANEnable(CAN1_BASE);

//
// Configure a receive object.
//
sMsgObjectRx.ulMsgID = (0x400);
sMsgObjectRx.ulMsgIDMask = 0x7f8;
sMsgObjectRx.ulFlags = MSG_OBJ_USE_ID_FILTER;
sMsgObjectRx.ulMsgLen = 8;
sMsgObjectRx.pucMsgData = ucBufferIn;
CANMessageSet(CAN1_BASE, 1, &sMsgObjectRx, MSG_OBJ_TYPE_RX);

//
// Configure and start transmit of message object.
//
sMsgObjectTx.ulMsgID = 0x400;
sMsgObjectTx.ulFlags = 0;
sMsgObjectTx.ulMsgLen = 8;
sMsgObjectTx.pucMsgData = ucBufferOut;
CANMessageSet(CAN0_BASE, 2, &sMsgObjectTx, MSG_OBJ_TYPE_TX);

//
// Wait for new data to become available.
//
while((CANStatusGet(CAN1_BASE, CAN_STS_NEWDAT) & 1) == 0)
{
    //
    // Read the message out of the message object.
    //
    CANMessageGet(CAN1_BASE, 1, &sMsgObjectRx, true);
}

//
// Process new data in sMsgObjectRx.pucMsgData.
//
...
```


8 Ethernet Controller

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8.1 Introduction

The Stellaris Ethernet controller consists of a fully integrated media access controller (MAC) and a network physical (PHY) interface device. The Ethernet controller conforms to IEEE 802.3 specifications and fully supports 10BASE-T and 100BASE-TX standards.

The Ethernet API provides the set of functions required to implement an interrupt-driven Ethernet driver for this Ethernet controller. Functions are provided to configure and control the MAC, to access the register set on the PHY, to transmit and receive Ethernet packets, and to configure and control the interrupts that are available.

This driver is contained in `src/ethernet.c`, with `src/ethernet.h` containing the API definitions for use by applications.

8.2 API Functions

Functions

- unsigned long [EthernetConfigGet](#) (unsigned long ulBase)
- void [EthernetConfigSet](#) (unsigned long ulBase, unsigned long ulConfig)
- void [EthernetDisable](#) (unsigned long ulBase)
- void [EthernetEnable](#) (unsigned long ulBase)
- void [EthernetInitExpClk](#) (unsigned long ulBase, unsigned long ulEthClk)
- void [EthernetIntClear](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [EthernetIntDisable](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [EthernetIntEnable](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [EthernetIntRegister](#) (unsigned long ulBase, void (*pfnHandler)(void))
- unsigned long [EthernetIntStatus](#) (unsigned long ulBase, tBoolean bMasked)
- void [EthernetIntUnregister](#) (unsigned long ulBase)
- void [EthernetMACAddrGet](#) (unsigned long ulBase, unsigned char *pucMACAddr)
- void [EthernetMACAddrSet](#) (unsigned long ulBase, unsigned char *pucMACAddr)
- tBoolean [EthernetPacketAvail](#) (unsigned long ulBase)
- long [EthernetPacketGet](#) (unsigned long ulBase, unsigned char *pucBuf, long lBufLen)
- long [EthernetPacketGetNonBlocking](#) (unsigned long ulBase, unsigned char *pucBuf, long lBufLen)
- long [EthernetPacketPut](#) (unsigned long ulBase, unsigned char *pucBuf, long lBufLen)
- long [EthernetPacketPutNonBlocking](#) (unsigned long ulBase, unsigned char *pucBuf, long lBufLen)
- unsigned long [EthernetPHYRead](#) (unsigned long ulBase, unsigned char ucRegAddr)

- void [EthernetPHYWrite](#) (unsigned long ulBase, unsigned char ucRegAddr, unsigned long ulData)
- tBoolean [EthernetSpaceAvail](#) (unsigned long ulBase)

8.2.1 Detailed Description

For any application, the [EthernetInitExpClk\(\)](#) function must be called first to prepare the Ethernet controller for operation. This function will configure the Ethernet controller options that are based on system parameters, such as the system clock speed.

Once initialized, access to the PHY is available via the [EthernetPHYRead\(\)](#) and [EthernetPHYWrite\(\)](#) functions. By default, the PHY will auto-negotiate the line speed and duplex modes. For most applications, this will be sufficient. If a special configuration is required, the PHY read and write functions can be used to reconfigure the PHY to the desired mode of operation.

The MAC must also be configured using the [EthernetConfigSet\(\)](#) function. The parameters for this function will allow the configuration of options such as Promiscuous Mode, Multicast Reception, Transmit Data Length Padding, and so on. The [EthernetConfigGet\(\)](#) function can be used to query the current configuration of the Ethernet MAC.

The MAC address, used for incoming packet filtering, must also be programmed using the [EthernetMACAddrSet\(\)](#) function. The current value can be queried using the [EthernetMACAddrGet\(\)](#) function.

When configuration has been completed, the Ethernet controller can be enabled using the [EthernetEnable\(\)](#) function. When getting ready to terminate operations on the Ethernet controller, the [EthernetDisable\(\)](#) function may be called.

After the Ethernet controller has been enabled, Ethernet frames can be transmitted and received using the [EthernetPacketPut\(\)](#) and [EthernetPacketGet\(\)](#) functions. Care must be taken when using these functions, as they are blocking functions, and will not return until data is available (for RX) or buffer space is available (for TX). The [EthernetSpaceAvail\(\)](#) and [EthernetPacketAvail\(\)](#) functions can be called to determine if there is room for a TX packet or if there is an RX packet available prior to calling these blocking functions. Alternatively, the [EthernetPacketGetNonBlocking\(\)](#) and [EthernetPacketPutNonBlocking\(\)](#) functions will return immediately if a packet cannot be processed. Otherwise, the packet will be processed normally.

When developing a mapping layer for a TCP/IP stack, you may wish to use the interrupt capability of the Ethernet controller. The [EthernetIntRegister\(\)](#) and [EthernetIntUnregister\(\)](#) functions are used to register an ISR with the system and to enable or disable the Ethernet controller's interrupt signal. The [EthernetIntEnable\(\)](#) and [EthernetIntDisable\(\)](#) functions are used to manipulate the individual interrupt sources available in the Ethernet controller (for example, RX Error, TX Complete). The [EthernetIntStatus\(\)](#) and [EthernetIntClear\(\)](#) functions would be used to query the active interrupts to determine which process to service, and to clear the indicated interrupts prior to returning from the registered ISR.

The [EthernetInit\(\)](#), [EthernetPacketNonBlockingGet\(\)](#), and [EthernetPacketNonBlockingPut\(\)](#) APIs from previous versions of the peripheral driver library have been replaced by the [EthernetInitExpClk\(\)](#), [EthernetPacketGetNonBlocking\(\)](#), and [EthernetPacketPutNonBlocking\(\)](#) APIs, respectively. Macros have been provided in `ethernet.h` to map the old APIs to the new APIs, allowing existing applications to link and run with the new APIs. It is recommended that new applications utilize the new APIs in favor of the old ones.

8.2.2 Function Documentation

8.2.2.1 EthernetConfigGet

Gets the current configuration of the Ethernet controller.

Prototype:

```
unsigned long  
EthernetConfigGet(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the controller.

Description:

This function will query the control registers of the Ethernet controller and return a bit-mapped configuration value.

See also:

The description of the [EthernetConfigSet\(\)](#) function provides detailed information for the bit-mapped configuration values that will be returned.

Returns:

Returns the bit-mapped Ethernet controller configuration value.

8.2.2.2 EthernetConfigSet

Sets the configuration of the Ethernet controller.

Prototype:

```
void  
EthernetConfigSet(unsigned long ulBase,  
                  unsigned long ulConfig)
```

Parameters:

ulBase is the base address of the controller.

ulConfig is the configuration for the controller.

Description:

After the [EthernetInitExpClk\(\)](#) function has been called, this API function can be used to configure the various features of the Ethernet controller.

The Ethernet controller provides three control registers that are used to configure the controller's operation. The transmit control register provides settings to enable full duplex operation, to auto-generate the frame check sequence, and to pad the transmit packets to the minimum length as required by the IEEE standard. The receive control register provides settings to enable reception of packets with bad frame check sequence values and to enable multi-cast or promiscuous modes. The timestamp control register provides settings that enable support logic in the controller that allow the use of the General Purpose Timer 3 to capture timestamps for the transmitted and received packets.

The *ulConfig* parameter is the logic OR of the following values:

- **ETH_CFG_TS_TSEN** - Enable TX and RX interrupt status as CCP timer inputs

- **ETH_CFG_RX_BADCRCDIS** - Disable reception of packets with a bad CRC
- **ETH_CFG_RX_PRMSSEN** - Enable promiscuous mode reception (all packets)
- **ETH_CFG_RX_AMULEN** - Enable reception of multicast packets
- **ETH_CFG_TX_DPLXEN** - Enable full duplex transmit mode
- **ETH_CFG_TX_CRCEN** - Enable transmit with auto CRC generation
- **ETH_CFG_TX_PADEN** - Enable padding of transmit data to minimum size

These bit-mapped values are programmed into the transmit, receive, and/or timestamp control register.

Returns:

None.

8.2.2.3 EthernetDisable

Disables the Ethernet controller.

Prototype:

```
void  
EthernetDisable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the controller.

Description:

When terminating operations on the Ethernet interface, this function should be called. This function will disable the transmitter and receiver, and will clear out the receive FIFO.

Returns:

None.

8.2.2.4 EthernetEnable

Enables the Ethernet controller for normal operation.

Prototype:

```
void  
EthernetEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the controller.

Description:

Once the Ethernet controller has been configured using the [EthernetConfigSet\(\)](#) function and the MAC address has been programmed using the [EthernetMACAddrSet\(\)](#) function, this API function can be called to enable the controller for normal operation.

This function will enable the controller's transmitter and receiver, and will reset the receive FIFO.

Returns:

None.

8.2.2.5 EthernetInitExpClk

Initializes the Ethernet controller for operation.

Prototype:

```
void  
EthernetInitExpClk(unsigned long ulBase,  
                  unsigned long ulEthClk)
```

Parameters:

ulBase is the base address of the controller.

ulEthClk is the rate of the clock supplied to the Ethernet module.

Description:

This function will prepare the Ethernet controller for first time use in a given hardware/software configuration. This function should be called before any other Ethernet API functions are called.

The peripheral clock will be the same as the processor clock. This will be the value returned by [SysCtlClockGet\(\)](#), or it can be explicitly hard-coded if it is constant and known (to save the code/execution overhead of a call to [SysCtlClockGet\(\)](#)).

This function replaces the original EthernetInit() API and performs the same actions. A macro is provided in `ethernet.h` to map the original API to this API.

Note:

If the device configuration is changed (for example, the system clock is reprogrammed to a different speed), then the Ethernet controller must be disabled by calling the [EthernetDisable\(\)](#) function and the controller must be reinitialized by calling the [EthernetInitExpClk\(\)](#) function again. After the controller has been reinitialized, the controller should be reconfigured using the appropriate Ethernet API calls.

Returns:

None.

8.2.2.6 EthernetIntClear

Clears Ethernet interrupt sources.

Prototype:

```
void  
EthernetIntClear(unsigned long ulBase,  
                unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the controller.

ulIntFlags is a bit mask of the interrupt sources to be cleared.

Description:

The specified Ethernet interrupt sources are cleared so that they no longer assert. This must be done in the interrupt handler to keep it from being called again immediately upon exit.

The *ulIntFlags* parameter has the same definition as the *ulIntFlags* parameter to [EthernetIntEnable\(\)](#).

Returns:

None.

8.2.2.7 EthernetIntDisable

Disables individual Ethernet interrupt sources.

Prototype:

```
void  
EthernetIntDisable(unsigned long ulBase,  
                   unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the controller.

ulIntFlags is the bit mask of the interrupt sources to be disabled.

Description:

Disables the indicated Ethernet interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor.

The *ulIntFlags* parameter has the same definition as the *ulIntFlags* parameter to [EthernetIntEnable\(\)](#).

Returns:

None.

8.2.2.8 EthernetIntEnable

Enables individual Ethernet interrupt sources.

Prototype:

```
void  
EthernetIntEnable(unsigned long ulBase,  
                  unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the controller.

ulIntFlags is the bit mask of the interrupt sources to be enabled.

Description:

Enables the indicated Ethernet interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor.

The *ulIntFlags* parameter is the logical OR of any of the following:

- **ETH_INT_PHY** - An interrupt from the PHY has occurred. The integrated PHY supports a number of interrupt conditions. The PHY register, PHY_MR17, must be read to determine which PHY interrupt has occurred. This register can be read using the [EthernetPHYRead\(\)](#) API function.
- **ETH_INT_MDIO** - This interrupt indicates that a transaction on the management interface has completed successfully.

- **ETH_INT_RXER** - This interrupt indicates that an error has occurred during reception of a frame. This error can indicate a length mismatch, a CRC failure, or an error indication from the PHY.
- **ETH_INT_RXOF** - This interrupt indicates that a frame has been received that exceeds the available space in the RX FIFO.
- **ETH_INT_TX** - This interrupt indicates that the packet stored in the TX FIFO has been successfully transmitted.
- **ETH_INT_TXER** - This interrupt indicates that an error has occurred during the transmission of a packet. This error can be either a retry failure during the back-off process, or an invalid length stored in the TX FIFO.
- **ETH_INT_RX** - This interrupt indicates that one (or more) packets are available in the RX FIFO for processing.

Returns:

None.

8.2.2.9 EthernetIntRegister

Registers an interrupt handler for an Ethernet interrupt.

Prototype:

```
void  
EthernetIntRegister(unsigned long ulBase,  
                    void (*pfnHandler)(void))
```

Parameters:

ulBase is the base address of the controller.

pfnHandler is a pointer to the function to be called when the enabled Ethernet interrupts occur.

Description:

This function sets the handler to be called when the Ethernet interrupt occurs. This will enable the global interrupt in the interrupt controller; specific Ethernet interrupts must be enabled via [EthernetIntEnable\(\)](#). It is the interrupt handler's responsibility to clear the interrupt source.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

8.2.2.10 EthernetIntStatus

Gets the current Ethernet interrupt status.

Prototype:

```
unsigned long  
EthernetIntStatus(unsigned long ulBase,  
                  tBoolean bMasked)
```

Parameters:

ulBase is the base address of the controller.

bMasked is false if the raw interrupt status is required and true if the masked interrupt status is required.

Description:

This returns the interrupt status for the Ethernet controller. Either the raw interrupt status or the status of interrupts that are allowed to reflect to the processor can be returned.

Returns:

Returns the current interrupt status, enumerated as a bit field of values described in [Ethernet-IntEnable\(\)](#).

8.2.2.11 EthernetIntUnregister

Unregisters an interrupt handler for an Ethernet interrupt.

Prototype:

```
void  
EthernetIntUnregister(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the controller.

Description:

This function unregisters the interrupt handler. This will disable the global interrupt in the interrupt controller so that the interrupt handler no longer is called.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

8.2.2.12 EthernetMACAddrGet

Gets the MAC address of the Ethernet controller.

Prototype:

```
void  
EthernetMACAddrGet(unsigned long ulBase,  
                   unsigned char *pucMACAddr)
```

Parameters:

ulBase is the base address of the controller.

pucMACAddr is the pointer to the location in which to store the array of MAC-48 address octets.

Description:

This function will read the currently programmed MAC address into the *pucMACAddr* buffer.

See also:

Refer to [EthernetMACAddrSet\(\)](#) API description for more details about the MAC address format.

Returns:

None.

8.2.2.13 EthernetMACAddrSet

Sets the MAC address of the Ethernet controller.

Prototype:

```
void  
EthernetMACAddrSet(unsigned long ulBase,  
                   unsigned char *pucMACAddr)
```

Parameters:

ulBase is the base address of the controller.

pucMACAddr is the pointer to the array of MAC-48 address octets.

Description:

This function will program the IEEE-defined MAC-48 address specified in *pucMACAddr* into the Ethernet controller. This address is used by the Ethernet controller for hardware-level filtering of incoming Ethernet packets (when promiscuous mode is not enabled).

The MAC-48 address is defined as 6 octets, illustrated by the following example address. The numbers are shown in hexadecimal format.

AC-DE-48-00-00-80

In this representation, the first three octets (AC-DE-48) are the Organizationally Unique Identifier (OUI). This is a number assigned by the IEEE to an organization that requests a block of MAC addresses. The last three octets (00-00-80) are a 24-bit number managed by the OUI owner to uniquely identify a piece of hardware within that organization that is to be connected to the Ethernet.

In this representation, the octets are transmitted from left to right, with the “AC” octet being transmitted first and the “80” octet being transmitted last. Within an octet, the bits are transmitted LSB to MSB. For this address, the first bit to be transmitted would be “0”, the LSB of “AC”, and the last bit to be transmitted would be “1”, the MSB of “80”.

Returns:

None.

8.2.2.14 EthernetPacketAvail

Check for packet available from the Ethernet controller.

Prototype:

```
tBoolean  
EthernetPacketAvail(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the controller.

Description:

The Ethernet controller provides a register that contains the number of packets available in the receive FIFO. When the last bytes of a packet are successfully received (that is, the frame check sequence bytes), the packet count is incremented. Once the packet has been fully read (including the frame check sequence bytes) from the FIFO, the packet count will be decremented.

Returns:

Returns **true** if there are one or more packets available in the receive FIFO, including the current packet being read, and **false** otherwise.

8.2.2.15 EthernetPacketGet

Waits for a packet from the Ethernet controller.

Prototype:

```
long  
EthernetPacketGet(unsigned long ulBase,  
                  unsigned char *pucBuf,  
                  long lBufLen)
```

Parameters:

ulBase is the base address of the controller.

pucBuf is the pointer to the packet buffer.

lBufLen is the maximum number of bytes to be read into the buffer.

Description:

This function reads a packet from the receive FIFO of the controller and places it into *pucBuf*. The function will wait until a packet is available in the FIFO. Then the function will read the entire packet from the receive FIFO. If there are more bytes in the packet than will fit into *pucBuf* (as specified by *lBufLen*), the function will return the negated length of the packet and the buffer will contain *lBufLen* bytes of the packet. Otherwise, the function will return the length of the packet that was read and *pucBuf* will contain the entire packet (excluding the frame check sequence bytes).

Note:

This function is blocking and will not return until a packet arrives.

Returns:

Returns the negated packet length **-n** if the packet is too large for *pucBuf*, and returns the packet length **n** otherwise.

8.2.2.16 EthernetPacketGetNonBlocking

Receives a packet from the Ethernet controller.

Prototype:

```
long  
EthernetPacketGetNonBlocking(unsigned long ulBase,  
                             unsigned char *pucBuf,  
                             long lBufLen)
```

Parameters:

ulBase is the base address of the controller.

pucBuf is the pointer to the packet buffer.

lBufLen is the maximum number of bytes to be read into the buffer.

Description:

This function reads a packet from the receive FIFO of the controller and places it into *pucBuf*. If no packet is available the function will return immediately. Otherwise, the function will read the entire packet from the receive FIFO. If there are more bytes in the packet than will fit into *pucBuf* (as specified by *lBufLen*), the function will return the negated length of the packet and the buffer will contain *lBufLen* bytes of the packet. Otherwise, the function will return the length of the packet that was read and *pucBuf* will contain the entire packet (excluding the frame check sequence bytes).

This function replaces the original EthernetPacketNonBlockingGet() API and performs the same actions. A macro is provided in `ethernet.h` to map the original API to this API.

Note:

This function will return immediately if no packet is available.

Returns:

Returns **0** if no packet is available, the negated packet length **-n** if the packet is too large for *pucBuf*, and the packet length **n** otherwise.

8.2.2.17 EthernetPacketPut

Waits to send a packet from the Ethernet controller.

Prototype:

```
long  
EthernetPacketPut(unsigned long ulBase,  
                  unsigned char *pucBuf,  
                  long lBufLen)
```

Parameters:

ulBase is the base address of the controller.

pucBuf is the pointer to the packet buffer.

lBufLen is number of bytes in the packet to be transmitted.

Description:

This function writes *lBufLen* bytes of the packet contained in *pucBuf* into the transmit FIFO of the controller and then activates the transmitter for this packet. This function will wait until the transmit FIFO is empty. Once space is available, the function will return once *lBufLen* bytes of the packet have been placed into the FIFO and the transmitter has been started. The function will not wait for the transmission to complete. The function will return the negated *lBufLen* if the length is larger than the space available in the transmit FIFO.

Note:

This function blocks and will wait until space is available for the transmit packet before returning.

Returns:

Returns the negated packet length **-IBufLen** if the packet is too large for FIFO, and the packet length **IBufLen** otherwise.

8.2.2.18 EthernetPacketPutNonBlocking

Sends a packet to the Ethernet controller.

Prototype:

```
long  
EthernetPacketPutNonBlocking(unsigned long ulBase,  
                             unsigned char *pucBuf,  
                             long lBufLen)
```

Parameters:

ulBase is the base address of the controller.

pucBuf is the pointer to the packet buffer.

IBufLen is number of bytes in the packet to be transmitted.

Description:

This function writes *IBufLen* bytes of the packet contained in *pucBuf* into the transmit FIFO of the controller and then activates the transmitter for this packet. If no space is available in the FIFO, the function will return immediately. If space is available, the function will return once *IBufLen* bytes of the packet have been placed into the FIFO and the transmitter has been started. The function will not wait for the transmission to complete. The function will return the negated *IBufLen* if the length is larger than the space available in the transmit FIFO.

This function replaces the original EthernetPacketNonBlockingPut() API and performs the same actions. A macro is provided in `ethernet.h` to map the original API to this API.

Note:

This function does not block and will return immediately if no space is available for the transmit packet.

Returns:

Returns **0** if no space is available in the transmit FIFO, the negated packet length **-IBufLen** if the packet is too large for FIFO, and the packet length **IBufLen** otherwise.

8.2.2.19 EthernetPHYRead

Reads from a PHY register.

Prototype:

```
unsigned long  
EthernetPHYRead(unsigned long ulBase,  
                unsigned char ucRegAddr)
```

Parameters:

ulBase is the base address of the controller.

ucRegAddr is the address of the PHY register to be accessed.

Description:

This function will return the contents of the PHY register specified by *ucRegAddr*.

Returns:

Returns the 16-bit value read from the PHY.

8.2.2.20 EthernetPHYWrite

Writes to the PHY register.

Prototype:

```
void  
EthernetPHYWrite(unsigned long ulBase,  
                 unsigned char ucRegAddr,  
                 unsigned long ulData)
```

Parameters:

ulBase is the base address of the controller.

ucRegAddr is the address of the PHY register to be accessed.

ulData is the data to be written to the PHY register.

Description:

This function will write the *ulData* to the PHY register specified by *ucRegAddr*.

Returns:

None.

8.2.2.21 EthernetSpaceAvail

Checks for packet space available in the Ethernet controller.

Prototype:

```
tBoolean  
EthernetSpaceAvail(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the controller.

Description:

The Ethernet controller's transmit FIFO is designed to support a single packet at a time. After the packet has been written into the FIFO, the transmit request bit must be set to enable the transmission of the packet. Only after the packet has been transmitted can a new packet be written into the FIFO. This function will simply check to see if a packet is in progress. If so, there is no space available in the transmit FIFO.

Returns:

Returns **true** if a space is available in the transmit FIFO, and **false** otherwise.

8.3 Programming Example

The following example shows how to use the this API to initialize the Ethernet controller to transmit and receive packets.

```
unsigned char pucMACAddress[6];
unsigned char pucMyRxPacket[];
unsigned char pucMyTxPacket[];
unsigned long ulMyTxPacketLength;

//
// Initialize the Ethernet controller for operation
//
EthernetInitExpClk(ETH_BASE, SysCtlClockGet());

//
// Configure the Ethernet controller for normal operation
// Enable TX Duplex Mode
// Enable TX Padding
//
EthernetConfigSet(ETH_BASE, (ETH_CFG_TX_DPLXEN | ETH_CFG_TX_PADEN));

//
// Program the MAC Address (01-23-45-67-89-AB)
//
pucMACAddress[0] = 0x01;
pucMACAddress[1] = 0x23;
pucMACAddress[2] = 0x45;
pucMACAddress[3] = 0x67;
pucMACAddress[4] = 0x89;
pucMACAddress[5] = 0xAB;
EthernetMACAddrSet(ETH_BASE, pucMACAddress);

//
// Enable the Ethernet controller
//
EthernetEnable(ETH_BASE);

//
// Send a packet.
// (assume that the packet has been filled in appropriately elsewhere
// in the code).
//
EthernetPacketPut(ETH_BASE, pucMyTxPacket, ulMyTxPacketLength);

//
// Wait for a packet to come in.
//
EthernetPacketGet(ETH_BASE, pucMyRxPacket, sizeof(pucMyRxPacket));
```

9 Flash

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9.1 Introduction

The flash API provides a set of functions for dealing with the on-chip flash. Functions are provided to program and erase the flash, configure the flash protection, and handle the flash interrupt.

The flash is organized as a set of 1 kB blocks that can be individually erased. Erasing a block causes the entire contents of the block to be reset to all ones. These blocks are paired into a set of 2 kB blocks that can be individually protected. The blocks can be marked as read-only or execute-only, providing differing levels of code protection. Read-only blocks cannot be erased or programmed, protecting the contents of those blocks from being modified. Execute-only blocks cannot be erased or programmed, and can only be read by the processor instruction fetch mechanism, protecting the contents of those blocks from being read by either the processor or by debuggers.

The flash can be programmed on a word-by-word basis. Programming causes 1 bits to become 0 bits (where appropriate); because of this, a word can be repeatedly programmed so long as each programming operation only requires changing 1 bits to 0 bits.

The timing for the flash is automatically handled by the flash controller. In order to do this, the flash controller must know the clock rate of the system in order to be able to time the number of micro-seconds certain signals are asserted. The number of clock cycles per micro-second must be provided to the flash controller for it to accomplish this timing.

The flash controller has the ability to generate an interrupt when an invalid access is attempted (such as reading from execute-only flash). This can be used to validate the operation of a program; the interrupt will keep invalid accesses from being silently ignored, hiding potential bugs. The flash protection can be applied without being permanently enabled; this, along with the interrupt, allows the program to be debugged before the flash protection is permanently applied to the device (which is a non-reversible operation). An interrupt can also be generated when an erase or programming operation has completed.

Depending upon the member of the Stellaris family used, the amount of available flash is 8 KB, 16 KB, 32 KB, 64 KB, 96 KB, 128 KB, or 256 KB.

This driver is contained in `src/flash.c`, with `src/flash.h` containing the API definitions for use by applications.

9.2 API Functions

Functions

- long [FlashErase](#) (unsigned long ulAddress)
- void [FlashIntClear](#) (unsigned long ulIntFlags)
- void [FlashIntDisable](#) (unsigned long ulIntFlags)

- void [FlashIntEnable](#) (unsigned long ulIntFlags)
- unsigned long [FlashIntGetStatus](#) (tBoolean bMasked)
- void [FlashIntRegister](#) (void (*pfnHandler)(void))
- void [FlashIntUnregister](#) (void)
- long [FlashProgram](#) (unsigned long *pulData, unsigned long ulAddress, unsigned long ulCount)
- tFlashProtection [FlashProtectGet](#) (unsigned long ulAddress)
- long [FlashProtectSave](#) (void)
- long [FlashProtectSet](#) (unsigned long ulAddress, tFlashProtection eProtect)
- unsigned long [FlashUsecGet](#) (void)
- void [FlashUsecSet](#) (unsigned long ulClocks)
- long [FlashUserGet](#) (unsigned long *pulUser0, unsigned long *pulUser1)
- long [FlashUserSave](#) (void)
- long [FlashUserSet](#) (unsigned long ulUser0, unsigned long ulUser1)

9.2.1 Detailed Description

The flash API is broken into three groups of functions: those that deal with programming the flash, those that deal with flash protection, and those that deal with interrupt handling.

Flash programming is managed with [FlashErase\(\)](#), [FlashProgram\(\)](#), [FlashUsecGet\(\)](#), and [FlashUsecSet\(\)](#).

Flash protection is managed with [FlashProtectGet\(\)](#), [FlashProtectSet\(\)](#), and [FlashProtectSave\(\)](#).

Interrupt handling is managed with [FlashIntRegister\(\)](#), [FlashIntUnregister\(\)](#), [FlashIntEnable\(\)](#), [FlashIntDisable\(\)](#), [FlashIntGetStatus\(\)](#), and [FlashIntClear\(\)](#).

9.2.2 Function Documentation

9.2.2.1 FlashErase

Erases a block of flash.

Prototype:

```
long  
FlashErase(unsigned long ulAddress)
```

Parameters:

ulAddress is the start address of the flash block to be erased.

Description:

This function will erase a 1 kB block of the on-chip flash. After erasing, the block will be filled with 0xFF bytes. Read-only and execute-only blocks cannot be erased.

This function will not return until the block has been erased.

Returns:

Returns 0 on success, or -1 if an invalid block address was specified or the block is write-protected.

9.2.2.2 FlashIntClear

Clears flash controller interrupt sources.

Prototype:

```
void  
FlashIntClear(unsigned long ulIntFlags)
```

Parameters:

ulIntFlags is the bit mask of the interrupt sources to be cleared. Can be any of the **FLASH_FCMISC_PROGRAM** or **FLASH_FCMISC_AMISC** values.

Description:

The specified flash controller interrupt sources are cleared, so that they no longer assert. This must be done in the interrupt handler to keep it from being called again immediately upon exit.

Returns:

None.

9.2.2.3 FlashIntDisable

Disables individual flash controller interrupt sources.

Prototype:

```
void  
FlashIntDisable(unsigned long ulIntFlags)
```

Parameters:

ulIntFlags is a bit mask of the interrupt sources to be disabled. Can be any of the **FLASH_FCIM_PROGRAM** or **FLASH_FCIM_ACCESS** values.

Description:

Disables the indicated flash controller interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor.

Returns:

None.

9.2.2.4 FlashIntEnable

Enables individual flash controller interrupt sources.

Prototype:

```
void  
FlashIntEnable(unsigned long ulIntFlags)
```

Parameters:

ulIntFlags is a bit mask of the interrupt sources to be enabled. Can be any of the **FLASH_FCIM_PROGRAM** or **FLASH_FCIM_ACCESS** values.

Description:

Enables the indicated flash controller interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor.

Returns:

None.

9.2.2.5 FlashIntGetStatus

Gets the current interrupt status.

Prototype:

```
unsigned long  
FlashIntGetStatus (tBoolean bMasked)
```

Parameters:

bMasked is false if the raw interrupt status is required and true if the masked interrupt status is required.

Description:

This returns the interrupt status for the flash controller. Either the raw interrupt status or the status of interrupts that are allowed to reflect to the processor can be returned.

Returns:

The current interrupt status, enumerated as a bit field of **FLASH_FCMISC_PROGRAM** and **FLASH_FCMISC_AMISC**.

9.2.2.6 FlashIntRegister

Registers an interrupt handler for the flash interrupt.

Prototype:

```
void  
FlashIntRegister (void (*pfnHandler) (void))
```

Parameters:

pfnHandler is a pointer to the function to be called when the flash interrupt occurs.

Description:

This sets the handler to be called when the flash interrupt occurs. The flash controller can generate an interrupt when an invalid flash access occurs, such as trying to program or erase a read-only block, or trying to read from an execute-only block. It can also generate an interrupt when a program or erase operation has completed. The interrupt will be automatically enabled when the handler is registered.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

9.2.2.7 FlashIntUnregister

Unregisters the interrupt handler for the flash interrupt.

Prototype:

```
void  
FlashIntUnregister(void)
```

Description:

This function will clear the handler to be called when the flash interrupt occurs. This will also mask off the interrupt in the interrupt controller so that the interrupt handler is no longer called.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

9.2.2.8 FlashProgram

Programs flash.

Prototype:

```
long  
FlashProgram(unsigned long *pulData,  
              unsigned long ulAddress,  
              unsigned long ulCount)
```

Parameters:

pulData is a pointer to the data to be programmed.

ulAddress is the starting address in flash to be programmed. Must be a multiple of four.

ulCount is the number of bytes to be programmed. Must be a multiple of four.

Description:

This function will program a sequence of words into the on-chip flash. Programming each location consists of the result of an AND operation of the new data and the existing data; in other words bits that contain 1 can remain 1 or be changed to 0, but bits that are 0 cannot be changed to 1. Therefore, a word can be programmed multiple times as long as these rules are followed; if a program operation attempts to change a 0 bit to a 1 bit, that bit will not have its value changed.

Since the flash is programmed one word at a time, the starting address and byte count must both be multiples of four. It is up to the caller to verify the programmed contents, if such verification is required.

This function will not return until the data has been programmed.

Returns:

Returns 0 on success, or -1 if a programming error is encountered.

9.2.2.9 FlashProtectGet

Gets the protection setting for a block of flash.

Prototype:

```
tFlashProtection  
FlashProtectGet(unsigned long ulAddress)
```

Parameters:

ulAddress is the start address of the flash block to be queried.

Description:

This function will get the current protection for the specified 2 kB block of flash. Each block can be read/write, read-only, or execute-only. Read/write blocks can be read, executed, erased, and programmed. Read-only blocks can be read and executed. Execute-only blocks can only be executed; processor and debugger data reads are not allowed.

Returns:

Returns the protection setting for this block. See [FlashProtectSet\(\)](#) for possible values.

9.2.2.10 FlashProtectSave

Saves the flash protection settings.

Prototype:

```
long  
FlashProtectSave(void)
```

Description:

This function will make the currently programmed flash protection settings permanent. This is a non-reversible operation; a chip reset or power cycle will not change the flash protection.

This function will not return until the protection has been saved.

Returns:

Returns 0 on success, or -1 if a hardware error is encountered.

9.2.2.11 FlashProtectSet

Sets the protection setting for a block of flash.

Prototype:

```
long  
FlashProtectSet(unsigned long ulAddress,  
                tFlashProtection eProtect)
```

Parameters:

ulAddress is the start address of the flash block to be protected.

eProtect is the protection to be applied to the block. Can be one of **FlashReadWrite**, **FlashReadOnly**, or **FlashExecuteOnly**.

Description:

This function will set the protection for the specified 2 kB block of flash. Blocks which are read/write can be made read-only or execute-only. Blocks which are read-only can be made execute-only. Blocks which are execute-only cannot have their protection modified. Attempts to make the block protection less stringent (that is, read-only to read/write) will result in a failure (and be prevented by the hardware).

Changes to the flash protection are maintained only until the next reset. This allows the application to be executed in the desired flash protection environment to check for inappropriate flash access (via the flash interrupt). To make the flash protection permanent, use the [FlashProtectSave\(\)](#) function.

Returns:

Returns 0 on success, or -1 if an invalid address or an invalid protection was specified.

9.2.2.12 FlashUsecGet

Gets the number of processor clocks per micro-second.

Prototype:

```
unsigned long  
FlashUsecGet(void)
```

Description:

This function returns the number of clocks per micro-second, as presently known by the flash controller.

Returns:

Returns the number of processor clocks per micro-second.

9.2.2.13 FlashUsecSet

Sets the number of processor clocks per micro-second.

Prototype:

```
void  
FlashUsecSet(unsigned long ulClocks)
```

Parameters:

ulClocks is the number of processor clocks per micro-second.

Description:

This function is used to tell the flash controller the number of processor clocks per micro-second. This value must be programmed correctly or the flash most likely will not program correctly; it has no affect on reading flash.

Returns:

None.

9.2.2.14 FlashUserGet

Gets the User Registers

Prototype:

```
long  
FlashUserGet(unsigned long *pulUser0,  
             unsigned long *pulUser1)
```

Parameters:

pulUser0 is a pointer to the location to store USER Register 0.

pulUser1 is a pointer to the location to store USER Register 1.

Description:

This function will read the contents of User Registers (0 and 1), and store them in the specified locations.

Returns:

Returns 0 on success, or -1 if a hardware error is encountered.

9.2.2.15 FlashUserSave

Saves the User Registers

Prototype:

```
long  
FlashUserSave(void)
```

Description:

This function will make the currently programmed User register settings permanent. This is a non-reversible operation; a chip reset or power cycle will not change this setting.

This function will not return until the protection has been saved.

Returns:

Returns 0 on success, or -1 if a hardware error is encountered.

9.2.2.16 FlashUserSet

Sets the User Registers

Prototype:

```
long  
FlashUserSet(unsigned long ulUser0,  
             unsigned long ulUser1)
```

Parameters:

ulUser0 is the value to store in USER Register 0.

ulUser1 is the value to store in USER Register 1.

Description:

This function will set the contents of the User Registers (0 and 1) to the specified values.

Returns:

Returns 0 on success, or -1 if a hardware error is encountered.

9.3 Programming Example

The following example shows how to use the flash API to erase a block of the flash and program a few words.

```
unsigned long pulData[2];

//
// Set the uSec value to 20, indicating that the processor is running at
// 20 MHz.
//
FlashUsecSet(20);

//
// Erase a block of the flash.
//
FlashErase(0x800);

//
// Program some data into the newly erased block of the flash.
//
pulData[0] = 0x12345678;
pulData[1] = 0x56789abc;
FlashProgram(pulData, 0x800, sizeof(pulData));
```


10 GPIO

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10.1 Introduction

The GPIO module provides control for up to eight independent GPIO pins (the actual number present depend upon the GPIO port and part number). Each pin has the following capabilities:

- Can be configured as an input or an output. On reset, they default to being an input.
- In input mode, can generate interrupts on high level, low level, rising edge, falling edge, or both edges.
- In output mode, can be configured for 2 mA, 4 mA, or 8 mA drive strength. The 8 mA drive strength configuration has optional slew rate control to limit the rise and fall times of the signal. On reset, they default to 2 mA drive strength.
- Optional weak pull-up or pull-down resistors. On reset, they default to a weak pull-up.
- Optional open-drain operation. On reset, they default to standard push/pull operation.
- Can be configured to be a GPIO or a peripheral pin. On reset, they default to being GPIOs. Note that not all pins on all parts have peripheral functions, in which case the pin is only useful as a GPIO (that is, when configured for peripheral function the pin will not do anything useful).

Most of the GPIO functions can operate on more than one GPIO pin (within a single module) at a time. The *ucPins* parameter to these functions is used to specify the pins that are affected; the GPIO pins whose corresponding bits in this parameter that are set will be affected (where pin 0 is in bit 0, pin 1 in bit 1, and so on). For example, if *ucPins* is 0x09, then pins 0 and 3 will be affected by the function.

This is most useful for the [GPiOPinRead\(\)](#) and [GPiOPinWrite\(\)](#) functions; a read will return only the value of the requested pins (with the other pin values masked out) and a write will affect the requested pins simultaneously (that is, the state of multiple GPIO pins can be changed at the same time). This data masking for the GPIO pin state occurs in the hardware; a single read or write is issued to the hardware, which interprets some of the address bits as an indication of the GPIO pins to operate upon (and therefore the ones to not affect). See the part data sheet for details of the GPIO data register address-based bit masking.

For functions that have a *ucPin* (singular) parameter, only a single pin is affected by the function. In this case, this value specifies the pin number (that is, 0 through 7).

This driver is contained in `src/gpio.c`, with `src/gpio.h` containing the API definitions for use by applications.

10.2 API Functions

Functions

- unsigned long [GPiODirModeGet](#) (unsigned long ulPort, unsigned char ucPin)

- void [GPIODirModeSet](#) (unsigned long ulPort, unsigned char ucPins, unsigned long ulPinIO)
- unsigned long [GPIOIntTypeGet](#) (unsigned long ulPort, unsigned char ucPin)
- void [GPIOIntTypeSet](#) (unsigned long ulPort, unsigned char ucPins, unsigned long ulIntType)
- void [GPIOPadConfigGet](#) (unsigned long ulPort, unsigned char ucPin, unsigned long *pulStrength, unsigned long *pulPinType)
- void [GPIOPadConfigSet](#) (unsigned long ulPort, unsigned char ucPins, unsigned long ulStrength, unsigned long ulPinType)
- void [GPIOPinIntClear](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinIntDisable](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinIntEnable](#) (unsigned long ulPort, unsigned char ucPins)
- long [GPIOPinIntStatus](#) (unsigned long ulPort, tBoolean bMasked)
- long [GPIOPinRead](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinTypeCAN](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinTypeComparator](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinTypeGPIOInput](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinTypeGPIOOutput](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinTypeGPIOOutputOD](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinTypeI2C](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinTypePWM](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinTypeQEI](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinTypeSSI](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinTypeTimer](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinTypeUART](#) (unsigned long ulPort, unsigned char ucPins)
- void [GPIOPinWrite](#) (unsigned long ulPort, unsigned char ucPins, unsigned char ucVal)
- void [GPIOPortIntRegister](#) (unsigned long ulPort, void (*pfnIntHandler)(void))
- void [GPIOPortIntUnregister](#) (unsigned long ulPort)

10.2.1 Detailed Description

The GPIO API is broken into three groups of functions: those that deal with configuring the GPIO pins, those that deal with interrupts, and those that access the pin value.

The GPIO pins are configured with [GPIODirModeSet\(\)](#) and [GPIOPadConfigSet\(\)](#). The configuration can be read back with [GPIODirModeGet\(\)](#) and [GPIOPadConfigGet\(\)](#). There are also convenience functions for configuring the pin in the required or recommended configuration for a particular peripheral; these are [GPIOPinTypeCAN\(\)](#), [GPIOPinTypeComparator\(\)](#), [GPIOPinTypeGPIOInput\(\)](#), [GPIOPinTypeGPIOOutput\(\)](#), [GPIOPinTypeGPIOOutputOD\(\)](#), [GPIOPinTypeI2C\(\)](#), [GPIOPinTypePWM\(\)](#), [GPIOPinTypeQEI\(\)](#), [GPIOPinTypeSSI\(\)](#), [GPIOPinTypeTimer\(\)](#), and [GPIOPinTypeUART\(\)](#).

The GPIO interrupts are handled with [GPIOIntTypeSet\(\)](#), [GPIOIntTypeGet\(\)](#), [GPIOPinIntEnable\(\)](#), [GPIOPinIntDisable\(\)](#), [GPIOPinIntStatus\(\)](#), [GPIOPinIntClear\(\)](#), [GPIOPortIntRegister\(\)](#), and [GPIOPortIntUnregister\(\)](#).

The GPIO pin state is accessed with [GPIOPinRead\(\)](#) and [GPIOPinWrite\(\)](#).

10.2.2 Function Documentation

10.2.2.1 GPIODirModeGet

Gets the direction and mode of a pin.

Prototype:

```
unsigned long
GPIODirModeGet(unsigned long ulPort,
                unsigned char ucPin)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPin is the pin number.

Description:

This function gets the direction and control mode for a specified pin on the selected GPIO port. The pin can be configured as either an input or output under software control, or it can be under hardware control. The type of control and direction are returned as an enumerated data type.

Returns:

Returns one of the enumerated data types described for [GPIODirModeSet\(\)](#).

10.2.2.2 GPIODirModeSet

Sets the direction and mode of the specified pin(s).

Prototype:

```
void
GPIODirModeSet(unsigned long ulPort,
                unsigned char ucPins,
                unsigned long ulPinIO)
```

Parameters:

ulPort is the base address of the GPIO port

ucPins is the bit-packed representation of the pin(s).

ulPinIO is the pin direction and/or mode.

Description:

This function will set the specified pin(s) on the selected GPIO port as either an input or output under software control, or it will set the pin to be under hardware control.

The parameter *ulPinIO* is an enumerated data type that can be one of the following values:

- **GPIO_DIR_MODE_IN**
- **GPIO_DIR_MODE_OUT**
- **GPIO_DIR_MODE_HW**

where **GPIO_DIR_MODE_IN** specifies that the pin will be programmed as a software controlled input, **GPIO_DIR_MODE_OUT** specifies that the pin will be programmed as a software controlled output, and **GPIO_DIR_MODE_HW** specifies that the pin will be placed under hardware control.

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

10.2.2.3 GPIOIntTypeGet

Gets the interrupt type for a pin.

Prototype:

```
unsigned long
GPIOIntTypeGet(unsigned long ulPort,
               unsigned char ucPin)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPin is the pin number.

Description:

This function gets the interrupt type for a specified pin on the selected GPIO port. The pin can be configured as a falling edge, rising edge, or both edge detected interrupt, or it can be configured as a low level or high level detected interrupt. The type of interrupt detection mechanism is returned as an enumerated data type.

Returns:

Returns one of the enumerated data types described for [GPIOIntTypeSet\(\)](#).

10.2.2.4 GPIOIntTypeSet

Sets the interrupt type for the specified pin(s).

Prototype:

```
void
GPIOIntTypeSet(unsigned long ulPort,
               unsigned char ucPins,
               unsigned long ulIntType)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

ulIntType specifies the type of interrupt trigger mechanism.

Description:

This function sets up the various interrupt trigger mechanisms for the specified pin(s) on the selected GPIO port.

The parameter *ulIntType* is an enumerated data type that can be one of the following values:

- **GPIO_FALLING_EDGE**

- **GPIO_RISING_EDGE**
- **GPIO_BOTH_EDGES**
- **GPIO_LOW_LEVEL**
- **GPIO_HIGH_LEVEL**

where the different values describe the interrupt detection mechanism (edge or level) and the particular triggering event (falling, rising, or both edges for edge detect, low or high for level detect).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Note:

In order to avoid any spurious interrupts, the user must ensure that the GPIO inputs remain stable for the duration of this function.

Returns:

None.

10.2.2.5 GPIOPadConfigGet

Gets the pad configuration for a pin.

Prototype:

```
void  
GPIOPadConfigGet(unsigned long ulPort,  
                 unsigned char ucPin,  
                 unsigned long *pulStrength,  
                 unsigned long *pulPinType)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPin is the pin number.

pulStrength is a pointer to storage for the output drive strength.

pulPinType is a pointer to storage for the output drive type.

Description:

This function gets the pad configuration for a specified pin on the selected GPIO port. The values returned in *pulStrength* and *pulPinType* correspond to the values used in [GPIOPadConfigSet\(\)](#). This function also works for pin(s) configured as input pin(s); however, the only meaningful data returned is whether the pin is terminated with a pull-up or down resistor.

Returns:

None

10.2.2.6 GPIOPadConfigSet

Sets the pad configuration for the specified pin(s).

Prototype:

```
void  
GPIOPadConfigSet(unsigned long ulPort,  
                 unsigned char ucPins,  
                 unsigned long ulStrength,  
                 unsigned long ulPinType)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

ulStrength specifies the output drive strength.

ulPinType specifies the pin type.

Description:

This function sets the drive strength and type for the specified pin(s) on the selected GPIO port. For pin(s) configured as input ports, the pad is configured as requested, but the only real effect on the input is the configuration of the pull-up or pull-down termination.

The parameter *ulStrength* can be one of the following values:

- **GPIO_STRENGTH_2MA**
- **GPIO_STRENGTH_4MA**
- **GPIO_STRENGTH_8MA**
- **GPIO_STRENGTH_8MA_SC**

where **GPIO_STRENGTH_xMA** specifies either 2, 4, or 8 mA output drive strength, and **GPIO_OUT_STRENGTH_8MA_SC** specifies 8 mA output drive with slew control.

The parameter *ulPinType* can be one of the following values:

- **GPIO_PIN_TYPE_STD**
- **GPIO_PIN_TYPE_STD_WPU**
- **GPIO_PIN_TYPE_STD_WPD**
- **GPIO_PIN_TYPE_OD**
- **GPIO_PIN_TYPE_OD_WPU**
- **GPIO_PIN_TYPE_OD_WPD**
- **GPIO_PIN_TYPE_ANALOG**

where **GPIO_PIN_TYPE_STD*** specifies a push-pull pin, **GPIO_PIN_TYPE_OD*** specifies an open-drain pin, ***_WPU** specifies a weak pull-up, ***_WPD** specifies a weak pull-down, and **GPIO_PIN_TYPE_ANALOG** specifies an analog input (for the comparators).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

10.2.2.7 GPIOPinIntClear

Clears the interrupt for the specified pin(s).

Prototype:

```
void  
GPIOPinIntClear(unsigned long ulPort,  
                unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

Clears the interrupt for the specified pin(s).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

10.2.2.8 GPIOPinIntDisable

Disables interrupts for the specified pin(s).

Prototype:

```
void  
GPIOPinIntDisable(unsigned long ulPort,  
                  unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

Masks the interrupt for the specified pin(s).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

10.2.2.9 GPIOPinIntEnable

Enables interrupts for the specified pin(s).

Prototype:

```
void  
GPIOPinIntEnable(unsigned long ulPort,  
                 unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

Unmasks the interrupt for the specified pin(s).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

10.2.2.10 GPIOPinIntStatus

Gets interrupt status for the specified GPIO port.

Prototype:

```
long
GPIOPinIntStatus(unsigned long ulPort,
                  tBoolean bMasked)
```

Parameters:

ulPort is the base address of the GPIO port.

bMasked specifies whether masked or raw interrupt status is returned.

Description:

If ***bMasked*** is set as **true**, then the masked interrupt status is returned; otherwise, the raw interrupt status will be returned.

Returns:

Returns a bit-packed byte, where each bit that is set identifies an active masked or raw interrupt, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on. Bits 31:8 should be ignored.

10.2.2.11 GPIOPinRead

Reads the values present of the specified pin(s).

Prototype:

```
long
GPIOPinRead(unsigned long ulPort,
             unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

The values at the specified pin(s) are read, as specified by *ucPins*. Values are returned for both input and output pin(s), and the value for pin(s) that are not specified by *ucPins* are set to 0.

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

Returns a bit-packed byte providing the state of the specified pin, where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on. Any bit that is not specified by *ucPins* is returned as a 0. Bits 31:8 should be ignored.

10.2.2.12 GPIOPinTypeCAN

Configures pin(s) for use as a CAN device.

Prototype:

```
void  
GPIOPinTypeCAN(unsigned long ulPort,  
                unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

The CAN pins must be properly configured for the CAN peripherals to function correctly. This function provides a typical configuration for those pin(s); other configurations may work as well depending upon the board setup (for example, using the on-chip pull-ups).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Note:

This cannot be used to turn any pin into a CAN pin; it only configures a CAN pin for proper operation.

Returns:

None.

10.2.2.13 GPIOPinTypeComparator

Configures pin(s) for use as an analog comparator input.

Prototype:

```
void  
GPIOPinTypeComparator(unsigned long ulPort,  
                       unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

The analog comparator input pins must be properly configured for the analog comparator to function correctly. This function provides the proper configuration for those pin(s).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Note:

This cannot be used to turn any pin into an analog comparator input; it only configures an analog comparator pin for proper operation.

Returns:

None.

10.2.2.14 GPIOPinTypeGPIOInput

Configures pin(s) for use as GPIO inputs.

Prototype:

```
void  
GPIOPinTypeGPIOInput(unsigned long ulPort,  
                      unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

The GPIO pins must be properly configured in order to function correctly as GPIO inputs; this is especially true of Fury-class devices where the digital input enable is turned off by default. This function provides the proper configuration for those pin(s).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

10.2.2.15 GPIOPinTypeGPIOOutput

Configures pin(s) for use as GPIO outputs.

Prototype:

```
void  
GPIOPinTypeGPIOOutput(unsigned long ulPort,  
                      unsigned char ucPins)
```


Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

The GPIO pins must be properly configured in order to function correctly as GPIO outputs; this is especially true of Fury-class devices where the digital input enable is turned off by default. This function provides the proper configuration for those pin(s).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

10.2.2.16 GPIOPinTypeGPIOOutputOD

Configures pin(s) for use as GPIO open drain outputs.

Prototype:

```
void  
GPIOPinTypeGPIOOutputOD(unsigned long ulPort,  
                          unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

The GPIO pins must be properly configured in order to function correctly as GPIO outputs; this is especially true of Fury-class devices where the digital input enable is turned off by default. This function provides the proper configuration for those pin(s).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:

None.

10.2.2.17 GPIOPinTypeI2C

Configures pin(s) for use by the I2C peripheral.

Prototype:

```
void  
GPIOPinTypeI2C(unsigned long ulPort,  
                unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

The I2C pins must be properly configured for the I2C peripheral to function correctly. This function provides the proper configuration for those pin(s).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Note:

This cannot be used to turn any pin into an I2C pin; it only configures an I2C pin for proper operation.

Returns:

None.

10.2.2.18 GPIOPinTypePWM

Configures pin(s) for use by the PWM peripheral.

Prototype:

```
void  
GPIOPinTypePWM(unsigned long ulPort,  
                unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

The PWM pins must be properly configured for the PWM peripheral to function correctly. This function provides a typical configuration for those pin(s); other configurations may work as well depending upon the board setup (for example, using the on-chip pull-ups).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Note:

This cannot be used to turn any pin into a PWM pin; it only configures a PWM pin for proper operation.

Returns:

None.

10.2.2.19 GPIOPinTypeQEI

Configures pin(s) for use by the QEI peripheral.

Prototype:

```
void  
GPIOPinTypeQEI(unsigned long ulPort,  
               unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

The QEI pins must be properly configured for the QEI peripheral to function correctly. This function provides a typical configuration for those pin(s); other configurations may work as well depending upon the board setup (for example, not using the on-chip pull-ups).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Note:

This cannot be used to turn any pin into a QEI pin; it only configures a QEI pin for proper operation.

Returns:

None.

10.2.2.20 GPIOPinTypeSSI

Configures pin(s) for use by the SSI peripheral.

Prototype:

```
void  
GPIOPinTypeSSI(unsigned long ulPort,  
               unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

The SSI pins must be properly configured for the SSI peripheral to function correctly. This function provides a typical configuration for those pin(s); other configurations may work as well depending upon the board setup (for example, using the on-chip pull-ups).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Note:

This cannot be used to turn any pin into a SSI pin; it only configures a SSI pin for proper operation.

Returns:

None.

10.2.2.21 GPIOPinTypeTimer

Configures pin(s) for use by the Timer peripheral.

Prototype:

```
void  
GPIOPinTypeTimer(unsigned long ulPort,  
                  unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

The CCP pins must be properly configured for the timer peripheral to function correctly. This function provides a typical configuration for those pin(s); other configurations may work as well depending upon the board setup (for example, using the on-chip pull-ups).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Note:

This cannot be used to turn any pin into a timer pin; it only configures a timer pin for proper operation.

Returns:

None.

10.2.2.22 GPIOPinTypeUART

Configures pin(s) for use by the UART peripheral.

Prototype:

```
void  
GPIOPinTypeUART(unsigned long ulPort,  
                 unsigned char ucPins)
```

Parameters:

ulPort is the base address of the GPIO port.

ucPins is the bit-packed representation of the pin(s).

Description:

The UART pins must be properly configured for the UART peripheral to function correctly. This function provides a typical configuration for those pin(s); other configurations may work as well depending upon the board setup (for example, using the on-chip pull-ups).

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Note:

This cannot be used to turn any pin into a UART pin; it only configures a UART pin for proper operation.

Returns:
None.

10.2.2.23 GPIOPinWrite

Writes a value to the specified pin(s).

Prototype:

```
void
GPIOPinWrite(unsigned long ulPort,
              unsigned char ucPins,
              unsigned char ucVal)
```

Parameters:
ulPort is the base address of the GPIO port.
ucPins is the bit-packed representation of the pin(s).
ucVal is the value to write to the pin(s).

Description:
Writes the corresponding bit values to the output pin(s) specified by *ucPins*. Writing to a pin configured as an input pin has no effect.

The pin(s) are specified using a bit-packed byte, where each bit that is set identifies the pin to be accessed, and where bit 0 of the byte represents GPIO port pin 0, bit 1 represents GPIO port pin 1, and so on.

Returns:
None.

10.2.2.24 GPIOPortIntRegister

Registers an interrupt handler for a GPIO port.

Prototype:

```
void
GPIOPortIntRegister(unsigned long ulPort,
                    void (*pfnIntHandler)(void))
```

Parameters:
ulPort is the base address of the GPIO port.
pfnIntHandler is a pointer to the GPIO port interrupt handling function.

Description:
This function will ensure that the interrupt handler specified by *pfnIntHandler* is called when an interrupt is detected from the selected GPIO port. This function will also enable the corresponding GPIO interrupt in the interrupt controller; individual pin interrupts and interrupt sources must be enabled with [GPIOPinIntEnable\(\)](#).

See also:
[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:
None.

10.2.2.25 GPIOPortIntUnregister

Removes an interrupt handler for a GPIO port.

Prototype:
`void
GPIOPortIntUnregister(unsigned long ulPort)`

Parameters:
ulPort is the base address of the GPIO port.

Description:
This function will unregister the interrupt handler for the specified GPIO port. This function will also disable the corresponding GPIO port interrupt in the interrupt controller; individual GPIO interrupts and interrupt sources must be disabled with [GPIOPinIntDisable\(\)](#).

See also:
[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:
None.

10.3 Programming Example

The following example shows how to use the GPIO API to initialize the GPIO, enable interrupts, read data from pins, and write data to pins.

```
int iVal;  
  
//  
// Register the port-level interrupt handler. This handler is the  
// first level interrupt handler for all the pin interrupts.  
//  
GPIOPortIntRegister(GPIO_PORTA_BASE, PortAIntHandler);  
  
//  
// Initialize the GPIO pin configuration.  
//  
// Set pins 2, 4, and 5 as input, SW controlled.  
//  
GPIOPinTypeGPIOInput(GPIO_PORTA_BASE,  
                      GPIO_PIN_2 | GPIO_PIN_4 | GPIO_PIN_5);  
  
//  
// Set pins 0 and 3 as output, SW controlled.  
//  
GPIOPinTypeGPIOOutput(GPIO_PORTA_BASE, GPIO_PIN_0 | GPIO_PIN_3);  
  
//  
// Make pins 2 and 4 rising edge triggered interrupts.  
//
```

```
GPIOIntTypeSet(GPIO_PORTA_BASE, GPIO_PIN_2 | GPIO_PIN_4, GPIO_RISING_EDGE);

//
// Make pin 5 high level triggered interrupts.
//
GPIOIntTypeSet(GPIO_PORTA_BASE, GPIO_PIN_5, GPIO_HIGH_LEVEL);

//
// Read some pins.
//
iVal = GPIOPinRead(GPIO_PORTA_BASE,
                   (GPIO_PIN_0 | GPIO_PIN_2 | GPIO_PIN_3 |
                    GPIO_PIN_4 | GPIO_PIN_5));

//
// Write some pins. Even though pins 2, 4, and 5 are specified, those
// pins are unaffected by this write since they are configured as inputs.
// At the end of this write, pin 0 will be a 0, and pin 3 will be a 1.
//
GPIOPinWrite(GPIO_PORTA_BASE,
             (GPIO_PIN_0 | GPIO_PIN_2 | GPIO_PIN_3 |
              GPIO_PIN_4 | GPIO_PIN_5),
             0xF4);

//
// Enable the pin interrupts.
//
GPIOPinIntEnable(GPIO_PORTA_BASE, GPIO_PIN_2 | GPIO_PIN_4 | GPIO_PIN_5);
```


11 Hibernation Module

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11.1 Introduction

The Hibernate API provides a set of functions for using the Hibernation module on the Stellaris microcontroller. The Hibernation module allows the software application to cause power to be removed from the microcontroller, and then be powered on later based on specific time or a signal on the external **WAKE** pin. The API provides functions to configure wake conditions, manage interrupts, read status, save and restore program state information, and request hibernation mode.

Some of the features of the Hibernation module are:

- 32-bit real time clock
- Trim register for fine tuning the RTC rate
- Two RTC match registers for generating RTC events
- External **WAKE** pin to initiate a wake-up
- Low-battery detection
- 64 32-bit words of non-volatile memory
- Programmable interrupts for hibernation events

This driver is contained in `src/hibernate.c`, with `src/hibernate.h` containing the API definitions for use by applications.

11.2 API Functions

Functions

- void [HibernateClockSelect](#) (unsigned long ulClockInput)
- void [HibernateDataGet](#) (unsigned long *pulData, unsigned long ulCount)
- void [HibernateDataSet](#) (unsigned long *pulData, unsigned long ulCount)
- void [HibernateDisable](#) (void)
- void [HibernateEnableExpClk](#) (unsigned long ulHibClk)
- void [HibernateIntClear](#) (unsigned long ullIntFlags)
- void [HibernateIntDisable](#) (unsigned long ullIntFlags)
- void [HibernateIntEnable](#) (unsigned long ullIntFlags)
- void [HibernateIntRegister](#) (void (*pfnHandler)(void))
- unsigned long [HibernateIntStatus](#) (tBoolean bMasked)
- void [HibernateIntUnregister](#) (void)
- unsigned int [HibernateIsActive](#) (void)
- unsigned long [HibernateLowBatGet](#) (void)

- void [HibernateLowBatSet](#) (unsigned long ulLowBatFlags)
- void [HibernateRequest](#) (void)
- void [HibernateRTCDisable](#) (void)
- void [HibernateRTCEnable](#) (void)
- unsigned long [HibernateRTCGet](#) (void)
- unsigned long [HibernateRTCMatch0Get](#) (void)
- void [HibernateRTCMatch0Set](#) (unsigned long ulMatch)
- unsigned long [HibernateRTCMatch1Get](#) (void)
- void [HibernateRTCMatch1Set](#) (unsigned long ulMatch)
- void [HibernateRTCSet](#) (unsigned long ulRTCValue)
- unsigned long [HibernateRTCTrimGet](#) (void)
- void [HibernateRTCTrimSet](#) (unsigned long ulTrim)
- unsigned long [HibernateWakeGet](#) (void)
- void [HibernateWakeSet](#) (unsigned long ulWakeFlags)

11.2.1 Detailed Description

The Hibernation module must be enabled before it can be used. Use the [HibernateEnableExpClk\(\)](#) function to enable it. If a crystal is used for the clock source, then the initializing code must allow time for the crystal to stabilize after calling the [HibernateEnableExpClk\(\)](#) function. Refer to the device data sheet for information about crystal stabilization time. If an oscillator is used, then no delay is necessary. After the module is enabled, the clock source must be configured by calling [HibernateClockSelect\(\)](#).

In order to use the RTC feature of the Hibernation module, the RTC must be enabled by calling [HibernateRTCEnable\(\)](#). It can be later disabled by calling [HibernateRTCDisable\(\)](#). These functions can be called at any time to start and stop the RTC. The RTC value can be read or set by using the [HibernateRTCGet\(\)](#) and [HibernateRTCSet\(\)](#) functions. The two match registers can be read and set by using the [HibernateRTCMatch0Get\(\)](#), [HibernateRTCMatch0Set\(\)](#), [HibernateRTCMatch1Get\(\)](#), and [HibernateRTCMatch1Set\(\)](#) functions. The real-time clock rate can be adjusted by using the trim register. Use the [HibernateRTCTrimGet\(\)](#) and [HibernateRTCTrimSet\(\)](#) functions for this purpose.

Application state information can be stored in the non-volatile memory of the Hibernation module when the processor is powered off. Use the [HibernateDataSet\(\)](#) and [HibernateDataGet\(\)](#) functions to access the non-volatile memory area.

The module can be configured to wake when the external **WAKE** pin is asserted, or when an RTC match occurs, or both. Use the [HibernateWakeSet\(\)](#) function to configure the wake conditions. The present configuration can be read by calling [HibernateWakeGet\(\)](#).

The Hibernation module can detect a low battery and signal the processor. It can also be configured to abort a hibernation request if the battery voltage is too low. Use the [HibernateLowBatSet\(\)](#) and [HibernateLowBatGet\(\)](#) functions to configure this feature.

Several functions are provided for managing interrupts. Use the [HibernateIntRegister\(\)](#) and [HibernateIntUnregister\(\)](#) functions to install or uninstall an interrupt handler into the vector table. Refer to the [IntRegister\(\)](#) function for notes about using the interrupt vector table. The module can generate several different interrupts. Use the [HibernateIntEnable\(\)](#) and [HibernateIntDisable\(\)](#) functions to enable and disable specific interrupt sources. The present interrupt status can be found by calling [HibernateIntStatus\(\)](#). In the interrupt handler, all pending interrupts must be cleared. Use the [HibernateIntClear\(\)](#) function to clear pending interrupts.

Finally, once the module is appropriately configured, the state saved, and the software application is ready to hibernate, call the [HibernateRequest\(\)](#) function. This will initiate the sequence to remove power from the processor. At a power-on reset, the software application can use the [HibernateIsActive\(\)](#) function to determine if the Hibernation module is already active and therefore does not need to be enabled. This can provide a hint to the software that the processor is waking from hibernation instead of a cold start. The software can then use the [HibernateIntStatus\(\)](#) and [HibernateDataGet\(\)](#) functions to discover the cause of the wake and to get the saved system state.

The `HibernateEnable()` API from previous versions of the peripheral driver library has been replaced by the [HibernateEnableExpClk\(\)](#) API. A macro has been provided in `hibernate.h` to map the old API to the new API, allowing existing applications to link and run with the new API. It is recommended that new applications utilize the new API in favor of the old one.

11.2.2 Function Documentation

11.2.2.1 HibernateClockSelect

Selects the clock input for the Hibernation module.

Prototype:

```
void  
HibernateClockSelect(unsigned long ulClockInput)
```

Parameters:

ulClockInput specifies the clock input.

Description:

Configures the clock input for the Hibernation module. The configuration option chosen depends entirely on hardware design. The clock input for the module will either be a 32.768 kHz oscillator or a 4.194304 MHz crystal. The parameter *ulClockFlags* must be one of the following:

- **HIBERNATE_CLOCK_SEL_RAW** - use the raw signal from a 32.768 kHz oscillator.
- **HIBERNATE_CLOCK_SEL_DIV128** - use the crystal input, divided by 128.

Returns:

None.

11.2.2.2 HibernateDataGet

Reads a set of data from the non-volatile memory of the Hibernation module.

Prototype:

```
void  
HibernateDataGet(unsigned long *pulData,  
                 unsigned long ulCount)
```

Parameters:

pulData points to a location where the data that is read from the Hibernation module will be stored.

ulCount is the count of 32-bit words to read.

Description:

Retrieves a set of data from the Hibernation module non-volatile memory that was previously stored with the [HibernateDataSet\(\)](#) function. The caller must ensure that *pulData* points to a large enough memory block to hold all the data that is read from the non-volatile memory.

Returns:

None.

11.2.2.3 HibernateDataSet

Stores data in the non-volatile memory of the Hibernation module.

Prototype:

```
void  
HibernateDataSet(unsigned long *pulData,  
                 unsigned long ulCount)
```

Parameters:

pulData points to the data that the caller wants to store in the memory of the Hibernation module.

ulCount is the count of 32-bit words to store.

Description:

Stores a set of data in the Hibernation module non-volatile memory. This memory will be preserved when the power to the processor is turned off, and can be used to store application state information which will be available when the processor wakes. Up to 64 32-bit words can be stored in the non-volatile memory. The data can be restored by calling the [HibernateDataGet\(\)](#) function.

Returns:

None.

11.2.2.4 HibernateDisable

Disables the Hibernation module for operation.

Prototype:

```
void  
HibernateDisable(void)
```

Description:

Disables the Hibernation module for operation. After this function is called, none of the Hibernation module features are available.

Returns:

None.

11.2.2.5 HibernateEnableExpClk

Enables the Hibernation module for operation.

Prototype:

```
void  
HibernateEnableExpClk(unsigned long ulHibClk)
```

Parameters:

ulHibClk is the rate of the clock supplied to the Hibernation module.

Description:

Enables the Hibernation module for operation. This function should be called before any of the Hibernation module features are used.

The peripheral clock will be the same as the processor clock. This will be the value returned by [SysCtlClockGet\(\)](#), or it can be explicitly hard-coded if it is constant and known (to save the code/execution overhead of a call to [SysCtlClockGet\(\)](#)).

This function replaces the original `HibernateEnable()` API and performs the same actions. A macro is provided in `hibernate.h` to map the original API to this API.

Returns:

None.

11.2.2.6 HibernateIntClear

Clears pending interrupts from the Hibernation module.

Prototype:

```
void  
HibernateIntClear(unsigned long ulIntFlags)
```

Parameters:

ulIntFlags is the bit mask of the interrupts to be cleared.

Description:

Clears the specified interrupt sources. This must be done from within the interrupt handler or else the handler will be called again upon exit.

The *ulIntFlags* parameter has the same definition as the *ulIntFlags* parameter to the [HibernateIntEnable\(\)](#) function.

Returns:

None.

11.2.2.7 HibernateIntDisable

Disables interrupts for the Hibernation module.

Prototype:

```
void  
HibernateIntDisable(unsigned long ulIntFlags)
```

Parameters:

ullntFlags is the bit mask of the interrupts to be disabled.

Description:

Disables the specified interrupt sources from the Hibernation module.

The *ullntFlags* parameter has the same definition as the *ullntFlags* parameter to the [HibernateIntEnable\(\)](#) function.

Returns:

None.

11.2.2.8 HibernateIntEnable

Enables interrupts for the Hibernation module.

Prototype:

```
void  
HibernateIntEnable(unsigned long ulIntFlags)
```

Parameters:

ullntFlags is the bit mask of the interrupts to be enabled.

Description:

Enables the specified interrupt sources from the Hibernation module.

The *ullntFlags* parameter must be the logical OR of any combination of the following:

- **HIBERNATE_INT_PIN_WAKE** - wake from pin interrupt
- **HIBERNATE_INT_LOW_BAT** - low battery interrupt
- **HIBERNATE_INT_RTC_MATCH_0** - RTC match 0 interrupt
- **HIBERNATE_INT_RTC_MATCH_1** - RTC match 1 interrupt

Returns:

None.

11.2.2.9 HibernateIntRegister

Registers an interrupt handler for the Hibernation module interrupt.

Prototype:

```
void  
HibernateIntRegister(void (*pfnHandler)(void))
```

Parameters:

pfnHandler points to the function to be called when a hibernation interrupt occurs.

Description:

Registers the interrupt handler in the system interrupt controller. The interrupt is enabled at the global level, but individual interrupt sources must still be enabled with a call to [HibernateIntEnable\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

11.2.2.10 HibernateIntStatus

Gets the current interrupt status of the Hibernation module.

Prototype:

```
unsigned long  
HibernateIntStatus (tBoolean bMasked)
```

Parameters:

bMasked is false to retrieve the raw interrupt status, and true to retrieve the masked interrupt status.

Description:

Returns the interrupt status of the Hibernation module. The caller can use this to determine the cause of a hibernation interrupt. Either the masked or raw interrupt status can be returned.

Returns:

Returns the interrupt status as a bit field with the values as described in the [HibernateIntEnable\(\)](#) function.

11.2.2.11 HibernateIntUnregister

Unregisters an interrupt handler for the Hibernation module interrupt.

Prototype:

```
void  
HibernateIntUnregister (void)
```

Description:

Unregisters the interrupt handler in the system interrupt controller. The interrupt is disabled at the global level, and the interrupt handler will no longer be called.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

11.2.2.12 HibernateIsActive

Checks to see if the Hibernation module is already powered up.

Prototype:

```
unsigned int  
HibernateIsActive(void)
```

Description:

This function queries the control register to determine if the module is already active. This function can be called at a power-on reset to help determine if the reset is due to a wake from hibernation or a cold start. If the Hibernation module is already active, then it does not need to be re-enabled and its status can be queried immediately.

The software application should also use the [HibernateIntStatus\(\)](#) function to read the raw interrupt status to determine the cause of the wake. The [HibernateDataGet\(\)](#) function can be used to restore state. These combinations of functions can be used by the software to determine if the processor is waking from hibernation and the appropriate action to take as a result.

Returns:

Returns **true** if the module is already active, and **false** if not.

11.2.2.13 HibernateLowBatGet

Gets the currently configured low battery detection behavior.

Prototype:

```
unsigned long  
HibernateLowBatGet(void)
```

Description:

Returns a value representing the currently configured low battery detection behavior. The return value will be one of the following:

- **HIBERNATE_LOW_BAT_DETECT** - detect a low battery condition.
- **HIBERNATE_LOW_BAT_ABORT** - detect a low battery condition, and abort hibernation if low battery is detected.

Returns:

Returns a value indicating the configured low battery detection.

11.2.2.14 HibernateLowBatSet

Configures the low battery detection.

Prototype:

```
void  
HibernateLowBatSet(unsigned long ulLowBatFlags)
```

Parameters:

ulLowBatFlags specifies behavior of low battery detection.

Description:

Enables the low battery detection and whether hibernation is allowed if a low battery is detected. If low battery detection is enabled, then a low battery condition will be indicated in the

raw interrupt status register, and can also trigger an interrupt. Optionally, hibernation can be aborted if a low battery is detected.

The `ulLowBatFlags` parameter is one of the following values:

- **HIBERNATE_LOW_BAT_DETECT** - detect a low battery condition.
- **HIBERNATE_LOW_BAT_ABORT** - detect a low battery condition, and abort hibernation if low battery is detected.

Returns:

None.

11.2.2.15 HibernateRequest

Requests hibernation mode.

Prototype:

```
void  
HibernateRequest(void)
```

Description:

This function requests the Hibernation module to disable the external regulator, thus removing power from the processor and all peripherals. The Hibernation module will remain powered from the battery or auxiliary power supply.

The Hibernation module will re-enable the external regulator when one of the configured wake conditions occurs (such as RTC match or external **WAKE** pin). When the power is restored the processor will go through a normal power-on reset. The processor can retrieve saved state information with the [HibernateDataGet\(\)](#) function. Prior to calling the function to request hibernation mode, the conditions for waking must have already been set by using the [HibernateWakeSet\(\)](#) function.

Note that this function may return because some time may elapse before the power is actually removed, or it may not be removed at all. For this reason, the processor will continue to execute instructions for some time and the caller should be prepared for this function to return. There are various reasons why the power may not be removed. For example, if the [HibernateLowBatSet\(\)](#) function was used to configure an abort if low battery is detected, then the power will not be removed if the battery voltage is too low. There may be other reasons, related to the external circuit design, that a request for hibernation may not actually occur.

For all these reasons, the caller must be prepared for this function to return. The simplest way to handle it is to just enter an infinite loop and wait for the power to be removed.

Returns:

None.

11.2.2.16 HibernateRTCDisable

Disables the RTC feature of the Hibernation module.

Prototype:

```
void  
HibernateRTCDisable(void)
```

Description:

Disables the RTC in the Hibernation module. After calling this function the RTC features of the Hibernation module will not be available.

Returns:

None.

11.2.2.17 HibernateRTCEnable

Enables the RTC feature of the Hibernation module.

Prototype:

```
void  
HibernateRTCEnable(void)
```

Description:

Enables the RTC in the Hibernation module. The RTC can be used to wake the processor from hibernation at a certain time, or to generate interrupts at certain times. This function must be called before using any of the RTC features of the Hibernation module.

Returns:

None.

11.2.2.18 HibernateRTCGet

Gets the value of the real time clock (RTC) counter.

Prototype:

```
unsigned long  
HibernateRTCGet(void)
```

Description:

Gets the value of the RTC and returns it to the caller.

Returns:

Returns the value of the RTC.

11.2.2.19 HibernateRTCMatch0Get

Gets the value of the RTC match 0 register.

Prototype:

```
unsigned long  
HibernateRTCMatch0Get(void)
```

Description:

Gets the value of the match 0 register for the RTC.

Returns:

Returns the value of the match register.

11.2.2.20 HibernateRTCMatch0Set

Sets the value of the RTC match 0 register.

Prototype:

```
void  
HibernateRTCMatch0Set(unsigned long ulMatch)
```

Parameters:

ulMatch is the value for the match register.

Description:

Sets the match 0 register for the RTC. The Hibernation module can be configured to wake from hibernation, and/or generate an interrupt when the value of the RTC counter is the same as the match register.

Returns:

None.

11.2.2.21 HibernateRTCMatch1Get

Gets the value of the RTC match 1 register.

Prototype:

```
unsigned long  
HibernateRTCMatch1Get(void)
```

Description:

Gets the value of the match 1 register for the RTC.

Returns:

Returns the value of the match register.

11.2.2.22 HibernateRTCMatch1Set

Sets the value of the RTC match 1 register.

Prototype:

```
void  
HibernateRTCMatch1Set(unsigned long ulMatch)
```

Parameters:

ulMatch is the value for the match register.

Description:

Sets the match 1 register for the RTC. The Hibernation module can be configured to wake from hibernation, and/or generate an interrupt when the value of the RTC counter is the same as the match register.

Returns:

None.

11.2.2.23 HibernateRTCSet

Sets the value of the real time clock (RTC) counter.

Prototype:

```
void  
HibernateRTCSet(unsigned long ulRTCValue)
```

Parameters:

ulRTCValue is the new value for the RTC.

Description:

Sets the value of the RTC. The RTC will count seconds if the hardware is configured correctly. The RTC must be enabled by calling [HibernateRTCEnable\(\)](#) before calling this function.

Returns:

None.

11.2.2.24 HibernateRTCTrimGet

Gets the value of the RTC predivider trim register.

Prototype:

```
unsigned long  
HibernateRTCTrimGet(void)
```

Description:

Gets the value of the pre-divider trim register. This function can be used to get the current value of the trim register prior to making an adjustment by using the [HibernateRTCTrimSet\(\)](#) function.

Returns:

None.

11.2.2.25 HibernateRTCTrimSet

Sets the value of the RTC predivider trim register.

Prototype:

```
void  
HibernateRTCTrimSet(unsigned long ulTrim)
```

Parameters:

ulTrim is the new value for the pre-divider trim register.

Description:

Sets the value of the pre-divider trim register. The input time source is divided by the pre-divider to achieve a one-second clock rate. Once every 64 seconds, the value of the pre-divider trim register is applied to the predivider to allow fine-tuning of the RTC rate, in order to make corrections to the rate. The software application can make adjustments to the predivider trim register to account for variations in the accuracy of the input time source. The nominal value is 0x7FFF, and it can be adjusted up or down in order to fine-tune the RTC rate.

Returns:
None.

11.2.2.26 HibernateWakeGet

Gets the currently configured wake conditions for the Hibernation module.

Prototype:
`unsigned long
HibernateWakeGet(void)`

Description:
Returns the flags representing the wake configuration for the Hibernation module. The return value will be a combination of the following flags:

- **HIBERNATE_WAKE_PIN** - wake when the external wake pin is asserted.
- **HIBERNATE_WAKE_RTC** - wake when one of the RTC matches occurs.

Returns:
Returns flags indicating the configured wake conditions.

11.2.2.27 HibernateWakeSet

Configures the wake conditions for the Hibernation module.

Prototype:
`void
HibernateWakeSet(unsigned long ulWakeFlags)`

Parameters:
ulWakeFlags specifies which conditions should be used for waking.

Description:
Enables the conditions under which the Hibernation module will wake. The *ulWakeFlags* parameter is the logical OR of any combination of the following:

- **HIBERNATE_WAKE_PIN** - wake when the external wake pin is asserted.
- **HIBERNATE_WAKE_RTC** - wake when one of the RTC matches occurs.

Returns:
None.

11.3 Programming Example

The following example shows how to determine if the processor reset is due to a wake from hibernation, and to restore saved state:

```
unsigned long ulStatus;
unsigned long ulNVData[64];

//
// Need to enable the hibernation peripheral after wake/reset, before using
// it.
//
SysCtlPeripheralEnable(SYSCTL_PERIPH_HIBERNATE);

//
// Determine if the Hibernation module is active.
//
if(HibernateIsActive())
{
    //
    // Read the status to determine cause of wake.
    //
    ulStatus = HibernateIntStatus(false);

    //
    // Test the status bits to see the cause.
    //
    if(ulStatus & HIBERNATE_INT_PIN_WAKE)
    {
        //
        // Wakeup was due to WAKE pin assertion.
        //
    }
    if(ulStatus & HIBERNATE_INT_RTC_MATCH_0)
    {
        //
        // Wakeup was due to RTC match0 register.
        //
    }

    //
    // Restore program state information that was saved prior to
    // hibernation.
    //
    HibernateDataGet(ulNVData, 64);

    //
    // Now that wakeup cause has been determined and state has been
    // restored, the program can proceed with normal processor and
    // peripheral initialization.
    //
}

//
// Hibernation module was not active so this is a cold power-up/reset.
//
else
{
    //
    // Perform normal power-on initialization.
    //
}
```

The following example shows how to set up the Hibernation module and initiate a hibernation with wake up at a future time:

```
unsigned long ulStatus;
unsigned long ulNVData[64];

//
```

```
// Need to enable the hibernation peripheral before using it.
//
SysCtlPeripheralEnable(SYSCTL_PERIPH_HIBERNATE);

//
// Enable clocking to the Hibernation module.
//
HibernateEnableExpClk(SysCtlClockGet());

//
// User-implemented delay here to allow crystal to power up and stabilize.
//

//
// Configure the clock source for Hibernation module, and enable the RTC
// feature. This configuration is for a 4.194304 MHz crystal.
//
HibernateClockSelect(HIBERNATE_CLOCK_SEL_DIV128);
HibernateRTCEnable();

//
// Set the RTC to 0, or an initial value. The RTC can be set once when the
// system is initialized after the cold-startup, and then left to run. Or
// it can be initialized before every hibernate.
//
HibernateRTCSet(0);

//
// Set the match 0 register for 30 seconds from now.
//
HibernateRTCMatch0Set(HibernateRTCGet() + 30);

//
// Clear any pending status.
//
ulStatus = HibernateIntStatus(0);
HibernateIntClear(ulStatus);

//
// Save the program state information. The state information will be
// stored in the ulNVData[] array. It is not necessary to save the full 64
// words of data, only as much as is actually needed by the program.
//
HibernateDataSet(ulNVData, 64);

//
// Configure to wake on RTC match.
//
HibernateWakeSet(HIBERNATE_WAKE_RTC);

//
// Request hibernation. The following call may return since it takes a
// finite amount of time for power to be removed.
//
HibernateRequest();

//
// Need a loop here to wait for the power to be removed. Power will be
// removed while executing in this loop.
//
for(;;)
{
}
```

The following example shows how to use the Hibernation module RTC to generate an interrupt at a certain time:

```
//
// Handler for hibernate interrupts.
//
void
HibernateHandler(void)
{
    unsigned long ulStatus;

    //
    // Get the interrupt status, and clear any pending interrupts.
    //
    ulStatus = HibernateIntStatus(1);
    HibernateIntClear(ulStatus);

    //
    // Process the RTC match 0 interrupt.
    //
    if(ulStatus & HIBERNATE_INT_RTC_MATCH_0)
    {
        //
        // RTC match 0 interrupt actions go here.
        //
    }
}

//
// Main function.
//
int
main(void)
{
    //
    // System initialization code ...
    //

    //
    // Enable the Hibernation module.
    //
    SysCtlPeripheralEnable(SYSCTL_PERIPH_HIBERNATE);
    HibernateEnableExpClk(SysCtlClockGet());

    //
    // Wait an amount of time for the module to power up.
    //

    //
    // Configure the clock source for Hibernation module, and enable the
    // RTC feature. This configuration is for the 4.194304 MHz crystal.
    //
    HibernateClockSelect(HIBERNATE_CLOCK_SEL_DIV128);
    HibernateRTCEnable();

    //
    // Set the RTC to an initial value.
    //
    HibernateRTCSet(0);

    //
    // Set Match 0 for 30 seconds from now.
    //
    HibernateRTCMatch0Set(HibernateRTCGet() + 30);

    //

```



```
// Set up interrupts on the Hibernation module to enable the RTC match
// 0 interrupt. Clear all pending interrupts and register the
// interrupt handler.
//
HibernateIntEnable(HIBERNATE_INT_RTC_MATCH_0);
HibernateIntClear(HIBERNATE_INT_PIN_WAKE | HIBERNATE_INT_LOW_BAT |
                  HIBERNATE_INT_RTC_MATCH_0 |
                  HIBERNATE_INT_RTC_MATCH_1);
HibernateIntRegister(HibernateHandler);

//
// Hibernate handler (above) will now be invoked in 30 seconds.
//

// ...
```


12 Inter-Integrated Circuit (I2C)

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12.1 Introduction

The Inter-Integrated Circuit (I2C) API provides a set of functions for using the Stellaris I2C master and slave modules. Functions are provided to initialize the I2C modules, to send and receive data, obtain status, and to manage interrupts for the I2C modules.

The I2C master and slave modules provide the ability to communicate to other IC devices over an I2C bus. The I2C bus is specified to support devices that can both transmit and receive (write and read) data. Also, devices on the I2C bus can be designated as either a master or a slave. The Stellaris I2C modules support both sending and receiving data as either a master or a slave, and also support the simultaneous operation as both a master and a slave. Finally, the Stellaris I2C modules can operate at two speeds: Standard (100 kb/s) and Fast (400 kb/s).

Both the master and slave I2C modules can generate interrupts. The I2C master module will generate interrupts when a transmit or receive operation is completed (or aborted due to an error). The I2C slave module will generate interrupts when data has been sent or requested by a master.

12.1.1 Master Operations

When using this API to drive the I2C master module, the user must first initialize the I2C master module with a call to [I2CMasterInitExpClk\(\)](#). That function will set the bus speed and enable the master module.

The user may transmit or receive data after the successful initialization of the I2C master module. Data is transferred by first setting the slave address using [I2CMasterSlaveAddrSet\(\)](#). That function is also used to define whether the transfer is a send (a write to the slave from the master) or a receive (a read from the slave by the master). Then, if connected to an I2C bus that has multiple masters, the Stellaris I2C master must first call [I2CMasterBusBusy\(\)](#) before attempting to initiate the desired transaction. After determining that the bus is not busy, if trying to send data, the user must call the [I2CMasterDataPut\(\)](#) function. The transaction can then be initiated on the bus by calling the [I2CMasterControl\(\)](#) function with any of the following commands:

- **I2C_MASTER_CMD_SINGLE_SEND**
- **I2C_MASTER_CMD_SINGLE_RECEIVE**
- **I2C_MASTER_CMD_BURST_SEND_START**
- **I2C_MASTER_CMD_BURST_RECEIVE_START**

Any of those commands will result in the master arbitrating for the bus, driving the start sequence onto the bus, and sending the slave address and direction bit across the bus. The remainder of the transaction can then be driven using either a polling or interrupt-driven method.

For the single send and receive cases, the polling method will involve looping on the return from [I2CMasterBusy\(\)](#). Once that function indicates that the I2C master is no longer busy, the bus transaction has been completed and can be checked for errors using [I2CMasterErr\(\)](#). If there are no

errors, then the data has been sent or is ready to be read using [I2CMasterDataGet\(\)](#). For the burst send and receive cases, the polling method also involves calling the [I2CMasterControl\(\)](#) function for each byte transmitted or received (using either the **I2C_MASTER_CMD_BURST_SEND_CONT** or **I2C_MASTER_CMD_BURST_RECEIVE_CONT** commands), and for the last byte sent or received (using either the **I2C_MASTER_CMD_BURST_SEND_FINISH** or **I2C_MASTER_CMD_BURST_RECEIVE_FINISH** commands). If any error is detected during the burst transfer, the [I2CMasterControl\(\)](#) function should be called using the appropriate stop command (**I2C_MASTER_CMD_BURST_SEND_ERROR_STOP** or **I2C_MASTER_CMD_BURST_RECEIVE_ERROR_STOP**).

For the interrupt-driven transaction, the user must register an interrupt handler for the I2C devices and enable the I2C master interrupt; the interrupt will occur when the master is no longer busy.

12.1.2 Slave Operations

When using this API to drive the I2C slave module, the user must first initialize the I2C slave module with a call to [I2CSlaveInit\(\)](#). This will enable the I2C slave module and initialize the slave's own address. After the initialization is complete, the user may poll the slave status using [I2CSlaveStatus\(\)](#) to determine if a master requested a send or receive operation. Depending on the type of operation requested, the user can call [I2CSlaveDataPut\(\)](#) or [I2CSlaveDataGet\(\)](#) to complete the transaction. Alternatively, the I2C slave can handle transactions using an interrupt handler registered with [I2CIntRegister](#), and by enabling the I2C slave interrupt.

This driver is contained in `src/i2c.c`, with `src/i2c.h` containing the API definitions for use by applications.

12.2 API Functions

Functions

- void [I2CIntRegister](#) (unsigned long ulBase, void (*pfnHandler)(void))
- void [I2CIntUnregister](#) (unsigned long ulBase)
- tBoolean [I2CMasterBusBusy](#) (unsigned long ulBase)
- tBoolean [I2CMasterBusy](#) (unsigned long ulBase)
- void [I2CMasterControl](#) (unsigned long ulBase, unsigned long ulCmd)
- unsigned long [I2CMasterDataGet](#) (unsigned long ulBase)
- void [I2CMasterDataPut](#) (unsigned long ulBase, unsigned char ucData)
- void [I2CMasterDisable](#) (unsigned long ulBase)
- void [I2CMasterEnable](#) (unsigned long ulBase)
- unsigned long [I2CMasterErr](#) (unsigned long ulBase)
- void [I2CMasterInitExpClk](#) (unsigned long ulBase, unsigned long ullI2CClk, tBoolean bFast)
- void [I2CMasterIntClear](#) (unsigned long ulBase)
- void [I2CMasterIntDisable](#) (unsigned long ulBase)
- void [I2CMasterIntEnable](#) (unsigned long ulBase)
- tBoolean [I2CMasterIntStatus](#) (unsigned long ulBase, tBoolean bMasked)
- void [I2CMasterSlaveAddrSet](#) (unsigned long ulBase, unsigned char ucSlaveAddr, tBoolean bReceive)

- unsigned long [I2CSlaveDataGet](#) (unsigned long ulBase)
- void [I2CSlaveDataPut](#) (unsigned long ulBase, unsigned char ucData)
- void [I2CSlaveDisable](#) (unsigned long ulBase)
- void [I2CSlaveEnable](#) (unsigned long ulBase)
- void [I2CSlaveInit](#) (unsigned long ulBase, unsigned char ucSlaveAddr)
- void [I2CSlaveIntClear](#) (unsigned long ulBase)
- void [I2CSlaveIntDisable](#) (unsigned long ulBase)
- void [I2CSlaveIntEnable](#) (unsigned long ulBase)
- tBoolean [I2CSlaveIntStatus](#) (unsigned long ulBase, tBoolean bMasked)
- unsigned long [I2CSlaveStatus](#) (unsigned long ulBase)

12.2.1 Detailed Description

The I2C API is broken into three groups of functions: those that deal with interrupts, those that handle status and initialization, and those that deal with sending and receiving data.

The I2C master and slave interrupts are handled by the [I2CIntRegister\(\)](#), [I2CIntUnregister\(\)](#), [I2CMasterIntEnable\(\)](#), [I2CMasterIntDisable\(\)](#), [I2CMasterIntClear\(\)](#), [I2CMasterIntStatus\(\)](#), [I2CSlaveIntEnable\(\)](#), [I2CSlaveIntDisable\(\)](#), [I2CSlaveIntClear\(\)](#), and [I2CSlaveIntStatus\(\)](#) functions.

Status and initialization functions for the I2C modules are [I2CMasterInitExpClk\(\)](#), [I2CMasterEnable\(\)](#), [I2CMasterDisable\(\)](#), [I2CMasterBusBusy\(\)](#), [I2CMasterBusy\(\)](#), [I2CMasterErr\(\)](#), [I2CSlaveInit\(\)](#), [I2CSlaveEnable\(\)](#), [I2CSlaveDisable\(\)](#), and [I2CSlaveStatus\(\)](#).

Sending and receiving data from the I2C modules are handled by the [I2CMasterSlaveAddrSet\(\)](#), [I2CMasterControl\(\)](#), [I2CMasterDataGet\(\)](#), [I2CMasterDataPut\(\)](#), [I2CSlaveDataGet\(\)](#), and [I2CSlaveDataPut\(\)](#) functions.

The [I2CMasterInit\(\)](#) API from previous versions of the peripheral driver library has been replaced by the [I2CMasterInitExpClk\(\)](#) API. A macro has been provided in `i2c.h` to map the old API to the new API, allowing existing applications to link and run with the new API. It is recommended that new applications utilize the new API in favor of the old one.

12.2.2 Function Documentation

12.2.2.1 I2CIntRegister

Registers an interrupt handler for the I2C module.

Prototype:

```
void
I2CIntRegister(unsigned long ulBase,
               void (*pfnHandler)(void))
```

Parameters:

ulBase is the base address of the I2C Master module.

pfnHandler is a pointer to the function to be called when the I2C interrupt occurs.

Description:

This sets the handler to be called when an I2C interrupt occurs. This will enable the global interrupt in the interrupt controller; specific I2C interrupts must be enabled via [I2CMasterIntEnable\(\)](#) and [I2CSlaveIntEnable\(\)](#). If necessary, it is the interrupt handler's responsibility to clear the interrupt source via [I2CMasterIntClear\(\)](#) and [I2CSlaveIntClear\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

12.2.2.2 I2CIntUnregister

Unregisters an interrupt handler for the I2C module.

Prototype:

```
void  
I2CIntUnregister(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Master module.

Description:

This function will clear the handler to be called when an I2C interrupt occurs. This will also mask off the interrupt in the interrupt controller so that the interrupt handler no longer is called.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

12.2.2.3 I2CMasterBusBusy

Indicates whether or not the I2C bus is busy.

Prototype:

```
tBoolean  
I2CMasterBusBusy(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Master module.

Description:

This function returns an indication of whether or not the I2C bus is busy. This function can be used in a multi-master environment to determine if another master is currently using the bus.

Returns:

Returns **true** if the I2C bus is busy; otherwise, returns **false**.

12.2.2.4 I2CMasterBusy

Indicates whether or not the I2C Master is busy.

Prototype:

```
tBoolean  
I2CMasterBusy(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Master module.

Description:

This function returns an indication of whether or not the I2C Master is busy transmitting or receiving data.

Returns:

Returns **true** if the I2C Master is busy; otherwise, returns **false**.

12.2.2.5 I2CMasterControl

Controls the state of the I2C Master module.

Prototype:

```
void  
I2CMasterControl(unsigned long ulBase,  
                 unsigned long ulCmd)
```

Parameters:

ulBase is the base address of the I2C Master module.

ulCmd command to be issued to the I2C Master module

Description:

This function is used to control the state of the Master module send and receive operations. The parameter *ucCmd* can be one of the following values:

- I2C_MASTER_CMD_SINGLE_SEND
- I2C_MASTER_CMD_SINGLE_RECEIVE
- I2C_MASTER_CMD_BURST_SEND_START
- I2C_MASTER_CMD_BURST_SEND_CONT
- I2C_MASTER_CMD_BURST_SEND_FINISH
- I2C_MASTER_CMD_BURST_SEND_ERROR_STOP
- I2C_MASTER_CMD_BURST_RECEIVE_START
- I2C_MASTER_CMD_BURST_RECEIVE_CONT
- I2C_MASTER_CMD_BURST_RECEIVE_FINISH
- I2C_MASTER_CMD_BURST_RECEIVE_ERROR_STOP

Returns:

None.

12.2.2.6 I2CMasterDataGet

Receives a byte that has been sent to the I2C Master.

Prototype:

```
unsigned long  
I2CMasterDataGet(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Master module.

Description:

This function reads a byte of data from the I2C Master Data Register.

Returns:

Returns the byte received from by the I2C Master, cast as an unsigned long.

12.2.2.7 I2CMasterDataPut

Transmits a byte from the I2C Master.

Prototype:

```
void  
I2CMasterDataPut(unsigned long ulBase,  
                 unsigned char ucData)
```

Parameters:

ulBase is the base address of the I2C Master module.

ucData data to be transmitted from the I2C Master

Description:

This function will place the supplied data into I2C Master Data Register.

Returns:

None.

12.2.2.8 I2CMasterDisable

Disables the I2C master block.

Prototype:

```
void  
I2CMasterDisable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Master module.

Description:

This will disable operation of the I2C master block.

Returns:

None.

12.2.2.9 I2CMasterEnable

Enables the I2C Master block.

Prototype:

```
void  
I2CMasterEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Master module.

Description:

This will enable operation of the I2C Master block.

Returns:

None.

12.2.2.10 I2CMasterErr

Gets the error status of the I2C Master module.

Prototype:

```
unsigned long  
I2CMasterErr(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Master module.

Description:

This function is used to obtain the error status of the Master module send and receive operations. It returns one of the following values:

- **I2C_MASTER_ERR_NONE**
- **I2C_MASTER_ERR_ADDR_ACK**
- **I2C_MASTER_ERR_DATA_ACK**
- **I2C_MASTER_ERR_ARB_LOST**

Returns:

None.

12.2.2.11 I2CMasterInitExpClk

Initializes the I2C Master block.

Prototype:

```
void  
I2CMasterInitExpClk(unsigned long ulBase,  
                    unsigned long ulI2CClk,  
                    tBoolean bFast)
```

Parameters:

ulBase is the base address of the I2C Master module.

ull2CClk is the rate of the clock supplied to the I2C module.

bFast set up for fast data transfers

Description:

This function initializes operation of the I2C Master block. Upon successful initialization of the I2C block, this function will have set the bus speed for the master, and will have enabled the I2C Master block.

If the parameter ***bFast*** is **true**, then the master block will be set up to transfer data at 400 kbps; otherwise, it will be set up to transfer data at 100 kbps.

The peripheral clock will be the same as the processor clock. This will be the value returned by [SysCtlClockGet\(\)](#), or it can be explicitly hard coded if it is constant and known (to save the code/execution overhead of a call to [SysCtlClockGet\(\)](#)).

This function replaces the original I2CMasterInit() API and performs the same actions. A macro is provided in `i2c.h` to map the original API to this API.

Returns:

None.

12.2.2.12 I2CMasterIntClear

Clears I2C Master interrupt sources.

Prototype:

```
void  
I2CMasterIntClear(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Master module.

Description:

The I2C Master interrupt source is cleared, so that it no longer asserts. This must be done in the interrupt handler to keep it from being called again immediately upon exit.

Returns:

None.

12.2.2.13 I2CMasterIntDisable

Disables the I2C Master interrupt.

Prototype:

```
void  
I2CMasterIntDisable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Master module.

Description:

Disables the I2C Master interrupt source.

Returns:

None.

12.2.2.14 I2CMasterIntEnable

Enables the I2C Master interrupt.

Prototype:

```
void  
I2CMasterIntEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Master module.

Description:

Enables the I2C Master interrupt source.

Returns:

None.

12.2.2.15 I2CMasterIntStatus

Gets the current I2C Master interrupt status.

Prototype:

```
tBoolean  
I2CMasterIntStatus(unsigned long ulBase,  
                   tBoolean bMasked)
```

Parameters:

ulBase is the base address of the I2C Master module.

bMasked is false if the raw interrupt status is requested and true if the masked interrupt status is requested.

Description:

This returns the interrupt status for the I2C Master module. Either the raw interrupt status or the status of interrupts that are allowed to reflect to the processor can be returned.

Returns:

The current interrupt status, returned as **true** if active or **false** if not active.

12.2.2.16 I2CMasterSlaveAddrSet

Sets the address that the I2C Master will place on the bus.

Prototype:

```
void  
I2CMasterSlaveAddrSet(unsigned long ulBase,  
                      unsigned char ucSlaveAddr,  
                      tBoolean bReceive)
```

Parameters:

ulBase is the base address of the I2C Master module.

ucSlaveAddr 7-bit slave address

bReceive flag indicating the type of communication with the slave

Description:

This function will set the address that the I2C Master will place on the bus when initiating a transaction. When the parameter ***bReceive*** is set to **true**, the address will indicate that the I2C Master is initiating a read from the slave; otherwise the address will indicate that the I2C Master is initiating a write to the slave.

Returns:

None.

12.2.2.17 I2CSlaveDataGet

Receives a byte that has been sent to the I2C Slave.

Prototype:

```
unsigned long  
I2CSlaveDataGet(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Slave module.

Description:

This function reads a byte of data from the I2C Slave Data Register.

Returns:

Returns the byte received from by the I2C Slave, cast as an unsigned long.

12.2.2.18 I2CSlaveDataPut

Transmits a byte from the I2C Slave.

Prototype:

```
void  
I2CSlaveDataPut(unsigned long ulBase,  
                unsigned char ucData)
```

Parameters:

ulBase is the base address of the I2C Slave module.

ucData data to be transmitted from the I2C Slave

Description:

This function will place the supplied data into I2C Slave Data Register.

Returns:

None.

12.2.2.19 I2CSlaveDisable

Disables the I2C slave block.

Prototype:

```
void  
I2CSlaveDisable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Slave module.

Description:

This will disable operation of the I2C slave block.

Returns:

None.

12.2.2.20 I2CSlaveEnable

Enables the I2C Slave block.

Prototype:

```
void  
I2CSlaveEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Slave module.

Description:

This will enable operation of the I2C Slave block.

Returns:

None.

12.2.2.21 I2CSlaveInit

Initializes the I2C Slave block.

Prototype:

```
void  
I2CSlaveInit(unsigned long ulBase,  
              unsigned char ucSlaveAddr)
```

Parameters:

ulBase is the base address of the I2C Slave module.

ucSlaveAddr 7-bit slave address

Description:

This function initializes operation of the I2C Slave block. Upon successful initialization of the I2C blocks, this function will have set the slave address and have enabled the I2C Slave block.

The parameter *ucSlaveAddr* is the value that will be compared against the slave address sent by an I2C master.

Returns:

None.

12.2.2.22 I2CSlaveIntClear

Clears I2C Slave interrupt sources.

Prototype:

```
void  
I2CSlaveIntClear(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Slave module.

Description:

The I2C Slave interrupt source is cleared, so that it no longer asserts. This must be done in the interrupt handler to keep it from being called again immediately upon exit.

Returns:

None.

12.2.2.23 I2CSlaveIntDisable

Disables the I2C Slave interrupt.

Prototype:

```
void  
I2CSlaveIntDisable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Slave module.

Description:

Disables the I2C Slave interrupt source.

Returns:

None.

12.2.2.24 I2CSlaveIntEnable

Enables the I2C Slave interrupt.

Prototype:

```
void  
I2CSlaveIntEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the I2C Slave module.

Description:

Enables the I2C Slave interrupt source.

Returns:
None.

12.2.2.25 I2CSlaveIntStatus

Gets the current I2C Slave interrupt status.

Prototype:
`tBoolean
I2CSlaveIntStatus(unsigned long ulBase,
tBoolean bMasked)`

Parameters:
ulBase is the base address of the I2C Slave module.
bMasked is false if the raw interrupt status is requested and true if the masked interrupt status is requested.

Description:
This returns the interrupt status for the I2C Slave module. Either the raw interrupt status or the status of interrupts that are allowed to reflect to the processor can be returned.

Returns:
The current interrupt status, returned as **true** if active or **false** if not active.

12.2.2.26 I2CSlaveStatus

Gets the I2C Slave module status

Prototype:
`unsigned long
I2CSlaveStatus(unsigned long ulBase)`

Parameters:
ulBase is the base address of the I2C Slave module.

Description:
This function will return the action requested from a master, if any. Possible values are:

- **I2C_SLAVE_ACT_NONE**
- **I2C_SLAVE_ACT_RREQ**
- **I2C_SLAVE_ACT_TREQ**
- **I2C_SLAVE_ACT_RREQ_FBR**

Returns:
Returns **I2C_SLAVE_ACT_NONE** to indicate that no action has been requested of the I2C Slave module, **I2C_SLAVE_ACT_RREQ** to indicate that an I2C master has sent data to the I2C Slave module, **I2C_SLAVE_ACT_TREQ** to indicate that an I2C master has requested that the I2C Slave module send data, and **I2C_SLAVE_ACT_RREQ_FBR** to indicate that an I2C master has sent data to the I2C slave and the first byte following the slave's own address has been received.

12.3 Programming Example

The following example shows how to use the I2C API to send data as a master.

```
//
// Initialize Master and Slave
//
I2CMasterInitExpClk(I2C_MASTER_BASE, SysCtlClockGet(), true);

//
// Specify slave address
//
I2CMasterSlaveAddrSet(I2C_MASTER_BASE, 0x3B, false);

//
// Place the character to be sent in the data register
//
I2CMasterDataPut(I2C_MASTER_BASE, 'Q');

//
// Initiate send of character from Master to Slave
//
I2CMasterControl(I2C_MASTER_BASE, I2C_MASTER_CMD_SINGLE_SEND);

//
// Delay until transmission completes
//
while(I2CMasterBusBusy(I2C_MASTER_BASE))
{
}
```


13 Interrupt Controller (NVIC)

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13.1 Introduction

The interrupt controller API provides a set of functions for dealing with the Nested Vectored Interrupt Controller (NVIC). Functions are provided to enable and disable interrupts, register interrupt handlers, and set the priority of interrupts.

The NVIC provides global interrupt masking, prioritization, and handler dispatching. This version of the Stellaris family supports thirty-two interrupt sources and eight priority levels. Individual interrupt sources can be masked, and the processor interrupt can be globally masked as well (without affecting the individual source masks).

The NVIC is tightly coupled with the Cortex-M3 microprocessor. When the processor responds to an interrupt, NVIC will supply the address of the function to handle the interrupt directly to the processor. This eliminates the need for a global interrupt handler that queries the interrupt controller to determine the cause of the interrupt and branch to the appropriate handler, reducing interrupt response time.

The interrupt prioritization in the NVIC allows higher priority interrupts to be handled before lower priority interrupts, as well as allowing preemption of lower priority interrupt handlers by higher priority interrupts. Again, this helps reduce interrupt response time (for example, a 1 ms system control interrupt is not held off by the execution of a lower priority 1 second housekeeping interrupt handler).

Sub-prioritization is also possible; instead of having N bits of preemptable prioritization, NVIC can be configured (via software) for N - M bits of preemptable prioritization and M bits of subpriority. In this scheme, two interrupts with the same preemptable prioritization but different subpriorities will not cause a preemption; tail chaining will instead be used to process the two interrupts back-to-back.

If two interrupts with the same priority (and subpriority if so configured) are asserted at the same time, the one with the lower interrupt number will be processed first. NVIC keeps track of the nesting of interrupt handlers, allowing the processor to return from interrupt context only once all nested and pending interrupts have been handled.

Interrupt handlers can be configured in one of two ways; statically at compile time or dynamically at run time. Static configuration of interrupt handlers is accomplished by editing the interrupt handler table in the application's startup code. When statically configured, the interrupts must be explicitly enabled in NVIC via [IntEnable\(\)](#) before the processor will respond to the interrupt (in addition to any interrupt enabling required within the peripheral itself).

Alternatively, interrupts can be configured at run-time using [IntRegister\(\)](#) (or the analog in each individual driver). When using [IntRegister\(\)](#), the interrupt must also be enabled as before; when using the analogue in each individual driver, [IntEnable\(\)](#) is called by the driver and does not need to be call by the application.

Run-time configuration of interrupt handlers requires that the interrupt handler table be placed on a 1 kB boundary in SRAM (typically this would be at the beginning of SRAM). Failure to do so will result in an incorrect vector address being fetched in response to an interrupt. The vector table is

in a section called “vtable” and should be placed appropriately with a linker script. Tools that do not support linker scripts (such as the evaluation version of RV-MDK) therefore do not support run-time configuration of interrupt handlers (though the full version of RV-MDK does).

This driver is contained in `src/interrupt.c`, with `src/interrupt.h` containing the API definitions for use by applications.

13.2 API Functions

Functions

- void [IntDisable](#) (unsigned long ulInterrupt)
- void [IntEnable](#) (unsigned long ulInterrupt)
- tBoolean [IntMasterDisable](#) (void)
- tBoolean [IntMasterEnable](#) (void)
- long [IntPriorityGet](#) (unsigned long ulInterrupt)
- unsigned long [IntPriorityGroupingGet](#) (void)
- void [IntPriorityGroupingSet](#) (unsigned long ulBits)
- void [IntPrioritySet](#) (unsigned long ulInterrupt, unsigned char ucPriority)
- void [IntRegister](#) (unsigned long ulInterrupt, void (*pfnHandler)(void))
- void [IntUnregister](#) (unsigned long ulInterrupt)

13.2.1 Detailed Description

The primary function of the interrupt controller API is to manage the interrupt vector table used by the NVIC to dispatch interrupt requests. Registering an interrupt handler is a simple matter of inserting the handler address into the table. By default, the table is filled with pointers to an internal handler that loops forever; it is an error for an interrupt to occur when there is no interrupt handler registered to process it. Therefore, interrupt sources should not be enabled before a handler has been registered, and interrupt sources should be disabled before a handler is unregistered. Interrupt handlers are managed with [IntRegister\(\)](#) and [IntUnregister\(\)](#).

Each interrupt source can be individually enabled and disabled via [IntEnable\(\)](#) and [IntDisable\(\)](#). The processor interrupt can be enabled and disabled via [IntMasterEnable\(\)](#) and [IntMasterDisable\(\)](#); this does not affect the individual interrupt enable states. Masking of the processor interrupt can be utilized as a simple critical section (only NMI will interrupt the processor while the processor interrupt is disabled), though this will have adverse effects on the interrupt response time.

The priority of each interrupt source can be set and examined via [IntPrioritySet\(\)](#) and [IntPriorityGet\(\)](#). The priority assignments are defined by the hardware; the upper N bits of the 8-bit priority are examined to determine the priority of an interrupt (for the Stellaris family, N is 3). This allows priorities to be defined without a real need to know the exact number of supported priorities; moving to a device with more or fewer priority bits will continue to treat the interrupt source with a similar level of priority. Smaller priority numbers correspond to higher interrupt priority, so 0 is the highest priority.

13.2.2 Function Documentation

13.2.2.1 IntDisable

Disables an interrupt.

Prototype:

```
void  
IntDisable(unsigned long ulInterrupt)
```

Parameters:

ulInterrupt specifies the interrupt to be disabled.

Description:

The specified interrupt is disabled in the interrupt controller. Other enables for the interrupt (such as at the peripheral level) are unaffected by this function.

Returns:

None.

13.2.2.2 IntEnable

Enables an interrupt.

Prototype:

```
void  
IntEnable(unsigned long ulInterrupt)
```

Parameters:

ulInterrupt specifies the interrupt to be enabled.

Description:

The specified interrupt is enabled in the interrupt controller. Other enables for the interrupt (such as at the peripheral level) are unaffected by this function.

Returns:

None.

13.2.2.3 IntMasterDisable

Disables the processor interrupt.

Prototype:

```
tBoolean  
IntMasterDisable(void)
```

Description:

Prevents the processor from receiving interrupts. This does not affect the set of interrupts enabled in the interrupt controller; it just gates the single interrupt from the controller to the processor.

Note:

Previously, this function had no return value. As such, it was possible to include `interrupt.h` and call this function without having included `hw_types.h`. Now that the return is a `tBoolean`, a compiler error will occur in this case. The solution is to include `hw_types.h` before including `interrupt.h`.

Returns:

Returns **true** if interrupts were already disabled when the function was called or **false** if they were initially enabled.

13.2.2.4 IntMasterEnable

Enables the processor interrupt.

Prototype:

```
tBoolean
IntMasterEnable(void)
```

Description:

Allows the processor to respond to interrupts. This does not affect the set of interrupts enabled in the interrupt controller; it just gates the single interrupt from the controller to the processor.

Note:

Previously, this function had no return value. As such, it was possible to include `interrupt.h` and call this function without having included `hw_types.h`. Now that the return is a `tBoolean`, a compiler error will occur in this case. The solution is to include `hw_types.h` before including `interrupt.h`.

Returns:

Returns **true** if interrupts were disabled when the function was called or **false** if they were initially enabled.

13.2.2.5 IntPriorityGet

Gets the priority of an interrupt.

Prototype:

```
long
IntPriorityGet(unsigned long ulInterrupt)
```

Parameters:

ulInterrupt specifies the interrupt in question.

Description:

This function gets the priority of an interrupt. See [IntPrioritySet\(\)](#) for a definition of the priority value.

Returns:

Returns the interrupt priority, or -1 if an invalid interrupt was specified.

13.2.2.6 IntPriorityGroupingGet

Gets the priority grouping of the interrupt controller.

Prototype:

```
unsigned long  
IntPriorityGroupingGet(void)
```

Description:

This function returns the split between preemptable priority levels and subpriority levels in the interrupt priority specification.

Returns:

The number of bits of preemptable priority.

13.2.2.7 IntPriorityGroupingSet

Sets the priority grouping of the interrupt controller.

Prototype:

```
void  
IntPriorityGroupingSet(unsigned long ulBits)
```

Parameters:

ulBits specifies the number of bits of preemptable priority.

Description:

This function specifies the split between preemptable priority levels and subpriority levels in the interrupt priority specification. The range of the grouping values are dependent upon the hardware implementation; on the Stellaris family, three bits are available for hardware interrupt prioritization and therefore priority grouping values of three through seven have the same effect.

Returns:

None.

13.2.2.8 IntPrioritySet

Sets the priority of an interrupt.

Prototype:

```
void  
IntPrioritySet(unsigned long ulInterrupt,  
              unsigned char ucPriority)
```

Parameters:

ulInterrupt specifies the interrupt in question.

ucPriority specifies the priority of the interrupt.

Description:

This function is used to set the priority of an interrupt. When multiple interrupts are asserted simultaneously, the ones with the highest priority are processed before the lower priority interrupts. Smaller numbers correspond to higher interrupt priorities; priority 0 is the highest interrupt priority.

The hardware priority mechanism will only look at the upper N bits of the priority level (where N is 3 for the Stellaris family), so any prioritization must be performed in those bits. The remaining bits can be used to sub-prioritize the interrupt sources, and may be used by the hardware priority mechanism on a future part. This arrangement allows priorities to migrate to different NVIC implementations without changing the gross prioritization of the interrupts.

Returns:

None.

13.2.2.9 IntRegister

Registers a function to be called when an interrupt occurs.

Prototype:

```
void  
IntRegister(unsigned long ulInterrupt,  
            void (*pfnHandler)(void))
```

Parameters:

ulInterrupt specifies the interrupt in question.

pfnHandler is a pointer to the function to be called.

Description:

This function is used to specify the handler function to be called when the given interrupt is asserted to the processor. When the interrupt occurs, if it is enabled (via [IntEnable\(\)](#)), the handler function will be called in interrupt context. Since the handler function can preempt other code, care must be taken to protect memory or peripherals that are accessed by the handler and other non-handler code.

Note:

The use of this function (directly or indirectly via a peripheral driver interrupt register function) moves the interrupt vector table from flash to SRAM. Therefore, care must be taken when linking the application to ensure that the SRAM vector table is located at the beginning of SRAM; otherwise NVIC will not look in the correct portion of memory for the vector table (it requires the vector table be on a 1 kB memory alignment). Normally, the SRAM vector table is so placed via the use of linker scripts; some tool chains, such as the evaluation version of RV-MDK, do not support linker scripts and therefore will not produce a valid executable. See the discussion of compile-time versus run-time interrupt handler registration in the introduction to this chapter.

Returns:

None.

13.2.2.10 IntUnregister

Unregisters the function to be called when an interrupt occurs.

Prototype:

```
void  
IntUnregister(unsigned long ulInterrupt)
```

Parameters:

ulInterrupt specifies the interrupt in question.

Description:

This function is used to indicate that no handler should be called when the given interrupt is asserted to the processor. The interrupt source will be automatically disabled (via [IntDisable\(\)](#)) if necessary.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

13.3 Programming Example

The following example shows how to use the Interrupt Controller API to register an interrupt handler and enable the interrupt.

```
//  
// The interrupt handler function.  
//  
extern void IntHandler(void);  
  
//  
// Register the interrupt handler function for interrupt 5.  
//  
IntRegister(5, IntHandler);  
  
//  
// Enable interrupt 5.  
//  
IntEnable(5);  
  
//  
// Enable interrupt 5.  
//  
IntMasterEnable();
```


14 Memory Protection Unit (MPU)

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14.1 Introduction

The Memory Protection Unit (MPU) API provides functions to configure the MPU. The MPU is tightly coupled to the Cortex-M3 processor core and provides a means to establish access permissions on regions of memory.

Up to eight memory regions can be defined. Each region has a base address and a size. The size is specified as a power of 2 between 32 bytes and 4 GB, inclusive. The region's base address must be aligned to the size of the region. Each region also has access permissions. Code execution can be allowed or disallowed for a region. A region can be set for read-only access, read/write access, or no access for both privileged and user modes. This can be used to set up an environment where only kernel or system code can access certain hardware registers or sections of code.

The MPU creates 8 sub-regions within each region. Any sub-region or combination of sub-regions can be disabled, allowing creation of "holes" or complex overlaying regions with different permissions. The sub-regions can also be used to create an unaligned beginning or ending of a region by disabling one or more of the leading or trailing sub-regions.

Once the regions are defined and the MPU is enabled, any access violation of a region will cause a memory management fault, and the fault handler will be activated.

This driver is contained in `src/mpu.c`, with `src/mpu.h` containing the API definitions for use by applications.

14.2 API Functions

Functions

- void [MPUDisable](#) (void)
- void [MPUEnable](#) (unsigned long ulMPUConfig)
- void [MPUIntRegister](#) (void (*pfnHandler)(void))
- void [MPUIntUnregister](#) (void)
- unsigned long [MPURegionCountGet](#) (void)
- void [MPURegionDisable](#) (unsigned long ulRegion)
- void [MPURegionEnable](#) (unsigned long ulRegion)
- void [MPURegionGet](#) (unsigned long ulRegion, unsigned long *pulAddr, unsigned long *pulFlags)
- void [MPURegionSet](#) (unsigned long ulRegion, unsigned long ulAddr, unsigned long ulFlags)

14.2.1 Detailed Description

The MPU APIs provide a means to enable and configure the MPU and memory protection regions.

Generally, the memory protection regions should be defined before enabling the MPU. The regions can be configured by calling [MPURegionSet\(\)](#) once for each region to be configured.

A region that is defined by [MPURegionSet\(\)](#) can be initially enabled or disabled. If the region is not initially enabled, it can be enabled later by calling [MPURegionEnable\(\)](#). An enabled region can be disabled by calling [MPURegionDisable\(\)](#). When a region is disabled, its configuration is preserved as long as it is not overwritten. In this case it can be enabled again with [MPURegionEnable\(\)](#) without the need to reconfigure the region.

Care must be taken when setting up a protection region using [MPURegionSet\(\)](#). The function will write to multiple registers and is not protected from interrupts. Therefore, it is possible that an interrupt which accesses a region may occur while that region is in the process of being changed. The safest way to protect against this is to make sure that a region is always disabled before making any changes. Otherwise, it is up to the caller to ensure that [MPURegionSet\(\)](#) is always called from within code that cannot be interrupted, or from code that will not be affected if an interrupt occurs while the region attributes are being changed.

The attributes of a region that has already been programmed can be retrieved and saved using the [MPURegionGet\(\)](#) function. This function is intended to save the attributes in a format that can be used later to reload the region using the [MPURegionSet\(\)](#) function. Note that the enable state of the region is saved with the attributes and will take effect when the region is reloaded.

When one or more regions are defined, the MPU can be enabled by calling [MPUEnable\(\)](#). This turns on the MPU and also defines the behavior in privileged mode and in the Hard Fault and NMI fault handlers. The MPU can be configured so that when in privileged mode and no regions are enabled, a default memory map is applied. If this feature is not enabled, then a memory management fault is generated if the MPU is enabled and no regions are configured and enabled. The MPU can also be set to use a default memory map when in the Hard Fault or NMI handlers, instead of using the configured regions. All of these features are selected when calling [MPUEnable\(\)](#). When the MPU is enabled, it can be disabled by calling [MPUDisable\(\)](#).

Finally, if the application is using run-time interrupt registration (see [IntRegister\(\)](#)), then the function [MPUIntRegister\(\)](#) can be used to install the fault handler which will be called whenever a memory protection violation occurs. This function will also enable the fault handler. If compile-time interrupt registration is used, then the [IntEnable\(\)](#) function with the parameter **FAULT_MPU** must be used to enable the memory management fault handler. When the memory management fault handler has been installed with [MPUIntRegister\(\)](#), it can be removed by calling [MPUIntUnregister\(\)](#).

14.2.2 Function Documentation

14.2.2.1 MPUDisable

Disables the MPU for use.

Prototype:

```
void  
MPUDisable(void)
```

Description:

This function disables the Cortex-M3 memory protection unit. When the MPU is disabled, the

default memory map is used and memory management faults are not generated.

Returns:

None.

14.2.2.2 MPUEnable

Enables and configures the MPU for use.

Prototype:

```
void  
MPUEnable(unsigned long ulMPUConfig)
```

Parameters:

ulMPUConfig is the logical OR of the possible configurations.

Description:

This function enables the Cortex-M3 memory protection unit. It also configures the default behavior when in privileged mode and while handling a hard fault or NMI. Prior to enabling the MPU, at least one region must be set by calling [MPURegionSet\(\)](#) or else by enabling the default region for privileged mode by passing the **MPU_CONFIG_PRIV_DEFAULT** flag to [MPUEnable\(\)](#). Once the MPU is enabled, a memory management fault will be generated for any memory access violations.

The *ulMPUConfig* parameter should be the logical OR of any of the following:

- **MPU_CONFIG_PRIV_DEFAULT** enables the default memory map when in privileged mode and when no other regions are defined. If this option is not enabled, then there must be at least one valid region already defined when the MPU is enabled.
- **MPU_CONFIG_HARDFLT_NMI** enables the MPU while in a hard fault or NMI exception handler. If this option is not enabled, then the MPU is disabled while in one of these exception handlers and the default memory map is applied.
- **MPU_CONFIG_NONE** chooses none of the above options. In this case, no default memory map is provided in privileged mode, and the MPU will not be enabled in the fault handlers.

Returns:

None.

14.2.2.3 MPUIntRegister

Registers an interrupt handler for the memory management fault.

Prototype:

```
void  
MPUIntRegister(void (*pfnHandler)(void))
```

Parameters:

pfnHandler is a pointer to the function to be called when the memory management fault occurs.

Description:

This sets and enables the handler to be called when the MPU generates a memory management fault due to a protection region access violation.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

14.2.2.4 MPUIntUnregister

Unregisters an interrupt handler for the memory management fault.

Prototype:

```
void  
MPUIntUnregister(void)
```

Description:

This function will disable and clear the handler to be called when a memory management fault occurs.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

14.2.2.5 MPURegionCountGet

Gets the count of regions supported by the MPU.

Prototype:

```
unsigned long  
MPURegionCountGet(void)
```

Description:

This function is used to get the number of regions that are supported by the MPU. This is the total number that are supported, including regions that are already programmed.

Returns:

The number of memory protection regions that are available for programming using [MPURegionSet\(\)](#).

14.2.2.6 MPURegionDisable

Disables a specific region.

Prototype:

```
void  
MPURegionDisable(unsigned long ulRegion)
```

Parameters:

ulRegion is the region number to disable.

Description:

This function is used to disable a previously enabled memory protection region. The region will remain configured if it is not overwritten with another call to [MPURegionSet\(\)](#), and can be enabled again by calling [MPURegionEnable\(\)](#).

Returns:

None.

14.2.2.7 MPURegionEnable

Enables a specific region.

Prototype:

```
void  
MPURegionEnable(unsigned long ulRegion)
```

Parameters:

ulRegion is the region number to enable.

Description:

This function is used to enable a memory protection region. The region should already be set up with the [MPURegionSet\(\)](#) function. Once enabled, the memory protection rules of the region will be applied and access violations will cause a memory management fault.

Returns:

None.

14.2.2.8 MPURegionGet

Gets the current settings for a specific region.

Prototype:

```
void  
MPURegionGet(unsigned long ulRegion,  
              unsigned long *pulAddr,  
              unsigned long *pulFlags)
```

Parameters:

ulRegion is the region number to get.

pulAddr points to storage for the base address of the region.

pulFlags points to the attribute flags for the region.

Description:

This function retrieves the configuration of a specific region. The meanings and format of the parameters is the same as that of the [MPURegionSet\(\)](#) function.

This function can be used to save the configuration of a region for later use with the [MPURegionSet\(\)](#) function. The region's enable state will be preserved in the attributes that are saved.

Returns:

None.

14.2.2.9 MPURegionSet

Sets up the access rules for a specific region.

Prototype:

```
void  
MPURegionSet(unsigned long ulRegion,  
              unsigned long ulAddr,  
              unsigned long ulFlags)
```

Parameters:

ulRegion is the region number to set up.

ulAddr is the base address of the region. It must be aligned according to the size of the region specified in ulFlags.

ulFlags is a set of flags to define the attributes of the region.

Description:

This function sets up the protection rules for a region. The region has a base address and a set of attributes including the size, which must be a power of 2. The base address parameter, *ulAddr*, must be aligned according to the size.

The *ulFlags* parameter is the logical OR of all of the attributes of the region. It is a combination of choices for region size, execute permission, read/write permissions, disabled sub-regions, and a flag to determine if the region is enabled.

The size flag determines the size of a region, and must be one of the following:

- MPU_RGN_SIZE_32B
- MPU_RGN_SIZE_64B
- MPU_RGN_SIZE_128B
- MPU_RGN_SIZE_256B
- MPU_RGN_SIZE_512B
- MPU_RGN_SIZE_1K
- MPU_RGN_SIZE_2K
- MPU_RGN_SIZE_4K
- MPU_RGN_SIZE_8K
- MPU_RGN_SIZE_16K
- MPU_RGN_SIZE_32K
- MPU_RGN_SIZE_64K
- MPU_RGN_SIZE_128K
- MPU_RGN_SIZE_256K

- **MPU_RGN_SIZE_512K**
- **MPU_RGN_SIZE_1M**
- **MPU_RGN_SIZE_2M**
- **MPU_RGN_SIZE_4M**
- **MPU_RGN_SIZE_8M**
- **MPU_RGN_SIZE_16M**
- **MPU_RGN_SIZE_32M**
- **MPU_RGN_SIZE_64M**
- **MPU_RGN_SIZE_128M**
- **MPU_RGN_SIZE_256M**
- **MPU_RGN_SIZE_512M**
- **MPU_RGN_SIZE_1G**
- **MPU_RGN_SIZE_2G**
- **MPU_RGN_SIZE_4G**

The execute permission flag must be one of the following:

- **MPU_RGN_PERM_EXEC** enables the region for execution of code
- **MPU_RGN_PERM_NOEXEC** disables the region for execution of code

The read/write access permissions are applied separately for the privileged and user modes. The read/write access flags must be one of the following:

- **MPU_RGN_PERM_PRV_NO_USR_NO** - no access in privileged or user mode
- **MPU_RGN_PERM_PRV_RW_USR_NO** - privileged read/write, user no access
- **MPU_RGN_PERM_PRV_RW_USR_RO** - privileged read/write, user read-only
- **MPU_RGN_PERM_PRV_RW_USR_RW** - privileged read/write, user read/write
- **MPU_RGN_PERM_PRV_RO_USR_NO** - privileged read-only, user no access
- **MPU_RGN_PERM_PRV_RO_USR_RO** - privileged read-only, user read-only

The region is automatically divided into 8 equally-sized sub-regions by the MPU. Sub-regions can only be used in regions of size 256 bytes or larger. Any of these 8 sub-regions can be disabled. This allows for creation of “holes” in a region which can be left open, or overlaid by another region with different attributes. Any of the 8 sub-regions can be disabled with a logical OR of any of the following flags:

- **MPU_SUB_RGN_DISABLE_0**
- **MPU_SUB_RGN_DISABLE_1**
- **MPU_SUB_RGN_DISABLE_2**
- **MPU_SUB_RGN_DISABLE_3**
- **MPU_SUB_RGN_DISABLE_4**
- **MPU_SUB_RGN_DISABLE_5**
- **MPU_SUB_RGN_DISABLE_6**
- **MPU_SUB_RGN_DISABLE_7**

Finally, the region can be initially enabled or disabled with one of the following flags:

- **MPU_RGN_ENABLE**
- **MPU_RGN_DISABLE**

As an example, to set a region with the following attributes: size of 32 KB, execution enabled, read-only for both privileged and user, one sub-region disabled, and initially enabled; the *ulFlags* parameter would have the following value:

```
(MPU_RG_SIZE_32K | MPU_RGN_PERM_EXEC | MPU_RGN_PERM_PRV_RO_USR_RO |  
MPU_SUB_RGN_DISABLE_2 | MPU_RGN_ENABLE)
```

Note:

This function will write to multiple registers and is not protected from interrupts. It is possible that an interrupt which accesses a region may occur while that region is in the process of being changed. The safest way to handle this is to disable a region before changing it. Refer to the discussion of this in the API Detailed Description section.

Returns:

None.

14.3 Programming Example

The following example sets up a basic set of protection regions to provide the following:

- a 28 KB region in flash for read-only code execution
- 32 KB of RAM for read-write access in privileged and user modes
- an additional 8 KB of RAM for use only in privileged mode
- 1 MB of peripheral space for access only in privileged mode, except for a 128 KB hole that is not accessible at all, and another 128 KB region within that is accessible from user mode

```
//  
// Define a 28 KB region of flash from 0x00000000 to 0x00007000. The  
// region will be executable, and read-only for both privileged and user  
// modes. To set up the region, a 32 KB region (#0) will be defined  
// starting at address 0, and then a 4 KB hole removed at the end by  
// disabling the last sub-region. The region will be initially enabled.  
//  
MPURegionSet(0, 0,  
             MPU_RGN_SIZE_32K |  
             MPU_RGN_PERM_EXEC |  
             MPU_RGN_PERM_PRV_RO_USR_RO |  
             MPU_SUB_RGN_DISABLE_7 |  
             MPU_RGN_ENABLE);  
  
//  
// Define a 32 KB region (#1) of RAM from 0x20000000 to 0x20008000. The  
// region will not be executable, and will be read/write access for  
// privileged and user modes.  
//  
MPURegionSet(1, 0x20000000,  
             MPU_RGN_SIZE_32K |  
             MPU_RGN_PERM_NOEXEC |  
             MPU_RGN_PERM_PRV_RW_USR_RW |  
             MPU_RGN_ENABLE);  
  
//  
// Define an additional 8 KB region (#2) in RAM from 0x20008000 to  
// 0x2000A000, which will be read/write accessible only from privileged  
// mode. This region will be initially disabled, to be enabled later.  
//
```



```

MPURegionSet(2, 0x20008000,
             MPU_RGN_SIZE_8K |
             MPU_RGN_PERM_NOEXEC |
             MPU_RGN_PERM_PRV_RW_USR_NO |
             MPU_RGN_DISABLE);

//
// Define a region (#3) in peripheral space from 0x40000000 to 0x40100000
// (1 MB). This region is accessible only in privileged mode. There is a
// an area from 0x40020000 to 0x40040000 that has no peripherals and is not
// accessible at all. This is created by disabling the second sub-region
// (1) and creating a hole. Further, there is an area from 0x40080000 to
// 0x400A0000 that should be accessible from user mode as well. This is
// created by disabling the fifth sub-region (4), and overlaying an
// additional region (#4) in that space with the appropriate permissions.
//
MPURegionSet(3, 0x40000000,
             MPU_RGN_SIZE_1M |
             MPU_RGN_PERM_NOEXEC |
             MPU_RGN_PERM_PRV_RW_USR_NO |
             MPU_SUB_RGN_DISABLE_1 | MPU_SUB_RGN_DISABLE_4 |
             MPU_RGN_ENABLE);
MPURegionSet(4, 0x40080000,
             MPU_RGN_SIZE_128K |
             MPU_RGN_PERM_NOEXEC |
             MPU_RGN_PERM_PRV_RW_USR_RW |
             MPU_RGN_ENABLE);

//
// In this example, compile-time registration of interrupts is used, so the
// handler does not need to be registered. However, it does need to be
// enabled.
//
IntEnable(FAULT_MPU);

//
// When setting up the regions, region 2 was initially disabled for some
// reason. At some point it needs to be enabled.
//
MPURegionEnable(2);

//
// Now the MPU will be enabled. It will be configured so that a default
// map is available in privileged mode if no regions are defined. The MPU
// will not be enabled for the hard fault and NMI handlers, which means a
// default map will be used whenever these handlers are active, effectively
// giving the fault handlers access to all of memory without any
// protection.
//
MPUEnable(MPU_CONFIG_PRIV_DEFAULT);

//
// At this point the MPU is configured and enabled and if any code causes
// an access violation, the memory management fault will occur.
//

```

The following example shows how to save and restore region configurations.

```

//
// The following arrays provide space for saving the address and
// attributes for 4 region configurations.
//
unsigned long ulRegionAddr[4];
unsigned long ulRegionAttr[4];

```

```
...

//
// At some point in the system code, we want to save the state of 4 regions
// (0-3).
//
for(uIdx = 0; uIdx < 4; uIdx++)
{
    MPURegionGet(uIdx, &ulRegionAddr[uIdx], &ulRegionAttr[uIdx]);
}

...

//
// At some other point, the previously saved regions should be restored.
//
for(uIdx = 0; uIdx < 4; uIdx++)
{
    MPURegionSet(uIdx, ulRegionAddr[uIdx], ulRegionAttr[uIdx]);
}
```

15 Peripheral Pin Mapping

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15.1 Introduction

The peripheral pin mapping functions provide an easy method of configuring a peripheral pin without having to know which GPIO pin is shared with the peripheral pin. This makes peripheral pin configuration easier (and clearer) since the pin can be specified by the peripheral pin name instead of the GPIO name (which may be error prone).

The mapping of peripheral pins to GPIO pins varies from part to part, meaning that the associated definitions change based on the part being used. The part to be used can be specified in two ways; either via an explicit `#define` in the source code or via a definition provided to the compiler. Using a `#define` is very direct, but not very flexible. Using a definition provided to the compiler is not as explicit (since it does not appear clearly in the source code) but is much more flexible. The real value of the peripheral pin mapping functions is the ability to share a piece of peripheral configuration/control code between projects that utilize different parts; if the part definition is provided to the compiler instead of in the source code, each project can provide its own definition and the code will automatically reconfigure itself based on the target part.

Since the peripheral pin mapping functions configure a single pin at a time, it may be more efficient to use the `GPIOPinType*()` functions instead of the `PinType*()` functions, although this requires explicit knowledge of the GPIO pin(s) to be used. For example, it will take four `PinTypeSSI()` calls to configure the four pins on the SSI peripheral, but this could be done with a single call to `GPIOPinTypeSSI()` if the pins are all in the same GPIO module. But using `GPIOPinType*()` instead of `PinType*()` results in the code no longer automatically reconfiguring itself (without the use of explicit conditionals in the code, of course).

This driver is contained in `src/pin_map.h`.

15.2 API Functions

Functions

- void `PinTypeCAN` (unsigned long ulName)
- void `PinTypeComparator` (unsigned long ulName)
- void `PinTypeI2C` (unsigned long ulName)
- void `PinTypePWM` (unsigned long ulName)
- void `PinTypeQEI` (unsigned long ulName)
- void `PinTypeSSI` (unsigned long ulName)
- void `PinTypeTimer` (unsigned long ulName)
- void `PinTypeUART` (unsigned long ulName)

15.2.1 Detailed Description

The peripheral pin mapping functions require that the part being used be specified by a define of the `PART_LM3Sxxx` form. The `xxx` portion is replaced with the part number of the part being used; for example, if using the LM3S6965 microcontroller, the define will be `PART_LM3S6965`. This must be defined before `pin_map.h` is included by the source code.

15.2.2 Function Documentation

15.2.2.1 PinTypeCAN

This function configures the specified CAN pin to function as a CAN pin.

Prototype:

```
void  
PinTypeCAN(unsigned long ulName)
```

Parameters:

ulName is one of the valid names for the CAN pins.

Description:

This function takes one of the valid names for a CAN pin and configures the pin for its CAN functionality depending on the part that is defined.

The valid names for the pins are as follows: **CAN0RX**, **CAN0TX**, **CAN1RX**, **CAN1TX**, **CAN2RX**, or **CAN2TX**.

See also:

[GPIOPinTypeCAN\(\)](#) in order to configure multiple CAN pins at once.

Returns:

None.

15.2.2.2 PinTypeComparator

This function configures the specified comparator pin to function as a comparator pin.

Prototype:

```
void  
PinTypeComparator(unsigned long ulName)
```

Parameters:

ulName is one of the valid names for the Comparator pins.

Description:

This function takes one of the valid names for a comparator pin and configures the pin for its comparator functionality depending on the part that is defined.

The valid names for the pins are as follows: **C0_MINUS**, **C0_PLUS**, **C1_MINUS**, **C1_PLUS**, **C2_MINUS**, or **C2_PLUS**.

See also:

[GPIOPinTypeComparator\(\)](#) in order to configure multiple comparator pins at once.

Returns:

None.

15.2.2.3 PinTypeI2C

This function configures the specified I2C pin to function as an I2C pin.

Prototype:

```
void  
PinTypeI2C(unsigned long ulName)
```

Parameters:

ulName is one of the valid names for the I2C pins.

Description:

This function takes one of the valid names for an I2C pin and configures the pin for its I2C functionality depending on the part that is defined.

The valid names for the pins are as follows: **I2C0SCL**, **I2C0SDA**, **I2C1SCL**, or **I2C1SDA**.

See also:

[GPIOPinTypeI2C\(\)](#) in order to configure multiple I2C pins at once.

Returns:

None.

15.2.2.4 PinTypePWM

This function configures the specified PWM pin to function as a PWM pin.

Prototype:

```
void  
PinTypePWM(unsigned long ulName)
```

Parameters:

ulName is one of the valid names for the PWM pins.

Description:

This function takes one of the valid names for a PWM pin and configures the pin for its PWM functionality depending on the part that is defined.

The valid names for the pins are as follows: **PWM0**, **PWM1**, **PWM2**, **PWM3**, **PWM4**, **PWM5**, or **FAULT**.

See also:

[GPIOPinTypePWM\(\)](#) in order to configure multiple PWM pins at once.

Returns:

None.

15.2.2.5 PinTypeQEI

This function configures the specified QEI pin to function as a QEI pin.

Prototype:

```
void  
PinTypeQEI(unsigned long ulName)
```

Parameters:

ulName is one of the valid names for the QEI pins.

Description:

This function takes one of the valid names for a QEI pin and configures the pin for its QEI functionality depending on the part that is defined.

The valid names for the pins are as follows: **PHA0**, **PHB0**, **IDX0**, **PHA1**, **PHB1**, or **IDX1**.

See also:

[GPIOPinTypeQEI\(\)](#) in order to configure multiple QEI pins at once.

Returns:

None.

15.2.2.6 PinTypeSSI

This function configures the specified SSI pin to function as an SSI pin.

Prototype:

```
void  
PinTypeSSI(unsigned long ulName)
```

Parameters:

ulName is one of the valid names for the SSI pins.

Description:

This function takes one of the valid names for an SSI pin and configures the pin for its SSI functionality depending on the part that is defined.

The valid names for the pins are as follows: **SSI0CLK**, **SSI0FSS**, **SSI0RX**, **SSI0TX**, **SSI1CLK**, **SSI1FSS**, **SSI1RX**, or **SSI1TX**.

See also:

[GPIOPinTypeSSI\(\)](#) in order to configure multiple SSI pins at once.

Returns:

None.

15.2.2.7 PinTypeTimer

This function configures the specified Timer pin to function as a Timer pin.

Prototype:

```
void  
PinTypeTimer(unsigned long ulName)
```

Parameters:

ulName is one of the valid names for the Timer pins.

Description:

This function takes one of the valid names for a Timer pin and configures the pin for its Timer functionality depending on the part that is defined.

The valid names for the pins are as follows: **CCP0**, **CCP1**, **CCP2**, **CCP3**, **CCP4**, **CCP5**, **CCP6**, or **CCP7**.

See also:

[GPIOPinTypeTimer\(\)](#) in order to configure multiple CCP pins at once.

Returns:

None.

15.2.2.8 PinTypeUART

This function configures the specified UART pin to function as a UART pin.

Prototype:

```
void  
PinTypeUART(unsigned long ulName)
```

Parameters:

ulName is one of the valid names for the UART pins.

Description:

This function takes one of the valid names for a UART pin and configures the pin for its UART functionality depending on the part that is defined.

The valid names for the pins are as follows: **U0RX**, **U0TX**, **U1RX**, **U1TX**, **U2RX**, or **U2TX**.

See also:

[GPIOPinTypeUART\(\)](#) in order to configure multiple UART pins at once.

Returns:

None.

15.3 Programming Example

This example shows the difference in code when configuring a PWM pin on two different parts in the same application. In this case, the PWM0 pin is actually on a different GPIO port on the two parts and requires special conditional code if the [GPIOPinTypePWM\(\)](#) function is used directly. Instead, if [PinTypePWM\(\)](#) is used, then the code can remain the same and only the part definition in the project file needs to change.

Example for PWM0 pin configuration using [PinTypePWM\(\)](#):

```
...

//
// Configure the pin for use as a PWM pin.
//
PinTypePWM(PWM0);

...
```

Example for PWM0 pin configuration using [GPIOPinTypePWM\(\)](#):

```
...

#ifdef LM3S2110
//
// Configure the pin for use as a PWM pin.
//
GPIOPinTypePWM(GPIO_PORTF_BASE, GPIO_PIN_0);
#endif
#ifdef LM3S2620
//
// Configure the pin for use as a PWM pin.
//
GPIOPinTypeTimer(GPIO_PORTG_BASE, GPIO_PIN_0);
#endif

...
```


16 Pulse Width Modulator (PWM)

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16.1 Introduction

Each instance of a Stellaris PWM module provides three instances of a PWM generator block, and an output control block. Each generator block has two PWM output signals, which can be operated independently, or as a pair of signals with dead band delays inserted. Each generator block also has an interrupt output and a trigger output. The control block determines the polarity of the PWM signals, and which signals are passed through to the pins.

Some of the features of the Stellaris PWM module are:

- Three generator blocks, each containing
 - One 16-bit down or up/down counter
 - Two comparators
 - PWM generator
 - Dead band generator
- Control block
 - PWM output enable
 - Output polarity control
 - Synchronization
 - Fault handling
 - Interrupt status

This driver is contained in `src/pwm.c`, with `src/pwm.h` containing the API definitions for use by applications.

16.2 API Functions

Functions

- void [PWMDeadBandDisable](#) (unsigned long ulBase, unsigned long ulGen)
- void [PWMDeadBandEnable](#) (unsigned long ulBase, unsigned long ulGen, unsigned short usRise, unsigned short usFall)
- void [PWMFaultIntClear](#) (unsigned long ulBase)
- void [PWMFaultIntRegister](#) (unsigned long ulBase, void (*pfnIntHandler)(void))
- void [PWMFaultIntUnregister](#) (unsigned long ulBase)
- void [PWMGenConfigure](#) (unsigned long ulBase, unsigned long ulGen, unsigned long ulConfig)
- void [PWMGenDisable](#) (unsigned long ulBase, unsigned long ulGen)
- void [PWMGenEnable](#) (unsigned long ulBase, unsigned long ulGen)

- void [PWMGenIntClear](#) (unsigned long ulBase, unsigned long ulGen, unsigned long ulInts)
- void [PWMGenIntRegister](#) (unsigned long ulBase, unsigned long ulGen, void (*pfnIntHandler)(void))
- unsigned long [PWMGenIntStatus](#) (unsigned long ulBase, unsigned long ulGen, tBoolean bMasked)
- void [PWMGenIntTrigDisable](#) (unsigned long ulBase, unsigned long ulGen, unsigned long ulIntTrig)
- void [PWMGenIntTrigEnable](#) (unsigned long ulBase, unsigned long ulGen, unsigned long ulIntTrig)
- void [PWMGenIntUnregister](#) (unsigned long ulBase, unsigned long ulGen)
- unsigned long [PWMGenPeriodGet](#) (unsigned long ulBase, unsigned long ulGen)
- void [PWMGenPeriodSet](#) (unsigned long ulBase, unsigned long ulGen, unsigned long ulPeriod)
- void [PWMIntDisable](#) (unsigned long ulBase, unsigned long ulGenFault)
- void [PWMIntEnable](#) (unsigned long ulBase, unsigned long ulGenFault)
- unsigned long [PWMIntStatus](#) (unsigned long ulBase, tBoolean bMasked)
- void [PWMOutputFault](#) (unsigned long ulBase, unsigned long ulPWMOutBits, tBoolean bFaultKill)
- void [PWMOutputInvert](#) (unsigned long ulBase, unsigned long ulPWMOutBits, tBoolean bInvert)
- void [PWMOutputState](#) (unsigned long ulBase, unsigned long ulPWMOutBits, tBoolean bEnable)
- unsigned long [PWMPulseWidthGet](#) (unsigned long ulBase, unsigned long ulPWMOut)
- void [PWMPulseWidthSet](#) (unsigned long ulBase, unsigned long ulPWMOut, unsigned long ulWidth)
- void [PWMSyncTimeBase](#) (unsigned long ulBase, unsigned long ulGenBits)
- void [PWMSyncUpdate](#) (unsigned long ulBase, unsigned long ulGenBits)

16.2.1 Detailed Description

These are a group of functions for performing high-level operations on PWM modules. Although Stellaris only has one PWM module, these functions are defined to support using multiple instances of PWM modules.

The following functions provide the user with a way to configure the PWM for the most common operations, such as setting the period, generating left and center aligned pulses, modifying the pulse width, and controlling interrupts, triggers, and output characteristics. However, the PWM module is very versatile, and it can be configured in a number of different ways, many of which are beyond the scope of this API. In order to fully exploit the many features of the PWM module, users are advised to use register access macros.

When discussing the various components of a PWM module, this API uses the following labeling convention:

- The three generator blocks are called **Gen0**, **Gen1**, and **Gen2**.
- The two PWM output signals associated with each generator block are called **OutA** and **OutB**.
- The six output signals are called **PWM0**, **PWM1**, **PWM2**, **PWM3**, **PWM4**, and **PWM5**.
- **PWM0** and **PWM1** are associated with **Gen0**, **PWM2** and **PWM3** are associated with **Gen1**, and **PWM4** and **PWM5** are associated with **Gen2**.

Also, as a simplifying assumption for this API, comparator A for each generator block is used exclusively to adjust the pulse width of the even numbered PWM outputs (**PWM0**, **PWM2**, and **PWM4**). In addition, comparator B is used exclusively for the odd numbered PWM outputs (**PWM1**, **PWM3**, **PWM5**).

16.2.2 Function Documentation

16.2.2.1 PWMDeadBandDisable

Disables the PWM dead band output.

Prototype:

```
void
PWMDeadBandDisable(unsigned long ulBase,
                    unsigned long ulGen)
```

Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator to modify. Must be one of **PWM_GEN_0**, **PWM_GEN_1**, or **PWM_GEN_2**.

Description:

This function disables the dead band mode for the specified PWM generator. Doing so decouples the **OutA** and **OutB** signals.

Returns:

None.

16.2.2.2 PWMDeadBandEnable

Enables the PWM dead band output, and sets the dead band delays.

Prototype:

```
void
PWMDeadBandEnable(unsigned long ulBase,
                  unsigned long ulGen,
                  unsigned short usRise,
                  unsigned short usFall)
```

Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator to modify. Must be one of **PWM_GEN_0**, **PWM_GEN_1**, or **PWM_GEN_2**.

usRise specifies the width of delay from the rising edge.

usFall specifies the width of delay from the falling edge.

Description:

This function sets the dead bands for the specified PWM generator, where the dead bands are defined as the number of **PWM** clock ticks from the rising or falling edge of the generator's **OutA** signal. Note that this function causes the coupling of **OutB** to **OutA**.

Returns:

None.

16.2.2.3 PWMFaultIntClear

Clears the fault interrupt for a PWM module.

Prototype:

```
void  
PWMFaultIntClear(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the PWM module.

Description:

Clears the fault interrupt by writing to the appropriate bit of the interrupt status register for the selected PWM module.

Returns:

None.

16.2.2.4 PWMFaultIntRegister

Registers an interrupt handler for a fault condition detected in a PWM module.

Prototype:

```
void  
PWMFaultIntRegister(unsigned long ulBase,  
                    void (*pfnIntHandler)(void))
```

Parameters:

ulBase is the base address of the PWM module.

pfnIntHandler is a pointer to the function to be called when the PWM fault interrupt occurs.

Description:

This function will ensure that the interrupt handler specified by *pfnIntHandler* is called when a fault interrupt is detected for the selected PWM module. This function will also enable the PWM fault interrupt in the NVIC; the PWM fault interrupt must also be enabled at the module level using [PWMIntEnable\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

16.2.2.5 PWMFaultIntUnregister

Removes the PWM fault condition interrupt handler.

Prototype:

```
void  
PWMFaultIntUnregister(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the PWM module.

Description:

This function will remove the interrupt handler for a PWM fault interrupt from the selected PWM module. This function will also disable the PWM fault interrupt in the NVIC; the PWM fault interrupt must also be disabled at the module level using [PWMIntDisable\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

16.2.2.6 PWMGenConfigure

Configures a PWM generator.

Prototype:

```
void  
PWMGenConfigure(unsigned long ulBase,  
                unsigned long ulGen,  
                unsigned long ulConfig)
```

Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator to configure. Must be one of **PWM_GEN_0**, **PWM_GEN_1**, or **PWM_GEN_2**.

ulConfig is the configuration for the PWM generator.

Description:

This function is used to set the mode of operation for a PWM generator. The counting mode, synchronization mode, and debug behavior are all configured. After configuration, the generator is left in the disabled state.

A PWM generator can count in two different modes: count down mode or count up/down mode. In count down mode, it will count from a value down to zero, and then reset to the preset value. This will produce left-aligned PWM signals (that is the rising edge of the two PWM signals produced by the generator will occur at the same time). In count up/down mode, it will count up from zero to the preset value, count back down to zero, and then repeat the process. This will produce center-aligned PWM signals (that is, the middle of the high/low period of the PWM signals produced by the generator will occur at the same time).

When the PWM generator parameters (period and pulse width) are modified, their affect on the output PWM signals can be delayed. In synchronous mode, the parameter updates are not applied until a synchronization event occurs. This allows multiple parameters to be modified and take affect simultaneously, instead of one at a time. Additionally, parameters to multiple PWM generators in synchronous mode can be updated simultaneously, allowing them to be treated as if they were a unified generator. In non-synchronous mode, the parameter updates

are not delayed until a synchronization event. In either mode, the parameter updates only occur when the counter is at zero to help prevent oddly formed PWM signals during the update (that is, a PWM pulse that is too short or too long).

The PWM generator can either pause or continue running when the processor is stopped via the debugger. If configured to pause, it will continue to count until it reaches zero, at which point it will pause until the processor is restarted. If configured to continue running, it will keep counting as if nothing had happened.

The *ulConfig* parameter contains the desired configuration. It is the logical OR of the following: **PWM_GEN_MODE_DOWN** or **PWM_GEN_MODE_UP_DOWN** to specify the counting mode, **PWM_GEN_MODE_SYNC** or **PWM_GEN_MODE_NO_SYNC** to specify the synchronization mode, and **PWM_GEN_MODE_DBG_RUN** or **PWM_GEN_MODE_DBG_STOP** to specify the debug behavior.

Note:

Changes to the counter mode will affect the period of the PWM signals produced. [PWMGenPeriodSet\(\)](#) and [PWMPulseWidthSet\(\)](#) should be called after any changes to the counter mode of a generator.

Returns:

None.

16.2.2.7 PWMGenDisable

Disables the timer/counter for a PWM generator block.

Prototype:

```
void
PWMGenDisable(unsigned long ulBase,
               unsigned long ulGen)
```

Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator to be disabled. Must be one of **PWM_GEN_0**, **PWM_GEN_1**, or **PWM_GEN_2**.

Description:

This function blocks the PWM clock from driving the timer/counter for the specified generator block.

Returns:

None.

16.2.2.8 PWMGenEnable

Enables the timer/counter for a PWM generator block.

Prototype:

```
void
PWMGenEnable(unsigned long ulBase,
              unsigned long ulGen)
```

Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator to be enabled. Must be one of **PWM_GEN_0**, **PWM_GEN_1**, or **PWM_GEN_2**.

Description:

This function allows the PWM clock to drive the timer/counter for the specified generator block.

Returns:

None.

16.2.2.9 PWMGenIntClear

Clears the specified interrupt(s) for the specified PWM generator block.

Prototype:

```
void
PWMGenIntClear(unsigned long ulBase,
               unsigned long ulGen,
               unsigned long ulInts)
```

Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator to query. Must be one of **PWM_GEN_0**, **PWM_GEN_1**, or **PWM_GEN_2**.

ulInts specifies the interrupts to be cleared.

Description:

Clears the specified interrupt(s) by writing a 1 to the specified bits of the interrupt status register for the specified PWM generator. The defined values for the bits are as follows:

- **PWM_INT_CNT_ZERO**
- **PWM_INT_CNT_LOAD**
- **PWM_INT_CNT_AU**
- **PWM_INT_CNT_AD**
- **PWM_INT_CNT_BU**
- **PWM_INT_CNT_BD**

Returns:

None.

16.2.2.10 PWMGenIntRegister

Registers an interrupt handler for the specified PWM generator block.

Prototype:

```
void
PWMGenIntRegister(unsigned long ulBase,
                  unsigned long ulGen,
                  void (*pfnIntHandler)(void))
```

Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator in question.

pfnIntHandler is a pointer to the function to be called when the PWM generator interrupt occurs.

Description:

This function will ensure that the interrupt handler specified by *pfnIntHandler* is called when an interrupt is detected for the specified PWM generator block. This function will also enable the corresponding PWM generator interrupt in the interrupt controller; individual generator interrupts and interrupt sources must be enabled with [PWMIntEnable\(\)](#) and [PWMGenIntTrigEnable\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

16.2.2.11 PWMGenIntStatus

Gets interrupt status for the specified PWM generator block.

Prototype:

```
unsigned long
PWMGenIntStatus(unsigned long ulBase,
                 unsigned long ulGen,
                 tBoolean bMasked)
```

Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator to query. Must be one of **PWM_GEN_0**, **PWM_GEN_1**, or **PWM_GEN_2**.

bMasked specifies whether masked or raw interrupt status is returned.

Description:

If *bMasked* is set as **true**, then the masked interrupt status is returned; otherwise, the raw interrupt status will be returned.

Returns:

Returns the contents of the interrupt status register, or the contents of the raw interrupt status register, for the specified PWM generator.

16.2.2.12 PWMGenIntTrigDisable

Disables interrupts for the specified PWM generator block.

Prototype:

```
void
PWMGenIntTrigDisable(unsigned long ulBase,
                     unsigned long ulGen,
                     unsigned long ulIntTrig)
```


Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator to have interrupts and triggers disabled. Must be one of **PWM_GEN_0**, **PWM_GEN_1**, or **PWM_GEN_2**.

ullIntTrig specifies the interrupts and triggers to be disabled.

Description:

Masks the specified interrupt(s) and trigger(s) by clearing the specified bits of the interrupt/trigger enable register for the specified PWM generator. The defined values for the bits are as follows:

- **PWM_INT_CNT_ZERO**
- **PWM_INT_CNT_LOAD**
- **PWM_INT_CNT_AU**
- **PWM_INT_CNT_AD**
- **PWM_INT_CNT_BU**
- **PWM_INT_CNT_BD**
- **PWM_TR_CNT_ZERO**
- **PWM_TR_CNT_LOAD**
- **PWM_TR_CNT_AU**
- **PWM_TR_CNT_AD**
- **PWM_TR_CNT_BU**
- **PWM_TR_CNT_BD**

Returns:

None.

16.2.2.13 PWMGenIntTrigEnable

Enables interrupts and triggers for the specified PWM generator block.

Prototype:

```
void
PWMGenIntTrigEnable(unsigned long ulBase,
                    unsigned long ulGen,
                    unsigned long ulIntTrig)
```

Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator to have interrupts and triggers enabled. Must be one of **PWM_GEN_0**, **PWM_GEN_1**, or **PWM_GEN_2**.

ullIntTrig specifies the interrupts and triggers to be enabled.

Description:

Unmasks the specified interrupt(s) and trigger(s) by setting the specified bits of the interrupt/trigger enable register for the specified PWM generator. The defined values for the bits are as follows:

- **PWM_INT_CNT_ZERO**
- **PWM_INT_CNT_LOAD**

- PWM_INT_CNT_AU
- PWM_INT_CNT_AD
- PWM_INT_CNT_BU
- PWM_INT_CNT_BD
- PWM_TR_CNT_ZERO
- PWM_TR_CNT_LOAD
- PWM_TR_CNT_AU
- PWM_TR_CNT_AD
- PWM_TR_CNT_BU
- PWM_TR_CNT_BD

Returns:

None.

16.2.2.14 PWMGenIntUnregister

Removes an interrupt handler for the specified PWM generator block.

Prototype:

```
void  
PWMGenIntUnregister(unsigned long ulBase,  
                    unsigned long ulGen)
```

Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator in question.

Description:

This function will unregister the interrupt handler for the specified PWM generator block. This function will also disable the corresponding PWM generator interrupt in the interrupt controller; individual generator interrupts and interrupt sources must be disabled with [PWMIntDisable\(\)](#) and [PWMGenIntTrigDisable\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

16.2.2.15 PWMGenPeriodGet

Gets the period of a PWM generator block.

Prototype:

```
unsigned long  
PWMGenPeriodGet(unsigned long ulBase,  
                unsigned long ulGen)
```

Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator to query. Must be one of **PWM_GEN_0**, **PWM_GEN_1**, or **PWM_GEN_2**.

Description:

This function gets the period of the specified PWM generator block. The period of the generator block is defined as the number of PWM clock ticks between pulses on the generator block zero signal.

If the update of the counter for the specified PWM generator has yet to be completed, the value returned may not be the active period. The value returned is the programmed period, measured in PWM clock ticks.

Returns:

Returns the programmed period of the specified generator block in PWM clock ticks.

16.2.2.16 PWMGenPeriodSet

Set the period of a PWM generator.

Prototype:

```
void  
PWMGenPeriodSet(unsigned long ulBase,  
                unsigned long ulGen,  
                unsigned long ulPeriod)
```

Parameters:

ulBase is the base address of the PWM module.

ulGen is the PWM generator to be modified. Must be one of **PWM_GEN_0**, **PWM_GEN_1**, or **PWM_GEN_2**.

ulPeriod specifies the period of PWM generator output, measured in clock ticks.

Description:

This function sets the period of the specified PWM generator block, where the period of the generator block is defined as the number of PWM clock ticks between pulses on the generator block zero signal.

Note:

Any subsequent calls made to this function before an update occurs will cause the previous values to be overwritten.

Returns:

None.

16.2.2.17 PWMIntDisable

Disables generator and fault interrupts for a PWM module.

Prototype:

```
void  
PWMIntDisable(unsigned long ulBase,  
              unsigned long ulGenFault)
```

Parameters:

ulBase is the base address of the PWM module.

ulGenFault contains the interrupts to be disabled. Must be a logical OR of any of **PWM_INT_GEN_0**, **PWM_INT_GEN_1**, **PWM_INT_GEN_2**, or **PWM_INT_FAULT**.

Description:

Masks the specified interrupt(s) by clearing the specified bits of the interrupt enable register for the selected PWM module.

Returns:

None.

16.2.2.18 PWMIntEnable

Enables generator and fault interrupts for a PWM module.

Prototype:

```
void  
PWMIntEnable(unsigned long ulBase,  
              unsigned long ulGenFault)
```

Parameters:

ulBase is the base address of the PWM module.

ulGenFault contains the interrupts to be enabled. Must be a logical OR of any of **PWM_INT_GEN_0**, **PWM_INT_GEN_1**, **PWM_INT_GEN_2**, or **PWM_INT_FAULT**.

Description:

Unmasks the specified interrupt(s) by setting the specified bits of the interrupt enable register for the selected PWM module.

Returns:

None.

16.2.2.19 PWMIntStatus

Gets the interrupt status for a PWM module.

Prototype:

```
unsigned long  
PWMIntStatus(unsigned long ulBase,  
              tBoolean bMasked)
```

Parameters:

ulBase is the base address of the PWM module.

bMasked specifies whether masked or raw interrupt status is returned.

Description:

If **bMasked** is set as **true**, then the masked interrupt status is returned; otherwise, the raw interrupt status will be returned.

Returns:

The current interrupt status, enumerated as a bit field of **PWM_INT_GEN_0**, **PWM_INT_GEN_1**, **PWM_INT_GEN_2**, and **PWM_INT_FAULT**.

16.2.2.20 PWMOutputFault

Specifies the state of PWM outputs in response to a fault condition.

Prototype:

```
void  
PWMOutputFault(unsigned long ulBase,  
               unsigned long ulPWMOutBits,  
               tBoolean bFaultKill)
```

Parameters:

ulBase is the base address of the PWM module.

ulPWMOutBits are the PWM outputs to be modified. Must be the logical OR of any of **PWM_OUT_0_BIT**, **PWM_OUT_1_BIT**, **PWM_OUT_2_BIT**, **PWM_OUT_3_BIT**, **PWM_OUT_4_BIT**, or **PWM_OUT_5_BIT**.

bFaultKill determines if the signal is killed or passed through during an active fault condition.

Description:

This function sets the fault handling characteristics of the selected PWM outputs. The outputs are selected using the parameter *ulPWMOutBits*. The parameter *bFaultKill* determines the fault handling characteristics for the selected outputs. If *bFaultKill* is **true**, then the selected outputs will be made inactive. If *bFaultKill* is **false**, then the selected outputs are unaffected by the detected fault.

Returns:

None.

16.2.2.21 PWMOutputInvert

Selects the inversion mode for PWM outputs.

Prototype:

```
void  
PWMOutputInvert(unsigned long ulBase,  
               unsigned long ulPWMOutBits,  
               tBoolean bInvert)
```

Parameters:

ulBase is the base address of the PWM module.

ulPWMOutBits are the PWM outputs to be modified. Must be the logical OR of any of **PWM_OUT_0_BIT**, **PWM_OUT_1_BIT**, **PWM_OUT_2_BIT**, **PWM_OUT_3_BIT**, **PWM_OUT_4_BIT**, or **PWM_OUT_5_BIT**.

bInvert determines if the signal is inverted or passed through.

Description:

This function is used to select the inversion mode for the selected PWM outputs. The outputs are selected using the parameter *ulPWMOutBits*. The parameter *bInvert* determines the inversion mode for the selected outputs. If *bInvert* is **true**, this function will cause the specified PWM output signals to be inverted, or made active low. If *bInvert* is **false**, the specified output will be passed through as is, or be made active high.

Returns:

None.

16.2.2.22 PWMOutputState

Enables or disables PWM outputs.

Prototype:

```
void  
PWMOutputState(unsigned long ulBase,  
               unsigned long ulPWMOutBits,  
               tBoolean bEnable)
```

Parameters:

ulBase is the base address of the PWM module.

ulPWMOutBits are the PWM outputs to be modified. Must be the logical OR of any of **PWM_OUT_0_BIT**, **PWM_OUT_1_BIT**, **PWM_OUT_2_BIT**, **PWM_OUT_3_BIT**, **PWM_OUT_4_BIT**, or **PWM_OUT_5_BIT**.

bEnable determines if the signal is enabled or disabled.

Description:

This function is used to enable or disable the selected PWM outputs. The outputs are selected using the parameter *ulPWMOutBits*. The parameter *bEnable* determines the state of the selected outputs. If *bEnable* is **true**, then the selected PWM outputs are enabled, or placed in the active state. If *bEnable* is **false**, then the selected outputs are disabled, or placed in the inactive state.

Returns:

None.

16.2.2.23 PWMPulseWidthGet

Gets the pulse width of a PWM output.

Prototype:

```
unsigned long  
PWMPulseWidthGet(unsigned long ulBase,  
                unsigned long ulPWMOut)
```

Parameters:

ulBase is the base address of the PWM module.

ulPWMOut is the PWM output to query. Must be one of **PWM_OUT_0**, **PWM_OUT_1**, **PWM_OUT_2**, **PWM_OUT_3**, **PWM_OUT_4**, or **PWM_OUT_5**.

Description:

This function gets the currently programmed pulse width for the specified PWM output. If the update of the comparator for the specified output has yet to be completed, the value returned may not be the active pulse width. The value returned is the programmed pulse width, measured in PWM clock ticks.

Returns:

Returns the width of the pulse in PWM clock ticks.

16.2.2.24 PWMPulseWidthSet

Sets the pulse width for the specified PWM output.

Prototype:

```
void  
PWMPulseWidthSet(unsigned long ulBase,  
                  unsigned long ulPWMOut,  
                  unsigned long ulWidth)
```

Parameters:

ulBase is the base address of the PWM module.

ulPWMOut is the PWM output to modify. Must be one of **PWM_OUT_0**, **PWM_OUT_1**, **PWM_OUT_2**, **PWM_OUT_3**, **PWM_OUT_4**, or **PWM_OUT_5**.

ulWidth specifies the width of the positive portion of the pulse.

Description:

This function sets the pulse width for the specified PWM output, where the pulse width is defined as the number of PWM clock ticks.

Note:

Any subsequent calls made to this function before an update occurs will cause the previous values to be overwritten.

Returns:

None.

16.2.2.25 PWMSyncTimeBase

Synchronizes the counters in one or multiple PWM generator blocks.

Prototype:

```
void  
PWMSyncTimeBase(unsigned long ulBase,  
                 unsigned long ulGenBits)
```

Parameters:

ulBase is the base address of the PWM module.

ulGenBits are the PWM generator blocks to be synchronized. Must be the logical OR of any of **PWM_GEN_0_BIT**, **PWM_GEN_1_BIT**, or **PWM_GEN_2_BIT**.

Description:

For the selected PWM module, this function synchronizes the time base of the generator blocks by causing the specified generator counters to be reset to zero.

Returns:

None.

16.2.2.26 PWMSyncUpdate

Synchronizes all pending updates.

Prototype:

```
void  
PWMSyncUpdate(unsigned long ulBase,  
               unsigned long ulGenBits)
```

Parameters:

ulBase is the base address of the PWM module.

ulGenBits are the PWM generator blocks to be updated. Must be the logical OR of any of **PWM_GEN_0_BIT**, **PWM_GEN_1_BIT**, or **PWM_GEN_2_BIT**.

Description:

For the selected PWM generators, this function causes all queued updates to the period or pulse width to be applied the next time the corresponding counter becomes zero.

Returns:

None.

16.3 Programming Example

The following example shows how to use the PWM API to initialize the PWM0 with a 50 KHz frequency, and with a 25% duty cycle on **PWM0** and a 75% duty cycle on **PWM1**.

```
//  
// Configure the PWM generator for count down mode with immediate updates  
// to the parameters.  
//  
PWMGenConfigure(PWM_BASE, PWM_GEN_0,  
                PWM_GEN_MODE_DOWN | PWM_GEN_MODE_NO_SYNC);  
  
//  
// Set the period. For a 50 KHz frequency, the period = 1/50,000, or 20  
// microseconds. For a 20 MHz clock, this translates to 400 clock ticks.  
// Use this value to set the period.  
//  
PWMGenPeriodSet(PWM_BASE, PWM_GEN_0, 400);  
  
//  
// Set the pulse width of PWM0 for a 25% duty cycle.  
//  
PWMPulseWidthSet(PWM_BASE, PWM_OUT_0, 100);  
  
//  
// Set the pulse width of PWM1 for a 75% duty cycle.  
//  
PWMPulseWidthSet(PWM_BASE, PWM_OUT_1, 300);  
  
//  
// Start the timers in generator 0.  
//  
PWMGenEnable(PWM_BASE, PWM_GEN_0);  
  
//  
// Enable the outputs.
```



```
//  
PWMAOutputState(PWM_BASE, (PWM_OUT_0_BIT | PWM_OUT_1_BIT), true);
```


17 Quadrature Encoder (QEI)

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17.1 Introduction

The quadrature encoder API provides a set of functions for dealing with the Quadrature Encoder with Index (QEI). Functions are provided to configure and read the position and velocity captures, register a QEI interrupt handler, and handle QEI interrupt masking/clearing.

The quadrature encoder module provides hardware encoding of the two channels and the index signal from a quadrature encoder device into an absolute or relative position. There is additional hardware for capturing a measure of the encoder velocity, which is simply a count of encoder pulses during a fixed time period; the number of pulses is directly proportional to the encoder speed. Note that the velocity capture can only operate when the position capture is enabled.

The QEI module supports two modes of operation: phase mode and clock/direction mode. In phase mode, the encoder produces two clocks that are 90 degrees out of phase; the edge relationship is used to determine the direction of rotation. In clock/direction mode, the encoder produces a clock signal to indicate steps and a direction signal to indicate the direction of rotation.

When in phase mode, edges on the first channel or edges on both channels can be counted; counting edges on both channels provides higher encoder resolution if required. In either mode, the input signals can be swapped before being processed; this allows wiring mistakes on the circuit board to be corrected without modifying the board.

The index pulse can be used to reset the position counter; this causes the position counter to maintain the absolute encoder position. Otherwise, the position counter maintains the relative position and is never reset.

The velocity capture has a timer to measure equal periods of time. The number of encoder pulses over each time period is accumulated as a measure of the encoder velocity. The running total for the current time period and the final count for the previous time period are available to be read. The final count for the previous time period is usually used as the velocity measure.

The QEI module will generate interrupts when the index pulse is detected, when the velocity timer expires, when the encoder direction changes, and when a phase signal error is detected. These interrupt sources can be individually masked so that only the events of interest cause a processor interrupt.

This driver is contained in `src/qei.c`, with `src/qei.h` containing the API definitions for use by applications.

17.2 API Functions

Functions

- void [QEIConfigure](#) (unsigned long ulBase, unsigned long ulConfig, unsigned long ulMaxPosition)
- long [QEIDirectionGet](#) (unsigned long ulBase)
- void [QEIDisable](#) (unsigned long ulBase)
- void [QEIEnable](#) (unsigned long ulBase)
- tBoolean [QEIErrorGet](#) (unsigned long ulBase)
- void [QEIntClear](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [QEIntDisable](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [QEIntEnable](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [QEIntRegister](#) (unsigned long ulBase, void (*pfnHandler)(void))
- unsigned long [QEIntStatus](#) (unsigned long ulBase, tBoolean bMasked)
- void [QEIntUnregister](#) (unsigned long ulBase)
- unsigned long [QEIPositionGet](#) (unsigned long ulBase)
- void [QEIPositionSet](#) (unsigned long ulBase, unsigned long ulPosition)
- void [QEIVelocityConfigure](#) (unsigned long ulBase, unsigned long ulPreDiv, unsigned long ulPeriod)
- void [QEIVelocityDisable](#) (unsigned long ulBase)
- void [QEIVelocityEnable](#) (unsigned long ulBase)
- unsigned long [QEIVelocityGet](#) (unsigned long ulBase)

17.2.1 Detailed Description

The quadrature encoder API is broken into three groups of functions: those that deal with position capture, those that deal with velocity capture, and those that deal with interrupt handling.

The position capture is managed with [QEIEnable\(\)](#), [QEIDisable\(\)](#), [QEIConfigure\(\)](#), and [QEIPositionSet\(\)](#). The positional information is retrieved with [QEIPositionGet\(\)](#), [QEIDirectionGet\(\)](#), and [QEIErrorGet\(\)](#).

The velocity capture is managed with [QEIVelocityEnable\(\)](#), [QEIVelocityDisable\(\)](#), and [QEIVelocityConfigure\(\)](#). The computed encoder velocity is retrieved with [QEIVelocityGet\(\)](#).

The interrupt handler for the QEI interrupt is managed with [QEIntRegister\(\)](#) and [QEIntUnregister\(\)](#). The individual interrupt sources within the QEI module are managed with [QEIntEnable\(\)](#), [QEIntDisable\(\)](#), [QEIntStatus\(\)](#), and [QEIntClear\(\)](#).

17.2.2 Function Documentation

17.2.2.1 QEIConfigure

Configures the quadrature encoder.

Prototype:

```
void
QEIConfigure(unsigned long ulBase,
             unsigned long ulConfig,
             unsigned long ulMaxPosition)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

ulConfig is the configuration for the quadrature encoder. See below for a description of this parameter.

ulMaxPosition specifies the maximum position value.

Description:

This will configure the operation of the quadrature encoder. The *ulConfig* parameter provides the configuration of the encoder and is the logical OR of several values:

- **QEI_CONFIG_CAPTURE_A** or **QEI_CONFIG_CAPTURE_A_B** to specify if edges on channel A or on both channels A and B should be counted by the position integrator and velocity accumulator.
- **QEI_CONFIG_NO_RESET** or **QEI_CONFIG_RESET_IDX** to specify if the position integrator should be reset when the index pulse is detected.
- **QEI_CONFIG_QUADRATURE** or **QEI_CONFIG_CLOCK_DIR** to specify if quadrature signals are being provided on ChA and ChB, or if a direction signal and a clock are being provided instead.
- **QEI_CONFIG_NO_SWAP** or **QEI_CONFIG_SWAP** to specify if the signals provided on ChA and ChB should be swapped before being processed.

ulMaxPosition is the maximum value of the position integrator, and is the value used to reset the position capture when in index reset mode and moving in the reverse (negative) direction.

Returns:

None.

17.2.2.2 QEIDirectionGet

Gets the current direction of rotation.

Prototype:

```
long
QEIDirectionGet(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

Description:

This returns the current direction of rotation. In this case, current means the most recently detected direction of the encoder; it may not be presently moving but this is the direction it last moved before it stopped.

Returns:

Returns 1 if moving in the forward direction or -1 if moving in the reverse direction.

17.2.2.3 QEIDisable

Disables the quadrature encoder.

Prototype:

```
void  
QEIDisable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

Description:

This will disable operation of the quadrature encoder module.

Returns:

None.

17.2.2.4 QEIEnable

Enables the quadrature encoder.

Prototype:

```
void  
QEIEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

Description:

This will enable operation of the quadrature encoder module. It must be configured before it is enabled.

See also:

[QEIConfigure\(\)](#)

Returns:

None.

17.2.2.5 QEIErrorGet

Gets the encoder error indicator.

Prototype:

```
tBoolean  
QEIErrorGet(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

Description:

This returns the error indicator for the quadrature encoder. It is an error for both of the signals of the quadrature input to change at the same time.

Returns:

Returns **true** if an error has occurred and **false** otherwise.

17.2.2.6 QEIntClear

Clears quadrature encoder interrupt sources.

Prototype:

```
void  
QEIntClear(unsigned long ulBase,  
            unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

ulIntFlags is a bit mask of the interrupt sources to be cleared. Can be any of the **QE_INTERROR**, **QE_INTDIR**, **QE_INTTIMER**, or **QE_INTINDEX** values.

Description:

The specified quadrature encoder interrupt sources are cleared, so that they no longer assert. This must be done in the interrupt handler to keep it from being called again immediately upon exit.

Returns:

None.

17.2.2.7 QEIntDisable

Disables individual quadrature encoder interrupt sources.

Prototype:

```
void  
QEIntDisable(unsigned long ulBase,  
              unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

ulIntFlags is a bit mask of the interrupt sources to be disabled. Can be any of the **QE_INTERROR**, **QE_INTDIR**, **QE_INTTIMER**, or **QE_INTINDEX** values.

Description:

Disables the indicated quadrature encoder interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor.

Returns:

None.

17.2.2.8 QEIntEnable

Enables individual quadrature encoder interrupt sources.

Prototype:

```
void  
QEIntEnable(unsigned long ulBase,  
             unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

ulIntFlags is a bit mask of the interrupt sources to be enabled. Can be any of the **QEI_INTERRUPT**, **QEI_INTDIR**, **QEI_INTTIMER**, or **QEI_INTINDEX** values.

Description:

Enables the indicated quadrature encoder interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor.

Returns:

None.

17.2.2.9 QEIntRegister

Registers an interrupt handler for the quadrature encoder interrupt.

Prototype:

```
void  
QEIntRegister(unsigned long ulBase,  
               void (*pfnHandler)(void))
```

Parameters:

ulBase is the base address of the quadrature encoder module.

pfnHandler is a pointer to the function to be called when the quadrature encoder interrupt occurs.

Description:

This sets the handler to be called when a quadrature encoder interrupt occurs. This will enable the global interrupt in the interrupt controller; specific quadrature encoder interrupts must be enabled via [QEIntEnable\(\)](#). It is the interrupt handler's responsibility to clear the interrupt source via [QEIntClear\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

17.2.2.10 QEIntStatus

Gets the current interrupt status.

Prototype:

```
unsigned long  
QEIntStatus(unsigned long ulBase,  
             tBoolean bMasked)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

bMasked is false if the raw interrupt status is required and true if the masked interrupt status is required.

Description:

This returns the interrupt status for the quadrature encoder module. Either the raw interrupt status or the status of interrupts that are allowed to reflect to the processor can be returned.

Returns:

Returns the current interrupt status, enumerated as a bit field of **QE_INTERRUPT**, **QE_INTDIR**, **QE_INTTIMER**, and **QE_INTINDEX**.

17.2.2.11 QEIntUnregister

Unregisters an interrupt handler for the quadrature encoder interrupt.

Prototype:

```
void  
QEIntUnregister(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

Description:

This function will clear the handler to be called when a quadrature encoder interrupt occurs. This will also mask off the interrupt in the interrupt controller so that the interrupt handler no longer is called.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

17.2.2.12 QEIPositionGet

Gets the current encoder position.

Prototype:

```
unsigned long  
QEIPositionGet(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

Description:

This returns the current position of the encoder. Depending upon the configuration of the encoder, and the incident of an index pulse, this value may or may not contain the expected data (that is, if in reset on index mode, if an index pulse has not been encountered, the position counter will not be aligned with the index pulse yet).

Returns:

The current position of the encoder.

17.2.2.13 QEIPositionSet

Sets the current encoder position.

Prototype:

```
void
QEIPositionSet(unsigned long ulBase,
               unsigned long ulPosition)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

ulPosition is the new position for the encoder.

Description:

This sets the current position of the encoder; the encoder position will then be measured relative to this value.

Returns:

None.

17.2.2.14 QEIVelocityConfigure

Configures the velocity capture.

Prototype:

```
void
QEIVelocityConfigure(unsigned long ulBase,
                    unsigned long ulPreDiv,
                    unsigned long ulPeriod)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

ulPreDiv specifies the predivider applied to the input quadrature signal before it is counted; can be one of **QEI_VELDIV_1**, **QEI_VELDIV_2**, **QEI_VELDIV_4**, **QEI_VELDIV_8**, **QEI_VELDIV_16**, **QEI_VELDIV_32**, **QEI_VELDIV_64**, or **QEI_VELDIV_128**.

ulPeriod specifies the number of clock ticks over which to measure the velocity; must be non-zero.

Description:

This will configure the operation of the velocity capture portion of the quadrature encoder. The position increment signal is predivided as specified by *ulPreDiv* before being accumulated by the velocity capture. The divided signal is accumulated over *ulPeriod* system clock before being saved and resetting the accumulator.

Returns:

None.

17.2.2.15 QEIVelocityDisable

Disables the velocity capture.

Prototype:

```
void  
QEIVelocityDisable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

Description:

This will disable operation of the velocity capture in the quadrature encoder module.

Returns:

None.

17.2.2.16 QEIVelocityEnable

Enables the velocity capture.

Prototype:

```
void  
QEIVelocityEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the quadrature encoder module.

Description:

This will enable operation of the velocity capture in the quadrature encoder module. It must be configured before it is enabled. Velocity capture will not occur if the quadrature encoder is not enabled.

See also:

[QEIVelocityConfigure\(\)](#) and [QEIEnable\(\)](#)

Returns:

None.

17.2.2.17 QEIVelocityGet

Gets the current encoder speed.

Prototype:

```
unsigned long  
QEIVelocityGet(unsigned long ulBase)
```

Parameters:

uiBase is the base address of the quadrature encoder module.

Description:

This returns the current speed of the encoder. The value returned is the number of pulses detected in the specified time period; this number can be multiplied by the number of time periods per second and divided by the number of pulses per revolution to obtain the number of revolutions per second.

Returns:

Returns the number of pulses captured in the given time period.

17.3 Programming Example

The following example shows how to use the Quadrature Encoder API to configure the quadrature encoder read back an absolute position.

```
//
// Configure the quadrature encoder to capture edges on both signals and
// maintain an absolute position by resetting on index pulses. Using a
// 1000 line encoder at four edges per line, there are 4000 pulses per
// revolution; therefore set the maximum position to 3999 since the count
// is zero based.
//
QEIConfigure(QEI_BASE, (QEI_CONFIG_CAPTURE_A_B | QEI_CONFIG_RESET_IDX |
                       QEI_CONFIG_QUADRATURE | QEI_CONFIG_NO_SWAP), 3999);

//
// Enable the quadrature encoder.
//
QEIEnable(QEI_BASE);

//
// Delay for some time...
//

//
// Read the encoder position.
//
QEIPositionGet(QEI_BASE);
```

18 Synchronous Serial Interface (SSI)

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18.1 Introduction

The Synchronous Serial Interface (SSI) module provides the functionality for synchronous serial communications with peripheral devices, and can be configured to use either the Motorola® SPI™, National Semiconductor® Microwire, or the Texas Instruments® synchronous serial interface frame formats. The size of the data frame is also configurable, and can be set to be between 4 and 16 bits, inclusive.

The SSI module performs serial-to-parallel data conversion on data received from a peripheral device, and parallel-to-serial conversion on data transmitted to a peripheral device. The TX and RX paths are buffered with internal FIFOs allowing up to eight 16-bit values to be stored independently.

The SSI module can be configured as either a master or a slave device. As a slave device, the SSI module can also be configured to disable its output, which allows a master device to be coupled with multiple slave devices.

The SSI module also includes a programmable bit rate clock divider and prescaler to generate the output serial clock derived from the SSI module's input clock. Bit rates are generated based on the input clock and the maximum bit rate supported by the connected peripheral.

This driver is contained in `src/ssi.c`, with `src/ssi.h` containing the API definitions for use by applications.

18.2 API Functions

Functions

- void [SSISetExpClk](#) (unsigned long ulBase, unsigned long ulSSIClk, unsigned long ulProtocol, unsigned long ulMode, unsigned long ulBitRate, unsigned long ulDataWidth)
- void [SSIDataGet](#) (unsigned long ulBase, unsigned long *pulData)
- long [SSIDataGetNonBlocking](#) (unsigned long ulBase, unsigned long *pulData)
- void [SSIDataPut](#) (unsigned long ulBase, unsigned long ulData)
- long [SSIDataPutNonBlocking](#) (unsigned long ulBase, unsigned long ulData)
- void [SSIDisable](#) (unsigned long ulBase)
- void [SSIEnable](#) (unsigned long ulBase)
- void [SSIIntClear](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [SSIIntDisable](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [SSIIntEnable](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [SSIIntRegister](#) (unsigned long ulBase, void (*pfnHandler)(void))
- unsigned long [SSIIntStatus](#) (unsigned long ulBase, tBoolean bMasked)
- void [SSIIntUnregister](#) (unsigned long ulBase)

18.2.1 Detailed Description

The SSI API is broken into 3 groups of functions: those that deal with configuration and state, those that handle data, and those that manage interrupts.

The configuration of the SSI module is managed by the [SSISetConfigExpClk\(\)](#) function, while state is managed by the [SSIEnable\(\)](#) and [SSIDisable\(\)](#) functions.

Data handling is performed by the [SSIDataPut\(\)](#), [SSIDataPutNonBlocking\(\)](#), [SSIDataGet\(\)](#), and [SSIDataGetNonBlocking\(\)](#) functions.

Interrupts from the SSI module are managed using the [SSIIntClear\(\)](#), [SSIIntDisable\(\)](#), [SSIIntEnable\(\)](#), [SSIIntRegister\(\)](#), [SSIIntStatus\(\)](#), and [SSIIntUnregister\(\)](#) functions.

The [SSISetConfig\(\)](#), [SSIDataNonBlockingGet\(\)](#), and [SSIDataNonBlockingPut\(\)](#) APIs from previous versions of the peripheral driver library have been replaced by the [SSISetConfigExpClk\(\)](#), [SSIDataGetNonBlocking\(\)](#), and [SSIDataPutNonBlocking\(\)](#) APIs. Macros have been provided in `ssi.h` to map the old APIs to the new APIs, allowing existing applications to link and run with the new APIs. It is recommended that new applications utilize the new APIs in favor of the old ones.

18.2.2 Function Documentation

18.2.2.1 SSISetConfigExpClk

Configures the synchronous serial interface.

Prototype:

```
void
SSISetConfigExpClk(unsigned long ulBase,
                   unsigned long ulSSIClk,
                   unsigned long ulProtocol,
                   unsigned long ulMode,
                   unsigned long ulBitRate,
                   unsigned long ulDataWidth)
```

Parameters:

ulBase specifies the SSI module base address.
ulSSIClk is the rate of the clock supplied to the SSI module.
ulProtocol specifies the data transfer protocol.
ulMode specifies the mode of operation.
ulBitRate specifies the clock rate.
ulDataWidth specifies number of bits transferred per frame.

Description:

This function configures the synchronous serial interface. It sets the SSI protocol, mode of operation, bit rate, and data width.

The *ulProtocol* parameter defines the data frame format. The *ulProtocol* parameter can be one of the following values: **SSI_FRF_MOTO_MODE_0**, **SSI_FRF_MOTO_MODE_1**, **SSI_FRF_MOTO_MODE_2**, **SSI_FRF_MOTO_MODE_3**, **SSI_FRF_TI**, or **SSI_FRF_NMW**. The Motorola frame formats imply the following polarity and phase configurations:

Polarity	Phase	Mode
----------	-------	------

0	0	SSI_FRF_MOTO_MODE_0
0	1	SSI_FRF_MOTO_MODE_1
1	0	SSI_FRF_MOTO_MODE_2
1	1	SSI_FRF_MOTO_MODE_3

The *ulMode* parameter defines the operating mode of the SSI module. The SSI module can operate as a master or slave; if a slave, the SSI can be configured to disable output on its serial output line. The *ulMode* parameter can be one of the following values: **SSI_MODE_MASTER**, **SSI_MODE_SLAVE**, or **SSI_MODE_SLAVE_OD**.

The *ulBitRate* parameter defines the bit rate for the SSI. This bit rate must satisfy the following clock ratio criteria:

- $F_{SSI} \geq 2 * \text{bit rate}$ (master mode)
- $F_{SSI} \geq 12 * \text{bit rate}$ (slave modes)

where F_{SSI} is the frequency of the clock supplied to the SSI module.

The *ulDataWidth* parameter defines the width of the data transfers, and can be a value between 4 and 16, inclusive.

The peripheral clock will be the same as the processor clock. This will be the value returned by [SysCtlClockGet\(\)](#), or it can be explicitly hard coded if it is constant and known (to save the code/execution overhead of a call to [SysCtlClockGet\(\)](#)).

This function replaces the original SSIConfig() API and performs the same actions. A macro is provided in `ssi.h` to map the original API to this API.

Returns:

None.

18.2.2.2 SSIDataGet

Gets a data element from the SSI receive FIFO.

Prototype:

```
void
SSIDataGet(unsigned long ulBase,
            unsigned long *pulData)
```

Parameters:

ulBase specifies the SSI module base address.

pulData pointer to a storage location for data that was received over the SSI interface.

Description:

This function will get received data from the receive FIFO of the specified SSI module, and place that data into the location specified by the *pulData* parameter.

Note:

Only the lower N bits of the value written to *pulData* will contain valid data, where N is the data width as configured by [SSIConfigSetExpClk\(\)](#). For example, if the interface is configured for 8-bit data width, only the lower 8 bits of the value written to *pulData* will contain valid data.

Returns:

None.

18.2.2.3 SSIDataGetNonBlocking

Gets a data element from the SSI receive FIFO.

Prototype:

```
long  
SSIDataGetNonBlocking(unsigned long ulBase,  
                      unsigned long *pulData)
```

Parameters:

ulBase specifies the SSI module base address.

pulData pointer to a storage location for data that was received over the SSI interface.

Description:

This function will get received data from the receive FIFO of the specified SSI module, and place that data into the location specified by the *ulData* parameter. If there is no data in the FIFO, then this function will return a zero.

This function replaces the original `SSIDataNonBlockingGet()` API and performs the same actions. A macro is provided in `ssi.h` to map the original API to this API.

Note:

Only the lower N bits of the value written to *pulData* will contain valid data, where N is the data width as configured by [SSISetExpClk\(\)](#). For example, if the interface is configured for 8-bit data width, only the lower 8 bits of the value written to *pulData* will contain valid data.

Returns:

Returns the number of elements read from the SSI receive FIFO.

18.2.2.4 SSIDataPut

Puts a data element into the SSI transmit FIFO.

Prototype:

```
void  
SSIDataPut(unsigned long ulBase,  
           unsigned long ulData)
```

Parameters:

ulBase specifies the SSI module base address.

ulData data to be transmitted over the SSI interface.

Description:

This function will place the supplied data into the transmit FIFO of the specified SSI module.

Note:

The upper 32 - N bits of the *ulData* will be discarded by the hardware, where N is the data width as configured by [SSISetExpClk\(\)](#). For example, if the interface is configured for 8-bit data width, the upper 24 bits of *ulData* will be discarded.

Returns:

None.

18.2.2.5 SSIDataPutNonBlocking

Puts a data element into the SSI transmit FIFO.

Prototype:

```
long  
SSIDataPutNonBlocking(unsigned long ulBase,  
                      unsigned long ulData)
```

Parameters:

ulBase specifies the SSI module base address.

ulData data to be transmitted over the SSI interface.

Description:

This function will place the supplied data into the transmit FIFO of the specified SSI module. If there is no space in the FIFO, then this function will return a zero.

This function replaces the original `SSIDataNonBlockingPut()` API and performs the same actions. A macro is provided in `ssi.h` to map the original API to this API.

Note:

The upper 32 - N bits of the *ulData* will be discarded by the hardware, where N is the data width as configured by [SSISetExpClk\(\)](#). For example, if the interface is configured for 8-bit data width, the upper 24 bits of *ulData* will be discarded.

Returns:

Returns the number of elements written to the SSI transmit FIFO.

18.2.2.6 SSIDisable

Disables the synchronous serial interface.

Prototype:

```
void  
SSIDisable(unsigned long ulBase)
```

Parameters:

ulBase specifies the SSI module base address.

Description:

This will disable operation of the synchronous serial interface.

Returns:

None.

18.2.2.7 SSIEnable

Enables the synchronous serial interface.

Prototype:

```
void  
SSIEnable(unsigned long ulBase)
```

Parameters:

ulBase specifies the SSI module base address.

Description:

This will enable operation of the synchronous serial interface. It must be configured before it is enabled.

Returns:

None.

18.2.2.8 SSIIIntClear

Clears SSI interrupt sources.

Prototype:

```
void  
SSIIIntClear(unsigned long ulBase,  
             unsigned long ulIntFlags)
```

Parameters:

ulBase specifies the SSI module base address.

ulIntFlags is a bit mask of the interrupt sources to be cleared.

Description:

The specified SSI interrupt sources are cleared, so that they no longer assert. This must be done in the interrupt handler to keep it from being called again immediately upon exit. The ***ulIntFlags*** parameter can consist of either or both the **SSI_RXTO** and **SSI_RXOR** values.

Returns:

None.

18.2.2.9 SSIIIntDisable

Disables individual SSI interrupt sources.

Prototype:

```
void  
SSIIIntDisable(unsigned long ulBase,  
               unsigned long ulIntFlags)
```

Parameters:

ulBase specifies the SSI module base address.

ulIntFlags is a bit mask of the interrupt sources to be disabled.

Description:

Disables the indicated SSI interrupt sources. The ***ulIntFlags*** parameter can be any of the **SSI_TXFF**, **SSI_RXFF**, **SSI_RXTO**, or **SSI_RXOR** values.

Returns:

None.

18.2.2.10 SSIntEnable

Enables individual SSI interrupt sources.

Prototype:

```
void  
SSIntEnable(unsigned long ulBase,  
             unsigned long ulIntFlags)
```

Parameters:

ulBase specifies the SSI module base address.

ulIntFlags is a bit mask of the interrupt sources to be enabled.

Description:

Enables the indicated SSI interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor. The *ulIntFlags* parameter can be any of the **SSI_TXFF**, **SSI_RXFF**, **SSI_RXT0**, or **SSI_RXOR** values.

Returns:

None.

18.2.2.11 SSIntRegister

Registers an interrupt handler for the synchronous serial interface.

Prototype:

```
void  
SSIntRegister(unsigned long ulBase,  
              void (*pfnHandler)(void))
```

Parameters:

ulBase specifies the SSI module base address.

pfnHandler is a pointer to the function to be called when the synchronous serial interface interrupt occurs.

Description:

This sets the handler to be called when an SSI interrupt occurs. This will enable the global interrupt in the interrupt controller; specific SSI interrupts must be enabled via [SSIntEnable\(\)](#). If necessary, it is the interrupt handler's responsibility to clear the interrupt source via [SSIntClear\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

18.2.2.12 SSIntStatus

Gets the current interrupt status.

Prototype:

```
unsigned long  
SSIIntStatus(unsigned long ulBase,  
             tBoolean bMasked)
```

Parameters:

ulBase specifies the SSI module base address.

bMasked is **false** if the raw interrupt status is required and **true** if the masked interrupt status is required.

Description:

This returns the interrupt status for the SSI module. Either the raw interrupt status or the status of interrupts that are allowed to reflect to the processor can be returned.

Returns:

The current interrupt status, enumerated as a bit field of **SSI_TXFF**, **SSI_RXFF**, **SSI_RXTO**, and **SSI_RXOR**.

18.2.2.13 SSIIntUnregister

Unregisters an interrupt handler for the synchronous serial interface.

Prototype:

```
void  
SSIIntUnregister(unsigned long ulBase)
```

Parameters:

ulBase specifies the SSI module base address.

Description:

This function will clear the handler to be called when a SSI interrupt occurs. This will also mask off the interrupt in the interrupt controller so that the interrupt handler no longer is called.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

18.3 Programming Example

The following example shows how to use the SSI API to configure the SSI module as a master device, and how to do a simple send of data.

```
char *pcChars = "SSI Master send data.";  
long lIdx;  
  
//  
// Configure the SSI.  
//  
SSIConfigSetExpClk(SSI_BASE, SysCtlClockGet(), SSI_FRF_MOTO_MODE0,
```

```
        SSI_MODE_MASTER, 2000000, 8);

//
// Enable the SSI module.
//
SSIEnable(SSI_BASE);

//
// Send some data.
//
lIdx = 0;
while (pcChars[lIdx])
{
    if (SSIDataPut (SSI_BASE, pcChars[lIdx]))
    {
        lIdx++;
    }
}
```


19 System Control

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19.1 Introduction

System control determines the overall operation of the device. It controls the clocking of the device, the set of peripherals that are enabled, configuration of the device and its resets, and provides information about the device.

The members of the Stellaris family have a varying peripheral set and memory sizes. The device has a set of read-only registers that indicate the size of the memories, the peripherals that are present, and the pins that are present for peripherals that have a varying number of pins. This information can be used to write adaptive software that will run on more than one member of the Stellaris family.

The device can be clocked from one of five sources: an external oscillator, the main oscillator, the internal oscillator, the internal oscillator divided by four, or the PLL. The PLL can use any of the four oscillators as its input. Since the internal oscillator has a very wide error range ($\pm 50\%$), it cannot be used for applications that require specific timing; its real use is for detecting failures of the main oscillator and the PLL, and for applications that strictly respond to external events and do not use time-based peripherals (such as a UART). When using the PLL, the input clock frequency is constrained to specific frequencies between 3.579545 MHz and 8.192 MHz (that is, the standard crystal frequencies in that range). When direct clocking with an external oscillator or the main oscillator, the frequency is constrained to between 0 Hz and 50 MHz (depending on the part). The internal oscillator is 15 MHz, $\pm 50\%$; its frequency will vary by device, with voltage, and with temperature. The internal oscillator provides no tuning or frequency measurement mechanism; its frequency is not adjustable.

Almost the entire device operates from a single clock. The ADC and PWM blocks have their own clocks. In order to use the ADC, the PLL must be used; the PLL output will be used to create the clock required by the ADC. The PWM has its own optional divider from the system clock; this can be power of two divides between 1 and 64.

Three modes of operation are supported by the Stellaris family: run mode, sleep mode, and deep-sleep mode. In run mode, the processor is actively executing code. In sleep mode, the clocking of the device is unchanged but the processor no longer executes code (and is no longer clocked). In deep-sleep mode, the clocking of the device may change (depending upon the run mode clock configuration) and the processor no longer executes code (and is no longer clocked). An interrupt will return the device to run mode from one of the sleep modes; the sleep modes are entered upon request from the code.

The device has an internal LDO for generating the on-chip 2.5 V power supply; the output voltage of the LDO can be adjusted between 2.25 V and 2.75 V. Depending upon the application, lower voltage may be advantageous for its power savings, or higher voltage may be advantageous for its improved performance. The default setting of 2.5 V is a good compromise between the two, and should not be changed without careful consideration and evaluation.

There are several system events that, when detected, will cause system control to reset the device. These events are the input voltage dropping too low, the LDO voltage dropping too low, an external

reset, a software reset request, and a watchdog timeout. The properties of some of these events can be configured, and the reason for a reset can be determined from system control.

Each peripheral in the device can be individually enabled, disabled, or reset. Additionally, the set of peripherals that remain enabled during sleep mode and deep-sleep mode can be configured, allowing custom sleep and deep-sleep modes to be defined. Care must be taken with deep-sleep mode, though, since in this mode the PLL is no longer used and the system is clocked by the input crystal. Peripherals that depend upon a particular input clock rate (such as a UART) will not operate as expected in deep-sleep mode due to the clock rate change; these peripherals must either be reconfigured upon entry to and exit from deep-sleep mode, or simply not enabled in deep-sleep mode.

There are various system events that, when detected, will cause system control to generate a processor interrupt. These events are the PLL achieving lock, the internal LDO current limit being exceeded, the internal oscillator failing, the main oscillator failing, the input voltage dropping too low, the internal LDO voltage dropping too low, and the PLL failing. Each of these interrupts can be individually enabled or disabled, and the sources must be cleared by the interrupt handler when they occur.

This driver is contained in `src/sysctl.c`, with `src/sysctl.h` containing the API definitions for use by applications.

19.2 API Functions

Functions

- unsigned long [SysCtlADCSpeedGet](#) (void)
- void [SysCtlADCSpeedSet](#) (unsigned long ulSpeed)
- void [SysCtlBrownOutConfigSet](#) (unsigned long ulConfig, unsigned long ulDelay)
- void [SysCtlClkVerificationClear](#) (void)
- unsigned long [SysCtlClockGet](#) (void)
- void [SysCtlClockSet](#) (unsigned long ulConfig)
- void [SysCtlDeepSleep](#) (void)
- unsigned long [SysCtlFlashSizeGet](#) (void)
- void [SysCtlIntClear](#) (unsigned long ulInts)
- void [SysCtlIntDisable](#) (unsigned long ulInts)
- void [SysCtlIntEnable](#) (unsigned long ulInts)
- void [SysCtlIntRegister](#) (void (*pfnHandler)(void))
- unsigned long [SysCtlIntStatus](#) (tBoolean bMasked)
- void [SysCtlIntUnregister](#) (void)
- void [SysCtlIOSCVerificationSet](#) (tBoolean bEnable)
- void [SysCtlLDOConfigSet](#) (unsigned long ulConfig)
- unsigned long [SysCtlLDOGet](#) (void)
- void [SysCtlLDOSet](#) (unsigned long ulVoltage)
- void [SysCtlMOSCVerificationSet](#) (tBoolean bEnable)
- void [SysCtlPeripheralClockGating](#) (tBoolean bEnable)
- void [SysCtlPeripheralDeepSleepDisable](#) (unsigned long ulPeripheral)
- void [SysCtlPeripheralDeepSleepEnable](#) (unsigned long ulPeripheral)

- void [SysCtlPeripheralDisable](#) (unsigned long ulPeripheral)
- void [SysCtlPeripheralEnable](#) (unsigned long ulPeripheral)
- tBoolean [SysCtlPeripheralPresent](#) (unsigned long ulPeripheral)
- void [SysCtlPeripheralReset](#) (unsigned long ulPeripheral)
- void [SysCtlPeripheralSleepDisable](#) (unsigned long ulPeripheral)
- void [SysCtlPeripheralSleepEnable](#) (unsigned long ulPeripheral)
- tBoolean [SysCtlPinPresent](#) (unsigned long ulPin)
- void [SysCtlPLLVerificationSet](#) (tBoolean bEnable)
- unsigned long [SysCtlPWMClockGet](#) (void)
- void [SysCtlPWMClockSet](#) (unsigned long ulConfig)
- void [SysCtlReset](#) (void)
- void [SysCtlResetCauseClear](#) (unsigned long ulCauses)
- unsigned long [SysCtlResetCauseGet](#) (void)
- void [SysCtlSleep](#) (void)
- unsigned long [SysCtlSRAMSizeGet](#) (void)

19.2.1 Detailed Description

The SysCtl API is broken up into eight groups of functions: those that provide device information, those that deal with device clocking, those that provide peripheral control, those that deal with the SysCtl interrupt, those that deal with the LDO, those that deal with sleep modes, those that deal with reset reasons, those that deal with the brown-out reset, and those that deal with clock verification timers.

Information about the device is provided by [SysCtlSRAMSizeGet\(\)](#), [SysCtlFlashSizeGet\(\)](#), [SysCtlPeripheralPresent\(\)](#), and [SysCtlPinPresent\(\)](#).

Clocking of the device is configured with [SysCtlClockSet\(\)](#) and [SysCtlPWMClockSet\(\)](#). Information about device clocking is provided by [SysCtlClockGet\(\)](#) and [SysCtlPWMClockGet\(\)](#).

Peripheral enabling and reset are controlled with [SysCtlPeripheralReset\(\)](#), [SysCtlPeripheralEnable\(\)](#), [SysCtlPeripheralDisable\(\)](#), [SysCtlPeripheralSleepEnable\(\)](#), [SysCtlPeripheralSleepDisable\(\)](#), [SysCtlPeripheralDeepSleepEnable\(\)](#), [SysCtlPeripheralDeepSleepDisable\(\)](#), and [SysCtlPeripheralClockGating\(\)](#).

The system control interrupt is managed with [SysCtlIntRegister\(\)](#), [SysCtlIntUnregister\(\)](#), [SysCtlIntEnable\(\)](#), [SysCtlIntDisable\(\)](#), [SysCtlIntClear\(\)](#), and [SysCtlIntStatus\(\)](#).

The LDO is controlled with [SysCtlLDOSet\(\)](#) and [SysCtlLDOConfigSet\(\)](#). Its status is provided by [SysCtlLDOGet\(\)](#).

The device is put into sleep modes with [SysCtlSleep\(\)](#) and [SysCtlDeepSleep\(\)](#).

The reset reason is managed with [SysCtlResetCauseGet\(\)](#) and [SysCtlResetCauseClear\(\)](#). A software reset is performed with [SysCtlReset\(\)](#).

The brown-out reset is configured with [SysCtlBrownOutConfigSet\(\)](#).

The clock verification timers are managed with [SysCtlIOSCVerificationSet\(\)](#), [SysCtlMOSCVerificationSet\(\)](#), [SysCtlPLLVerificationSet\(\)](#), and [SysCtlClkVerificationClear\(\)](#).

19.2.2 Function Documentation

19.2.2.1 SysCtlADCSpeedGet

Gets the sample rate of the ADC.

Prototype:

```
unsigned long  
SysCtlADCSpeedGet(void)
```

Description:

This function gets the current sample rate of the ADC.

Returns:

Returns the current ADC sample rate; will be one of **SYSCTL_ADCSPEED_1MSPS**, **SYSCTL_ADCSPEED_500KSPS**, **SYSCTL_ADCSPEED_250KSPS**, or **SYSCTL_ADCSPEED_125KSPS**.

19.2.2.2 SysCtlADCSpeedSet

Sets the sample rate of the ADC.

Prototype:

```
void  
SysCtlADCSpeedSet(unsigned long ulSpeed)
```

Parameters:

ulSpeed is the desired sample rate of the ADC; must be one of **SYSCTL_ADCSPEED_1MSPS**, **SYSCTL_ADCSPEED_500KSPS**, **SYSCTL_ADCSPEED_250KSPS**, or **SYSCTL_ADCSPEED_125KSPS**.

Description:

This function sets the rate at which the ADC samples are captured by the ADC block. The sampling speed may be limited by the hardware, so the sample rate may end up being slower than requested. [SysCtlADCSpeedGet\(\)](#) will return the actual speed in use.

Returns:

None.

19.2.2.3 SysCtlBrownOutConfigSet

Configures the brown-out control.

Prototype:

```
void  
SysCtlBrownOutConfigSet(unsigned long ulConfig,  
                          unsigned long ulDelay)
```

Parameters:

ulConfig is the desired configuration of the brown-out control. Must be the logical OR of **SYSCTL_BOR_RESET** and/or **SYSCTL_BOR_RESAMPLE**.

uiDelay is the number of internal oscillator cycles to wait before resampling an asserted brown-out signal. This value only has meaning when **SYSCTL_BOR_RESAMPLE** is set and must be less than 8192.

Description:

This function configures how the brown-out control operates. It can detect a brown-out by looking at only the brown-out output, or it can wait for it to be active for two consecutive samples separated by a configurable time. When it detects a brown-out condition, it can either reset the device or generate a processor interrupt.

Returns:

None.

19.2.2.4 SysCtlClkVerificationClear

Clears the clock verification status.

Prototype:

```
void  
SysCtlClkVerificationClear(void)
```

Description:

This function clears the status of the clock verification timers, allowing them to assert another failure if detected.

The clock verification timers are only available on Sandstorm-class devices.

Returns:

None.

19.2.2.5 SysCtlClockGet

Gets the processor clock rate.

Prototype:

```
unsigned long  
SysCtlClockGet(void)
```

Description:

This function determines the clock rate of the processor clock. This is also the clock rate of all the peripheral modules (with the exception of PWM, which has its own clock divider).

Note:

This will not return accurate results if [SysCtlClockSet\(\)](#) has not been called to configure the clocking of the device, or if the device is directly clocked from a crystal (or a clock source) that is not one of the supported crystal frequencies. In the later case, this function should be modified to directly return the correct system clock rate.

Returns:

The processor clock rate.

19.2.2.6 SysCtlClockSet

Sets the clocking of the device.

Prototype:

```
void  
SysCtlClockSet(unsigned long ulConfig)
```

Parameters:

ulConfig is the required configuration of the device clocking.

Description:

This function configures the clocking of the device. The input crystal frequency, oscillator to be used, use of the PLL, and the system clock divider are all configured with this function.

The *ulConfig* parameter is the logical OR of several different values, many of which are grouped into sets where only one can be chosen.

The system clock divider is chosen with one of the following values: **SYSCTL_SYSDIV_1**, **SYSCTL_SYSDIV_2**, **SYSCTL_SYSDIV_3**, ... **SYSCTL_SYSDIV_64**. Only **SYSCTL_SYSDIV_1** through **SYSCTL_SYSDIV_16** are valid on Sandstorm-class devices.

The use of the PLL is chosen with either **SYSCTL_USE_PLL** or **SYSCTL_USE_OSC**.

The external crystal frequency is chosen with one of the following values: **SYSCTL_XTAL_1MHZ**, **SYSCTL_XTAL_1_84MHZ**, **SYSCTL_XTAL_2MHZ**, **SYSCTL_XTAL_2_45MHZ**, **SYSCTL_XTAL_3_57MHZ**, **SYSCTL_XTAL_3_68MHZ**, **SYSCTL_XTAL_4MHZ**, **SYSCTL_XTAL_4_09MHZ**, **SYSCTL_XTAL_4_91MHZ**, **SYSCTL_XTAL_5MHZ**, **SYSCTL_XTAL_5_12MHZ**, **SYSCTL_XTAL_6MHZ**, **SYSCTL_XTAL_6_14MHZ**, **SYSCTL_XTAL_7_37MHZ**, **SYSCTL_XTAL_8MHZ**, or **SYSCTL_XTAL_8_19MHZ**. Values below **SYSCTL_XTAL_3_57MHZ** are not valid when the PLL is in operation.

The oscillator source is chosen with one of the following values: **SYSCTL_OSC_MAIN**, **SYSCTL_OSC_INT**, **SYSCTL_OSC_INT4**, **SYSCTL_OSC_INT30**, or **SYSCTL_OSC_EXT32**. On Sandstorm-class devices, **SYSCTL_OSC_INT30** and **SYSCTL_OSC_EXT32** are not valid. **SYSCTL_OSC_EXT32** is only available on Fury-class devices with the hibernate module, and then only when the hibernate module has been enabled.

The internal and main oscillators are disabled with the **SYSCTL_INT_OSC_DIS** and **SYSCTL_MAIN_OSC_DIS** flags, respectively. The external oscillator must be enabled in order to use an external clock source. Note that attempts to disable the oscillator used to clock the device will be prevented by the hardware.

To clock the system from an external source (such as an external crystal oscillator), use **SYSCTL_USE_OSC | SYSCTL_OSC_MAIN**. To clock the system from the main oscillator, use **SYSCTL_USE_OSC | SYSCTL_OSC_MAIN**. To clock the system from the PLL, use **SYSCTL_USE_PLL | SYSCTL_OSC_MAIN**, and select the appropriate crystal with one of the **SYSCTL_XTAL_xxx** values.

Note:

If selecting the PLL as the system clock source (that is, via **SYSCTL_USE_PLL**), this function will poll the PLL lock interrupt to determine when the PLL has locked. If an interrupt handler for the system control interrupt is in place, and it responds to and clears the PLL lock interrupt, this function will delay until its timeout has occurred instead of completing as soon as PLL lock is achieved.

Returns:

None.

19.2.2.7 SysCtlDeepSleep

Puts the processor into deep-sleep mode.

Prototype:

```
void  
SysCtlDeepSleep(void)
```

Description:

This function places the processor into deep-sleep mode; it will not return until the processor returns to run mode. The peripherals that are enabled via [SysCtlPeripheralDeepSleepEnable\(\)](#) continue to operate and can wake up the processor (if automatic clock gating is enabled with [SysCtlPeripheralClockGating\(\)](#), otherwise all peripherals continue to operate).

Returns:

None.

19.2.2.8 SysCtlFlashSizeGet

Gets the size of the flash.

Prototype:

```
unsigned long  
SysCtlFlashSizeGet(void)
```

Description:

This function determines the size of the flash on the Stellaris device.

Returns:

The total number of bytes of flash.

19.2.2.9 SysCtlIntClear

Clears system control interrupt sources.

Prototype:

```
void  
SysCtlIntClear(unsigned long ulInts)
```

Parameters:

ulInts is a bit mask of the interrupt sources to be cleared. Must be a logical OR of **SYSCCTL_INT_PLL_LOCK**, **SYSCCTL_INT_CUR_LIMIT**, **SYSCCTL_INT_IOSC_FAIL**, **SYSCCTL_INT_MOSC_FAIL**, **SYSCCTL_INT_POR**, **SYSCCTL_INT_BOR**, and/or **SYSCCTL_INT_PLL_FAIL**.

Description:

The specified system control interrupt sources are cleared, so that they no longer assert. This must be done in the interrupt handler to keep it from being called again immediately upon exit.

Returns:

None.

19.2.2.10 SysCtlIntDisable

Disables individual system control interrupt sources.

Prototype:

```
void  
SysCtlIntDisable(unsigned long ulInts)
```

Parameters:

ulInts is a bit mask of the interrupt sources to be disabled. Must be a logical OR of **SYSCTL_INT_PLL_LOCK**, **SYSCTL_INT_CUR_LIMIT**, **SYSCTL_INT_IOSC_FAIL**, **SYSCTL_INT_MOSC_FAIL**, **SYSCTL_INT_POR**, **SYSCTL_INT_BOR**, and/or **SYSCTL_INT_PLL_FAIL**.

Description:

Disables the indicated system control interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor.

Returns:

None.

19.2.2.11 SysCtlIntEnable

Enables individual system control interrupt sources.

Prototype:

```
void  
SysCtlIntEnable(unsigned long ulInts)
```

Parameters:

ulInts is a bit mask of the interrupt sources to be enabled. Must be a logical OR of **SYSCTL_INT_PLL_LOCK**, **SYSCTL_INT_CUR_LIMIT**, **SYSCTL_INT_IOSC_FAIL**, **SYSCTL_INT_MOSC_FAIL**, **SYSCTL_INT_POR**, **SYSCTL_INT_BOR**, and/or **SYSCTL_INT_PLL_FAIL**.

Description:

Enables the indicated system control interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor.

Returns:

None.

19.2.2.12 SysCtlIntRegister

Registers an interrupt handler for the system control interrupt.

Prototype:

```
void  
SysCtlIntRegister(void (*pfnHandler)(void))
```

Parameters:

pfnHandler is a pointer to the function to be called when the system control interrupt occurs.

Description:

This sets the handler to be called when a system control interrupt occurs. This will enable the global interrupt in the interrupt controller; specific system control interrupts must be enabled via [SysCtlIntEnable\(\)](#). It is the interrupt handler's responsibility to clear the interrupt source via [SysCtlIntClear\(\)](#).

System control can generate interrupts when the PLL achieves lock, if the internal LDO current limit is exceeded, if the internal oscillator fails, if the main oscillator fails, if the internal LDO output voltage droops too much, if the external voltage droops too much, or if the PLL fails.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

19.2.2.13 SysCtlIntStatus

Gets the current interrupt status.

Prototype:

```
unsigned long  
SysCtlIntStatus(tBoolean bMasked)
```

Parameters:

bMasked is false if the raw interrupt status is required and true if the masked interrupt status is required.

Description:

This returns the interrupt status for the system controller. Either the raw interrupt status or the status of interrupts that are allowed to reflect to the processor can be returned.

Returns:

The current interrupt status, enumerated as a bit field of **SYSCTL_INT_PLL_LOCK**, **SYSCTL_INT_CUR_LIMIT**, **SYSCTL_INT_IOSCL_FAIL**, **SYSCTL_INT_MOSC_FAIL**, **SYSCTL_INT_POR**, **SYSCTL_INT_BOR**, and **SYSCTL_INT_PLL_FAIL**.

19.2.2.14 SysCtlIntUnregister

Unregisters the interrupt handler for the system control interrupt.

Prototype:

```
void  
SysCtlIntUnregister(void)
```

Description:

This function will clear the handler to be called when a system control interrupt occurs. This will also mask off the interrupt in the interrupt controller so that the interrupt handler no longer is called.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

19.2.2.15 SysCtlIOSCVerificationSet

Configures the internal oscillator verification timer.

Prototype:

```
void  
SysCtlIOSCVerificationSet(tBoolean bEnable)
```

Parameters:

bEnable is a boolean that is **true** if the internal oscillator verification timer should be enabled.

Description:

This function allows the internal oscillator verification timer to be enabled or disabled. When enabled, an interrupt will be generated if the internal oscillator ceases to operate.

The internal oscillator verification timer is only available on Sandstorm-class devices.

Note:

Both oscillators (main and internal) must be enabled for this verification timer to operate as the main oscillator will verify the internal oscillator.

Returns:

None.

19.2.2.16 SysCtlLDOConfigSet

Configures the LDO failure control.

Prototype:

```
void  
SysCtlLDOConfigSet(unsigned long ulConfig)
```

Parameters:

ulConfig is the required LDO failure control setting; can be either **SYSCCTL_LDOCFG_ARST** or **SYSCCTL_LDOCFG_NORST**.

Description:

This function allows the LDO to be configured to cause a processor reset when the output voltage becomes unregulated.

The LDO failure control is only available on Sandstorm-class devices.

Returns:

None.

19.2.2.17 SysCtlLDOGet

Gets the output voltage of the LDO.

Prototype:

```
unsigned long  
SysCtlLDOGet(void)
```

Description:

This function determines the output voltage of the LDO, as specified by the control register.

Returns:

Returns the current voltage of the LDO; will be one of **SYSCTL_LDO_2_25V**, **SYSCTL_LDO_2_30V**, **SYSCTL_LDO_2_35V**, **SYSCTL_LDO_2_40V**, **SYSCTL_LDO_2_45V**, **SYSCTL_LDO_2_50V**, **SYSCTL_LDO_2_55V**, **SYSCTL_LDO_2_60V**, **SYSCTL_LDO_2_65V**, **SYSCTL_LDO_2_70V**, or **SYSCTL_LDO_2_75V**.

19.2.2.18 SysCtlLDOSet

Sets the output voltage of the LDO.

Prototype:

```
void  
SysCtlLDOSet(unsigned long ulVoltage)
```

Parameters:

ulVoltage is the required output voltage from the LDO. Must be one of **SYSCTL_LDO_2_25V**, **SYSCTL_LDO_2_30V**, **SYSCTL_LDO_2_35V**, **SYSCTL_LDO_2_40V**, **SYSCTL_LDO_2_45V**, **SYSCTL_LDO_2_50V**, **SYSCTL_LDO_2_55V**, **SYSCTL_LDO_2_60V**, **SYSCTL_LDO_2_65V**, **SYSCTL_LDO_2_70V**, or **SYSCTL_LDO_2_75V**.

Description:

This function sets the output voltage of the LDO. The default voltage is 2.5 V; it can be adjusted +/- 10%.

Returns:

None.

19.2.2.19 SysCtlMOSCVerificationSet

Configures the main oscillator verification timer.

Prototype:

```
void  
SysCtlMOSCVerificationSet (tBoolean bEnable)
```

Parameters:

bEnable is a boolean that is **true** if the main oscillator verification timer should be enabled.

Description:

This function allows the main oscillator verification timer to be enabled or disabled. When enabled, an interrupt will be generated if the main oscillator ceases to operate.

The main oscillator verification timer is only available on Sandstorm-class devices.

Note:

Both oscillators (main and internal) must be enabled for this verification timer to operate as the internal oscillator will verify the main oscillator.

Returns:

None.

19.2.2.20 SysCtlPeripheralClockGating

Controls peripheral clock gating in sleep and deep-sleep mode.

Prototype:

```
void  
SysCtlPeripheralClockGating (tBoolean bEnable)
```

Parameters:

bEnable is a boolean that is **true** if the sleep and deep-sleep peripheral configuration should be used and **false** if not.

Description:

This function controls how peripherals are clocked when the processor goes into sleep or deep-sleep mode. By default, the peripherals are clocked the same as in run mode; if peripheral clock gating is enabled they are clocked according to the configuration set by [SysCtlPeripheralSleepEnable\(\)](#), [SysCtlPeripheralSleepDisable\(\)](#), [SysCtlPeripheralDeepSleepEnable\(\)](#), and [SysCtlPeripheralDeepSleepDisable\(\)](#).

Returns:

None.

19.2.2.21 SysCtlPeripheralDeepSleepDisable

Disables a peripheral in deep-sleep mode.

Prototype:

```
void  
SysCtlPeripheralDeepSleepDisable (unsigned long ulPeripheral)
```

Parameters:

ulPeripheral is the peripheral to disable in deep-sleep mode.

Description:

This function causes a peripheral to stop operating when the processor goes into deep-sleep mode. Disabling peripherals while in deep-sleep mode helps to lower the current draw of the device, and can keep peripherals that require a particular clock frequency from operating when the clock changes as a result of entering deep-sleep mode. If enabled (via [SysCtlPeripheralEnable\(\)](#)), the peripheral will automatically resume operation when the processor leaves deep-sleep mode, maintaining its entire state from before deep-sleep mode was entered.

Deep-sleep mode clocking of peripherals must be enabled via [SysCtlPeripheralClockGating\(\)](#); if disabled, the peripheral deep-sleep mode configuration is maintained but has no effect when deep-sleep mode is entered.

The *ulPeripheral* parameter must be one of the following values: **SYSCCTL_PERIPH_ADC**, **SYSCCTL_PERIPH_CAN0**, **SYSCCTL_PERIPH_CAN1**, **SYSCCTL_PERIPH_CAN2**, **SYSCCTL_PERIPH_COMP0**, **SYSCCTL_PERIPH_COMP1**, **SYSCCTL_PERIPH_COMP2**, **SYSCCTL_PERIPH_ETH**, **SYSCCTL_PERIPH_GPIOA**, **SYSCCTL_PERIPH_GPIOB**, **SYSCCTL_PERIPH_GPIOC**, **SYSCCTL_PERIPH_GPIOD**, **SYSCCTL_PERIPH_GPIOE**, **SYSCCTL_PERIPH_GPIOF**, **SYSCCTL_PERIPH_GPIOG**, **SYSCCTL_PERIPH_GPIOH**, **SYSCCTL_PERIPH_HIBERNATE**, **SYSCCTL_PERIPH_I2C0**, **SYSCCTL_PERIPH_I2C1**, **SYSCCTL_PERIPH_PWM**, **SYSCCTL_PERIPH_QEI0**, **SYSCCTL_PERIPH_QEI1**, **SYSCCTL_PERIPH_SSI0**, **SYSCCTL_PERIPH_SSI1**, **SYSCCTL_PERIPH_TIMER0**, **SYSCCTL_PERIPH_TIMER1**, **SYSCCTL_PERIPH_TIMER2**, **SYSCCTL_PERIPH_TIMER3**, **SYSCCTL_PERIPH_UART0**, **SYSCCTL_PERIPH_UART1**, **SYSCCTL_PERIPH_UART2**, or **SYSCCTL_PERIPH_WDOG**.

Returns:

None.

19.2.2.22 SysCtlPeripheralDeepSleepEnable

Enables a peripheral in deep-sleep mode.

Prototype:

```
void
SysCtlPeripheralDeepSleepEnable(unsigned long ulPeripheral)
```

Parameters:

ulPeripheral is the peripheral to enable in deep-sleep mode.

Description:

This function allows a peripheral to continue operating when the processor goes into deep-sleep mode. Since the clocking configuration of the device may change, not all peripherals can safely continue operating while the processor is in sleep mode. Those that must run at a particular frequency (such as a UART) will not work as expected if the clock changes. It is the responsibility of the caller to make sensible choices.

Deep-sleep mode clocking of peripherals must be enabled via [SysCtlPeripheralClockGating\(\)](#); if disabled, the peripheral deep-sleep mode configuration is maintained but has no effect when deep-sleep mode is entered.

The *ulPeripheral* parameter must be one of the following values: **SYSCCTL_PERIPH_ADC**, **SYSCCTL_PERIPH_CAN0**, **SYSCCTL_PERIPH_CAN1**, **SYSCCTL_PERIPH_CAN2**,

SYSCTL_PERIPH_COMP0, SYSCTL_PERIPH_COMP1, SYSCTL_PERIPH_COMP2,
SYSCTL_PERIPH_ETH, SYSCTL_PERIPH_GPIOA, SYSCTL_PERIPH_GPIOB,
SYSCTL_PERIPH_GPIOC, SYSCTL_PERIPH_GPIOD, SYSCTL_PERIPH_GPIOE,
SYSCTL_PERIPH_GPIOF, SYSCTL_PERIPH_GPIOG, SYSCTL_PERIPH_GPIOH,
SYSCTL_PERIPH_HIBERNATE, SYSCTL_PERIPH_I2C0, SYSCTL_PERIPH_I2C1,
SYSCTL_PERIPH_PWM, SYSCTL_PERIPH_QEI0, SYSCTL_PERIPH_QEI1,
SYSCTL_PERIPH_SSI0, SYSCTL_PERIPH_SSI1, SYSCTL_PERIPH_TIMER0,
SYSCTL_PERIPH_TIMER1, SYSCTL_PERIPH_TIMER2, SYSCTL_PERIPH_TIMER3,
SYSCTL_PERIPH_UART0, SYSCTL_PERIPH_UART1, SYSCTL_PERIPH_UART2, or
SYSCTL_PERIPH_WDOG.

Returns:

None.

19.2.2.23 SysCtlPeripheralDisable

Disables a peripheral.

Prototype:

```
void  
SysCtlPeripheralDisable(unsigned long ulPeripheral)
```

Parameters:

ulPeripheral is the peripheral to disable.

Description:

Peripherals are disabled with this function. Once disabled, they will not operate or respond to register reads/writes.

The *ulPeripheral* parameter must be only one of the following values: SYSCTL_PERIPH_ADC, SYSCTL_PERIPH_CAN0, SYSCTL_PERIPH_CAN1, SYSCTL_PERIPH_CAN2, SYSCTL_PERIPH_COMP0, SYSCTL_PERIPH_COMP1, SYSCTL_PERIPH_COMP2, SYSCTL_PERIPH_ETH, SYSCTL_PERIPH_GPIOA, SYSCTL_PERIPH_GPIOB, SYSCTL_PERIPH_GPIOC, SYSCTL_PERIPH_GPIOD, SYSCTL_PERIPH_GPIOE, SYSCTL_PERIPH_GPIOF, SYSCTL_PERIPH_GPIOG, SYSCTL_PERIPH_GPIOH, SYSCTL_PERIPH_HIBERNATE, SYSCTL_PERIPH_I2C0, SYSCTL_PERIPH_I2C1, SYSCTL_PERIPH_PWM, SYSCTL_PERIPH_QEI0, SYSCTL_PERIPH_QEI1, SYSCTL_PERIPH_SSI0, SYSCTL_PERIPH_SSI1, SYSCTL_PERIPH_TIMER0, SYSCTL_PERIPH_TIMER1, SYSCTL_PERIPH_TIMER2, SYSCTL_PERIPH_TIMER3, SYSCTL_PERIPH_UART0, SYSCTL_PERIPH_UART1, SYSCTL_PERIPH_UART2, or SYSCTL_PERIPH_WDOG.

Returns:

None.

19.2.2.24 SysCtlPeripheralEnable

Enables a peripheral.

Prototype:

```
void  
SysCtlPeripheralEnable(unsigned long ulPeripheral)
```

Parameters:

ulPeripheral is the peripheral to enable.

Description:

Peripherals are enabled with this function. At power-up, all peripherals are disabled; they must be enabled in order to operate or respond to register reads/writes.

The *ulPeripheral* parameter must be only one of the following values: **SYSCTL_PERIPH_ADC**, **SYSCTL_PERIPH_CAN0**, **SYSCTL_PERIPH_CAN1**, **SYSCTL_PERIPH_CAN2**, **SYSCTL_PERIPH_COMP0**, **SYSCTL_PERIPH_COMP1**, **SYSCTL_PERIPH_COMP2**, **SYSCTL_PERIPH_ETH**, **SYSCTL_PERIPH_GPIOA**, **SYSCTL_PERIPH_GPIOB**, **SYSCTL_PERIPH_GPIOC**, **SYSCTL_PERIPH_GPIOD**, **SYSCTL_PERIPH_GPIOE**, **SYSCTL_PERIPH_GPIOF**, **SYSCTL_PERIPH_GPIOG**, **SYSCTL_PERIPH_GPIOH**, **SYSCTL_PERIPH_HIBERNATE**, **SYSCTL_PERIPH_I2C0**, **SYSCTL_PERIPH_I2C1**, **SYSCTL_PERIPH_PWM**, **SYSCTL_PERIPH_QEI0**, **SYSCTL_PERIPH_QEI1**, **SYSCTL_PERIPH_SSI0**, **SYSCTL_PERIPH_SSI1**, **SYSCTL_PERIPH_TIMER0**, **SYSCTL_PERIPH_TIMER1**, **SYSCTL_PERIPH_TIMER2**, **SYSCTL_PERIPH_TIMER3**, **SYSCTL_PERIPH_UART0**, **SYSCTL_PERIPH_UART1**, **SYSCTL_PERIPH_UART2**, or **SYSCTL_PERIPH_WDOG**.

Returns:

None.

19.2.2.25 SysCtlPeripheralPresent

Determines if a peripheral is present.

Prototype:

```
tBoolean  
SysCtlPeripheralPresent(unsigned long ulPeripheral)
```

Parameters:

ulPeripheral is the peripheral in question.

Description:

Determines if a particular peripheral is present in the device. Each member of the Stellaris family has a different peripheral set; this will determine which are present on this device.

The *ulPeripheral* parameter must be only one of the following values: **SYSCTL_PERIPH_ADC**, **SYSCTL_PERIPH_CAN0**, **SYSCTL_PERIPH_CAN1**, **SYSCTL_PERIPH_CAN2**, **SYSCTL_PERIPH_COMP0**, **SYSCTL_PERIPH_COMP1**, **SYSCTL_PERIPH_COMP2**, **SYSCTL_PERIPH_ETH**, **SYSCTL_PERIPH_GPIOA**, **SYSCTL_PERIPH_GPIOB**, **SYSCTL_PERIPH_GPIOC**, **SYSCTL_PERIPH_GPIOD**, **SYSCTL_PERIPH_GPIOE**, **SYSCTL_PERIPH_GPIOF**, **SYSCTL_PERIPH_GPIOG**, **SYSCTL_PERIPH_GPIOH**, **SYSCTL_PERIPH_HIBERNATE**, **SYSCTL_PERIPH_I2C0**, **SYSCTL_PERIPH_I2C1**, **SYSCTL_PERIPH_IEEE1588**, **SYSCTL_PERIPH_MPU**, **SYSCTL_PERIPH_PLL**, **SYSCTL_PERIPH_PWM**, **SYSCTL_PERIPH_QEI0**, **SYSCTL_PERIPH_QEI1**, **SYSCTL_PERIPH_SSI0**, **SYSCTL_PERIPH_SSI1**, **SYSCTL_PERIPH_TEMP**, **SYSCTL_PERIPH_TIMER0**, **SYSCTL_PERIPH_TIMER1**, **SYSCTL_PERIPH_TIMER2**, **SYSCTL_PERIPH_TIMER3**, **SYSCTL_PERIPH_UART0**, **SYSCTL_PERIPH_UART1**, **SYSCTL_PERIPH_UART2**, or **SYSCTL_PERIPH_WDOG**.

Returns:

Returns **true** if the specified peripheral is present and **false** if it is not.

19.2.2.26 SysCtlPeripheralReset

Performs a software reset of a peripheral.

Prototype:

```
void  
SysCtlPeripheralReset(unsigned long ulPeripheral)
```

Parameters:

ulPeripheral is the peripheral to reset.

Description:

This function performs a software reset of the specified peripheral. An individual peripheral reset signal is asserted for a brief period and then deasserted, leaving the peripheral in a operating state but in its reset condition.

The *ulPeripheral* parameter must be only one of the following values: **SYSCTL_PERIPH_ADC**, **SYSCTL_PERIPH_CAN0**, **SYSCTL_PERIPH_CAN1**, **SYSCTL_PERIPH_CAN2**, **SYSCTL_PERIPH_COMP0**, **SYSCTL_PERIPH_COMP1**, **SYSCTL_PERIPH_COMP2**, **SYSCTL_PERIPH_ETH**, **SYSCTL_PERIPH_GPIOA**, **SYSCTL_PERIPH_GPIOB**, **SYSCTL_PERIPH_GPIOC**, **SYSCTL_PERIPH_GPIOD**, **SYSCTL_PERIPH_GPIOE**, **SYSCTL_PERIPH_GPIOF**, **SYSCTL_PERIPH_GPIOG**, **SYSCTL_PERIPH_GPIOH**, **SYSCTL_PERIPH_HIBERNATE**, **SYSCTL_PERIPH_I2C0**, **SYSCTL_PERIPH_I2C1**, **SYSCTL_PERIPH_PWM**, **SYSCTL_PERIPH_QEI0**, **SYSCTL_PERIPH_QEI1**, **SYSCTL_PERIPH_SSI0**, **SYSCTL_PERIPH_SSI1**, **SYSCTL_PERIPH_TIMER0**, **SYSCTL_PERIPH_TIMER1**, **SYSCTL_PERIPH_TIMER2**, **SYSCTL_PERIPH_TIMER3**, **SYSCTL_PERIPH_UART0**, **SYSCTL_PERIPH_UART1**, **SYSCTL_PERIPH_UART2**, or **SYSCTL_PERIPH_WDOG**.

Returns:

None.

19.2.2.27 SysCtlPeripheralSleepDisable

Disables a peripheral in sleep mode.

Prototype:

```
void  
SysCtlPeripheralSleepDisable(unsigned long ulPeripheral)
```

Parameters:

ulPeripheral is the peripheral to disable in sleep mode.

Description:

This function causes a peripheral to stop operating when the processor goes into sleep mode. Disabling peripherals while in sleep mode helps to lower the current draw of the device. If enabled (via [SysCtlPeripheralEnable\(\)](#)), the peripheral will automatically resume operation when the processor leaves sleep mode, maintaining its entire state from before sleep mode was entered.

Sleep mode clocking of peripherals must be enabled via [SysCtlPeripheralClockGating\(\)](#); if disabled, the peripheral sleep mode configuration is maintained but has no effect when sleep mode is entered.

The *ulPeripheral* parameter must be only one of the following values: `SYSCTL_PERIPH_ADC`, `SYSCTL_PERIPH_CAN0`, `SYSCTL_PERIPH_CAN1`, `SYSCTL_PERIPH_CAN2`, `SYSCTL_PERIPH_COMP0`, `SYSCTL_PERIPH_COMP1`, `SYSCTL_PERIPH_COMP2`, `SYSCTL_PERIPH_ETH`, `SYSCTL_PERIPH_GPIOA`, `SYSCTL_PERIPH_GPIOB`, `SYSCTL_PERIPH_GPIOC`, `SYSCTL_PERIPH_GPIOD`, `SYSCTL_PERIPH_GPIOE`, `SYSCTL_PERIPH_GPIOF`, `SYSCTL_PERIPH_GPIOG`, `SYSCTL_PERIPH_GPIOH`, `SYSCTL_PERIPH_HIBERNATE`, `SYSCTL_PERIPH_I2C0`, `SYSCTL_PERIPH_I2C1`, `SYSCTL_PERIPH_PWM`, `SYSCTL_PERIPH_QEI0`, `SYSCTL_PERIPH_QEI1`, `SYSCTL_PERIPH_SSI0`, `SYSCTL_PERIPH_SSI1`, `SYSCTL_PERIPH_TIMER0`, `SYSCTL_PERIPH_TIMER1`, `SYSCTL_PERIPH_TIMER2`, `SYSCTL_PERIPH_TIMER3`, `SYSCTL_PERIPH_UART0`, `SYSCTL_PERIPH_UART1`, `SYSCTL_PERIPH_UART2`, or `SYSCTL_PERIPH_WDOG`.

Returns:

None.

19.2.2.28 SysCtlPeripheralSleepEnable

Enables a peripheral in sleep mode.

Prototype:

```
void
SysCtlPeripheralSleepEnable(unsigned long ulPeripheral)
```

Parameters:

ulPeripheral is the peripheral to enable in sleep mode.

Description:

This function allows a peripheral to continue operating when the processor goes into sleep mode. Since the clocking configuration of the device does not change, any peripheral can safely continue operating while the processor is in sleep mode, and can therefore wake the processor from sleep mode.

Sleep mode clocking of peripherals must be enabled via [SysCtlPeripheralClockGating\(\)](#); if disabled, the peripheral sleep mode configuration is maintained but has no effect when sleep mode is entered.

The *ulPeripheral* parameter must be only one of the following values: `SYSCTL_PERIPH_ADC`, `SYSCTL_PERIPH_CAN0`, `SYSCTL_PERIPH_CAN1`, `SYSCTL_PERIPH_CAN2`, `SYSCTL_PERIPH_COMP0`, `SYSCTL_PERIPH_COMP1`, `SYSCTL_PERIPH_COMP2`, `SYSCTL_PERIPH_ETH`, `SYSCTL_PERIPH_GPIOA`, `SYSCTL_PERIPH_GPIOB`, `SYSCTL_PERIPH_GPIOC`, `SYSCTL_PERIPH_GPIOD`, `SYSCTL_PERIPH_GPIOE`, `SYSCTL_PERIPH_GPIOF`, `SYSCTL_PERIPH_GPIOG`, `SYSCTL_PERIPH_GPIOH`, `SYSCTL_PERIPH_HIBERNATE`, `SYSCTL_PERIPH_I2C0`, `SYSCTL_PERIPH_I2C1`, `SYSCTL_PERIPH_PWM`, `SYSCTL_PERIPH_QEI0`, `SYSCTL_PERIPH_QEI1`, `SYSCTL_PERIPH_SSI0`, `SYSCTL_PERIPH_SSI1`, `SYSCTL_PERIPH_TIMER0`, `SYSCTL_PERIPH_TIMER1`, `SYSCTL_PERIPH_TIMER2`, `SYSCTL_PERIPH_TIMER3`, `SYSCTL_PERIPH_UART0`, `SYSCTL_PERIPH_UART1`, `SYSCTL_PERIPH_UART2`, or `SYSCTL_PERIPH_WDOG`.

Returns:

None.

19.2.2.29 SysCtlPinPresent

Determines if a pin is present.

Prototype:

```
tBoolean  
SysCtlPinPresent(unsigned long ulPin)
```

Parameters:

ulPin is the pin in question.

Description:

Determines if a particular pin is present in the device. The PWM, analog comparators, ADC, and timers have a varying number of pins across members of the Stellaris family; this will determine which are present on this device.

The *ulPin* argument must be only one of the following values: **SYSCTL_PIN_PWM0**, **SYSCTL_PIN_PWM1**, **SYSCTL_PIN_PWM2**, **SYSCTL_PIN_PWM3**, **SYSCTL_PIN_PWM4**, **SYSCTL_PIN_PWM5**, **SYSCTL_PIN_C0MINUS**, **SYSCTL_PIN_C0PLUS**, **SYSCTL_PIN_C0O**, **SYSCTL_PIN_C1MINUS**, **SYSCTL_PIN_C1PLUS**, **SYSCTL_PIN_C1O**, **SYSCTL_PIN_C2MINUS**, **SYSCTL_PIN_C2PLUS**, **SYSCTL_PIN_C2O**, **SYSCTL_PIN_ADC0**, **SYSCTL_PIN_ADC1**, **SYSCTL_PIN_ADC2**, **SYSCTL_PIN_ADC3**, **SYSCTL_PIN_ADC4**, **SYSCTL_PIN_ADC5**, **SYSCTL_PIN_ADC6**, **SYSCTL_PIN_ADC7**, **SYSCTL_PIN_CCP0**, **SYSCTL_PIN_CCP1**, **SYSCTL_PIN_CCP2**, **SYSCTL_PIN_CCP3**, **SYSCTL_PIN_CCP4**, **SYSCTL_PIN_CCP5**, **SYSCTL_PIN_CCP6**, **SYSCTL_PIN_CCP7**, **SYSCTL_PIN_32KHZ**, or **SYSCTL_PIN_MC_FAULT0**.

Returns:

Returns **true** if the specified pin is present and **false** if it is not.

19.2.2.30 SysCtlPLLVerificationSet

Configures the PLL verification timer.

Prototype:

```
void  
SysCtlPLLVerificationSet(tBoolean bEnable)
```

Parameters:

bEnable is a boolean that is **true** if the PLL verification timer should be enabled.

Description:

This function allows the PLL verification timer to be enabled or disabled. When enabled, an interrupt will be generated if the PLL ceases to operate.

The PLL verification timer is only available on Sandstorm-class devices.

Note:

The main oscillator must be enabled for this verification timer to operate as it is used to check the PLL. Also, the verification timer should be disabled while the PLL is being reconfigured via [SysCtlClockSet\(\)](#).

Returns:

None.

19.2.2.31 SysCtlPWMClockGet

Gets the current PWM clock configuration.

Prototype:

```
unsigned long  
SysCtlPWMClockGet(void)
```

Description:

This function returns the current PWM clock configuration.

Returns:

Returns the current PWM clock configuration; will be one of **SYSCTL_PWMDIV_1**, **SYSCTL_PWMDIV_2**, **SYSCTL_PWMDIV_4**, **SYSCTL_PWMDIV_8**, **SYSCTL_PWMDIV_16**, **SYSCTL_PWMDIV_32**, or **SYSCTL_PWMDIV_64**.

19.2.2.32 SysCtlPWMClockSet

Sets the PWM clock configuration.

Prototype:

```
void  
SysCtlPWMClockSet(unsigned long ulConfig)
```

Parameters:

ulConfig is the configuration for the PWM clock; it must be one of **SYSCTL_PWMDIV_1**, **SYSCTL_PWMDIV_2**, **SYSCTL_PWMDIV_4**, **SYSCTL_PWMDIV_8**, **SYSCTL_PWMDIV_16**, **SYSCTL_PWMDIV_32**, or **SYSCTL_PWMDIV_64**.

Description:

This function sets the rate of the clock provided to the PWM module as a ratio of the processor clock. This clock is used by the PWM module to generate PWM signals; its rate forms the basis for all PWM signals.

Note:

The clocking of the PWM is dependent upon the system clock rate as configured by [SysCtlClockSet\(\)](#).

Returns:

None.

19.2.2.33 SysCtlReset

Resets the device.

Prototype:

```
void  
SysCtlReset(void)
```

Description:

This function will perform a software reset of the entire device. The processor and all peripherals will be reset and all device registers will return to their default values (with the exception of the reset cause register, which will maintain its current value but have the software reset bit set as well).

Returns:

This function does not return.

19.2.2.34 SysCtlResetCauseClear

Clears reset reasons.

Prototype:

```
void  
SysCtlResetCauseClear(unsigned long ulCauses)
```

Parameters:

ulCauses are the reset causes to be cleared; must be a logical OR of **SYSCTL_CAUSE_LDO**, **SYSCTL_CAUSE_SW**, **SYSCTL_CAUSE_WDOG**, **SYSCTL_CAUSE_BOR**, **SYSCTL_CAUSE_POR**, and/or **SYSCTL_CAUSE_EXT**.

Description:

This function clears the specified sticky reset reasons. Once cleared, another reset for the same reason can be detected, and a reset for a different reason can be distinguished (instead of having two reset causes set). If the reset reason is used by an application, all reset causes should be cleared after they are retrieved with [SysCtlResetCauseGet\(\)](#).

Returns:

None.

19.2.2.35 SysCtlResetCauseGet

Gets the reason for a reset.

Prototype:

```
unsigned long  
SysCtlResetCauseGet(void)
```

Description:

This function will return the reason(s) for a reset. Since the reset reasons are sticky until either cleared by software or an external reset, multiple reset reasons may be returned if multiple resets have occurred. The reset reason will be a logical OR of **SYSCTL_CAUSE_LDO**, **SYSCTL_CAUSE_SW**, **SYSCTL_CAUSE_WDOG**, **SYSCTL_CAUSE_BOR**, **SYSCTL_CAUSE_POR**, and/or **SYSCTL_CAUSE_EXT**.

Returns:

Returns the reason(s) for a reset.

19.2.2.36 SysCtlSleep

Puts the processor into sleep mode.

Prototype:

```
void  
SysCtlSleep(void)
```

Description:

This function places the processor into sleep mode; it will not return until the processor returns to run mode. The peripherals that are enabled via [SysCtlPeripheralSleepEnable\(\)](#) continue to operate and can wake up the processor (if automatic clock gating is enabled with [SysCtlPeripheralClockGating\(\)](#), otherwise all peripherals continue to operate).

Returns:

None.

19.2.2.37 SysCtlSRAMSizeGet

Gets the size of the SRAM.

Prototype:

```
unsigned long  
SysCtlSRAMSizeGet(void)
```

Description:

This function determines the size of the SRAM on the Stellaris device.

Returns:

The total number of bytes of SRAM.

19.3 Programming Example

The following example shows how to use the SysCtl API to configure the device for normal operation.

```
//  
// Configure the device to run at 20 MHz from the PLL using a 4 MHz crystal  
// as the input.  
//  
SysCtlClockSet(SYSCTL_SYSDIV_10 | SYSCTL_USE_PLL | SYSCTL_XTAL_4MHZ |  
               SYSCTL_OSC_MAIN);  
  
//  
// Enable the GPIO blocks and the SSI.  
//  
SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOA);  
SysCtlPeripheralEnable(SYSCTL_PERIPH_GPIOB);  
SysCtlPeripheralEnable(SYSCTL_PERIPH_SSI);  
  
//  
// Enable the GPIO blocks and the SSI in sleep mode.  
//
```

```
SysCtlPeripheralSleepEnable(SYSCTL_PERIPH_GPIOA);  
SysCtlPeripheralSleepEnable(SYSCTL_PERIPH_GPIOB);  
SysCtlPeripheralSleepEnable(SYSCTL_PERIPH_SSI);  
  
//  
// Enable peripheral clock gating.  
//  
SysCtlPeripheralClockGating(true);
```

20 System Tick (SysTick)

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20.1 Introduction

SysTick is a simple timer that is part of the NVIC controller in the Cortex-M3 microprocessor. Its intended purpose is to provide a periodic interrupt for a RTOS, but it can be used for other simple timing purposes.

The SysTick interrupt handler does not need to clear the SysTick interrupt source. This will be done automatically by NVIC when the SysTick interrupt handler is called.

This driver is contained in `src/systick.c`, with `src/systick.h` containing the API definitions for use by applications.

20.2 API Functions

Functions

- void [SysTickDisable](#) (void)
- void [SysTickEnable](#) (void)
- void [SysTickIntDisable](#) (void)
- void [SysTickIntEnable](#) (void)
- void [SysTickIntRegister](#) (void (*pfnHandler)(void))
- void [SysTickIntUnregister](#) (void)
- unsigned long [SysTickPeriodGet](#) (void)
- void [SysTickPeriodSet](#) (unsigned long ulPeriod)
- unsigned long [SysTickValueGet](#) (void)

20.2.1 Detailed Description

The SysTick API is fairly simple, like SysTick itself. There are functions for configuring and enabling SysTick ([SysTickEnable\(\)](#), [SysTickDisable\(\)](#), [SysTickPeriodSet\(\)](#), [SysTickPeriodGet\(\)](#), and [SysTickValueGet\(\)](#)) and functions for dealing with an interrupt handler for SysTick ([SysTickIntRegister\(\)](#), [SysTickIntUnregister\(\)](#), [SysTickIntEnable\(\)](#), and [SysTickIntDisable\(\)](#)).

20.2.2 Function Documentation

20.2.2.1 SysTickDisable

Disables the SysTick counter.

Prototype:

```
void  
SysTickDisable(void)
```

Description:

This will stop the SysTick counter. If an interrupt handler has been registered, it will no longer be called until SysTick is restarted.

Returns:

None.

20.2.2.2 SysTickEnable

Enables the SysTick counter.

Prototype:

```
void  
SysTickEnable(void)
```

Description:

This will start the SysTick counter. If an interrupt handler has been registered, it will be called when the SysTick counter rolls over.

Note:

Calling this function will cause the SysTick counter to (re)commence counting from its current value. The counter is not automatically reloaded with the period as specified in a previous call to [SysTickPeriodSet\(\)](#). If an immediate reload is required, the **NVIC_ST_CURRENT** register must be written to force this. Any write to this register clears the SysTick counter to 0 and will cause a reload with the supplied period on the next clock.

Returns:

None.

20.2.2.3 SysTickIntDisable

Disables the SysTick interrupt.

Prototype:

```
void  
SysTickIntDisable(void)
```

Description:

This function will disable the SysTick interrupt, preventing it from being reflected to the processor.

Returns:

None.

20.2.2.4 SysTickIntEnable

Enables the SysTick interrupt.

Prototype:

```
void  
SysTickIntEnable(void)
```

Description:

This function will enable the SysTick interrupt, allowing it to be reflected to the processor.

Note:

The SysTick interrupt handler does not need to clear the SysTick interrupt source as this is done automatically by NVIC when the interrupt handler is called.

Returns:

None.

20.2.2.5 SysTickIntRegister

Registers an interrupt handler for the SysTick interrupt.

Prototype:

```
void  
SysTickIntRegister(void (*pfnHandler) (void))
```

Parameters:

pfnHandler is a pointer to the function to be called when the SysTick interrupt occurs.

Description:

This sets the handler to be called when a SysTick interrupt occurs.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

20.2.2.6 SysTickIntUnregister

Unregisters the interrupt handler for the SysTick interrupt.

Prototype:

```
void  
SysTickIntUnregister(void)
```

Description:

This function will clear the handler to be called when a SysTick interrupt occurs.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:
None.

20.2.2.7 SysTickPeriodGet

Gets the period of the SysTick counter.

Prototype:
`unsigned long
SysTickPeriodGet(void)`

Description:
This function returns the rate at which the SysTick counter wraps; this equates to the number of processor clocks between interrupts.

Returns:
Returns the period of the SysTick counter.

20.2.2.8 SysTickPeriodSet

Sets the period of the SysTick counter.

Prototype:
`void
SysTickPeriodSet(unsigned long ulPeriod)`

Parameters:
ulPeriod is the number of clock ticks in each period of the SysTick counter; must be between 1 and 16,777,216, inclusive.

Description:
This function sets the rate at which the SysTick counter wraps; this equates to the number of processor clocks between interrupts.

Note:
Calling this function does not cause the SysTick counter to reload immediately. If an immediate reload is required, the **NVIC_ST_CURRENT** register must be written. Any write to this register clears the SysTick counter to 0 and will cause a reload with the *ulPeriod* supplied here on the next clock after the SysTick is enabled.

Returns:
None.

20.2.2.9 SysTickValueGet

Gets the current value of the SysTick counter.

Prototype:
`unsigned long
SysTickValueGet(void)`

Description:

This function returns the current value of the SysTick counter; this will be a value between the period - 1 and zero, inclusive.

Returns:

Returns the current value of the SysTick counter.

20.3 Programming Example

The following example shows how to use the SysTick API to configure the SysTick counter and read its value.

```
unsigned long ulValue;

//
// Configure and enable the SysTick counter.
//
SysTickPeriodSet(1000);
SysTickEnable();

//
// Delay for some time...
//

//
// Read the current SysTick value.
//
ulValue = SysTickValueGet();
```


21 Timer

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21.1 Introduction

The timer API provides a set of functions for dealing with the timer module. Functions are provided to configure and control the timer, along with functions to modify timer/counter values, and to manage interrupt handling for the timer.

The timer module provides two 16-bit timer/counters that can be configured to operate independently as timers or event counters, or they can be configured to operate as one 32-bit timer or one 32-bit Real Time Clock (RTC). For the purpose of this API, the two timers provided by the timer are referred to as TimerA and TimerB.

When configured as either a 32-bit or 16-bit timer, a timer can be set up to run as a one-shot timer or a continuous timer. If configured as a one-shot timer, when it reaches zero the timer will cease counting. If configured as a continuous timer, when it reaches zero the timer will continue counting from a reloaded value. When configured as a 32-bit timer, the timer can also be configured to operate as an RTC. In that case, the timer expects to be driven by a 32 KHz external clock, which is divided down to produce 1 second clock ticks.

When in 16-bit mode, the timer can also be configured for event capture or as a Pulse Width Modulation (PWM) generator. When configured for event capture, the timer acts as a counter. It can be configured to either count the time between events, or it can count the events themselves. The type of event being counted can be configured as a positive edge, a negative edge, or both edges. When a timer is configured as a PWM generator, the input line used to capture events becomes an output line, and the timer is used to drive an edge-aligned pulse onto that line.

The timer module also provides the ability to control other functional parameters, such as output inversion, output triggers, and timer behavior during stalls.

Control is also provided over interrupt sources and events. Interrupts can be generated to indicate that an event has been captured, or that a certain number of events have been captured. Interrupts can also be generated when the timer has counted down to zero, or when the RTC matches a certain value.

This driver is contained in `src/timer.c`, with `src/timer.h` containing the API definitions for use by applications.

21.2 API Functions

Functions

- void [TimerConfigure](#) (unsigned long ulBase, unsigned long ulConfig)
- void [TimerControlEvent](#) (unsigned long ulBase, unsigned long ulTimer, unsigned long ulEvent)
- void [TimerControlLevel](#) (unsigned long ulBase, unsigned long ulTimer, tBoolean blInvert)

- void [TimerControlStall](#) (unsigned long ulBase, unsigned long ulTimer, tBoolean bStall)
- void [TimerControlTrigger](#) (unsigned long ulBase, unsigned long ulTimer, tBoolean bEnable)
- void [TimerDisable](#) (unsigned long ulBase, unsigned long ulTimer)
- void [TimerEnable](#) (unsigned long ulBase, unsigned long ulTimer)
- void [TimerIntClear](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [TimerIntDisable](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [TimerIntEnable](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [TimerIntRegister](#) (unsigned long ulBase, unsigned long ulTimer, void (*pfnHandler)(void))
- unsigned long [TimerIntStatus](#) (unsigned long ulBase, tBoolean bMasked)
- void [TimerIntUnregister](#) (unsigned long ulBase, unsigned long ulTimer)
- unsigned long [TimerLoadGet](#) (unsigned long ulBase, unsigned long ulTimer)
- void [TimerLoadSet](#) (unsigned long ulBase, unsigned long ulTimer, unsigned long ulValue)
- unsigned long [TimerMatchGet](#) (unsigned long ulBase, unsigned long ulTimer)
- void [TimerMatchSet](#) (unsigned long ulBase, unsigned long ulTimer, unsigned long ulValue)
- unsigned long [TimerPrescaleGet](#) (unsigned long ulBase, unsigned long ulTimer)
- unsigned long [TimerPrescaleMatchGet](#) (unsigned long ulBase, unsigned long ulTimer)
- void [TimerPrescaleMatchSet](#) (unsigned long ulBase, unsigned long ulTimer, unsigned long ulValue)
- void [TimerPrescaleSet](#) (unsigned long ulBase, unsigned long ulTimer, unsigned long ulValue)
- void [TimerRTCDisable](#) (unsigned long ulBase)
- void [TimerRTCEnable](#) (unsigned long ulBase)
- unsigned long [TimerValueGet](#) (unsigned long ulBase, unsigned long ulTimer)

21.2.1 Detailed Description

The timer API is broken into three groups of functions: those that deal with timer configuration and control, those that deal with timer contents, and those that deal with interrupt handling.

Timer configuration is handled by [TimerConfigure\(\)](#), which performs the high level setup of the timer module; that is, it is used to set up 32- or 16-bit modes, and to select between PWM, capture, and timer operations. Timer control is performed by [TimerEnable\(\)](#), [TimerDisable\(\)](#), [TimerControlLevel\(\)](#), [TimerControlTrigger\(\)](#), [TimerControlEvent\(\)](#), [TimerControlStall\(\)](#), [TimerRTCEnable\(\)](#), and [TimerRTCDisable\(\)](#).

Timer content is managed with [TimerLoadSet\(\)](#), [TimerLoadGet\(\)](#), [TimerPrescaleSet\(\)](#), [TimerPrescaleGet\(\)](#), [TimerMatchSet\(\)](#), [TimerMatchGet\(\)](#), [TimerPrescaleMatchSet\(\)](#), [TimerPrescaleMatchGet\(\)](#), and [TimerValueGet\(\)](#).

The interrupt handler for the Timer interrupt is managed with [TimerIntRegister\(\)](#) and [TimerIntUnregister\(\)](#). The individual interrupt sources within the timer module are managed with [TimerIntEnable\(\)](#), [TimerIntDisable\(\)](#), [TimerIntStatus\(\)](#), and [TimerIntClear\(\)](#).

The [TimerQuiesce\(\)](#) API from previous versions of the peripheral driver library has been deprecated. [SysCtlPeripheralReset\(\)](#) should be used instead to return the timer to its reset state.

21.2.2 Function Documentation

21.2.2.1 TimerConfigure

Configures the timer(s).

Prototype:

```
void  
TimerConfigure(unsigned long ulBase,  
               unsigned long ulConfig)
```

Parameters:

ulBase is the base address of the timer module.

ulConfig is the configuration for the timer.

Description:

This function configures the operating mode of the timer(s). The timer module is disabled before being configured, and is left in the disabled state. The configuration is specified in *ulConfig* as one of the following values:

- **TIMER_CFG_32_BIT_OS** - 32-bit one shot timer
- **TIMER_CFG_32_BIT_PER** - 32-bit periodic timer
- **TIMER_CFG_32_RTC** - 32-bit real time clock timer
- **TIMER_CFG_16_BIT_PAIR** - Two 16-bit timers

When configured for a pair of 16-bit timers, each timer is separately configured. The first timer is configured by setting *ulConfig* to the result of a logical OR operation between one of the following values and *ulConfig*:

- **TIMER_CFG_A_ONE_SHOT** - 16-bit one shot timer
- **TIMER_CFG_A_PERIODIC** - 16-bit periodic timer
- **TIMER_CFG_A_CAP_COUNT** - 16-bit edge count capture
- **TIMER_CFG_A_CAP_TIME** - 16-bit edge time capture
- **TIMER_CFG_A_PWM** - 16-bit PWM output

Similarly, the second timer is configured by setting *ulConfig* to the result of a logical OR operation between one of the corresponding **TIMER_CFG_B_*** values and *ulConfig*.

Returns:

None.

21.2.2.2 TimerControlEvent

Controls the event type.

Prototype:

```
void  
TimerControlEvent(unsigned long ulBase,  
                  unsigned long ulTimer,  
                  unsigned long ulEvent)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer(s) to be adjusted; must be one of **TIMER_A**, **TIMER_B**, or **TIMER_BOTH**.

ulEvent specifies the type of event; must be one of **TIMER_EVENT_POS_EDGE**, **TIMER_EVENT_NEG_EDGE**, or **TIMER_EVENT_BOTH_EDGES**.

Description:

This function sets the signal edge(s) that will trigger the timer when in capture mode.

Returns:

None.

21.2.2.3 TimerControlLevel

Controls the output level.

Prototype:

```
void  
TimerControlLevel(unsigned long ulBase,  
                  unsigned long ulTimer,  
                  tBoolean bInvert)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer(s) to adjust; must be one of **TIMER_A**, **TIMER_B**, or **TIMER_BOTH**.

bInvert specifies the output level.

Description:

This function sets the PWM output level for the specified timer. If the *bInvert* parameter is **true**, then the timer's output will be made active low; otherwise, it will be made active high.

Returns:

None.

21.2.2.4 TimerControlStall

Controls the stall handling.

Prototype:

```
void  
TimerControlStall(unsigned long ulBase,  
                  unsigned long ulTimer,  
                  tBoolean bStall)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer(s) to be adjusted; must be one of **TIMER_A**, **TIMER_B**, or **TIMER_BOTH**.

bStall specifies the response to a stall signal.

Description:

This function controls the stall response for the specified timer. If the *bStall* parameter is **true**, then the timer will stop counting if the processor enters debug mode; otherwise the timer will keep running while in debug mode.

Returns:

None.

21.2.2.5 TimerControlTrigger

Enables or disables the trigger output.

Prototype:

```
void  
TimerControlTrigger(unsigned long ulBase,  
                    unsigned long ulTimer,  
                    tBoolean bEnable)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer to adjust; must be one of **TIMER_A**, **TIMER_B**, or **TIMER_BOTH**.

bEnable specifies the desired trigger state.

Description:

This function controls the trigger output for the specified timer. If the *bEnable* parameter is **true**, then the timer's output trigger is enabled; otherwise it is disabled.

Returns:

None.

21.2.2.6 TimerDisable

Disables the timer(s).

Prototype:

```
void  
TimerDisable(unsigned long ulBase,  
             unsigned long ulTimer)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer(s) to disable; must be one of **TIMER_A**, **TIMER_B**, or **TIMER_BOTH**.

Description:

This will disable operation of the timer module.

Returns:

None.

21.2.2.7 TimerEnable

Enables the timer(s).

Prototype:

```
void  
TimerEnable(unsigned long ulBase,  
            unsigned long ulTimer)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer(s) to enable; must be one of **TIMER_A**, **TIMER_B**, or **TIMER_BOTH**.

Description:

This will enable operation of the timer module. The timer must be configured before it is enabled.

Returns:

None.

21.2.2.8 TimerIntClear

Clears timer interrupt sources.

Prototype:

```
void  
TimerIntClear(unsigned long ulBase,  
              unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the timer module.

ulIntFlags is a bit mask of the interrupt sources to be cleared.

Description:

The specified timer interrupt sources are cleared, so that they no longer assert. This must be done in the interrupt handler to keep it from being called again immediately upon exit.

The *ulIntFlags* parameter has the same definition as the *ulIntFlags* parameter to [TimerIntEnable\(\)](#).

Returns:

None.

21.2.2.9 TimerIntDisable

Disables individual timer interrupt sources.

Prototype:

```
void  
TimerIntDisable(unsigned long ulBase,  
                unsigned long ulIntFlags)
```


Parameters:

ulBase is the base address of the timer module.

ullntFlags is the bit mask of the interrupt sources to be disabled.

Description:

Disables the indicated timer interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor.

The *ullntFlags* parameter has the same definition as the *ullntFlags* parameter to [TimerIntEnable\(\)](#).

Returns:

None.

21.2.2.10 TimerIntEnable

Enables individual timer interrupt sources.

Prototype:

```
void  
TimerIntEnable(unsigned long ulBase,  
               unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the timer module.

ullntFlags is the bit mask of the interrupt sources to be enabled.

Description:

Enables the indicated timer interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor.

The *ullntFlags* parameter must be the logical OR of any combination of the following:

- **TIMER_CAPB_EVENT** - Capture B event interrupt
- **TIMER_CAPB_MATCH** - Capture B match interrupt
- **TIMER_TIMB_TIMEOUT** - Timer B timeout interrupt
- **TIMER_RTC_MATCH** - RTC interrupt mask
- **TIMER_CAPA_EVENT** - Capture A event interrupt
- **TIMER_CAPA_MATCH** - Capture A match interrupt
- **TIMER_TIMA_TIMEOUT** - Timer A timeout interrupt

Returns:

None.

21.2.2.11 TimerIntRegister

Registers an interrupt handler for the timer interrupt.

Prototype:

```
void  
TimerIntRegister(unsigned long ulBase,
```

```
unsigned long ulTimer,  
void (*pfnHandler) (void))
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer(s); must be one of **TIMER_A**, **TIMER_B**, or **TIMER_BOTH**.

pfnHandler is a pointer to the function to be called when the timer interrupt occurs.

Description:

This sets the handler to be called when a timer interrupt occurs. This will enable the global interrupt in the interrupt controller; specific timer interrupts must be enabled via [TimerIntEnable\(\)](#). It is the interrupt handler's responsibility to clear the interrupt source via [TimerIntClear\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

21.2.2.12 TimerIntStatus

Gets the current interrupt status.

Prototype:

```
unsigned long  
TimerIntStatus(unsigned long ulBase,  
                tBoolean bMasked)
```

Parameters:

ulBase is the base address of the timer module.

bMasked is false if the raw interrupt status is required and true if the masked interrupt status is required.

Description:

This returns the interrupt status for the timer module. Either the raw interrupt status or the status of interrupts that are allowed to reflect to the processor can be returned.

Returns:

The current interrupt status, enumerated as a bit field of values described in [TimerIntEnable\(\)](#).

21.2.2.13 TimerIntUnregister

Unregisters an interrupt handler for the timer interrupt.

Prototype:

```
void  
TimerIntUnregister(unsigned long ulBase,  
                  unsigned long ulTimer)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer(s); must be one of **TIMER_A**, **TIMER_B**, or **TIMER_BOTH**.

Description:

This function will clear the handler to be called when a timer interrupt occurs. This will also mask off the interrupt in the interrupt controller so that the interrupt handler no longer is called.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

21.2.2.14 TimerLoadGet

Gets the timer load value.

Prototype:

```
unsigned long
TimerLoadGet(unsigned long ulBase,
              unsigned long ulTimer)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer; must be one of **TIMER_A** or **TIMER_B**. Only **TIMER_A** should be used when the timer is configured for 32-bit operation.

Description:

This function gets the currently programmed interval load value for the specified timer.

Returns:

Returns the load value for the timer.

21.2.2.15 TimerLoadSet

Sets the timer load value.

Prototype:

```
void
TimerLoadSet(unsigned long ulBase,
              unsigned long ulTimer,
              unsigned long ulValue)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer(s) to adjust; must be one of **TIMER_A**, **TIMER_B**, or **TIMER_BOTH**. Only **TIMER_A** should be used when the timer is configured for 32-bit operation.

ulValue is the load value.

Description:

This function sets the timer load value; if the timer is running then the value will be immediately loaded into the timer.

Returns:
None.

21.2.2.16 TimerMatchGet

Gets the timer match value.

Prototype:

```
unsigned long  
TimerMatchGet(unsigned long ulBase,  
               unsigned long ulTimer)
```

Parameters:
ulBase is the base address of the timer module.
ulTimer specifies the timer; must be one of **TIMER_A** or **TIMER_B**. Only **TIMER_A** should be used when the timer is configured for 32-bit operation.

Description:
This function gets the match value for the specified timer.

Returns:
Returns the match value for the timer.

21.2.2.17 TimerMatchSet

Sets the timer match value.

Prototype:

```
void  
TimerMatchSet(unsigned long ulBase,  
               unsigned long ulTimer,  
               unsigned long ulValue)
```

Parameters:
ulBase is the base address of the timer module.
ulTimer specifies the timer(s) to adjust; must be one of **TIMER_A**, **TIMER_B**, or **TIMER_BOTH**. Only **TIMER_A** should be used when the timer is configured for 32-bit operation.
ulValue is the match value.

Description:
This function sets the match value for a timer. This is used in capture count mode to determine when to interrupt the processor and in PWM mode to determine the duty cycle of the output signal.

Returns:
None.

21.2.2.18 TimerPrescaleGet

Get the timer prescale value.

Prototype:

```
unsigned long  
TimerPrescaleGet(unsigned long ulBase,  
                 unsigned long ulTimer)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer; must be one of **TIMER_A** or **TIMER_B**.

Description:

This function gets the value of the input clock prescaler. The prescaler is only operational when in 16-bit mode and is used to extend the range of the 16-bit timer modes.

Returns:

The value of the timer prescaler.

21.2.2.19 TimerPrescaleMatchGet

Get the timer prescale match value.

Prototype:

```
unsigned long  
TimerPrescaleMatchGet(unsigned long ulBase,  
                     unsigned long ulTimer)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer; must be one of **TIMER_A** or **TIMER_B**.

Description:

This function gets the value of the input clock prescaler match value. When in a 16-bit mode that uses the counter match (edge count or PWM), the prescale match effectively extends the range of the counter to 24-bits.

Returns:

The value of the timer prescale match.

21.2.2.20 TimerPrescaleMatchSet

Set the timer prescale match value.

Prototype:

```
void  
TimerPrescaleMatchSet(unsigned long ulBase,  
                     unsigned long ulTimer,  
                     unsigned long ulValue)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer(s) to adjust; must be one of **TIMER_A**, **TIMER_B**, or **TIMER_BOTH**.

ulValue is the timer prescale match value; must be between 0 and 255, inclusive.

Description:

This function sets the value of the input clock prescaler match value. When in a 16-bit mode that uses the counter match (edge count or PWM), the prescale match effectively extends the range of the counter to 24-bits.

Returns:

None.

21.2.2.21 TimerPrescaleSet

Set the timer prescale value.

Prototype:

```
void  
TimerPrescaleSet(unsigned long ulBase,  
                 unsigned long ulTimer,  
                 unsigned long ulValue)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer(s) to adjust; must be one of **TIMER_A**, **TIMER_B**, or **TIMER_BOTH**.

ulValue is the timer prescale value; must be between 0 and 255, inclusive.

Description:

This function sets the value of the input clock prescaler. The prescaler is only operational when in 16-bit mode and is used to extend the range of the 16-bit timer modes.

Returns:

None.

21.2.2.22 TimerRTCDisable

Disable RTC counting.

Prototype:

```
void  
TimerRTCDisable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the timer module.

Description:

This function causes the timer to stop counting when in RTC mode.

Returns:

None.

21.2.2.23 TimerRTCEnable

Enable RTC counting.

Prototype:

```
void  
TimerRTCEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the timer module.

Description:

This function causes the timer to start counting when in RTC mode. If not configured for RTC mode, this will do nothing.

Returns:

None.

21.2.2.24 TimerValueGet

Gets the current timer value.

Prototype:

```
unsigned long  
TimerValueGet(unsigned long ulBase,  
               unsigned long ulTimer)
```

Parameters:

ulBase is the base address of the timer module.

ulTimer specifies the timer; must be one of **TIMER_A** or **TIMER_B**. Only **TIMER_A** should be used when the timer is configured for 32-bit operation.

Description:

This function reads the current value of the specified timer.

Returns:

Returns the current value of the timer.

21.3 Programming Example

The following example shows how to use the timer API to configure the timer as a 16-bit one shot timer and a 16-bit edge capture counter.

```
//  
// Configure TimerA as a 16-bit one shot timer, and TimerB as a 16-bit edge  
// capture counter.
```

```
//
TimerConfigure(TIMER0_BASE, (TIMER_CFG_16_BIT_PAIR | TIMER_CFG_A_ONE_SHOT |
                             TIMER_CFG_B_CAP_COUNT));

//
// Configure the counter (TimerB) to count both edges.
//
TimerControlEvent(TIMER0_BASE, TIMER_B, TIMER_EVENT_BOTH_EDGES);

//
// Enable the timers.
//
TimerEnable(TIMER0_BASE, TIMER_BOTH);
```


22 UART

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22.1 Introduction

The Universal Asynchronous Receiver/Transmitter (UART) API provides a set of functions for using the Stellaris UART modules. Functions are provided to configure and control the UART modules, to send and receive data, and to manage interrupts for the UART modules.

The Stellaris UART performs the functions of parallel-to-serial and serial-to-parallel conversions. It is very similar in functionality to a 16C550 UART, but is not register-compatible.

Some of the features of the Stellaris UART are:

- A 16x12 bit receive FIFO and a 16x8 bit transmit FIFO.
- Programmable baud rate generator.
- Automatic generation and stripping of start, stop, and parity bits.
- Line break generation and detection.
- Programmable serial interface
 - 5, 6, 7, or 8 data bits
 - even, odd, stick, or no parity bit generation and detection
 - 1 or 2 stop bit generation
 - baud rate generation, from DC to processor clock/16
- IrDA serial-IR (SIR) encoder/decoder.

This driver is contained in `src/uart.c`, with `src/uart.h` containing the API definitions for use by applications.

22.2 API Functions

Functions

- void [UARTBreakCtl](#) (unsigned long ulBase, tBoolean bBreakState)
- long [UARTCharGet](#) (unsigned long ulBase)
- long [UARTCharGetNonBlocking](#) (unsigned long ulBase)
- void [UARTCharPut](#) (unsigned long ulBase, unsigned char ucData)
- tBoolean [UARTCharPutNonBlocking](#) (unsigned long ulBase, unsigned char ucData)
- tBoolean [UARTCharsAvail](#) (unsigned long ulBase)
- void [UARTConfigGetExpClk](#) (unsigned long ulBase, unsigned long ulUARTClk, unsigned long *pulBaud, unsigned long *pulConfig)
- void [UARTConfigSetExpClk](#) (unsigned long ulBase, unsigned long ulUARTClk, unsigned long ulBaud, unsigned long ulConfig)

- void [UARTDisable](#) (unsigned long ulBase)
- void [UARTDisableSIR](#) (unsigned long ulBase)
- void [UARTEnable](#) (unsigned long ulBase)
- void [UARTEnableSIR](#) (unsigned long ulBase, tBoolean bLowPower)
- void [UARTFIFOLevelGet](#) (unsigned long ulBase, unsigned long *pulTxLevel, unsigned long *pulRxLevel)
- void [UARTFIFOLevelSet](#) (unsigned long ulBase, unsigned long ulTxLevel, unsigned long ulRxLevel)
- void [UARTIntClear](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [UARTIntDisable](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [UARTIntEnable](#) (unsigned long ulBase, unsigned long ulIntFlags)
- void [UARTIntRegister](#) (unsigned long ulBase, void (*pfnHandler)(void))
- unsigned long [UARTIntStatus](#) (unsigned long ulBase, tBoolean bMasked)
- void [UARTIntUnregister](#) (unsigned long ulBase)
- unsigned long [UARTParityModeGet](#) (unsigned long ulBase)
- void [UARTParityModeSet](#) (unsigned long ulBase, unsigned long ulParity)
- tBoolean [UARTSpaceAvail](#) (unsigned long ulBase)

22.2.1 Detailed Description

The UART API provides the set of functions required to implement an interrupt driven UART driver. These functions may be used to control any of the available UART ports on a Stellaris microcontroller, and can be used with one port without causing conflicts with the other port.

The UART API is broken into three groups of functions: those that deal with configuration and control of the UART modules, those used to send and receive data, and those that deal with interrupt handling.

Configuration and control of the UART are handled by the [UARTConfigGetExpClk\(\)](#), [UARTConfigSetExpClk\(\)](#), [UARTDisable\(\)](#), [UARTEnable\(\)](#), [UARTParityModeGet\(\)](#), and [UARTParityModeSet\(\)](#) functions.

Sending and receiving data via the UART is handled by the [UARTCharGet\(\)](#), [UARTCharGetNonBlocking\(\)](#), [UARTCharPut\(\)](#), [UARTCharPutNonBlocking\(\)](#), [UARTBreakCtl\(\)](#), [UARTCharsAvail\(\)](#), and [UARTSpaceAvail\(\)](#) functions.

Managing the UART interrupts is handled by the [UARTIntClear\(\)](#), [UARTIntDisable\(\)](#), [UARTIntEnable\(\)](#), [UARTIntRegister\(\)](#), [UARTIntStatus\(\)](#), and [UARTIntUnregister\(\)](#) functions.

The [UARTConfigSet\(\)](#), [UARTConfigGet\(\)](#), [UARTCharNonBlockingGet\(\)](#), and [UARTCharNonBlockingPut\(\)](#) APIs from previous versions of the peripheral driver library have been replaced by the [UARTConfigSetExpClk\(\)](#), [UARTConfigGetExpClk\(\)](#), [UARTCharGetNonBlocking\(\)](#), and [UARTCharPutNonBlocking\(\)](#) APIs, respectively. Macros have been provided in `uart.h` to map the old APIs to the new APIs, allowing existing applications to link and run with the new APIs. It is recommended that new applications utilize the new APIs in favor of the old ones.

22.2.2 Function Documentation

22.2.2.1 UARTBreakCtl

Causes a BREAK to be sent.

Prototype:

```
void
UARTBreakCtl(unsigned long ulBase,
              tBoolean bBreakState)
```

Parameters:

ulBase is the base address of the UART port.

bBreakState controls the output level.

Description:

Calling this function with *bBreakState* set to **true** will assert a break condition on the UART. Calling this function with *bBreakState* set to **false** will remove the break condition. For proper transmission of a break command, the break must be asserted for at least two complete frames.

Returns:

None.

22.2.2.2 UARTCharGet

Waits for a character from the specified port.

Prototype:

```
long
UARTCharGet(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the UART port.

Description:

Gets a character from the receive FIFO for the specified port. If there are no characters available, this function will wait until a character is received before returning.

Returns:

Returns the character read from the specified port, cast as an *long*.

22.2.2.3 UARTCharGetNonBlocking

Receives a character from the specified port.

Prototype:

```
long
UARTCharGetNonBlocking(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the UART port.

Description:

Gets a character from the receive FIFO for the specified port.

This function replaces the original `UARTCharNonBlockingGet()` API and performs the same actions. A macro is provided in `uart.h` to map the original API to this API.

Returns:

Returns the character read from the specified port, cast as a *long*. A **-1** will be returned if there are no characters present in the receive FIFO. The [UARTCharsAvail\(\)](#) function should be called before attempting to call this function.

22.2.2.4 UARTCharPut

Waits to send a character from the specified port.

Prototype:

```
void
UARTCharPut(unsigned long ulBase,
             unsigned char ucData)
```

Parameters:

ulBase is the base address of the UART port.

ucData is the character to be transmitted.

Description:

Sends the character *ucData* to the transmit FIFO for the specified port. If there is no space available in the transmit FIFO, this function will wait until there is space available before returning.

Returns:

None.

22.2.2.5 UARTCharPutNonBlocking

Sends a character to the specified port.

Prototype:

```
tBoolean
UARTCharPutNonBlocking(unsigned long ulBase,
                       unsigned char ucData)
```

Parameters:

ulBase is the base address of the UART port.

ucData is the character to be transmitted.

Description:

Writes the character *ucData* to the transmit FIFO for the specified port. This function does not block, so if there is no space available, then a **false** is returned, and the application will have to retry the function later.

This function replaces the original `UARTCharNonBlockingPut()` API and performs the same actions. A macro is provided in `uart.h` to map the original API to this API.

Returns:

Returns **true** if the character was successfully placed in the transmit FIFO, and **false** if there was no space available in the transmit FIFO.

22.2.2.6 UARTCharsAvail

Determines if there are any characters in the receive FIFO.

Prototype:

```
tBoolean
UARTCharsAvail(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the UART port.

Description:

This function returns a flag indicating whether or not there is data available in the receive FIFO.

Returns:

Returns **true** if there is data in the receive FIFO, and **false** if there is no data in the receive FIFO.

22.2.2.7 UARTConfigGetExpClk

Gets the current configuration of a UART.

Prototype:

```
void
UARTConfigGetExpClk(unsigned long ulBase,
                    unsigned long ulUARTClk,
                    unsigned long *pulBaud,
                    unsigned long *pulConfig)
```

Parameters:

ulBase is the base address of the UART port.

ulUARTClk is the rate of the clock supplied to the UART module.

pulBaud is a pointer to storage for the baud rate.

pulConfig is a pointer to storage for the data format.

Description:

The baud rate and data format for the UART is determined, given an explicitly provided peripheral clock (hence the ExpClk suffix). The returned baud rate is the actual baud rate; it may not be the exact baud rate requested or an “official” baud rate. The data format returned in *pulConfig* is enumerated the same as the *ulConfig* parameter of [UARTConfigSetExpClk\(\)](#).

The peripheral clock will be the same as the processor clock. This will be the value returned by [SysCtlClockGet\(\)](#), or it can be explicitly hard coded if it is constant and known (to save the code/execution overhead of a call to [SysCtlClockGet\(\)](#)).

This function replaces the original UARTConfigGet() API and performs the same actions. A macro is provided in `uart.h` to map the original API to this API.

Returns:

None.

22.2.2.8 UARTConfigSetExpClk

Sets the configuration of a UART.

Prototype:

```
void
UARTConfigSetExpClk(unsigned long ulBase,
                    unsigned long ulUARTClk,
                    unsigned long ulBaud,
                    unsigned long ulConfig)
```

Parameters:

ulBase is the base address of the UART port.

ulUARTClk is the rate of the clock supplied to the UART module.

ulBaud is the desired baud rate.

ulConfig is the data format for the port (number of data bits, number of stop bits, and parity).

Description:

This function will configure the UART for operation in the specified data format. The baud rate is provided in the *ulBaud* parameter and the data format in the *ulConfig* parameter.

The *ulConfig* parameter is the logical OR of three values: the number of data bits, the number of stop bits, and the parity. **UART_CONFIG_WLEN_8**, **UART_CONFIG_WLEN_7**, **UART_CONFIG_WLEN_6**, and **UART_CONFIG_WLEN_5** select from eight to five data bits per byte (respectively). **UART_CONFIG_STOP_ONE** and **UART_CONFIG_STOP_TWO** select one or two stop bits (respectively). **UART_CONFIG_PAR_NONE**, **UART_CONFIG_PAR_EVEN**, **UART_CONFIG_PAR_ODD**, **UART_CONFIG_PAR_ONE**, and **UART_CONFIG_PAR_ZERO** select the parity mode (no parity bit, even parity bit, odd parity bit, parity bit always one, and parity bit always zero, respectively).

The peripheral clock will be the same as the processor clock. This will be the value returned by [SysCtlClockGet\(\)](#), or it can be explicitly hard coded if it is constant and known (to save the code/execution overhead of a call to [SysCtlClockGet\(\)](#)).

This function replaces the original UARTConfigSet() API and performs the same actions. A macro is provided in `uart.h` to map the original API to this API.

Returns:

None.

22.2.2.9 UARTDisable

Disables transmitting and receiving.

Prototype:

```
void
UARTDisable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the UART port.

Description:

Clears the UARTEN, TXE, and RXE bits, then waits for the end of transmission of the current character, and flushes the transmit FIFO.

Returns:

None.

22.2.2.10 UARTDisableSIR

Disables SIR (IrDA) mode on the specified UART.

Prototype:

```
void  
UARTDisableSIR(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the UART port.

Description:

Clears the SIREN (IrDA) and SIRLP (Low Power) bits.

Note:

SIR (IrDA) operation is supported only on Fury-class devices.

Returns:

None.

22.2.2.11 UARTEnable

Enables transmitting and receiving.

Prototype:

```
void  
UARTEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the UART port.

Description:

Sets the UARTEN, TXE, and RXE bits, and enables the transmit and receive FIFOs.

Returns:

None.

22.2.2.12 UARTEnableSIR

Enables SIR (IrDA) mode on specified UART.

Prototype:

```
void
UARTEnableSIR(unsigned long ulBase,
               tBoolean bLowPower)
```

Parameters:

ulBase is the base address of the UART port.

bLowPower indicates if SIR Low Power Mode is to be used.

Description:

Enables the SIREN control bit for IrDA mode on the UART. If the *bLowPower* flag is set, then SIRLP bit will also be set.

Note:

SIR (IrDA) operation is supported only on Fury-class devices.

Returns:

None.

22.2.2.13 UARTFIFOLevelGet

Gets the FIFO level at which interrupts are generated.

Prototype:

```
void
UARTFIFOLevelGet(unsigned long ulBase,
                  unsigned long *pulTxLevel,
                  unsigned long *pulRxLevel)
```

Parameters:

ulBase is the base address of the UART port.

pulTxLevel is a pointer to storage for the transmit FIFO level, returned as one of **UART_FIFO_TX1_8**, **UART_FIFO_TX2_8**, **UART_FIFO_TX4_8**, **UART_FIFO_TX6_8**, or **UART_FIFO_TX7_8**.

pulRxLevel is a pointer to storage for the receive FIFO level, returned as one of **UART_FIFO_RX1_8**, **UART_FIFO_RX2_8**, **UART_FIFO_RX4_8**, **UART_FIFO_RX6_8**, or **UART_FIFO_RX7_8**.

Description:

This function gets the FIFO level at which transmit and receive interrupts will be generated.

Returns:

None.

22.2.2.14 UARTFIFOLevelSet

Sets the FIFO level at which interrupts are generated.

Prototype:

```
void
UARTFIFOLevelSet(unsigned long ulBase,
                  unsigned long ulTxLevel,
                  unsigned long ulRxLevel)
```

Parameters:

ulBase is the base address of the UART port.

ulTxLevel is the transmit FIFO interrupt level, specified as one of **UART_FIFO_TX1_8**, **UART_FIFO_TX2_8**, **UART_FIFO_TX4_8**, **UART_FIFO_TX6_8**, or **UART_FIFO_TX7_8**.

ulRxLevel is the receive FIFO interrupt level, specified as one of **UART_FIFO_RX1_8**, **UART_FIFO_RX2_8**, **UART_FIFO_RX4_8**, **UART_FIFO_RX6_8**, or **UART_FIFO_RX7_8**.

Description:

This function sets the FIFO level at which transmit and receive interrupts will be generated.

Returns:

None.

22.2.2.15 UARTIntClear

Clears UART interrupt sources.

Prototype:

```
void
UARTIntClear(unsigned long ulBase,
              unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the UART port.

ulIntFlags is a bit mask of the interrupt sources to be cleared.

Description:

The specified UART interrupt sources are cleared, so that they no longer assert. This must be done in the interrupt handler to keep it from being called again immediately upon exit.

The *ulIntFlags* parameter has the same definition as the *ulIntFlags* parameter to [UARTIntEnable\(\)](#).

Returns:

None.

22.2.2.16 UARTIntDisable

Disables individual UART interrupt sources.

Prototype:

```
void
UARTIntDisable(unsigned long ulBase,
               unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the UART port.

ulIntFlags is the bit mask of the interrupt sources to be disabled.

Description:

Disables the indicated UART interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor.

The *ulIntFlags* parameter has the same definition as the *ulIntFlags* parameter to [UARTIntEnable\(\)](#).

Returns:

None.

22.2.2.17 UARTIntEnable

Enables individual UART interrupt sources.

Prototype:

```
void
UARTIntEnable(unsigned long ulBase,
              unsigned long ulIntFlags)
```

Parameters:

ulBase is the base address of the UART port.

ulIntFlags is the bit mask of the interrupt sources to be enabled.

Description:

Enables the indicated UART interrupt sources. Only the sources that are enabled can be reflected to the processor interrupt; disabled sources have no effect on the processor.

The *ulIntFlags* parameter is the logical OR of any of the following:

- **UART_INT_OE** - Overrun Error interrupt
- **UART_INT_BE** - Break Error interrupt
- **UART_INT_PE** - Parity Error interrupt
- **UART_INT_FE** - Framing Error interrupt
- **UART_INT_RT** - Receive Timeout interrupt
- **UART_INT_TX** - Transmit interrupt
- **UART_INT_RX** - Receive interrupt

Returns:

None.

22.2.2.18 UARTIntRegister

Registers an interrupt handler for a UART interrupt.

Prototype:

```
void
UARTIntRegister(unsigned long ulBase,
                void (*pfnHandler)(void))
```

Parameters:

ulBase is the base address of the UART port.

pfnHandler is a pointer to the function to be called when the UART interrupt occurs.

Description:

This function does the actual registering of the interrupt handler. This will enable the global interrupt in the interrupt controller; specific UART interrupts must be enabled via [UARTIntEnable\(\)](#). It is the interrupt handler's responsibility to clear the interrupt source.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

22.2.2.19 UARTIntStatus

Gets the current interrupt status.

Prototype:

```
unsigned long
UARTIntStatus(unsigned long ulBase,
               tBoolean bMasked)
```

Parameters:

ulBase is the base address of the UART port.

bMasked is false if the raw interrupt status is required and true if the masked interrupt status is required.

Description:

This returns the interrupt status for the specified UART. Either the raw interrupt status or the status of interrupts that are allowed to reflect to the processor can be returned.

Returns:

Returns the current interrupt status, enumerated as a bit field of values described in [UARTIntEnable\(\)](#).

22.2.2.20 UARTIntUnregister

Unregisters an interrupt handler for a UART interrupt.

Prototype:

```
void  
UARTIntUnregister(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the UART port.

Description:

This function does the actual unregistering of the interrupt handler. It will clear the handler to be called when a UART interrupt occurs. This will also mask off the interrupt in the interrupt controller so that the interrupt handler no longer is called.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

22.2.2.21 UARTParityModeGet

Gets the type of parity currently being used.

Prototype:

```
unsigned long  
UARTParityModeGet(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the UART port.

Description:

This function gets the type of parity used for transmitting data, and expected when receiving data.

Returns:

Returns the current parity settings, specified as one of **UART_CONFIG_PAR_NONE**, **UART_CONFIG_PAR_EVEN**, **UART_CONFIG_PAR_ODD**, **UART_CONFIG_PAR_ONE**, or **UART_CONFIG_PAR_ZERO**.

22.2.2.22 UARTParityModeSet

Sets the type of parity.

Prototype:

```
void  
UARTParityModeSet(unsigned long ulBase,  
                  unsigned long ulParity)
```

Parameters:

ulBase is the base address of the UART port.

ulParity specifies the type of parity to use.

Description:

Sets the type of parity to use for transmitting and expect when receiving. The *ulParity* parameter must be one of **UART_CONFIG_PAR_NONE**, **UART_CONFIG_PAR_EVEN**, **UART_CONFIG_PAR_ODD**, **UART_CONFIG_PAR_ONE**, or **UART_CONFIG_PAR_ZERO**. The last two allow direct control of the parity bit; it will always be either one or zero based on the mode.

Returns:

None.

22.2.2.23 UARTSpaceAvail

Determines if there is any space in the transmit FIFO.

Prototype:

```
tBoolean
UARTSpaceAvail(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the UART port.

Description:

This function returns a flag indicating whether or not there is space available in the transmit FIFO.

Returns:

Returns **true** if there is space available in the transmit FIFO, and **false** if there is no space available in the transmit FIFO.

22.3 Programming Example

The following example shows how to use the UART API to initialize the UART, transmit characters, and receive characters.

```
//
// Initialize the UART. Set the baud rate, number of data bits, turn off
// parity, number of stop bits, and stick mode.
//
UARTConfigSetExpClk(UART0_BASE, SysCtlClockGet(), 38400,
                    (UART_CONFIG_WLEN_8 | UART_CONFIG_STOP_ONE |
                     UART_CONFIG_PAR_NONE));

//
// Enable the UART.
//
UARTEnable(UART0_BASE);

//
// Check for characters. This will spin here until a character is placed
// into the receive FIFO.
//
while(!UARTCharsAvail(UART0_BASE))
{
}
```

```
//  
// Get the character(s) in the receive FIFO.  
//  
while (UARTCharGetNonBlocking (UART0_BASE))  
{  
}  
  
//  
// Put a character in the output buffer.  
//  
UARTCharPut (UART0_BASE, 'c');  
  
//  
// Disable the UART.  
//  
UARTDisable (UART0_BASE);
```

23 Watchdog Timer

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23.1 Introduction

The Watchdog Timer API provides a set of functions for using the Stellaris watchdog timer modules. Functions are provided to deal with the watchdog timer interrupts, and to handle status and configuration of the watchdog timer.

The watchdog timer module's function is to prevent system hangs. The watchdog timer module consists of a 32-bit down counter, a programmable load register, interrupt generation logic, and a locking register. Once the watchdog timer has been configured, the lock register can be written to prevent the timer configuration from being inadvertently altered.

The watchdog timer can be configured to generate an interrupt to the processor upon its first timeout, and to generate a reset signal upon its second timeout. The watchdog timer module generates the first timeout signal when the 32-bit counter reaches the zero state after being enabled; enabling the counter also enables the watchdog timer interrupt. After the first timeout event, the 32-bit counter is reloaded with the value of the watchdog timer load register, and the timer resumes counting down from that value. If the timer counts down to its zero state again before the first timeout interrupt is cleared, and the reset signal has been enabled, the watchdog timer asserts its reset signal to the system. If the interrupt is cleared before the 32-bit counter reaches its second timeout, the 32-bit counter is loaded with the value in the load register, and counting resumes from that value. If the load register is written with a new value while the watchdog timer counter is counting, then the counter is loaded with the new value and continues counting.

This driver is contained in `src/watchdog.c`, with `src/watchdog.h` containing the API definitions for use by applications.

23.2 API Functions

Functions

- void [WatchdogEnable](#) (unsigned long ulBase)
- void [WatchdogIntClear](#) (unsigned long ulBase)
- void [WatchdogIntEnable](#) (unsigned long ulBase)
- void [WatchdogIntRegister](#) (unsigned long ulBase, void (*pfnHandler)(void))
- unsigned long [WatchdogIntStatus](#) (unsigned long ulBase, tBoolean bMasked)
- void [WatchdogIntUnregister](#) (unsigned long ulBase)
- void [WatchdogLock](#) (unsigned long ulBase)
- tBoolean [WatchdogLockState](#) (unsigned long ulBase)
- unsigned long [WatchdogReloadGet](#) (unsigned long ulBase)
- void [WatchdogReloadSet](#) (unsigned long ulBase, unsigned long ulLoadVal)
- void [WatchdogResetDisable](#) (unsigned long ulBase)

- void [WatchdogResetEnable](#) (unsigned long ulBase)
- tBoolean [WatchdogRunning](#) (unsigned long ulBase)
- void [WatchdogStallDisable](#) (unsigned long ulBase)
- void [WatchdogStallEnable](#) (unsigned long ulBase)
- void [WatchdogUnlock](#) (unsigned long ulBase)
- unsigned long [WatchdogValueGet](#) (unsigned long ulBase)

23.2.1 Detailed Description

The Watchdog Timer API is broken into two groups of functions: those that deal with interrupts, and those that handle status and configuration.

The Watchdog Timer interrupts are handled by the [WatchdogIntRegister\(\)](#), [WatchdogIntUnregister\(\)](#), [WatchdogIntEnable\(\)](#), [WatchdogIntClear\(\)](#), and [WatchdogIntStatus\(\)](#) functions.

Status and configuration functions for the Watchdog Timer module are [WatchdogEnable\(\)](#), [WatchdogRunning\(\)](#), [WatchdogLock\(\)](#), [WatchdogUnlock\(\)](#), [WatchdogLockState\(\)](#), [WatchdogReloadSet\(\)](#), [WatchdogReloadGet\(\)](#), [WatchdogValueGet\(\)](#), [WatchdogResetEnable\(\)](#), [WatchdogResetDisable\(\)](#), [WatchdogStallEnable\(\)](#), and [WatchdogStallDisable\(\)](#).

23.2.2 Function Documentation

23.2.2.1 WatchdogEnable

Enables the watchdog timer.

Prototype:

```
void  
WatchdogEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

This will enable the watchdog timer counter and interrupt.

Note:

This function will have no effect if the watchdog timer has been locked.

See also:

[WatchdogLock\(\)](#), [WatchdogUnlock\(\)](#)

Returns:

None.

23.2.2.2 WatchdogIntClear

Clears the watchdog timer interrupt.

Prototype:

```
void  
WatchdogIntClear(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

The watchdog timer interrupt source is cleared, so that it no longer asserts.

Returns:

None.

23.2.2.3 WatchdogIntEnable

Enables the watchdog timer interrupt.

Prototype:

```
void  
WatchdogIntEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

Enables the watchdog timer interrupt.

Note:

This function will have no effect if the watchdog timer has been locked.

See also:

[WatchdogLock\(\)](#), [WatchdogUnlock\(\)](#), [WatchdogEnable\(\)](#)

Returns:

None.

23.2.2.4 WatchdogIntRegister

Registers an interrupt handler for watchdog timer interrupt.

Prototype:

```
void  
WatchdogIntRegister(unsigned long ulBase,  
                    void (*pfnHandler)(void))
```

Parameters:

ulBase is the base address of the watchdog timer module.

pfnHandler is a pointer to the function to be called when the watchdog timer interrupt occurs.

Description:

This function does the actual registering of the interrupt handler. This will enable the global interrupt in the interrupt controller; the watchdog timer interrupt must be enabled via [WatchdogEnable\(\)](#). It is the interrupt handler's responsibility to clear the interrupt source via [WatchdogIntClear\(\)](#).

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

23.2.2.5 WatchdogIntStatus

Gets the current watchdog timer interrupt status.

Prototype:

```
unsigned long  
WatchdogIntStatus(unsigned long ulBase,  
                  tBoolean bMasked)
```

Parameters:

ulBase is the base address of the watchdog timer module.

bMasked is **false** if the raw interrupt status is required and **true** if the masked interrupt status is required.

Description:

This returns the interrupt status for the watchdog timer module. Either the raw interrupt status or the status of interrupt that is allowed to reflect to the processor can be returned.

Returns:

Returns the current interrupt status, where a 1 indicates that the watchdog interrupt is active, and a 0 indicates that it is not active.

23.2.2.6 WatchdogIntUnregister

Unregisters an interrupt handler for the watchdog timer interrupt.

Prototype:

```
void  
WatchdogIntUnregister(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

This function does the actual unregistering of the interrupt handler. This function will clear the handler to be called when a watchdog timer interrupt occurs. This will also mask off the interrupt in the interrupt controller so that the interrupt handler no longer is called.

See also:

[IntRegister\(\)](#) for important information about registering interrupt handlers.

Returns:

None.

23.2.2.7 WatchdogLock

Enables the watchdog timer lock mechanism.

Prototype:

```
void  
WatchdogLock(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

Locks out write access to the watchdog timer configuration registers.

Returns:

None.

23.2.2.8 WatchdogLockState

Gets the state of the watchdog timer lock mechanism.

Prototype:

```
tBoolean  
WatchdogLockState(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

Returns the lock state of the watchdog timer registers.

Returns:

Returns **true** if the watchdog timer registers are locked, and **false** if they are not locked.

23.2.2.9 WatchdogReloadGet

Gets the watchdog timer reload value.

Prototype:

```
unsigned long  
WatchdogReloadGet(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

This function gets the value that is loaded into the watchdog timer when the count reaches zero for the first time.

See also:

[WatchdogReloadSet\(\)](#)

Returns:

None.

23.2.2.10 WatchdogReloadSet

Sets the watchdog timer reload value.

Prototype:

```
void  
WatchdogReloadSet(unsigned long ulBase,  
                  unsigned long ulLoadVal)
```

Parameters:

ulBase is the base address of the watchdog timer module.

ulLoadVal is the load value for the watchdog timer.

Description:

This function sets the value to load into the watchdog timer when the count reaches zero for the first time; if the watchdog timer is running when this function is called, then the value will be immediately loaded into the watchdog timer counter. If the *ulLoadVal* parameter is 0, then an interrupt is immediately generated.

Note:

This function will have no effect if the watchdog timer has been locked.

See also:

[WatchdogLock\(\)](#), [WatchdogUnlock\(\)](#), [WatchdogReloadGet\(\)](#)

Returns:

None.

23.2.2.11 WatchdogResetDisable

Disables the watchdog timer reset.

Prototype:

```
void  
WatchdogResetDisable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

Disables the capability of the watchdog timer to issue a reset to the processor upon a second timeout condition.

Note:

This function will have no effect if the watchdog timer has been locked.

See also:

[WatchdogLock\(\)](#), [WatchdogUnlock\(\)](#)

Returns:

None.

23.2.2.12 WatchdogResetEnable

Enables the watchdog timer reset.

Prototype:

```
void  
WatchdogResetEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

Enables the capability of the watchdog timer to issue a reset to the processor upon a second timeout condition.

Note:

This function will have no effect if the watchdog timer has been locked.

See also:

[WatchdogLock\(\)](#), [WatchdogUnlock\(\)](#)

Returns:

None.

23.2.2.13 WatchdogRunning

Determines if the watchdog timer is enabled.

Prototype:

```
tBoolean  
WatchdogRunning(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

This will check to see if the watchdog timer is enabled.

Returns:

Returns **true** if the watchdog timer is enabled, and **false** if it is not.

23.2.2.14 WatchdogStallDisable

Disables stalling of the watchdog timer during debug events.

Prototype:

```
void  
WatchdogStallDisable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

This function disables the debug mode stall of the watchdog timer. By doing so, the watchdog timer continues to count regardless of the processor debug state.

Returns:

None.

23.2.2.15 WatchdogStallEnable

Enables stalling of the watchdog timer during debug events.

Prototype:

```
void  
WatchdogStallEnable(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

This function allows the watchdog timer to stop counting when the processor is stopped by the debugger. By doing so, the watchdog is prevented from expiring (typically almost immediately from a human time perspective) and resetting the system (if reset is enabled). The watchdog will instead expire after the appropriate number of processor cycles have been executed while debugging (or at the appropriate time after the processor has been restarted).

Returns:

None.

23.2.2.16 WatchdogUnlock

Disables the watchdog timer lock mechanism.

Prototype:

```
void  
WatchdogUnlock(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

Enables write access to the watchdog timer configuration registers.

Returns:

None.

23.2.2.17 WatchdogValueGet

Gets the current watchdog timer value.

Prototype:

```
unsigned long  
WatchdogValueGet(unsigned long ulBase)
```

Parameters:

ulBase is the base address of the watchdog timer module.

Description:

This function reads the current value of the watchdog timer.

Returns:

Returns the current value of the watchdog timer.

23.3 Programming Example

The following example shows how to set up the watchdog timer API to reset the processor after two timeouts.

```
//  
// Check to see if the registers are locked, and if so, unlock them.  
//  
if(WatchdogLockState(WATCHDOG_BASE) == true)  
{  
    WatchdogUnlock(WATCHDOG_BASE);  
}  
  
//  
// Initialize the watchdog timer.  
//  
WatchdogReloadSet(WATCHDOG_BASE, 0xFEEFEE);  
  
//  
// Enable the reset.  
//  
WatchdogResetEnable(WATCHDOG_BASE);  
  
//  
// Enable the watchdog timer.  
//  
WatchdogEnable(WATCHDOG_BASE);  
  
//  
// Wait for the reset to occur.  
//  
while(1)
```

{
}

24 Utility Functions

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24.1 Introduction

The utility functions are a loose collection of functions that are not specific to any Stellaris peripheral or board. These functions provide mechanisms for communicating with the debugger and for providing a simple serial terminal on one of the UARTs. There are also lightweight implementations of functions for printf style formatted output.

24.2 API Functions

Functions

- int [CmdLineProcess](#) (char *pcCmdLine)
- int [DiagClose](#) (int iHandle)
- char * [DiagCommandString](#) (char *pcBuf, unsigned long ulLen)
- void [DiagExit](#) (int iRet)
- long [DiagFlen](#) (int iHandle)
- int [DiagOpen](#) (const char *pcName, int iMode)
- int [DiagOpenStdio](#) (void)
- void [DiagPrintf](#) (int iHandle, const char *pcString,...)
- int [DiagRead](#) (int iHandle, char *pcBuf, unsigned long ulLen, int iMode)
- int [DiagWrite](#) (int iHandle, const char *pcBuf, unsigned long ulLen, int iMode)
- int [UARTgets](#) (char *pcBuf, unsigned long ulLen)
- void [UARTprintf](#) (const char *pcString,...)
- void [UARTStdioInit](#) (unsigned long ulPortNum)
- void [ulocaltime](#) (unsigned long ulTime, tTime *psTime)
- int [usnprintf](#) (char *pcBuf, unsigned long ulSize, const char *pcString,...)
- int [usprintf](#) (char *pcBuf, const char *pcString,...)
- unsigned long [ustrtoul](#) (const char *pcStr, const char **ppcStrRet, int iBase)
- int [uvsnprintf](#) (char *pcBuf, unsigned long ulSize, const char *pcString, va_list vaArgP)

24.2.1 Detailed Description

The first group of utility functions are the diagnostic functions (“Diag”) used for interacting with the debugger (if the debugger supports that feature). The Diag functions allow the program to open a handle on the file system of the host system, allowing reading or writing of files, or communication with a console. This feature is sometimes referred to as “semihosting”. Not all debuggers support all of these features. The debugger specific support is provided in a source file that is linked into the application. The source files for debugger support can be found in the “utils” directory.

The Diag functions are used as follows: [DiagOpen\(\)](#) is used to open a file on the host system. [DiagOpenStdio\(\)](#) is used to open a handle to the console, typically for displaying messages to the user. Once a handle is opened, it can be closed with [DiagClose\(\)](#). The functions [DiagRead\(\)](#) and [DiagWrite\(\)](#) are used for reading and writing to the host, while [DiagPrintf\(\)](#) provides printf style formatting of output. [DiagFlen\(\)](#) is used to find the size of a file, [DiagCommandString\(\)](#) used to get the command line arguments from the debugger, and [DiagExit\(\)](#) to exit the program and return control to the debugger.

The second group of utility functions is used to provide a simple UART based console. [UARTStdioInit\(\)](#) is used to initialize a specific UART to be used as the console serial port. Then the function [UARTprintf\(\)](#) can be used to send formatted output to the serial port, which [UARTgets\(\)](#) can be used to get a line of input from the serial console.

The above functions, along with [CmdLineProcess\(\)](#) can be used to implement a simple command line processor. The function [CmdLineProcess\(\)](#) will break up any command line in a buffer into command line arguments in “argc, argv” form, match the first argument to a command name in a command table, and then call the function that implements the command.

The third group of functions are used for providing simple forms of some standard library string formatting functions. If the simplified functions meet the needs of the application for formatted output, then they may be used in place of the equivalent standard library functions, which may save on overall code size.

The library formatting functions are [usprintf\(\)](#) which is a simplified replacement for `sprintf()`. Likewise [usnprintf\(\)](#) and [uvsnprintf\(\)](#) are simplified replacements for `snprintf()` and `vsnprintf()` from the standard library. These functions are lighter weight than the equivalent library function because they offer simpler and reduced conversion options, and elimination of floating point support. If these features are needed then the standard library can still be used.

Refer to the individual function documentation for the name of it's source and header files.

24.2.2 Function Documentation

24.2.2.1 CmdLineProcess

Process a command line string into arguments and execute the command.

Prototype:

```
int  
CmdLineProcess(char *pcCmdLine)
```

Parameters:

pcCmdLine points to a string that contains a command line that was obtained by an application by some means.

Description:

This function will take the supplied command line string and break it up into individual arguments. The first argument is treated as a command and is searched for in the command table. If the command is found, then the command function is called and all of the command line arguments are passed in the normal argc, argv form.

The command table is contained in an array named `g_sCmdTable` which must be implemented in the application.

This function is contained in `utils/cmdline.c`, with `utils/cmdline.h` containing the API definition for use by applications.

Returns:

Returns **CMDLINE_BAD_CMD** if the command is not found, **CMDLINE_TOO_MANY_ARGS** if there are more arguments than can be parsed. Otherwise it returns the code that was returned by the command function.

24.2.2.2 DiagClose

Closes a host file system file.

Prototype:

```
int  
DiagClose(int iHandle)
```

Parameters:

iHandle is the handle of the file to close.

Description:

This function closes a file previously opened with [DiagOpen\(\)](#); this is similar to the `fclose()` function in the C library.

This function is contained in a debugger-specific `utils/<debugger>.`, with `utils/diag.h` containing the API definition for use by applications.

Returns:

Returns zero on success or non-zero on failure.

24.2.2.3 DiagCommandString

Gets the command line arguments from the debugger.

Prototype:

```
char *  
DiagCommandString(char *pcBuf,  
                  unsigned long ulLen)
```

Parameters:

pcBuf is a pointer to the buffer to be filled with the command line arguments.
ulLen is the length of the buffer.

Description:

This function retrieves the command line arguments from the debugger, if it is able to provide them. The raw command line string is returned; it is the responsibility of the application to parse it into an `argc/argv` pair if desired.

This function is contained in a debugger-specific `utils/<debugger>.`, with `utils/diag.h` containing the API definition for use by applications.

Returns:

Returns a pointer to the returned command line (typically the same as the supplied buffer) on success and NULL if the command line is not available.

24.2.2.4 DiagExit

Terminates the application.

Prototype:

```
void  
DiagExit(int iRet)
```

Parameters:

iRet is the return value from the application.

Description:

This function terminates the application; this is similar to the `exit()` function in the C library.

This function is contained in a debugger-specific `utils/<debugger>?.?`, with `utils/diag.h` containing the API definition for use by applications.

Returns:

Does not return.

24.2.2.5 DiagFlen

Gets the length of a host file system file.

Prototype:

```
long  
DiagFlen(int iHandle)
```

Parameters:

iHandle is the handle of the file to query.

Description:

This function determines the length of a file previously opened with [DiagOpen\(\)](#); this is similar to seeking to the end of the file with the `fseek()` function and then doing an `ftell()`, except that the file pointer is not moved.

This function is contained in a debugger-specific `utils/<debugger>?.?`, with `utils/diag.h` containing the API definition for use by applications.

Returns:

Returns the number of bytes in the file.

24.2.2.6 DiagOpen

Opens a host file system file.

Prototype:

```
int  
DiagOpen(const char *pcName,  
         int iMode)
```

Parameters:

pcName is the name of the file to be opened.
iMode is the mode used to open the file.

Description:

This function opens a file on the host file system; this is similar to the `fopen()` function in the C library.

The *iMode* parameter must be the logical OR of at least one of the following values (which are analogous to the mode parameter of the C library `fopen()` function):

- **OPEN_R** to open the file for reading.
- **OPEN_W** to open the file for writing.
- **OPEN_A** to append to the end of the file.
- **OPEN_B** to access the file in binary mode, which means that no end of line translations are made.
- **OPEN_PLUS** to open the file for reading and writing.

This function is contained in a debugger-specific `utils/<debugger>.`, with `utils/diag.h` containing the API definition for use by applications.

Returns:

Returns a positive number on success or -1 on failure.

24.2.2.7 DiagOpenStdio

Opens a handle for stdio functions (both stdin and stdout).

Prototype:

```
int  
DiagOpenStdio(void)
```

Description:

This function opens a handle for interacting with the user via the debugger (similar to stdin and stdout). This handle should be passed to [DiagRead\(\)](#) to get input from the user and to [DiagWrite\(\)](#) to display messages to the user (such as via [DiagPrintf\(\)](#)).

This function is contained in a debugger-specific `utils/<debugger>.`, with `utils/diag.h` containing the API definition for use by applications.

Returns:

Returns a positive number on success or -1 on failure.

24.2.2.8 DiagPrintf

A simple diagnostic printf function supporting %c, %d, %p, %s, %u, %x, and %X.

Prototype:

```
void  
DiagPrintf(int iHandle,  
           const char *pcString,  
           ...)
```

Parameters:

iHandle is the handle of the stream to which the string is written.

pcString is the format string.

... are the optional arguments, which depend on the contents of the format string.

Description:

This function is very similar to the C library `fprintf()` function. All of its output will be sent to `DiagWrite()` using the supplied handle. Only the following formatting characters are supported:

- `%c` to print a character
- `%d` to print a decimal value
- `%s` to print a string
- `%u` to print an unsigned decimal value
- `%x` to print a hexadecimal value using lower case letters
- `%X` to print a hexadecimal value using upper case letters (not lower case letters as would typically be used)
- `%p` to print a pointer as a hexadecimal value
- `%%` to print out a `%` character

For `%s`, `%d`, `%u`, `%p`, `%x`, and `%X`, an optional number may reside between the `%` and the format character, which specifies the minimum number of characters to use for that value; if preceded by a 0 then the extra characters will be filled with zeros instead of spaces. For example, `"%8d"` will use eight characters to print the decimal value with spaces added to reach eight; `"%08d"` will use eight characters as well but will add zeroes instead of spaces.

The type of the arguments after *pcString* must match the requirements of the format string. For example, if an integer was passed where a string was expected, an error of some kind will most likely occur.

This function is contained in `utils/diagprintf.c`, with `utils/diagprintf.h` containing the API definition for use by applications.

Returns:

None.

24.2.2.9 DiagRead

Reads data from a host file system file.

Prototype:

```
int
DiagRead(int iHandle,
         char *pcBuf,
         unsigned long ulLen,
         int iMode)
```

Parameters:

iHandle is the handle of the file to read.

pcBuf is a pointer to the buffer to contain the data read.

ulLen is the number of bytes to read from the file.

iMode is the mode used to open the file.

Description:

This function reads data from a file previously opened with [DiagOpen\(\)](#); this is similar to the `fread()` function in the C library.

The *iMode* parameter might be used in some debugger interfaces to adjust how the data is read from the file. Unexpected results may occur if the same value passed to [DiagOpen\(\)](#) is not passed to [DiagRead\(\)](#).

This function is contained in a debugger-specific `utils/<debugger>.`, with `utils/diag.h` containing the API definition for use by applications.

Returns:

Returns zero on success, a positive number to indicate the number of bytes not read, a number with the MSB set to indicate the number of bytes not read and that EOF was encountered, or -1 to indicate an error.

24.2.2.10 DiagWrite

Writes data to a host file system file.

Prototype:

```
int
DiagWrite(int iHandle,
          const char *pcBuf,
          unsigned long ulLen,
          int iMode)
```

Parameters:

iHandle is the handle of the file to which to write.

pcBuf is a pointer to the data to be written.

ulLen is the number of bytes to write to the file.

iMode is the mode used to open the file.

Description:

This function writes data to a file previously opened with [DiagOpen\(\)](#); this is similar to the `fwrite()` function in the C library.

The *iMode* parameter might be used in some debugger interfaces to adjust how the data is written to the file. Unexpected results may occur if the same value passed to [DiagOpen\(\)](#) is not passed to [DiagWrite\(\)](#).

This function is contained in a debugger-specific `utils/<debugger>.`, with `utils/diag.h` containing the API definition for use by applications.

Returns:

Returns zero on success, a positive number to indicate the number of bytes not written (which is an error of sorts), or a negative number to indicate an error.

24.2.2.11 UARTgets

A simple UART based get string function, with some line processing.

Prototype:

```
int
UARTgets(char *pcBuf,
          unsigned long ulLen)
```

Parameters:

pcBuf points to a buffer for the incoming string from the UART.

ulLen is the length of the buffer for storage of the string, including the trailing 0.

Description:

This function will receive a string from the UART input and store the characters in the buffer pointed to by *pcBuf*. The characters will continue to be stored until a termination character is received. The termination characters are CR, LF, or ESC. A CRLF pair is treated as a single termination character. The termination characters are not stored in the string. The string will be terminated with a 0 and the function will return. If more characters are received than will fit in the buffer, then the extra characters will be ignored and not stored.

Since the string will be null terminated, the user must ensure that the buffer is sized to allow for the additional null character.

This function is contained in `utils/uartstdio.c`, with `utils/uartstdio.h` containing the API definition for use by applications.

Returns:

Returns the count of characters that were stored, not including the trailing 0.

24.2.2.12 UARTprintf

A simple UART based printf function supporting %c, %d, %p, %s, %u, %x, and %X.

Prototype:

```
void
UARTprintf(const char *pcString,
           ...)
```

Parameters:

pcString is the format string.

... are the optional arguments, which depend on the contents of the format string.

Description:

This function is very similar to the C library `fprintf()` function. All of its output will be sent to the UART. Only the following formatting characters are supported:

- %c to print a character
- %d to print a decimal value
- %s to print a string
- %u to print an unsigned decimal value
- %x to print a hexadecimal value using lower case letters
- %X to print a hexadecimal value using upper case letters (not upper case letters as would typically be used)
- %p to print a pointer as a hexadecimal value
- %% to print out a % character

For %s, %d, %u, %p, %x, and %X, an optional number may reside between the % and the format character, which specifies the minimum number of characters to use for that value; if preceded by a 0 then the extra characters will be filled with zeros instead of spaces. For example, "%8d" will use eight characters to print the decimal value with spaces added to reach eight; "%08d" will use eight characters as well but will add zeroes instead of spaces.

The type of the arguments after *pcString* must match the requirements of the format string. For example, if an integer was passed where a string was expected, an error of some kind will most likely occur.

This function is contained in `utils/uartstdio.c`, with `utils/uartstdio.h` containing the API definition for use by applications.

Returns:

None.

24.2.2.13 UARTStdioInit

Initialize UART console.

Prototype:

```
void
UARTStdioInit(unsigned long ulPortNum)
```

Parameters:

ulPortNum is the number of UART port to use for the serial console (0-2)

Description:

This function will initialize the specified serial port to be used as a serial console. The serial parameters will be set to 115200, 8-N-1.

This function must be called prior to using any of the other UART console functions: [UARTprintf\(\)](#) or [UARTgets\(\)](#). In order for this function to work correctly, [SysCtlClockSet\(\)](#) must be called prior to calling this function.

This function is contained in `utils/uartstdio.c`, with `utils/uartstdio.h` containing the API definition for use by applications.

Returns:

None.

24.2.2.14 ulocaltime

Converts from seconds to calendar date and time.

Prototype:

```
void
ulocaltime(unsigned long ulTime,
            tTime *psTime)
```

Parameters:

ulTime is the number of seconds.

psTime is a pointer to the time structure that is filled in with the broken down date and time.

Description:

This function converts a number of seconds since midnight GMT on January 1, 1970 (traditional Unix epoch) into the equivalent month, day, year, hours, minutes, and seconds representation.

Returns:

None.

24.2.2.15 usnprintf

A simple snprintf function supporting %c, %d, %p, %s, %u, %x, and %X.

Prototype:

```
int
usnprintf(char *pcBuf,
          unsigned long ulSize,
          const char *pcString,
          ...)
```

Parameters:

pcBuf is the buffer where the converted string is stored.

ulSize is the size of the buffer.

pcString is the format string.

... are the optional arguments, which depend on the contents of the format string.

Description:

This function is very similar to the C library `sprintf()` function. Only the following formatting characters are supported:

- %c to print a character
- %d to print a decimal value
- %s to print a string
- %u to print an unsigned decimal value
- %x to print a hexadecimal value using lower case letters
- %X to print a hexadecimal value using upper case letters (not lower case letters as would typically be used)
- %p to print a pointer as a hexadecimal value
- %% to print out a % character

For %d, %p, %s, %u, %x, and %X, an optional number may reside between the % and the format character, which specifies the minimum number of characters to use for that value; if preceded by a 0 then the extra characters will be filled with zeros instead of spaces. For example, "%8d" will use eight characters to print the decimal value with spaces added to reach eight; "%08d" will use eight characters as well but will add zeros instead of spaces.

The type of the arguments after *pcString* must match the requirements of the format string. For example, if an integer was passed where a string was expected, an error of some kind will most likely occur.

The function will copy at most *ulSize* - 1 characters into the buffer *pcBuf*. One space is reserved in the buffer for the null termination character.

The function will return the number of characters that would be converted as if there were no limit on the buffer size. Therefore it is possible for the function to return a count that is greater than the specified buffer size. If this happens, it means that the output was truncated.

Returns:

Returns the number of characters that were to be stored, not including the NULL termination character, regardless of space in the buffer.

24.2.2.16 usprintf

A simple sprintf function supporting %c, %d, %p, %s, %u, %x, and %X.

Prototype:

```
int
usprintf(char *pcBuf,
         const char *pcString,
         ...)
```

Parameters:

pcBuf is the buffer where the converted string is stored.

pcString is the format string.

... are the optional arguments, which depend on the contents of the format string.

Description:

This function is very similar to the C library `sprintf()` function. Only the following formatting characters are supported:

- %c to print a character
- %d to print a decimal value
- %s to print a string
- %u to print an unsigned decimal value
- %x to print a hexadecimal value using lower case letters
- %X to print a hexadecimal value using upper case letters (not lower case letters as would typically be used)
- %p to print a pointer as a hexadecimal value
- %% to print out a % character

For %d, %p, %s, %u, %x, and %X, an optional number may reside between the % and the format character, which specifies the minimum number of characters to use for that value; if preceded by a 0 then the extra characters will be filled with zeros instead of spaces. For example, "%8d" will use eight characters to print the decimal value with spaces added to reach eight; "%08d" will use eight characters as well but will add zeros instead of spaces.

The type of the arguments after *pcString* must match the requirements of the format string. For example, if an integer was passed where a string was expected, an error of some kind will most likely occur.

The caller must ensure that the buffer *pcBuf* is large enough to hold the entire converted string, including the null termination character.

Returns:

Returns the count of characters that were written to the output buffer, not including the NULL termination character.

24.2.2.17 strtoul

Converts a string into its numeric equivalent.

Prototype:

```
unsigned long
strtoul(const char *pcStr,
        const char **ppcStrRet,
        int iBase)
```

Parameters:

pcStr is a pointer to the string containing the integer.

ppcStrRet is a pointer that will be set to the first character past the integer in the string.

iBase is the radix to use for the conversion; can be zero to auto-select the radix or between 2 and 16 to explicitly specify the radix.

Description:

This function is very similar to the C library `strtoul()` function. It scans a string for the first token (that is, non-whitespace) and converts the value at that location in the string into an integer value.

Returns:

Returns the result of the conversion.

24.2.2.18 uvsnprintf

A simple `vsprintf` function supporting %c, %d, %p, %s, %u, %x, and %X.

Prototype:

```
int
uvsnprintf(char *pcBuf,
           unsigned long ulSize,
           const char *pcString,
           va_list vaArgP)
```

Parameters:

pcBuf points to the buffer where the converted string is stored.

ulSize is the size of the buffer.

pcString is the format string.

vaArgP is the list of optional arguments, which depend on the contents of the format string.

Description:

This function is very similar to the C library `vsprintf()` function. Only the following formatting characters are supported:

- %c to print a character
- %d to print a decimal value
- %s to print a string
- %u to print an unsigned decimal value
- %x to print a hexadecimal value using lower case letters

- %X to print a hexadecimal value using lower case letters (not upper case letters as would typically be used)
- %p to print a pointer as a hexadecimal value
- %% to print out a % character

For %d, %p, %s, %u, %x, and %X, an optional number may reside between the % and the format character, which specifies the minimum number of characters to use for that value; if preceded by a 0 then the extra characters will be filled with zeros instead of spaces. For example, "%8d" will use eight characters to print the decimal value with spaces added to reach eight; "%08d" will use eight characters as well but will add zeroes instead of spaces.

The type of the arguments after *pcString* must match the requirements of the format string. For example, if an integer was passed where a string was expected, an error of some kind will most likely occur.

The *ulSize* parameter limits the number of characters that will be stored in the buffer pointed to by *pcBuf* to prevent the possibility of a buffer overflow. The buffer size should be large enough to hold the expected converted output string, including the null termination character.

The function will return the number of characters that would be converted as if there were no limit on the buffer size. Therefore it is possible for the function to return a count that is greater than the specified buffer size. If this happens, it means that the output was truncated.

Returns:

Returns the number of characters that were to be stored, not including the NULL termination character, regardless of space in the buffer.

25 Error Handling

Invalid arguments and error conditions are handled in a non-traditional manner in the peripheral driver library. Typically, a function would check its arguments to make sure that they are valid (if required; some may be unconditionally valid such as a 32-bit value used as the load value for a 32-bit timer). If an invalid argument is provided, it would return an error code. The caller then has to check the return code from each invocation of the function to make sure that it succeeded.

This results in a sizable amount of argument checking code in each function and return code checking code at each call site. For a self-contained application, this extra code becomes an unneeded burden once the application is debugged. Having a means of removing it allows the final code to be smaller and therefore run faster.

In the peripheral driver library, most functions do not return errors ([FlashProgram\(\)](#), [FlashErase\(\)](#), [FlashProtectSet\(\)](#), and [FlashProtectSave\(\)](#) are the notable exceptions). Argument checking is done via a call to the `ASSERT` macro (provided in `src/debug.h`). This macro has the usual definition of an assert macro; it takes an expression that “must” be true. By making this macro be empty, the argument checking is removed from the code.

There are two definitions of the `ASSERT` macro provided in `src/debug.h`; one that is empty (used for normal situations) and one that evaluates the expression (used when the library is built with debugging). The debug version will call the `__error__` function whenever the expression is not true, passing the file name and line number of the `ASSERT` macro invocation. The `__error__` function is prototyped in `src/debug.h` and must be provided by the application since it is the application's responsibility to deal with error conditions.

By setting a breakpoint on the `__error__` function, the debugger will immediately stop whenever an error occurs anywhere in the application (something that would be very difficult to do with other error checking methods). When the debugger stops, the arguments to the `__error__` function and the backtrace of the stack will pinpoint the function that found an error, what it found to be a problem, and where it was called from. As an example:

```
void
UARTParityModeSet(unsigned long ulBase, unsigned long ulParity)
{
    //
    // Check the arguments.
    //
    ASSERT((ulBase == UART0_BASE) || (ulBase == UART1_BASE) ||
           (ulBase == UART2_BASE));
    ASSERT((ulParity == UART_CONFIG_PAR_NONE) ||
           (ulParity == UART_CONFIG_PAR_EVEN) ||
           (ulParity == UART_CONFIG_PAR_ODD) ||
           (ulParity == UART_CONFIG_PAR_ONE) ||
           (ulParity == UART_CONFIG_PAR_ZERO));
}
```

Each argument is individually checked, so the line number of the failing `ASSERT` will indicate the argument that is invalid. The debugger will be able to display the values of the arguments (from the stack backtrace) as well as the caller of the function that had the argument error. This allows the problem to be quickly identified at the cost of a small amount of code.

26 Boot Loader

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26.1 Introduction

The boot loader is a small piece of code that can be programmed at the beginning of flash to act as an application loader as well as an update mechanism for applications running on a Stellaris microcontroller. The boot loader can be built to use either the UART0, SSI0, I2C0, or Ethernet ports to update the code on the microcontroller. The boot loader is customizable via source code modifications, or simply deciding at compile time which routines to include. Since full source code is provided, the boot loader can be completely customized.

Two update protocols are utilized. On UART0, SSI0, and I2C0, a custom protocol is used to communicate with the download utility to transfer the firmware image and program it into flash. When using Ethernet, the standard bootstrap protocol (BOOTP) is used instead.

When configured to use UART0, the LMFlashProgrammer GUI can be used to download an application via the boot loader. The LMFlashProgrammer utility is available for download from www.luminarymicro.com.

Note:

Building the boot loader requires the use of linker scripts, and building applications that run under its control requires the ability to specify a start address other than the beginning of flash. Neither of these capabilities are available in the evaluation version of Keil RealView Microcontroller Development Kit; therefore, the boot loader is not usable unless the full version is used. Additionally, the linker script specified in the uVision project file for the boot loader is simply ignored, resulting in a successful link of the boot loader but an image that will not operate correctly.

26.1.1 Source Files

The following is an overview of the organization of the source code provided with the boot loader.

<code>bl_autobaud.c</code>	The code for performing the auto-baud operation on the UART port. This is separate from the remainder of the UART code so that the linker can remove it when it is not used.
<code>bl_check.c</code>	The code to check if a firmware update is required, or if a firmware update is being requested by the user.
<code>bl_check.h</code>	Prototypes for the update check code.
<code>bl_commands.h</code>	The list of commands and return messages supported by the boot loader.

<code>bl_config.c</code>	A dummy source file used to translate the <code>bl_config.h</code> C header file into a header file that can be included in assembly code. This is needed for the Keil tool chain since it is not able to pass assembly source code through the C preprocessor.
<code>bl_config.h.tmpl</code>	A template for the boot loader configuration file. This contains all of the possible configuration values.
<code>bl_decrypt.c</code>	The code to perform an in-place decryption of the downloaded firmware image. No decryption is actually performed in this file; this is simply a stub that can be expanded to perform the require decryption.
<code>bl_decrypt.h</code>	Prototypes for the in-place decryption routines.
<code>bl_enet.c</code>	The functions for performing a firmware update via the Ethernet port.
<code>bl_i2c.c</code>	The functions for transferring data via the I2C0 port.
<code>bl_i2c.h</code>	Prototypes for the I2C0 transfer functions.
<code>bl_link.ld</code>	The linker script used when the gcc or sourcerygxx compiler is being used to build the boot loader.
<code>bl_link.sct</code>	The linker script used when the rvmdk compiler is being used to build the boot loader.
<code>bl_link.xcl</code>	The linker script used when the ewarm compiler is being used to build the boot loader.
<code>bl_main.c</code>	The main control loop of the boot loader.
<code>bl_packet.c</code>	The functions for handling the packet processing of commands and responses.
<code>bl_packet.h</code>	Prototypes for the packet handling functions.
<code>bl_ssi.c</code>	The functions for transferring data via the SSI0 port.
<code>bl_ssi.h</code>	Prototypes for the SSI0 transfer functions.
<code>bl_startup_ewarm.S</code>	The start-up code used when the ewarm compiler is being used to build the boot loader.
<code>bl_startup_gcc.S</code>	The start-up code used when the gcc compiler is being used to build the boot loader.
<code>bl_startup_rvmdk.S</code>	The start-up code used when the rvmdk compiler is being used to build the boot loader.

<code>bl_startup_sourcerygxx.S</code>	The start-up code used when the sourcerygxx compiler is being used to build the boot loader.
<code>bl_uart.c</code>	The functions for transferring data via the UART0 port.
<code>bl_uart.h</code>	Prototypes for the UART0 transfer functions.

26.1.2 Start-up Code

The start-up code contains the minimal set of code required to configure a vector table, initialize memory, copy the boot loader from flash to SRAM, and execute from SRAM. Because some tool chain-specific constructs are used to indicate where the code, data, and bss segments reside in memory, each supported tool chain has its own separate file that implements the start-up code. The start-up code is contained in the following files:

- `bl_startup_ewarm.S` (IAR Embedded Workbench)
- `bl_startup_gcc.S` (GNU GCC)
- `bl_startup_rvmdk.S` (Keil RV-MDK)
- `bl_startup_sourcerygxx.S` (CodeSourcery Sourcery G++)

Accompanying the start-up code for each tool chain are linker scripts that are used to place the vector table, code segment, data segment initializers, and data segments in the appropriate locations in memory. The scripts are located in the following files:

- `bl_link.ld` (GNU GCC and CodeSourcery Sourcery G++)
- `bl_link.sct` (Keil RV-MDK)
- `bl_link.xcl` (IAR Embedded Workbench)

The boot loader's code and its corresponding linker script use a memory layout that exists entirely in SRAM. This means that the load address of the code and read-only data are not the same as the execution address. This memory map allows the boot loader to update itself since it is actually running from SRAM only. The first part of SRAM is used as the copy space for the boot loader while the rest is reserved for stack and read/write data for the boot loader. Once the boot loader calls the application, all SRAM becomes usable by the application.

The vector table of the Cortex-M3 microprocessor contains four required entries: the initial stack pointer, the reset handler address, the NMI handler address, and the hard fault handler address. Upon reset, the processor loads the initial stack pointer and then starts executing the reset handler. The initial stack pointer is required since an NMI or hard fault can occur at any time; the stack is required to take those interrupts since the processor automatically pushes eight items onto the stack.

The `Vectors` array contains the boot loader's vector table which varies in size based on the addition of the auto-baud feature. The auto-baud feature requires an interrupt and expands the vector table slightly. Since the boot loader executes from SRAM and not from flash, tool chain-specific constructs are used to provide a hint to the linker that this array is located at `0x2000.0000`.

The `IntDefaultHandler` function contains the default fault handler. This is a simple infinite loop, effectively halting the application if any unexpected fault occurs. The application state is, therefore,

preserved for examination by a debugger. If desired, a customized boot loader can provide its own handlers by adding the appropriate handlers to the `Vectors` array.

After a reset, the start-up copies the boot loader from flash to SRAM, branches to the copy of the boot loader in SRAM, and checks to see if an application update should be performed by calling `CheckForceUpdate()`. If an update is not required, the application is called. Otherwise, the microcontroller is initialized by calling `ConfigureDevice()` (for UART0, SSI0, and I2C0) or `ConfigureEnet()` (for Ethernet), and then the control loop of the boot loader in `Updater()` (for UART0, SSI0, and I2C0) or `UpdateBOOTP()` is called.

The check for an application update (in `CheckForceUpdate()`) consists of checking the beginning of the application area and optionally checking the state of a GPIO pin. The application is assumed to be valid if the first location is a valid stack pointer (that is, it resides in SRAM, and has a value of `0x2xxx.xxxx`), and the second location is a valid reset handler address (that is, it resides in flash, and has a value of `0x000x.xxxx`, where the value is odd). If either of these tests fail, then the application is assumed to be invalid and an update is forced. The GPIO pin check can be enabled with **ENABLE_UPDATE_CHECK**, in which case an update can be forced by changing the state of a GPIO pin (for example, with a push button). If the application is valid and the GPIO pin is not requesting an update, the application is called. Otherwise, an update is started by entering the main loop of the boot loader.

Additionally, the boot loader can be called by the application in order to perform an application-directed update. In this case, the boot loader assumes that the peripheral in use for the update has already been configured by the application, and must simply be used by the boot loader to perform the update. The boot loader therefore copies itself to SRAM, branches to the SRAM copy of the boot loader, and starts the update by calling `Updater()` (for UART0, SSI0, and I2C0) or `UpdateBOOTP()` (for Ethernet). The `SVCall` entry of the vector table contains the location of the application-directed update entry point.

26.1.3 Ethernet Update

When performing an Ethernet update, `ConfigureEnet()` is used to configure the Ethernet controller, making it ready to be used to update the firmware. Then, `UpdateBOOTP()` begins the process of the firmware update.

The bootstrap protocol (BOOTP) is a predecessor to the DHCP protocol and is used to discover the IP address of the client, the IP address of the server, and the name of the firmware image to use. BOOTP uses UDP/IP packets to communicate between the client and the server; the boot loader acts as the client. First, it will send a BOOTP request using a broadcast message. When the server receives the request, it will reply, thereby informing the client of its IP address, the IP address of the server, and the name of the firmware image. Once this reply is received, the BOOTP protocol has completed.

Then, the trivial file transfer protocol (TFTP) is used to transfer the firmware image from the server to the client. TFTP also uses UDP/IP packets to communicate between the client and the server, and the boot loader also acts as the client in this protocol. As each data block is received, it is programmed into flash. Once all data blocks are received and programmed, the device is reset, causing it to start running the new firmware image.

The uIP stack (<http://www.sics.se/~adam/uip>) is used to implement the UDP/IP connections. The TCP support is not needed and is therefore disabled, greatly reducing the size of the stack.

Note:

When using the Ethernet update, the boot loader can not update itself since there is no mechanism in BOOTP to distinguish between a firmware image and a boot loader image. Therefore, the boot loader does not know if a given image is a new boot loader or a new firmware image. It assumes that all images provided are firmware images.

- RFC951 (<http://tools.ietf.org/html/rfc951.html>) defines the bootstrap protocol.
- RFC1350 (<http://tools.ietf.org/html/rfc1350.html>) defines the trivial file transfer protocol.

26.1.4 Serial Update

When performing an update via a serial port (UART0, SSI0, or I2C0), `ConfigureDevice()` is used to configure the selected serial port, making it ready to be used to update the firmware. Then, `Updater()` sits in an endless loop accepting commands and updating the firmware when requested. The commands are explained in detail in the [Commands](#) section. All transmissions from this main routine use the packet handler functions (`SendPacket()`, `ReceivePacket()`, `AckPacket()`, and `NakPacket()`). Once the update is complete, the boot loader can be reset by issuing a reset command to the boot loader.

When a request to update the application comes through and **FLASH_CODE_PROTECTION** is defined, the boot loader first erases the entire application area before accepting the binary for the new application. This prevents a partial erase of flash from exposing any of the code before the new binary is downloaded to the microcontroller. The boot loader itself is left in place so that it will not boot a partially erased program. Once all of the application flash area has been successfully erased, the boot loader proceeds with the download of the new binary. When **FLASH_CODE_PROTECTION** is not defined, the boot loader only erases enough space to fit the new application that is being downloaded.

In the event that the boot loader itself needs to be updated, the boot loader must replace itself in flash. An update of the boot loader is recognized by performing a download to address 0x0000.0000. Once again the boot loader operates differently based on the setting of **FLASH_CODE_PROTECTION**. When **FLASH_CODE_PROTECTION** is defined and the download address indicates an boot loader update, the boot loader protects any application code already on the microcontroller by erasing the entire application area before erasing and replacing itself. If the process is interrupted at any point, either the old boot loader remains present in the flash and does not boot the partial application or the application code will have already been erased. When **FLASH_CODE_PROTECTION** is not defined, the boot loader only erases enough space to fit its own code and leaves the application intact.

26.1.4.1 Packet Handling

The boot loader uses well-defined packets to ensure reliable communications with the update program. The packets are always acknowledged or not acknowledged by the communicating devices. The packets use the same format for receiving and sending packets. This includes the method used to acknowledge successful or unsuccessful reception of a packet. While the actual signaling on the serial ports is different, the packet format remains independent of the method of transporting the data.

The boot loader uses the `SendPacket()` function in order to send a packet of data to another device. This function encapsulates all of the steps necessary to send a valid packet to another de-

vice including waiting for the acknowledge or not-acknowledge from the other device. The following steps must be performed to successfully send a packet:

1. Send out the size of the packet that will be sent to the device. The size is always the size of the data + 2.
2. Send out the checksum of the data buffer to help ensure proper transmission of the command. The checksum algorithm is implemented in the `Checksum()` function provided and is simply a sum of the data bytes.
3. Send out the actual data bytes.
4. Wait for a single byte acknowledgment from the device that it either properly received the data or that it detected an error in the transmission.

Received packets use the same format as sent packets. The boot loader uses the `ReceivePacket()` function in order to receive or wait for a packet from another device. This function does not take care of acknowledging or not-acknowledging the packet to the other device. This allows the contents of the packet to be checked before sending back a response. The following steps must be performed to successfully receive a packet:

1. Wait for non-zero data to be returned from the device. This is important as the device may send zero bytes between a sent and received data packet. The first non-zero byte received will be the size of the packet that is being received.
2. Read the next byte which will be the checksum for the packet.
3. Read the data bytes from the device. There will be packet size - 2 bytes of data sent during the data phase. For example, if the packet size was 3, then there is only 1 byte of data to be received.
4. Calculate the checksum of the data bytes and ensure if it matches the checksum received in the packet.
5. Send an acknowledge or not-acknowledge to the device to indicate the successful or unsuccessful reception of the packet.

The steps necessary to acknowledge reception of a packet are implemented in the `AckPacket()` function. Acknowledge bytes are sent out whenever a packet is successfully received and verified by the boot loader.

A not-acknowledge byte is sent out whenever a sent packet is detected to have an error, usually as a result of a checksum error or just malformed data in the packet. This allows the sender to re-transmit the previous packet.

26.1.4.2 Transport Layer

The boot loader supports updating via the I2C0, SSI0, and UART0 ports which are available on Stellaris microcontrollers. The SSI port has the advantage of supporting higher and more flexible data rates but it also requires more connections to the microcontroller. The UART has the disadvantage of having slightly lower and possibly less flexible rates. However, the UART requires fewer pins and can be easily implemented with any standard UART connection. The I2C interface also provides a standard interface, only uses two wires, and can operate at comparable speeds to the UART and SSI interfaces.

26.1.4.3 I2C Transport

The I2C handling functions are `I2CSend()`, `I2CReceive()`, and `I2CFlush()` functions. The connections required to use the I2C port are the following pins: **I2CSCL** and **I2CSDA**. The device communicating with the boot loader must operate as the I2C master and provide the **I2CSCL** signal. The **I2CSDA** pin is open drain and can be driven by either the master or the slave I2C device.

26.1.4.4 SSI Transport

The SSI handling functions are `SSISend()`, `SSIReceive()`, and `SSIFlush()`. The connections required to use the SSI port are the following four pins: **SSITx**, **SSIRx**, **SSIClk**, and **SSIFss**. The device communicating with the boot loader is responsible for driving the **SSIRx**, **SSIClk**, and **SSIFss** pins, while the Stellaris microcontroller drives the **SSITx** pin. The format used for SSI communications is the Motorola format with SPH set to 1 and SPO set to 1 (see Stellaris Family data sheet for more information on this format). The SSI interface has a hardware requirement that limits the maximum rate of the SSI clock to be at most 1/12 the frequency of the microcontroller running the boot loader.

26.1.4.5 UART Transport

The UART handling functions are `UARTSend()`, `UARTReceive()`, and `UARTFlush()`. The connections required to use the UART port are the following two pins: **U0Tx** and **U0Rx**. The device communicating with the boot loader is responsible for driving the **U0Rx** pin on the Stellaris microcontroller, while the Stellaris microcontroller drives the **U0Tx** pin.

While the baud rate is flexible, the UART serial format is fixed at 8 data bits, no parity, and one stop bit. The baud rate used for communication can either be auto-detected by the boot loader, if the auto-baud feature is enabled, or it can be fixed at a baud rate supported by the device communicating with the boot loader. The only requirement on baud rate is that the baud rate should be no more than 1/32 the frequency of the microcontroller that is running the boot loader. This is the hardware requirement for the maximum baud rate for a UART on any Stellaris microcontroller.

When using a fixed baud rate, the frequency of the crystal connected to the microcontroller must be specified. Otherwise, the boot loader will not be able to configure the UART to operate at the requested baud rate.

The boot loader provides a method to automatically detect the baud rate being used to communicate with it. This automatic baud rate detection is implemented in the `UARTAutoBaud()` function. The auto-baud function attempts to synchronize with the updater application and indicates if it is successful in detecting the baud rate or if it failed to properly detect the baud rate. The boot loader can make multiple calls to `UARTAutoBaud()` to attempt to retry the synchronization if the first call fails. In the example boot loader provided, when the auto-baud feature is enabled, the boot loader will wait forever for a valid synchronization pattern from the host.

26.1.5 Customization

The boot loader allows for customization of its features as well as the interfaces used to update the microcontroller. This allows the boot loader to include only the features that are needed by the application. There are two types of features that can be customized. The first type are the features

that are conditionally included or excluded at compile time. The second type of customizations are more involved and include customizing the actual code that is used by the boot loader.

The boot loader can be modified to have any functionality. As an example, the main loop can be completely replaced to use a different set of commands and still use the packet and transport functions from the boot loader. The method of detecting a forced update can be modified to suit the needs of the application when toggling a GPIO to detect an update request may not be the best solution. If the boot loader's packet format does not meet the needs of the application, it can be completely replaced by replacing `ReceivePacket()`, `SendPacket()`, `AckPacket()`, and `NakPacket()`.

The boot loader also provides a method to add a new transmission interfaces beyond the UART, SSI, and I2C that are provided by the boot loader. In order for the packet functions to use the new transport functions, the `SendData`, `ReceiveData`, and `FlushData` defines need to be modified to use the new functions. For example:

```
#ifdef FOO_ENABLE_UPDATE
#define SendData          FooSend
#define FlushData         FooFlush
#define ReceiveData       FooReceive
#endif
```

would use the functions for the hypothetical Foo peripheral.

The combination of these customizable features provides a framework that allows the boot loader to define whatever protocol it needs, or use any port that it needs to perform updates of the micro-controller.

26.1.6 Commands

The following commands are used by the custom protocol on the UART0, SSI0, and I2C0 ports:

`COMMAND_PING`

This command is used to receive an acknowledge from the boot loader indicating that communication has been established. This command is a single byte.

The format of the command is as follows:

```
unsigned char ucCommand[1];

ucCommand[0] = COMMAND_PING;
```


COMMAND_DOWNLOAD

This command is sent to the boot loader to indicate where to store data and how many bytes will be sent by the **COMMAND_SEND_DATA** commands that follow. The command consists of two 32-bit values that are both transferred MSB first. The first 32-bit value is the address to start programming data into, while the second is the 32-bit size of the data that will be sent. This command also triggers an erasure of the full application area in the flash or possibly the entire flash depending on the address used. This causes the command to take longer to send the ACK/NAK in response to the command. This command should be followed by a **COMMAND_GET_STATUS** to ensure that the program address and program size were valid for the microcontroller running the boot loader.

The format of the command is as follows:

```
unsigned char ucCommand[9];

ucCommand[0] = COMMAND_DOWNLOAD;
ucCommand[1] = Program Address [31:24];
ucCommand[2] = Program Address [23:16];
ucCommand[3] = Program Address [15:8];
ucCommand[4] = Program Address [7:0];
ucCommand[5] = Program Size [31:24];
ucCommand[6] = Program Size [23:16];
ucCommand[7] = Program Size [15:8];
ucCommand[8] = Program Size [7:0];
```

COMMAND_RUN

This command is sent to the boot loader to transfer execution control to the specified address. The command is followed by a 32-bit value, transferred MSB first, that is the address to which execution control is transferred.

The format of the command is as follows:

```
unsigned char ucCommand[5];

ucCommand[0] = COMMAND_RUN;
ucCommand[1] = Run Address [31:24];
ucCommand[2] = Run Address [23:16];
ucCommand[3] = Run Address [15:8];
ucCommand[4] = Run Address [7:0];
```

COMMAND_GET_STATUS

This command returns the status of the last command that was issued. Typically, this command should be received after every command is sent to ensure that the previous command was successful or, if unsuccessful, to properly respond to a failure. The command requires one byte in the data of the packet and the boot loader should respond by sending a packet with one byte of data that contains the current status code.

The format of the command is as follows:

```
unsigned char ucCommand[1];

ucCommand[0] = COMMAND_GET_STATUS;
```

The following are the definitions for the possible status values that can be returned from the boot loader when **COMMAND_GET_STATUS** is sent to the the microcontroller.

```
COMMAND_RET_SUCCESS
COMMAND_RET_UNKNOWN_CMD
COMMAND_RET_INVALID_CMD
COMMAND_RET_INVALID_ADD
COMMAND_RET_FLASH_FAIL
```

COMMAND_SEND_DATA

This command should only follow a **COMMAND_DOWNLOAD** command or another **COMMAND_SEND_DATA** command, if more data is needed. Consecutive send data commands automatically increment the address and continue programming from the previous location. The transfer size is limited by the size of the receive buffer in the boot loader (as configured by the **BUFFER_SIZE** parameter). The command terminates programming once the number of bytes indicated by the **COMMAND_DOWNLOAD** command has been received. Each time this function is called, it should be followed by a **COMMAND_GET_STATUS** command to ensure that the data was successfully programmed into the flash. If the boot loader sends a NAK to this command, the boot loader will not increment the current address which allows for retransmission of the previous data.

The format of the command is as follows:

```
unsigned char ucCommand[9];

ucCommand[0] = COMMAND_SEND_DATA
ucCommand[1] = Data[0];
ucCommand[2] = Data[1];
ucCommand[3] = Data[2];
ucCommand[4] = Data[3];
ucCommand[5] = Data[4];
ucCommand[6] = Data[5];
ucCommand[7] = Data[6];
ucCommand[8] = Data[7];
```

COMMAND_RESET

This command is used to tell the boot loader to reset. This is used after downloading a new image to the microcontroller to cause the new application or the new boot loader to start from a reset. The normal boot sequence occurs and the image runs as if from a hardware reset. It can also be used to reset the boot loader if a critical error occurs and the host device wants to restart communication with the boot loader.

The boot loader responds with an ACK signal to the host device before actually executing the software reset on the microcontroller running the boot loader. This informs the updater application that the command was received successfully and the part will be reset.

The format of the command is as follows:

```
unsigned char ucCommand[1];

ucCommand[0] = COMMAND_RESET;
```

26.1.7 Configuration

There are a number of defines that are used to configure the operation of the boot loader. These defines are located in the `bl_config.h` header file, for which there is a template (`bl_config.h.tmpl`) provided with the boot loader.

The configuration options are:

CRYSTAL_FREQ

This defines the crystal frequency used by the microcontroller running the boot loader. If this is unknown at the time of production, then use the `UART_AUTOBAUD` feature to properly configure the UART.

- This value must be defined if using the UART for the update and not using the auto-baud feature, and when using Ethernet for the update.

BOOST_LDO_VOLTAGE

This enables the boosting of the LDO voltage to 2.75V. For boot loader configurations that enable the PLL (i.e. using the Ethernet port) on a part that has the PLL errata, this should be enabled. This applies to revision A2 of Fury-class devices.

APP_START_ADDRESS

The starting address of the application. This must be a multiple of 1024 bytes (making it aligned to a page boundary). A vector table is expected at this location, and the perceived validity of the vector table (stack located in SRAM, reset vector located in flash) is used as an indication of the validity of the application image.

- This value must be defined. The flash image of the boot loader must not be larger than this value.

FLASH_RSVD_SPACE	The amount of space at the end of flash to reserve. This must be a multiple of 1024 bytes (making it aligned to a page boundary). This reserved space is not erased when the application is updated, providing non-volatile storage that can be used for parameters.
STACK_SIZE	The number of words of stack space to reserve for the boot loader. <ul style="list-style-type: none"> ■ This value must be defined.
BUFFER_SIZE	The number of words in the data buffer used for receiving packets. This value must be at least 3. If using auto-baud on the UART, this must be at least 20. The maximum usable value is 65 (larger values will result in unused space in the buffer). This value is unused when updating via the Ethernet port. <ul style="list-style-type: none"> ■ This value must be defined.
ENABLE_BL_UPDATE	Enables updates to the boot loader. Updating the boot loader is an unsafe operation since it is not fully fault tolerant (losing power to the device partway through could result in the boot loader no longer being present in flash). The boot loader can not be updated via the Ethernet port.
FLASH_CODE_PROTECTION	This definition will cause the the boot loader to erase the entire flash on updates to the boot loader or to erase the entire application area when the application is updated. This erases any unused sections in the flash before the firmware is updated.
ENABLE_DECRYPTION	Enables the call to decrypt the downloaded data before writing it into flash. The decryption routine is empty in the reference boot loader source, which simply provides a placeholder for adding an actual decryption algorithm.
ENABLE_UPDATE_CHECK	Enables the pin-based forced update check. When enabled, the boot loader will go into update mode instead of calling the application if a pin is read at a particular polarity, forcing an update operation. In either case, the application is still able to return control to the boot loader in order to start an update.
FORCED_UPDATE_PERIPH	The GPIO module to enable in order to check for a forced update. This will be one of the <code>SYSCTL_RCGC2_GPIOx</code> values, where “x” is replaced with the port name (such as B). The value of “x” should match the value of “x” for <code>FORCED_UPDATE_PORT</code> . <ul style="list-style-type: none"> ■ This value must be defined if <code>ENABLE_UPDATE_CHECK</code> is defined.

FORCED_UPDATE_PORT	<p>The GPIO port to check for a forced update. This will be one of the <code>GPIO_PORTx_BASE</code> values, where “x” is replaced with the port name (such as B). The value of “x” should match the value of “x” for <code>FORCED_UPDATE_PERIPH</code>.</p> <ul style="list-style-type: none">■ This value must be defined if <code>ENABLE_UPDATE_CHECK</code> is defined.
FORCED_UPDATE_PIN	<p>The pin to check for a forced update. This is a value between 0 and 7.</p> <ul style="list-style-type: none">■ This value must be defined if <code>ENABLE_UPDATE_CHECK</code> is defined.
FORCED_UPDATE_POLARITY	<p>The polarity of the GPIO pin that results in a forced update. This value should be 0 if the pin should be low and 1 if the pin should be high.</p> <ul style="list-style-type: none">■ This value must be defined if <code>ENABLE_UPDATE_CHECK</code> is defined.
UART_ENABLE_UPDATE	<p>Selects the UART as the port for communicating with the boot loader.</p>
UART_AUTOBAUD	<p>Enables automatic baud rate detection. This can be used if the crystal frequency is unknown, or if operation at different baud rates is desired.</p>
UART_FIXED_BAUDRATE	<p>Selects the baud rate to be used for the UART.</p>
SSI_ENABLE_UPDATE	<p>Selects the SSI port as the port for communicating with the boot loader.</p>
I2C_ENABLE_UPDATE	<p>Selects the I2C port as the port for communicating with the boot loader.</p>
I2C_SLAVE_ADDR	<p>Specifies the I2C address of the boot loader.</p> <ul style="list-style-type: none">■ This value must be defined if <code>I2C_ENABLE_UPDATE</code> is defined.
ENET_ENABLE_UPDATE	<p>Selects an update via the Ethernet port.</p>
ENET_ENABLE_LEDS	<p>Enables the use of the Ethernet status LED outputs to indicate traffic and connection status.</p>

ENET_MAC_ADDR?	Specifies the hard coded MAC address for the Ethernet interface. There are six individual values (ENET_MAC_ADDR0 through ENET_MAC_ADDR5) that provide the six bytes of the MAC address, where ENET_MAC_ADDR0 through ENET_MAC_ADDR2 provide the organizationally unique identifier (OUI) and ENET_MAC_ADDR3 through ENET_MAC_ADDR5 provide the extension identifier. If these values are not provided, the MAC address will be extracted from the user registers.
ENET_BOOTP_SERVER	Specifies the name of the BOOTP server from which to request information. The use of this specifier allows a board-specific BOOTP server to co-exist on a network with the DHCP server that may be part of the network infrastructure. The BOOTP server provided by Luminary Micro requires that this be set to "stellaris".

26.2 Functions

Functions

- void [AckPacket](#) (void)
- char [BOOTPThread](#) (void)
- unsigned long [CheckForceUpdate](#) (void)
- unsigned long [CheckSum](#) (const unsigned char *pucData, unsigned long ulSize)
- void [ConfigureDevice](#) (void)
- void [ConfigureEnet](#) (void)
- void [DecryptData](#) (unsigned char *pucBuffer, unsigned long ulSize)
- void [GPIOIntHandler](#) (void)
- void [I2CFlush](#) (void)
- void [I2CReceive](#) (unsigned char *pucData, unsigned long ulSize)
- void [I2CSend](#) (const unsigned char *pucData, unsigned long ulSize)
- void [NakPacket](#) (void)
- int [ReceivePacket](#) (unsigned char *pucData, unsigned long *pulSize)
- int [SendPacket](#) (unsigned char *pucData, unsigned long ulSize)
- void [SSIFlush](#) (void)
- void [SSIReceive](#) (unsigned char *pucData, unsigned long ulSize)
- void [SSISend](#) (const unsigned char *pucData, unsigned long ulSize)
- void [SysTickIntHandler](#) (void)
- int [UARTAutoBaud](#) (unsigned long *pulRatio)
- void [UARTFlush](#) (void)
- void [UARTReceive](#) (unsigned char *pucData, unsigned long ulSize)
- void [UARTSend](#) (const unsigned char *pucData, unsigned long ulSize)
- void [UpdateBOOTP](#) (void)
- void [Updater](#) (void)

26.2.1 Detailed Description

The following functions make up the boot loader. In order to keep the size of the boot loader to a minimum, none of the APIs from the peripheral driver library are utilized.

26.2.2 Function Documentation

26.2.2.1 AckPacket

Sends an Acknowledge packet.

Prototype:

```
void  
AckPacket(void)
```

Description:

This function is called to acknowledge that a packet has been received by the microcontroller.

This function is contained in `bl_packet.c`.

Returns:

None.

26.2.2.2 BOOTPThread

Handles the BOOTP process.

Prototype:

```
char  
BOOTPThread(void)
```

Description:

This function contains the proto-thread for handling the BOOTP process. It first communicates with the BOOTP server to get its boot parameters (IP address, server address, and filename), then it communicates with the TFTP server on the specified server to read the firmware image file.

This function is contained in `bl_enet.c`.

Returns:

None.

26.2.2.3 CheckForceUpdate

Checks if an update is needed or is being requested.

Prototype:

```
unsigned long  
CheckForceUpdate(void)
```

Description:

This function detects if an update is being requested or if there is no valid code presently located on the microcontroller. This is used to tell whether or not to enter update mode.

This function is contained in `bl_check.c`.

Returns:

Returns a non-zero value if an update is needed or is being requested and zero otherwise.

26.2.2.4 CheckSum

Calculates an 8-bit checksum

Prototype:

```
unsigned long  
Checksum(const unsigned char *pucData,  
          unsigned long ulSize)
```

Parameters:

pucData is a pointer to an array of 8-bit data of size `ulSize`.

ulSize is the size of the array that will run through the checksum algorithm.

Description:

This function simply calculates an 8-bit checksum on the data passed in.

This function is contained in `bl_packet.c`.

Returns:

Returns the calculated checksum.

26.2.2.5 ConfigureDevice

Configures the microcontroller.

Prototype:

```
void  
ConfigureDevice(void)
```

Description:

This function configures the peripherals and GPIOs of the microcontroller, preparing it for use by the boot loader. The interface that has been selected as the update port will be configured, and auto-baud will be performed if required.

This function is contained in `bl_main.c`.

Returns:

None.

26.2.2.6 ConfigureEnet

Configures the Ethernet controller.

Prototype:

```
void  
ConfigureEnet(void)
```

Description:

This function configures the Ethernet controller, preparing it for use by the boot loader.

This function is contained in `bl_enet.c`.

Returns:

None.

26.2.2.7 DecryptData

Performs an in-place decryption of downloaded data.

Prototype:

```
void  
DecryptData(unsigned char *pucBuffer,  
            unsigned long ulSize)
```

Parameters:

pucBuffer is the buffer that holds the data to decrypt.

ulSize is the size, in bytes, of the buffer that was passed in via the `pucBuffer` parameter.

Description:

This function is a stub that could provide in-place decryption of the data that is being downloaded to the device.

This function is contained in `bl_decrypt.c`.

Returns:

None.

26.2.2.8 GPIOIntHandler

Handles the UART Rx GPIO interrupt.

Prototype:

```
void  
GPIOIntHandler(void)
```

Description:

When an edge is detected on the UART Rx pin, this function is called to save the time of the edge. These times are later used to determine the ratio of the UART baud rate to the processor clock rate.

This function is contained in `bl_autobaud.c`.

Returns:
None.

26.2.2.9 I2CFlush

Waits until all data has been transmitted by the I2C port.

Prototype:
`void
I2CFlush(void)`

Description:
This function waits until all data written to the I2C port has been read by the master.
This function is contained in `bl_i2c.c`.

Returns:
None.

26.2.2.10 I2CReceive

Receives data over the I2C port.

Prototype:
`void
I2CReceive(unsigned char *pucData,
 unsigned long ulSize)`

Parameters:
pucData is the buffer to read data into from the I2C port.
ulSize is the number of bytes provided in the *pucData* buffer that should be written with data from the I2C port.

Description:
This function reads back *ulSize* bytes of data from the I2C port, into the buffer that is pointed to by *pucData*. This function will not return until *ulSize* number of bytes have been received. This function will wait till the I2C Slave port has been properly addressed by the I2C Master before reading the first byte of data from the I2C port.
This function is contained in `bl_i2c.c`.

Returns:
None.

26.2.2.11 I2CSend

Sends data over the I2C port.

Prototype:

```
void  
I2CSend(const unsigned char *pucData,  
        unsigned long ulSize)
```

Parameters:

pucData is the buffer containing the data to write out to the I2C port.

ulSize is the number of bytes provided in *pucData* buffer that will be written out to the I2C port.

Description:

This function sends *ulSize* bytes of data from the buffer pointed to by *pucData* via the I2C port. The function will wait till the I2C Slave port has been properly addressed by the I2C Master device before sending the first byte.

This function is contained in `bl_i2c.c`.

Returns:

None.

26.2.2.12 NakPacket

Sends a no-acknowledge packet.

Prototype:

```
void  
NakPacket(void)
```

Description:

This function is called when an invalid packet has been received by the microcontroller, indicating that it should be retransmitted.

This function is contained in `bl_packet.c`.

Returns:

None.

26.2.2.13 ReceivePacket

Receives a data packet.

Prototype:

```
int  
ReceivePacket(unsigned char *pucData,  
              unsigned long *pulSize)
```

Parameters:

pucData is the location to store the data that is sent to the boot loader.

pulSize is the number of bytes returned in the *pucData* buffer that was provided.

Description:

This function receives a packet of data from specified transfer function.

This function is contained in `bl_packet.c`.

Returns:

Returns zero to indicate success while any non-zero value indicates a failure.

26.2.2.14 SendPacket

Sends a data packet.

Prototype:

```
int
SendPacket(unsigned char *pucData,
            unsigned long ulSize)
```

Parameters:

pucData is the location of the data to be sent.

ulSize is the number of bytes to send.

Description:

This function sends the data provided in the *pucData* parameter in the packet format used by the boot loader. The caller only needs to specify the buffer with the data that needs to be transferred. This function addresses all other packet formatting issues.

This function is contained in `bl_packet.c`.

Returns:

Returns zero to indicate success while any non-zero value indicates a failure.

26.2.2.15 SSIFlush

Waits until all data has been transmitted by the SSI port.

Prototype:

```
void
SSIFlush(void)
```

Description:

This function waits until all data written to the SSI port has been read by the master.

This function is contained in `bl_ssi.c`.

Returns:

None.

26.2.2.16 SSIReceive

Receives data from the SSI port in slave mode.

Prototype:

```
void
SSIReceive(unsigned char *pucData,
            unsigned long ulSize)
```

Parameters:

pucData is the location to store the data received from the SSI port.
ulSize is the number of bytes of data to receive.

Description:

This function receives data from the SSI port in slave mode. The function will not return until *ulSize* number of bytes have been received.

This function is contained in `bl_ssi.c`.

Returns:

None.

26.2.2.17 SSISend

Sends data via the SSI port in slave mode.

Prototype:

```
void  
SSISend(const unsigned char *pucData,  
        unsigned long ulSize)
```

Parameters:

pucData is the location of the data to send through the SSI port.
ulSize is the number of bytes of data to send.

Description:

This function sends data through the SSI port in slave mode. This function will not return until all bytes are sent.

This function is contained in `bl_ssi.c`.

Returns:

None.

26.2.2.18 SysTickIntHandler

Handles the SysTick interrupt.

Prototype:

```
void  
SysTickIntHandler(void)
```

Description:

This function is called when the SysTick interrupt occurs. It simply keeps a running count of interrupts, used as a time basis for the BOOTP and TFTP protocols.

This function is contained in `bl_enet.c`.

Returns:

None.

26.2.2.19 UARTAutoBaud

Performs auto-baud on the UART port.

Prototype:

```
int
UARTAutoBaud(unsigned long *pulRatio)
```

Parameters:

pulRatio is the ratio of the processor's crystal frequency to the baud rate being used by the UART port for communications.

Description:

This function attempts to synchronize to the updater program that is trying to communicate with the boot loader. The UART port is monitored for edges using interrupts. Once enough edges are detected, the boot loader determines the ratio of baud rate and crystal frequency needed to program the UART.

This function is contained in `bl_autobaud.c`.

Returns:

Returns a value of 0 to indicate that this call successfully synchronized with the other device communicating over the UART, and a negative value to indicate that this function did not successfully synchronize with the other UART device.

26.2.2.20 UARTFlush

Waits until all data has been transmitted by the UART port.

Prototype:

```
void
UARTFlush(void)
```

Description:

This function waits until all data written to the UART port has been transmitted.

This function is contained in `bl_uart.c`.

Returns:

None.

26.2.2.21 UARTReceive

Receives data over the UART port.

Prototype:

```
void
UARTReceive(unsigned char *pucData,
             unsigned long ulSize)
```

Parameters:

pucData is the buffer to read data into from the UART port.

ulSize is the number of bytes provided in the *pucData* buffer that should be written with data from the UART port.

Description:

This function reads back *ulSize* bytes of data from the UART port, into the buffer that is pointed to by *pucData*. This function will not return until *ulSize* number of bytes have been received.

This function is contained in `bl_uart.c`.

Returns:

None.

26.2.2.22 UARTSend

Sends data over the UART port.

Prototype:

```
void
UARTSend(const unsigned char *pucData,
          unsigned long ulSize)
```

Parameters:

pucData is the buffer containing the data to write out to the UART port.

ulSize is the number of bytes provided in *pucData* buffer that will be written out to the UART port.

Description:

This function sends *ulSize* bytes of data from the buffer pointed to by *pucData* via the UART port.

This function is contained in `bl_uart.c`.

Returns:

None.

26.2.2.23 UpdateBOOTP

Starts the update process via BOOTP.

Prototype:

```
void
UpdateBOOTP(void)
```

Description:

This function starts the Ethernet firmware update process. The BOOTP (as defined by RFC951 at <http://tools.ietf.org/html/rfc951>) and TFTP (as defined by RFC1350 at <http://tools.ietf.org/html/rfc1350>) protocols are used to transfer the firmware image over Ethernet.

This function is contained in `bl_enet.c`.

Returns:

Never returns.

26.2.2.24 Updater

This function performs the update on the selected port.

Prototype:

```
void  
Updater(void)
```

Description:

This function is called directly by the boot loader or it is called as a result of an update request from the application.

This function is contained in `bl_main.c`.

Returns:

Never returns.

27 Tool Chain Specifics

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27.1 Introduction

There are two aspects to the library's interaction with the supported tool chains; how it is built by the compilers and how it interacts with the debuggers. By separating it in this way, it is possible to use one tool chain to build the code and use the debugger from another tool chain to debug the code. Alternatively, the mechanism for interaction with the debugger can be replaced with something that uses one of the UARTs, eliminating (for the most part) the need for a debugger (other than for debugging).

Each of these aspects are discussed individually.

27.2 Compilers

There are four things that need special treatment between the various tool chains:

- How the compiler is invoked
- Compiler specific constructs
- Assembler specific constructs
- How code is linked

This discussion only applies to building from the command line; building with a project file utilizes the normal mechanisms for the GUI in question.

27.2.1 Invoking The Compiler

The `makedefs` file contains a set of rules for compiling C source files, compiling assembly source files, creating object libraries, and linking applications. These rules utilize the traditional variables for invoking the tools, such as `CC`, `CFLAGS`, and so on. These variables are given default values based on the tool chain being used; it is recommended that the variables that contain executable names be left alone and those that contain flags (such as `CFLAGS`) only be augmented.

All the rules place the targets into a tool chain-specific directory. For example, building a C source file with RealView Microcontroller Development Kit places the object file in the `rvmdk` directory; the linked application and/or object library would also go into the same directory. By doing this, the objects from multiple tool chains can exist simultaneously in the source tree without becoming intermingled.

Automatically generated dependencies are utilized by the rules as well. Most modern compilers support a `-MD` or similar option that causes it to write out a dependency file when compiling. In this manner, the dependencies are automatically generated when the file is first compiled, and

are regenerated whenever the file is recompiled (which would result if any of the dependencies changed, which might result in new dependencies). The dependencies are therefore always up to date. Dependency files are placed into the tool chain directory like the object files, and have a `.d` file name extension.

The Makefile rules have a set of special variables that control the how the applications is built. These take into account the tools being used to build the application as well as the target applications name so that a Makefile can build more than one application and have the same makefile. The link rules also have a set of variables that allow the linker to be uniquely configured for each application. In all of them are the base name of the application; for example, if the target is `foobar.axf` then the special variables would be `..._foobar`. The variables are:

PART	This is the Stellaris microcontroller for which the application is being built.
ROOT	This specifies the relative location of the base directory of the Stellaris Peripheral Driver Library installation. This is used to inform the build process where the rest of the peripheral driver library build tools are located.
VPATH	This variable allows the build process a search path to find source files that do not exist in this directory.
IPATH	This variable allows the build process a search path to find header files that do not exist in this directory.
ENTRY_target	This is the entry point for the application. Typically this is <code>ResetISR</code> .
ROBASE_target	This is the address to use for the base address of the read only area of the application. If this is undefined, then the value defaults to <code>0x0000.0000</code> . If it is specified, this is the location of the first byte of the application. This is useful for moving the starting address of an application to an address other than the beginning of flash or to move the address to SRAM for applications that need to be linked to run from SRAM. This value is only used by the Keil tools as other tool chains support linker scripts that can provide this functionality. When this value is specified in the Makefile, <code>SCATTERtools_target</code> should not be specified as this results in conflicting linker commands and causes the build to fail.
LDFLAGStools_target	This contains tool chain specific linker flags that are also specific to the application. The <code>tools</code> portion is replaced with the tool chain to which the flags apply; so, for example, to supply additional linker flags to the RealView linker, use <code>LDFLAGSrvmdk_target</code> .
SCATTERtools_target	This is the name of the tool chain specific linker script used to link the application. Typically this is <code>../\${COMPILER}/standalone.ld</code> .
CFLAGStools	This specifies any tool chain specific compiler options that need to be specified to compile the project.

With these rules, makefiles become a simple list of the targets to be built (either applications, libraries, or both), the object files that comprise the target, and a set of target-specific variables in the case of applications.

For the peripheral driver library itself (contained in the `src` directory), some special flags are passed to the compiler to place each global symbol (be it a variable or a function) into its own separate section. This makes it possible to minimize the impact of using a driver; for example, using the UART in an output only mode with only the [UARTConfigSetExpClk\(\)](#) and [UARTCharPut\(\)](#) APIs being used, all the APIs for reading data, getting the configuration, and so on, do not get linked into the application (as they would if all of the globals were built into a single section).

27.2.2 Understanding Linker Scripts

This section covers the default linker scripts that are provided as part of the peripheral driver library release. This will cover the basics of the various settings in each of the linker scripts for all of the tool chains supported by peripheral driver library in order to help better understand how to use the linker scripts that are provided. It should be noted that the evaluation version of the Keil tools do not allow the use of linker scripts. Because of this none of the Keil builds use a linker script. Instead the build process generates the appropriate linker command line options to modify the address map of the application.

27.2.2.1 CodeSourcery GCC

The default linker script for this tool chain is located in the file `gcc/standalone.ld`. This file is broken down into two sections, the first section describes the memory available on the device and the second describes where to place the code and data for the application.

Note:

When using the CodeSourcery Sourcery G++ tool chain you also have the option of using CodeSourcery's method for installing interrupt handlers and specifying linker scripts. The "Getting Started" documentation provided with the CodeSourcery release describes how to use their tools to install interrupt handlers as well as how to use the linker scripts that are provided with their tools.

The rest of this section will cover the linker scripts provided by the peripheral driver library release.

```
MEMORY
{
    FLASH (rx) : ORIGIN = 0x00000000, LENGTH = 0x00010000
    SRAM (rwx) : ORIGIN = 0x20000000, LENGTH = 0x00002000
}

SECTIONS
{
    .text :
    {
        _text = .;
        KEEP(*(.isr_vector))
        *(.text*)
        *(.rodata*)
        _etext = .;
    }
```

```
} > FLASH
.data : AT (ADDR(.text) + SIZEOF(.text))
{
    _data = .;
    *(vtable)
    *(.data*)
    _edata = .;
} > SRAM
.bss :
{
    _bss = .;
    *(.bss*)
    *(COMMON)
    _ebss = .;
} > SRAM}
```

The `MEMORY` section describes the amount of flash and SRAM available to the project. Each line has an `ORIGIN` and a `LENGTH` value that set the amount of flash or SRAM available. In this case the flash is set to start at address 0x0000.0000 and have 64K bytes available. The SRAM is set to start at address 0x2000.0000 and have 8K bytes available.

The next part of the file, labeled `SECTION`, describes in detail where the code and data will be placed for the application. The default linker script has sections that are put in very specific places in order for the application to function correctly.

KEEP(*(.isr_vector)) - This statement places the read only interrupt vectors at the beginning of this section, which in this case is the beginning of flash due to the `FLASH` at the end of this section definition. This section should be at the beginning of flash in order for the application to boot correctly from the flash. The beginning of the default startup file for gcc, provided by the peripheral driver library, has the following code snippet to place the fixed interrupt handlers in the appropriate section.

```
__attribute__((section(".isr_vector")))
void (* const g_pfnVectors[]) (void) =
{
    ...
}
```

***(.text*)** - Since `.text` is the default label applied to all “C” code, this statement places this read only code into the section following the interrupt vectors.

***(.rodata*)** - This section holds any constant read only data or the values for any initialized variables in the code. This section will normally immediately follow the `.text` read only code. This is important as any initialized values must be copied from flash to SRAM by the startup code.

_text = .; _etext = .; - These labels are inserted to allow application code to determine the size and the location of the read only area. These are accessible as global the following global variables:

```
extern unsigned long _text;
extern unsigned long _etext;
```

***(vtable)** - If an application uses the [IntRegister\(\)](#) or [IntUnregister\(\)](#) APIs, this entry places the vector table at the beginning of SRAM so that it can be modified by the APIs. This `vtable` label is attached to the code, or in this case data, by the following sequence in the file `DriverLib/src/interrupt.c`:

```
static __attribute__((section("vtable")))
void (*g_pfnRAMVectors[NUM_INTERRUPTS]) (void);
```

***(.data*)** - This section places all of the initialized read/write data after the SRAM based vector table. The `AT (ADDR(.text) + SIZEOF(.text))` actually modifies the load address to be at the end of the code section. This is where the actual initialization values for the variables are located. The actual run time address of the variables is located in SRAM. This allows the start up code to copy the initial data values from flash into the proper place in SRAM before executing the main application.

_data = .; _edata = .; - These labels are inserted to allow application code to determine the size and location of the initialized read/write data area. These values are accessible via the following global variables:

```
extern unsigned long _data;
extern unsigned long _edata;
```

***(.bss*)** - This section contain all of the uninitialized data for the project. This usually includes the stack and other variables that are not set to any value by default.

_bss = .; _ebss = .; - These labels are inserted to allow application code to determine the size and location of the uninitialized read/write data area. These values are accessible via the following global variables:

```
extern unsigned long _bss;
extern unsigned long _ebss;
```

***(COMMON)** - Under some circumstances, gcc will place some global variables in this section. This requires that this section should be included to insure that these variables are correctly located in SRAM.

27.2.2.2 Keil RV-MDK

The default linker script file is located in the `rvmdk/standalone.sct`. This file cannot be used with the evaluation version of the tool chain. Like the previous file format, this file is broken down into each value in the following example:

```
LR_IROM 0x00000000 0x00010000
{
    ;
    ; Specify the Execution Address of the code and the size.
    ;
    ER_IROM 0x00000000 0x00010000
    {
        *.o (RESET, +First)
        * (+RO)
    }

    ;
    ; Specify the Execution Address of the data area.
    ;
    RW_IRAM 0x20000000 0x00002000
    {
        * (+RW)
        * (+ZI)
    }
}
```

***.o (RESET, +First)** - This use of `RESET` allows the fixed vectors to be located at the beginning of flash. The code example below is taken from the default `rvmdk/Startup.s` that is used by the example code provided with the peripheral driver library.

```
        AREA      RESET, CODE, READONLY
        THUMB
Vectors
        DCD      StackMem + Stack          ; Top of Stack
        DCD      Reset_Handler            ; Reset Handler
...

```

* **(+RO)** - This section places all of the code and read only data at the beginning of flash. This section will also hold any constant read only data or the initial values for any variables in the code that have an initial value and it will immediately follow the `RESET` code section. This section must be located in flash since any initialized values must be copied from flash to SRAM by the startup code.

* **(+RW)** - This section places all the initialized read/write data after the modifiable vector table. The Keil “C” start up code takes care of copying the constant initializers from flash to this location in SRAM.

* **(+ZI)** - This section contain all of the uninitialized data for the project. This usually includes the stack and other variables that are not set to any value by default.

27.2.2.3 IAR EW-ARM

This default linker script file is located in the file `ewarm/standalone.xcl`. Unlike the other tool chains this linker script is written so that it is passed as command line options to the linker and not in a more formal linker script format. However each section label that is used by the peripheral driver library and the example code is covered in this section.

```
//
// Set the CPU type to ARM.
//
-carm

//
// Define the size of flash and SRAM.
//
-DROMSTART=00000000
-DROMEND=0000FFFF
-DRAMSTART=20000000
-DRAMEND=20001FFF

//
// Define the sections to place into flash, and the order to place them.
//
-Z (CODE) INTVEC=ROMSTART-ROMEND
-Z (CODE) ICODE,DIFUNCT=ROMSTART-ROMEND
-Z (CODE) CODE=ROMSTART-ROMEND
-Z (CONST) CODE_ID=ROMSTART-ROMEND
-Z (CONST) INITTAB,DATA_ID,DATA_C=ROMSTART-ROMEND
-Z (CONST) CHECKSUM=ROMSTART-ROMEND

```

INTVEC - This section holds the vector table for the application and should be located at the beginning of FLASH. The code example below shows how the default start up file, provided by the peripheral driver library, marks the vector table as belonging to this section.

```
__root const uVectorEntry g_pfnVectors[] @ "INTVEC" =
{
    { .ulPtr = (unsigned long)pulStack + sizeof(pulStack) },
                                     // The initial stack pointer

```

CODE - This section holds the remainder of the application code that will be used, minus any code that is has been marked to be run directly from SRAM.

INITTAB,DATA_ID,DATA_C - These sections holds constant or global data that has been copied from flash.

CHECKSUM - This section is not used by the peripheral driver library or any of the provided examples.

The following is the default memory map of a peripheral driver library application, regardless of the tool chain being used.

0x0000.0000	Code
	Read Only Data
	Read/Write Data Initializers
	Unused
end of flash	

0x2000.0000	Read/Write Data
	Zero Init Data
	Unused
end of SRAM	

Occasionally there is a need to use compiler-specific constructs in C source files. When that need arises, two options are available:

- Provide separate versions of the source file for each tool chain. This has been done with the boot code; it is basically identical from tool chain to tool chain, the exception being the construct used to tag the vector table for placement at the beginning of flash and the names of the symbols created by the linker as it creates the “code”, “data”, and “bss” segments.
- Use `#ifdef/#endif` around the constructs specific to each tool chain.

When providing separate files, the pathname of the file should contain the value of `$(COMPILER)` somewhere in it; either as a directory name or as part of the file name. This way, a dependency in the Makefile can utilize the value of the `$(COMPILER)` to cause the correct version of the file to be used. In the examples provided, this can be seen in the boot code; separate versions are provided for each tool chain supported. The correct version of the boot code is found via the `$(COMPILER)` in the Makefile for the boot code file name.

When using `#ifdef/#endif`, the value of `$(COMPILER)` again comes into play. Each source file is built with a `-D$(COMPILER)` passed to the compiler, so the value of the `$(COMPILER)` variable can be used in a `#ifdef` to include compiler specific code. This is not the preferred method since it is very error prone; if it is used to include a small piece of code within a function (for example), it would be too easy to forget about that when porting to a different tool chain which would result in that small piece of code not appearing in the object produced by new tool chain. In the first method, the file simply would not exist and a build error would occur.

27.2.4 Assembler Constructs

The macros in `asmdefs.h` hide the differences in syntax and directives between the assemblers of different tool chains. By utilizing these macros, the assembly files are free of `#ifdef toolchain` constructs, making them easier to understand and maintain. The following macros are provided for use in writing assembler independent source files:

<code>__ALIGN__</code>	This is used to place the next item on a four-byte alignment boundary in memory.
<code>__BSS__</code>	This is used to indicate that the items that follow should be placed into the “bss” segment of the executable. These items have storage space reserved but will not have initializers supplied in the executable, instead depending upon the boot code to zero fill the storage.
<code>__DATA__</code>	This is used to indicate that the items that follow should be placed into the “data” segment of the executable. These items have storage space reserved in SRAM, the initializers placed in flash, and the initializers copied from SRAM to flash by the boot code.
<code>__END__</code>	This indicates that the end of the assembly source file has been reached.
<code>__EXPORT__</code>	This indicates that a label should be made available to object files outside the current source file.
<code>__IMPORT__</code>	This indicates that a label from another object file is to be referenced from this source file.
<code>__LABEL__</code>	This provides a symbolic name for the current location. A label can be used as a branch target or to load/store data. Note that labels are not accessible outside the current source file unless exported with <code>__EXPORT__</code> .

<code>__STR__</code>	This is used to declare a string of data (that is, a zero terminated sequence of bytes).
<code>__TEXT__</code>	This is used to indicate that the items that follow should be placed into the “text” segment of the executable. This must be used before all code so that it are located correctly.
<code>__THUMB_LABEL__</code>	This indicates that the next label (which must immediately follow) is a Thumb label. All labels must be marked as Thumb labels or they will not work properly as a branch target.
<code>__WORD__</code>	This is used to declare a word (32-bits) of data.

`asmdefs.h` must included before anything else in the assembly language source file since it includes some common setup pseudo-ops that are required to put the assembler into the correct mode; failure to do so may cause the assembler to behave incorrectly.

27.2.5 Linking Applications

When linking applications, each global entity needs to be placed into the appropriate portion of memory in order for the application to work correctly. Some things must be placed at specific locations (such as the default vector table, which must reside at `0x0000.0000`). Other things must be placed into the correct portion of memory (all code needs to be placed in flash and all read/write data in SRAM).

A linker script is used to perform this task. Linker scripts are not portable between tool chains, so separate versions are supplied for each tool chain; they are in the `<toolchain>/standalone.ld` files (`standalone.xcl` in the case of IAR Embedded Workbench). These linker scripts are fairly simple; they place all the code in flash (the “code” segment), all the read/writes in SRAM (the “data” and “bss” segments), the “data” segment initializers in flash at the end of the “code” segment, the read-only vector table at the beginning of flash, and the read/write vector table from the interrupt driver (if it is used) at the beginning of SRAM. The boot code in `<toolchain>/startup.c` depends upon this layout of the memory; if the memory layout is changed then both file may need changes (or replacement).

27.3 Debuggers

Debuggers typically have a method for code running on the target to interact with the debugger: to read/write host files, print messages on the debugger console, and so on. These mechanisms have been abstracted into a set of functions that can be called by an application without regard to the debugger that they are using. These functions are discussed in chapter 24; they are the `Diag...` functions.

The debugger interface code resides in a file called `utils/${DEBUGGER}.S` (or `.c` if implemented in C). The rules in the makefile specify a dependency on `${DEBUGGER}.o`; therefore, by changing the value of `${DEBUGGER}`, the debugger interface code is changed. This is what allows the compiler from one tool chain and the debugger from another to be used together (assuming of

course that they support the same executable file format); `$(COMPILER)` specifies the tools used to build the code and `$(DEBUGGER)` specifies the debugger interface to use.

Several interesting things can be done with this interface:

- A serial version could be created, where files are not supported but stdio is supported. All stdio operations would go to a UART.
- A serial memory version could be created. The application could then be developed using host files via the debugger (where the file contents are much easier to examine) and then switched to use a serial memory version when appropriate.
- A stub version could be created where each function is a NOP. This would eliminate all debugger interaction from the application.
- A debug version could be created, where it normally acts as a NOP but if turned on via a special flag would start outputting stdio to a defined place (such as an unused UART). This would allow tracing capabilities to be left in production code; it would normally do nothing (giving customers no clues as to what it is doing/how it is doing things) but could be enabled by field support personnel to help determine why failures are occurring.

28 DK-LM3S101 Example Applications

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28.1 Introduction

The DK-LM3S101 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the Peripheral Device Controller on the Stellaris Family Development Kit board. The PDC is used to access the character LCD, eight user LEDs, eight user DIP switches, and twenty-four GPIOs.

There is an IAR workspace file (`dk-lm3s101.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`dk-lm3s101.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/dk-lm3s101` subdirectory of the peripheral driver library source distribution.

28.2 API Functions

Functions

- unsigned char [PDCDIPRead](#) (void)
- unsigned char [PDCGPIODirRead](#) (unsigned char ucIdx)
- void [PDCGPIODirWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- unsigned char [PDCGPIORead](#) (unsigned char ucIdx)
- void [PDCGPIOWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- void [PDCInit](#) (void)
- void [PDCLCDBacklightOff](#) (void)
- void [PDCLCDBacklightOn](#) (void)
- void [PDCLCDClear](#) (void)
- void [PDCLCDCreateChar](#) (unsigned char ucChar, unsigned char *pucData)
- void [PDCLCDInit](#) (void)
- void [PDCLCDSetPos](#) (unsigned char ucX, unsigned char ucY)
- void [PDCLCDWrite](#) (const char *pcStr, unsigned long ulCount)
- unsigned char [PDCLEDRead](#) (void)
- void [PDCLEDWrite](#) (unsigned char ucLED)

- unsigned char **PDCRead** (unsigned char ucAddr)
- void **PDCWrite** (unsigned char ucAddr, unsigned char ucData)

28.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

28.2.2 Function Documentation

28.2.2.1 PDCDIPRead

Read the current value of the PDC DIP switches.

Prototype:

```
unsigned char  
PDCDIPRead(void)
```

Description:

This function will read the current value of the DIP switches attached to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The current state of the DIP switches.

28.2.2.2 PDCGPIODirRead

Reads a GPIO direction register.

Prototype:

```
unsigned char  
PDCGPIODirRead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO direction registers in the PDC. The direction bit is set for pins that are outputs and clear for pins that are inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the direction register.

28.2.2.3 PDCGPIODirWrite

Write a GPIO direction register.

Prototype:

```
void
PDCGPIODirWrite(unsigned char ucIdx,
                 unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO direction register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO direction register.

Description:

This function writes ones of the GPIO direction registers in the PDC. The direction bit should be set for pins that are to be outputs and clear for pins that are to be inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

28.2.2.4 PDCGPIORead

Reads a GPIO data register.

Prototype:

```
unsigned char
PDCGPIORead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO data registers in the PDC. The value returned for a pin is the value being driven out for outputs or the value being read for inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the data register.

28.2.2.5 PDCGPIOWrite

Write a GPIO data register.

Prototype:

```
void
PDCGPIOWrite(unsigned char ucIdx,
              unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO data register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO data register.

Description:

This function writes one of the GPIO direction registers in the PDC. The written to a pin is driven out for output pins and ignored for input pins.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

28.2.2.6 PDCInit

Initializes the connection to the PDC.

Prototype:

```
void  
PDCInit(void)
```

Description:

This function will enable clocking to the SSI and GPIO A modules, configure the GPIO pins to be used for an SSI interface, and it will configure the SSI as a 1 Mbps master device, operating in MOTO mode. It will also enable the SSI module, and will enable the chip select for the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

28.2.2.7 PDCLCDBacklightOff

Turn off the backlight.

Prototype:

```
void  
PDCLCDBacklightOff(void)
```

Description:

This function turns off the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

28.2.2.8 PDCLCDBacklightOn

Turns on the backlight.

Prototype:

```
void  
PDCLCDBacklightOn(void)
```

Description:

This function turns on the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

28.2.2.9 PDCLCDClear

Clear the screen.

Prototype:

```
void  
PDCLCDClear(void)
```

Description:

This function clears the contents of the LCD screen. The cursor will be returned to the upper left corner.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

28.2.2.10 PDCLCDCreateChar

Write a character pattern to the LCD.

Prototype:

```
void  
PDCLCDCreateChar(unsigned char ucChar,  
                 unsigned char *pucData)
```

Parameters:

ucChar is the character index to create. Valid values are zero through seven.

pucData is the data for the character pattern. It contains eight bytes, with the first byte being the top row of the pattern. In each byte, the LSB is the right pixel of the pattern.

Description:

This function will write a character pattern into the LCD for use as a character to be displayed. After writing the pattern, it can be used on the LCD by writing the corresponding character index to the display.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

28.2.2.11 PDCLCDInit

Initializes the LCD display.

Prototype:

```
void  
PDCLCDInit(void)
```

Description:

This function will set up the LCD display for writing. It will set the data bus to 8 bits, set the number of lines to 2, and the font size to 5x10. It will also turn the display off, clear the display, turn the display back on, and enable the backlight.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Note:

The PDC must be initialized via the [PDCInit\(\)](#) function before this function can be called. Also, it may be necessary to adjust the contrast potentiometer in order to discern any output on the LCD display.

Returns:

None.

28.2.2.12 PDCLCDSetPos

Set the position of the cursor.

Prototype:

```
void  
PDCLCDSetPos(unsigned char ucX,  
              unsigned char ucY)
```

Parameters:

ucX is the horizontal position. Valid values are zero through fifteen.

ucY is the vertical position.. Valid values are zero and one.

Description:

This function will move the cursor to the specified position. All characters written to the LCD are placed at the current cursor position, which is automatically advanced.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

28.2.2.13 PDCLCDWrite

Writes a string to the LCD display.

Prototype:

```
void
PDCLCDWrite(const char *pcStr,
            unsigned long ulCount)
```

Parameters:

pcStr pointer to the string to be displayed.

ulCount is the number of characters to be displayed.

Description:

This function will display a string on the LCD at the current cursor position. It is the caller's responsibility to position the cursor to the place where the string should be displayed (either explicitly via [PDCLCDSetPos\(\)](#) or implicitly from where the cursor was left after a previous call to [PDCLCDWrite\(\)](#)), and to properly account for the LCD boundary (line wrapping is not automatically performed). Null characters are not treated special and are written to the LCD, which interprets it as a special programmable character glyph (see [PDCLCDCreateChar\(\)](#)).

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

28.2.2.14 PDCLEDRead

Read the current status of the PDC LEDs.

Prototype:

```
unsigned char
PDCLEDRead(void)
```

Description:

This function will read the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The value currently displayed by the LEDs.

28.2.2.15 PDCLEDWrite

Write to the PDC LEDs.

Prototype:

```
void
PDCLEDWrite(unsigned char ucLED)
```

Parameters:

ucLED value to write to the LEDs.

Description:

This function set the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

28.2.2.16 PDCRead

Read a PDC register.

Prototype:

```
unsigned char  
PDCRead(unsigned char ucAddr)
```

Parameters:

ucAddr specifies the PDC register to read.

Description:

This function will perform the SSI transfers required to read a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

Returns the value read from the PDC.

28.2.2.17 PDCWrite

Write a PDC register.

Prototype:

```
void  
PDCWrite(unsigned char ucAddr,  
          unsigned char ucData)
```

Parameters:

ucAddr specifies the PDC register to write.

ucData specifies the data to write.

Description:

This function will perform the SSI transfers required to write a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

28.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo2 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Comparator (comparator)

This example application demonstrates the operation of the analog comparator(s). Comparator zero (which is present on all devices that have analog comparators) is configured to compare its negative input to an internally generated 1.65 V reference and toggle the state of the LED on port B0 based on comparator change interrupts. The LED will be turned on by the interrupt handler when a rising edge on the comparator output is detected, and will be turned off when a falling edge is detected.

In order for this example to work properly, the ULED0 (JP22) jumper must be installed on the board.

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the user push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO. Note that because of errata in Rev Bx and Rev C0 of Sandstorm-class Stellaris microcontrollers, JTAG and SWD will not function if PB7 is configured as a GPIO. This errata is fixed in Rev C2 of Sandstorm-class Stellaris microcontrollers.

GPIO (gpio_led)

This example application uses LEDs connected to GPIO pins to create a “roving eye” display. Port B0-B3 are driven in a sequential manner to give the illusion of an eye looking back and forth.

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), ULED2 (JP24), and ULED3 (JP25) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the LCD and is a starting point for more complicated applications.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the LCD; individual LEDs connected to port B0-B2 will be turned on upon interrupt handler entry and off before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), and ULED2 (JP24) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

DK-LM3S101 Quickstart Application (qs_dk-lm3s101)

This example uses the photocell on the development board to create a geiger counter for visible light. In bright light, the click rate (that is, the count) increases; in low light it decreases. The light reading is also displayed on the LCD, and a log of the readings is output on the UART at 115,200, 8-n-1. The push button can be used to turn off the clicking noise on and off; when off the LCD and UART still provide the light reading.

In the default jumper configuration of the development board, this example actually samples the potentiometer and the push button will not work. In order for this example to fully work, the following jumper wire connections must be made: JP3 pin 1 to JP5 pin 2 (requiring the removal of the jumper on JP5) and JP19 pin 2 to J6 pin 6.

SSI (ssi_atmel)

This example application uses the SSI master to communicate with the Atmel AT25F1024A EEPROM that is on the development board. The first 256 bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the SSI interrupt; since a 256-byte read at a 1 MHz SSI bus speed takes around 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own GPIO (port B0 and B1) on each interrupt; the attached LED will indicate the occurrence and rate of interrupts.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (the SER0 connector on the Stellaris Family Development Board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED connected to port B0 is inverted so that it is easy to see that it is being fed, which occurs once every second.

29 DK-LM3S102 Example Applications

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29.1 Introduction

The DK-LM3S102 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the Peripheral Device Controller on the Stellaris Family Development Kit board. The PDC is used to access the character LCD, eight user LEDs, eight user DIP switches, and twenty-four GPIOs.

There is an IAR workspace file (`dk-lm3s102.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`dk-lm3s102.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/dk-lm3s102` subdirectory of the peripheral driver library source distribution.

29.2 API Functions

Functions

- unsigned char [PDCDIPRead](#) (void)
- unsigned char [PDCGPIODirRead](#) (unsigned char ucIdx)
- void [PDCGPIODirWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- unsigned char [PDCGPIORead](#) (unsigned char ucIdx)
- void [PDCGPIOWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- void [PDCInit](#) (void)
- void [PDCLCDBacklightOff](#) (void)
- void [PDCLCDBacklightOn](#) (void)
- void [PDCLCDClear](#) (void)
- void [PDCLCDCreateChar](#) (unsigned char ucChar, unsigned char *pucData)
- void [PDCLCDInit](#) (void)
- void [PDCLCDSetPos](#) (unsigned char ucX, unsigned char ucY)
- void [PDCLCDWrite](#) (const char *pcStr, unsigned long ulCount)
- unsigned char [PDCLEDRead](#) (void)
- void [PDCLEDWrite](#) (unsigned char ucLED)

- unsigned char **PDCRead** (unsigned char ucAddr)
- void **PDCWrite** (unsigned char ucAddr, unsigned char ucData)

29.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

29.2.2 Function Documentation

29.2.2.1 PDCDIPRead

Read the current value of the PDC DIP switches.

Prototype:

```
unsigned char  
PDCDIPRead(void)
```

Description:

This function will read the current value of the DIP switches attached to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The current state of the DIP switches.

29.2.2.2 PDCGPIODirRead

Reads a GPIO direction register.

Prototype:

```
unsigned char  
PDCGPIODirRead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO direction registers in the PDC. The direction bit is set for pins that are outputs and clear for pins that are inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the direction register.

29.2.2.3 PDCGPIODirWrite

Write a GPIO direction register.

Prototype:

```
void  
PDCGPIODirWrite(unsigned char ucIdx,  
                 unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO direction register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO direction register.

Description:

This function writes ones of the GPIO direction registers in the PDC. The direction bit should be set for pins that are to be outputs and clear for pins that are to be inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

29.2.2.4 PDCGPIORead

Reads a GPIO data register.

Prototype:

```
unsigned char  
PDCGPIORead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO data registers in the PDC. The value returned for a pin is the value being driven out for outputs or the value being read for inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the data register.

29.2.2.5 PDCGPIOWrite

Write a GPIO data register.

Prototype:

```
void  
PDCGPIOWrite(unsigned char ucIdx,  
              unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO data register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO data register.

Description:

This function writes one of the GPIO direction registers in the PDC. The written to a pin is driven out for output pins and ignored for input pins.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

29.2.2.6 PDCInit

Initializes the connection to the PDC.

Prototype:

```
void  
PDCInit(void)
```

Description:

This function will enable clocking to the SSI and GPIO A modules, configure the GPIO pins to be used for an SSI interface, and it will configure the SSI as a 1 Mbps master device, operating in MOTO mode. It will also enable the SSI module, and will enable the chip select for the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

29.2.2.7 PDCLCDBacklightOff

Turn off the backlight.

Prototype:

```
void  
PDCLCDBacklightOff(void)
```

Description:

This function turns off the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

29.2.2.8 PDCLCDBacklightOn

Turns on the backlight.

Prototype:

```
void  
PDCLCDBacklightOn(void)
```

Description:

This function turns on the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

29.2.2.9 PDCLCDClear

Clear the screen.

Prototype:

```
void  
PDCLCDClear(void)
```

Description:

This function clears the contents of the LCD screen. The cursor will be returned to the upper left corner.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

29.2.2.10 PDCLCDCreateChar

Write a character pattern to the LCD.

Prototype:

```
void  
PDCLCDCreateChar(unsigned char ucChar,  
                 unsigned char *pucData)
```

Parameters:

ucChar is the character index to create. Valid values are zero through seven.

pucData is the data for the character pattern. It contains eight bytes, with the first byte being the top row of the pattern. In each byte, the LSB is the right pixel of the pattern.

Description:

This function will write a character pattern into the LCD for use as a character to be displayed. After writing the pattern, it can be used on the LCD by writing the corresponding character index to the display.

This function is contained in `pdclcd.c`, with `pdclcd.h` containing the API definition for use by applications.

Returns:

None.

29.2.2.11 PDCLCDInit

Initializes the LCD display.

Prototype:

```
void  
PDCLCDInit(void)
```

Description:

This function will set up the LCD display for writing. It will set the data bus to 8 bits, set the number of lines to 2, and the font size to 5x10. It will also turn the display off, clear the display, turn the display back on, and enable the backlight.

This function is contained in `pdclcd.c`, with `pdclcd.h` containing the API definition for use by applications.

Note:

The PDC must be initialized via the [PDCInit\(\)](#) function before this function can be called. Also, it may be necessary to adjust the contrast potentiometer in order to discern any output on the LCD display.

Returns:

None.

29.2.2.12 PDCLCDSetPos

Set the position of the cursor.

Prototype:

```
void  
PDCLCDSetPos(unsigned char ucX,  
              unsigned char ucY)
```

Parameters:

ucX is the horizontal position. Valid values are zero through fifteen.

ucY is the vertical position.. Valid values are zero and one.

Description:

This function will move the cursor to the specified position. All characters written to the LCD are placed at the current cursor position, which is automatically advanced.

This function is contained in `pdclcd.c`, with `pdclcd.h` containing the API definition for use by applications.

Returns:

None.

29.2.2.13 PDCLCDWrite

Writes a string to the LCD display.

Prototype:

```
void  
PDCLCDWrite(const char *pcStr,  
            unsigned long ulCount)
```

Parameters:

pcStr pointer to the string to be displayed.

ulCount is the number of characters to be displayed.

Description:

This function will display a string on the LCD at the current cursor position. It is the caller's responsibility to position the cursor to the place where the string should be displayed (either explicitly via [PDCLCDSetPos\(\)](#) or implicitly from where the cursor was left after a previous call to [PDCLCDWrite\(\)](#)), and to properly account for the LCD boundary (line wrapping is not automatically performed). Null characters are not treated special and are written to the LCD, which interprets it as a special programmable character glyph (see [PDCLCDCreateChar\(\)](#)).

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

29.2.2.14 PDCLEDRead

Read the current status of the PDC LEDs.

Prototype:

```
unsigned char  
PDCLEDRead(void)
```

Description:

This function will read the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The value currently displayed by the LEDs.

29.2.2.15 PDCLEDWrite

Write to the PDC LEDs.

Prototype:

```
void  
PDCLEDWrite(unsigned char ucLED)
```

Parameters:

ucLED value to write to the LEDs.

Description:

This function set the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

29.2.2.16 PDCRead

Read a PDC register.

Prototype:

```
unsigned char  
PDCRead(unsigned char ucAddr)
```

Parameters:

ucAddr specifies the PDC register to read.

Description:

This function will perform the SSI transfers required to read a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

Returns the value read from the PDC.

29.2.2.17 PDCWrite

Write a PDC register.

Prototype:

```
void  
PDCWrite(unsigned char ucAddr,  
          unsigned char ucData)
```

Parameters:

ucAddr specifies the PDC register to write.

ucData specifies the data to write.

Description:

This function will perform the SSI transfers required to write a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

29.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo2 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Comparator (comparator)

This example application demonstrates the operation of the analog comparator(s). Comparator zero (which is present on all devices that have analog comparators) is configured to compare its negative input to an internally generated 1.65 V reference and toggle the state of the LED on port B0 based on comparator change interrupts. The LED will be turned on by the interrupt handler when a rising edge on the comparator output is detected, and will be turned off when a falling edge is detected.

In order for this example to work properly, the ULED0 (JP22) jumper must be installed on the board.

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the user push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO. Note that because of errata in Rev Bx and Rev C0 of Sandstorm-class Stellaris microcontrollers, JTAG and SWD will not function if PB7 is configured as a GPIO. This errata is fixed in Rev C2 of Sandstorm-class Stellaris microcontrollers.

GPIO (gpio_led)

This example application uses LEDs connected to GPIO pins to create a “roving eye” display. Port B0-B3 are driven in a sequential manner to give the illusion of an eye looking back and forth.

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), ULED2 (JP24), and ULED3 (JP25) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the LCD and is a starting point for more complicated applications.

I2C (i2c_atmel)

This example application uses the I2C master to communicate with the Atmel AT24C08A EEPROM that is on the development board. The first sixteen bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the I2C interrupt; since a sixteen-byte read at a 100 kHz I2C bus speed takes almost 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

In order for this example to work properly, the I2C_SCL (JP14), I2C_SDA (JP13), and I2CM_A2 (JP11) jumpers must be installed on the board, and the I2CM_WP (JP12) jumper must be removed.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the LCD; individual LEDs connected to port B0-B2 will be turned on upon interrupt handler entry and off before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), and ULED2 (JP24) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

DK-LM3S102 Quickstart Application (qs_dk-lm3s102)

This example uses the photocell on the development board to create a geiger counter for visible light. In bright light, the click rate (that is, the count) increases; in low light it decreases. The light reading is also displayed on the LCD, and a log of the readings is output on the UART at 115,200, 8-n-1. The push button can be used to turn off the clicking noise on and off; when off the LCD and UART still provide the light reading.

In the default jumper configuration of the development board, this example actually samples the potentiometer and the push button will not work. In order for this example to fully work, the following jumper wire connections must be made: JP3 pin 1 to JP5 pin 2 (requiring the removal of the jumper on JP5) and JP19 pin 2 to J6 pin 6.

SSI (ssi_atmel)

This example application uses the SSI master to communicate with the Atmel AT25F1024A EEPROM that is on the development board. The first 256 bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the SSI interrupt; since a 256-byte read at a 1 MHz SSI bus speed takes around 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own GPIO (port B0 and B1) on each interrupt; the attached LED will indicate the occurrence and rate of interrupts.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (the SER0 connector on the Stellaris Family Development Board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED connected to port B0 is inverted so that it is easy to see that it is being fed, which occurs once every second.

30 DK-LM3S301 Example Applications

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30.1 Introduction

The DK-LM3S301 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the Peripheral Device Controller on the Stellaris Family Development Kit board. The PDC is used to access the character LCD, eight user LEDs, eight user DIP switches, and twenty-four GPIOs.

There is an IAR workspace file (`dk-lm3s301.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`dk-lm3s301.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/dk-lm3s301` subdirectory of the peripheral driver library source distribution.

30.2 API Functions

Functions

- unsigned char [PDCDIPRead](#) (void)
- unsigned char [PDCGPIODirRead](#) (unsigned char ucIdx)
- void [PDCGPIODirWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- unsigned char [PDCGPIORead](#) (unsigned char ucIdx)
- void [PDCGPIOWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- void [PDCInit](#) (void)
- void [PDCLCDBacklightOff](#) (void)
- void [PDCLCDBacklightOn](#) (void)
- void [PDCLCDClear](#) (void)
- void [PDCLCDCreateChar](#) (unsigned char ucChar, unsigned char *pucData)
- void [PDCLCDInit](#) (void)
- void [PDCLCDSetPos](#) (unsigned char ucX, unsigned char ucY)
- void [PDCLCDWrite](#) (const char *pcStr, unsigned long ulCount)
- unsigned char [PDCLEDRead](#) (void)
- void [PDCLEDWrite](#) (unsigned char ucLED)

- unsigned char **PDCRead** (unsigned char ucAddr)
- void **PDCWrite** (unsigned char ucAddr, unsigned char ucData)

30.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

30.2.2 Function Documentation

30.2.2.1 PDCDIPRead

Read the current value of the PDC DIP switches.

Prototype:

```
unsigned char  
PDCDIPRead(void)
```

Description:

This function will read the current value of the DIP switches attached to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The current state of the DIP switches.

30.2.2.2 PDCGPIODirRead

Reads a GPIO direction register.

Prototype:

```
unsigned char  
PDCGPIODirRead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO direction registers in the PDC. The direction bit is set for pins that are outputs and clear for pins that are inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the direction register.

30.2.2.3 PDCGPIODirWrite

Write a GPIO direction register.

Prototype:

```
void  
PDCGPIODirWrite(unsigned char ucIdx,  
                 unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO direction register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO direction register.

Description:

This function writes ones of the GPIO direction registers in the PDC. The direction bit should be set for pins that are to be outputs and clear for pins that are to be inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

30.2.2.4 PDCGPIORead

Reads a GPIO data register.

Prototype:

```
unsigned char  
PDCGPIORead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO data registers in the PDC. The value returned for a pin is the value being driven out for outputs or the value being read for inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the data register.

30.2.2.5 PDCGPIOWrite

Write a GPIO data register.

Prototype:

```
void  
PDCGPIOWrite(unsigned char ucIdx,  
              unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO data register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO data register.

Description:

This function writes one of the GPIO direction registers in the PDC. The written to a pin is driven out for output pins and ignored for input pins.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

30.2.2.6 PDCInit

Initializes the connection to the PDC.

Prototype:

```
void  
PDCInit(void)
```

Description:

This function will enable clocking to the SSI and GPIO A modules, configure the GPIO pins to be used for an SSI interface, and it will configure the SSI as a 1 Mbps master device, operating in MOTO mode. It will also enable the SSI module, and will enable the chip select for the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

30.2.2.7 PDCLCDBacklightOff

Turn off the backlight.

Prototype:

```
void  
PDCLCDBacklightOff(void)
```

Description:

This function turns off the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

30.2.2.8 PDCLCDBacklightOn

Turns on the backlight.

Prototype:

```
void  
PDCLCDBacklightOn(void)
```

Description:

This function turns on the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

30.2.2.9 PDCLCDClear

Clear the screen.

Prototype:

```
void  
PDCLCDClear(void)
```

Description:

This function clears the contents of the LCD screen. The cursor will be returned to the upper left corner.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

30.2.2.10 PDCLCDCreateChar

Write a character pattern to the LCD.

Prototype:

```
void  
PDCLCDCreateChar(unsigned char ucChar,  
                  unsigned char *pucData)
```

Parameters:

ucChar is the character index to create. Valid values are zero through seven.

pucData is the data for the character pattern. It contains eight bytes, with the first byte being the top row of the pattern. In each byte, the LSB is the right pixel of the pattern.

Description:

This function will write a character pattern into the LCD for use as a character to be displayed. After writing the pattern, it can be used on the LCD by writing the corresponding character index to the display.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

30.2.2.11 PDCLCDInit

Initializes the LCD display.

Prototype:

```
void  
PDCLCDInit(void)
```

Description:

This function will set up the LCD display for writing. It will set the data bus to 8 bits, set the number of lines to 2, and the font size to 5x10. It will also turn the display off, clear the display, turn the display back on, and enable the backlight.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Note:

The PDC must be initialized via the [PDCInit\(\)](#) function before this function can be called. Also, it may be necessary to adjust the contrast potentiometer in order to discern any output on the LCD display.

Returns:

None.

30.2.2.12 PDCLCDSetPos

Set the position of the cursor.

Prototype:

```
void  
PDCLCDSetPos(unsigned char ucX,  
              unsigned char ucY)
```

Parameters:

ucX is the horizontal position. Valid values are zero through fifteen.

ucY is the vertical position.. Valid values are zero and one.

Description:

This function will move the cursor to the specified position. All characters written to the LCD are placed at the current cursor position, which is automatically advanced.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

30.2.2.13 PDCLCDWrite

Writes a string to the LCD display.

Prototype:

```
void
PDCLCDWrite(const char *pcStr,
            unsigned long ulCount)
```

Parameters:

pcStr pointer to the string to be displayed.

ulCount is the number of characters to be displayed.

Description:

This function will display a string on the LCD at the current cursor position. It is the caller's responsibility to position the cursor to the place where the string should be displayed (either explicitly via [PDCLCDSetPos\(\)](#) or implicitly from where the cursor was left after a previous call to [PDCLCDWrite\(\)](#)), and to properly account for the LCD boundary (line wrapping is not automatically performed). Null characters are not treated special and are written to the LCD, which interprets it as a special programmable character glyph (see [PDCLCDCreateChar\(\)](#)).

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

30.2.2.14 PDCLEDRead

Read the current status of the PDC LEDs.

Prototype:

```
unsigned char
PDCLEDRead(void)
```

Description:

This function will read the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The value currently displayed by the LEDs.

30.2.2.15 PDCLEDWrite

Write to the PDC LEDs.

Prototype:

```
void
PDCLEDWrite(unsigned char ucLED)
```

Parameters:

ucLED value to write to the LEDs.

Description:

This function set the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

30.2.2.16 PDCRead

Read a PDC register.

Prototype:

```
unsigned char  
PDCRead(unsigned char ucAddr)
```

Parameters:

ucAddr specifies the PDC register to read.

Description:

This function will perform the SSI transfers required to read a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

Returns the value read from the PDC.

30.2.2.17 PDCWrite

Write a PDC register.

Prototype:

```
void  
PDCWrite(unsigned char ucAddr,  
          unsigned char ucData)
```

Parameters:

ucAddr specifies the PDC register to write.

ucData specifies the data to write.

Description:

This function will perform the SSI transfers required to write a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

30.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo2 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Comparator (comparator)

This example application demonstrates the operation of the analog comparator(s). Comparator zero (which is present on all devices that have analog comparators) is configured to compare its negative input to an internally generated 1.65 V reference and toggle the state of the LED on port B0 based on comparator change interrupts. The LED will be turned on by the interrupt handler when a rising edge on the comparator output is detected, and will be turned off when a falling edge is detected.

In order for this example to work properly, the ULED0 (JP22) jumper must be installed on the board.

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the user push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO. Note that because of errata in Rev Bx and Rev C0 of Sandstorm-class Stellaris microcontrollers, JTAG and SWD will not function if PB7 is configured as a GPIO. This errata is fixed in Rev C2 of Sandstorm-class Stellaris microcontrollers.

GPIO (gpio_led)

This example application uses LEDs connected to GPIO pins to create a “roving eye” display. Port B0-B3 are driven in a sequential manner to give the illusion of an eye looking back and forth.

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), ULED2 (JP24), and ULED3 (JP25) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the LCD and is a starting point for more complicated applications.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the LCD; individual LEDs connected to port B0-B2 will be turned on upon interrupt handler entry and off before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), and ULED2 (JP24) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 50 kHz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

DK-LM3S301 Quickstart Application (qs_dk-lm3s301)

This example uses the photocell on the development board to create a geiger counter for visible light. In bright light, the click rate (that is, the count) increases; in low light it decreases. The light reading is also displayed on the LCD, and a log of the readings is output on the UART at 115,200, 8-n-1. The push button can be used to turn off the clicking noise on and off; when off the LCD and UART still provide the light reading.

In the default jumper configuration of the development board, this example actually samples the potentiometer and the push button will not work. In order for this example to fully work, the following jumper wire connections must be made: JP3 pin 1 to JP5 pin 2 (requiring the removal of the jumper on JP5) and JP19 pin 2 to J6 pin 6.

SSI (ssi_atmel)

This example application uses the SSI master to communicate with the Atmel AT25F1024A EEPROM that is on the development board. The first 256 bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the SSI interrupt; since a 256-byte read at a 1 MHz SSI bus speed takes around 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own GPIO (port B0 and B1) on each interrupt; the attached LED will indicate the occurrence and rate of interrupts.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (the SER0 connector on the Stellaris Family Development Board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED connected to port B0 is inverted so that it is easy to see that it is being fed, which occurs once every second.

31 DK-LM3S801 Example Applications

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31.1 Introduction

The DK-LM3S801 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the Peripheral Device Controller on the Stellaris Family Development Kit board. The PDC is used to access the character LCD, eight user LEDs, eight user DIP switches, and twenty-four GPIOs.

There is an IAR workspace file (`dk-lm3s801.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`dk-lm3s801.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/dk-lm3s801` subdirectory of the peripheral driver library source distribution.

31.2 API Functions

Functions

- unsigned char [PDCDIPRead](#) (void)
- unsigned char [PDCGPIODirRead](#) (unsigned char ucIdx)
- void [PDCGPIODirWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- unsigned char [PDCGPIORead](#) (unsigned char ucIdx)
- void [PDCGPIOWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- void [PDCInit](#) (void)
- void [PDCLCDBacklightOff](#) (void)
- void [PDCLCDBacklightOn](#) (void)
- void [PDCLCDClear](#) (void)
- void [PDCLCDCreateChar](#) (unsigned char ucChar, unsigned char *pucData)
- void [PDCLCDInit](#) (void)
- void [PDCLCDSetPos](#) (unsigned char ucX, unsigned char ucY)
- void [PDCLCDWrite](#) (const char *pcStr, unsigned long ulCount)
- unsigned char [PDCLEDRead](#) (void)
- void [PDCLEDWrite](#) (unsigned char ucLED)

- unsigned char **PDCRead** (unsigned char ucAddr)
- void **PDCWrite** (unsigned char ucAddr, unsigned char ucData)

31.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

31.2.2 Function Documentation

31.2.2.1 PDCDIPRead

Read the current value of the PDC DIP switches.

Prototype:

```
unsigned char  
PDCDIPRead(void)
```

Description:

This function will read the current value of the DIP switches attached to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The current state of the DIP switches.

31.2.2.2 PDCGPIODirRead

Reads a GPIO direction register.

Prototype:

```
unsigned char  
PDCGPIODirRead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO direction registers in the PDC. The direction bit is set for pins that are outputs and clear for pins that are inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the direction register.

31.2.2.3 PDCGPIODirWrite

Write a GPIO direction register.

Prototype:

```
void
PDCGPIODirWrite(unsigned char ucIdx,
                 unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO direction register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO direction register.

Description:

This function writes ones of the GPIO direction registers in the PDC. The direction bit should be set for pins that are to be outputs and clear for pins that are to be inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

31.2.2.4 PDCGPIORead

Reads a GPIO data register.

Prototype:

```
unsigned char
PDCGPIORead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO data registers in the PDC. The value returned for a pin is the value being driven out for outputs or the value being read for inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the data register.

31.2.2.5 PDCGPIOWrite

Write a GPIO data register.

Prototype:

```
void
PDCGPIOWrite(unsigned char ucIdx,
              unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO data register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO data register.

Description:

This function writes one of the GPIO direction registers in the PDC. The written to a pin is driven out for output pins and ignored for input pins.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

31.2.2.6 PDCInit

Initializes the connection to the PDC.

Prototype:

```
void  
PDCInit(void)
```

Description:

This function will enable clocking to the SSI and GPIO A modules, configure the GPIO pins to be used for an SSI interface, and it will configure the SSI as a 1 Mbps master device, operating in MOTO mode. It will also enable the SSI module, and will enable the chip select for the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

31.2.2.7 PDCLCDBacklightOff

Turn off the backlight.

Prototype:

```
void  
PDCLCDBacklightOff(void)
```

Description:

This function turns off the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

31.2.2.8 PDCLCDBacklightOn

Turns on the backlight.

Prototype:

```
void  
PDCLCDBacklightOn(void)
```

Description:

This function turns on the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

31.2.2.9 PDCLCDClear

Clear the screen.

Prototype:

```
void  
PDCLCDClear(void)
```

Description:

This function clears the contents of the LCD screen. The cursor will be returned to the upper left corner.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

31.2.2.10 PDCLCDCreateChar

Write a character pattern to the LCD.

Prototype:

```
void  
PDCLCDCreateChar(unsigned char ucChar,  
                  unsigned char *pucData)
```

Parameters:

ucChar is the character index to create. Valid values are zero through seven.

pucData is the data for the character pattern. It contains eight bytes, with the first byte being the top row of the pattern. In each byte, the LSB is the right pixel of the pattern.

Description:

This function will write a character pattern into the LCD for use as a character to be displayed. After writing the pattern, it can be used on the LCD by writing the corresponding character index to the display.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

31.2.2.11 PDCLCDInit

Initializes the LCD display.

Prototype:

```
void  
PDCLCDInit(void)
```

Description:

This function will set up the LCD display for writing. It will set the data bus to 8 bits, set the number of lines to 2, and the font size to 5x10. It will also turn the display off, clear the display, turn the display back on, and enable the backlight.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Note:

The PDC must be initialized via the [PDCInit\(\)](#) function before this function can be called. Also, it may be necessary to adjust the contrast potentiometer in order to discern any output on the LCD display.

Returns:

None.

31.2.2.12 PDCLCDSetPos

Set the position of the cursor.

Prototype:

```
void  
PDCLCDSetPos(unsigned char ucX,  
              unsigned char ucY)
```

Parameters:

ucX is the horizontal position. Valid values are zero through fifteen.

ucY is the vertical position.. Valid values are zero and one.

Description:

This function will move the cursor to the specified position. All characters written to the LCD are placed at the current cursor position, which is automatically advanced.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

31.2.2.13 PDCLCDWrite

Writes a string to the LCD display.

Prototype:

```
void
PDCLCDWrite(const char *pcStr,
            unsigned long ulCount)
```

Parameters:

pcStr pointer to the string to be displayed.

ulCount is the number of characters to be displayed.

Description:

This function will display a string on the LCD at the current cursor position. It is the caller's responsibility to position the cursor to the place where the string should be displayed (either explicitly via [PDCLCDSetPos\(\)](#) or implicitly from where the cursor was left after a previous call to [PDCLCDWrite\(\)](#)), and to properly account for the LCD boundary (line wrapping is not automatically performed). Null characters are not treated special and are written to the LCD, which interprets it as a special programmable character glyph (see [PDCLCDCreateChar\(\)](#)).

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

31.2.2.14 PDCLEDRead

Read the current status of the PDC LEDs.

Prototype:

```
unsigned char
PDCLEDRead(void)
```

Description:

This function will read the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The value currently displayed by the LEDs.

31.2.2.15 PDCLEDWrite

Write to the PDC LEDs.

Prototype:

```
void
PDCLEDWrite(unsigned char ucLED)
```

Parameters:

ucLED value to write to the LEDs.

Description:

This function set the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

31.2.2.16 PDCRead

Read a PDC register.

Prototype:

```
unsigned char
PDCRead(unsigned char ucAddr)
```

Parameters:

ucAddr specifies the PDC register to read.

Description:

This function will perform the SSI transfers required to read a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

Returns the value read from the PDC.

31.2.2.17 PDCWrite

Write a PDC register.

Prototype:

```
void
PDCWrite(unsigned char ucAddr,
         unsigned char ucData)
```

Parameters:

ucAddr specifies the PDC register to write.

ucData specifies the data to write.

Description:

This function will perform the SSI transfers required to write a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

31.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo2 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Comparator (comparator)

This example application demonstrates the operation of the analog comparator(s). Comparator zero (which is present on all devices that have analog comparators) is configured to compare its negative input to an internally generated 1.65 V reference and toggle the state of the LED on port B0 based on comparator change interrupts. The LED will be turned on by the interrupt handler when a rising edge on the comparator output is detected, and will be turned off when a falling edge is detected.

In order for this example to work properly, the ULED0 (JP22) jumper must be installed on the board.

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the user push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO. Note that because of errata in Rev Bx and Rev C0 of Sandstorm-class Stellaris microcontrollers, JTAG and SWD will not function if PB7 is configured as a GPIO. This errata is fixed in Rev C2 of Sandstorm-class Stellaris microcontrollers.

GPIO (gpio_led)

This example application uses LEDs connected to GPIO pins to create a “roving eye” display. Port B0-B3 are driven in a sequential manner to give the illusion of an eye looking back and forth.

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), ULED2 (JP24), and ULED3 (JP25) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the LCD and is a starting point for more complicated applications.

I2C (i2c_atmel)

This example application uses the I2C master to communicate with the Atmel AT24C08A EEPROM that is on the development board. The first sixteen bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the I2C interrupt; since a sixteen-byte read at a 100 kHz I2C bus speed takes almost 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

In order for this example to work properly, the I2C_SCL (JP14), I2C_SDA (JP13), and I2CM_A2 (JP11) jumpers must be installed on the board, and the I2CM_WP (JP12) jumper must be removed.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the LCD; individual LEDs connected to port B0-B2 will be turned on upon interrupt handler entry and off before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), and ULED2 (JP24) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 50 kHz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

DK-LM3S801 Quickstart Application (qs_dk-lm3s801)

This example uses the potentiometer on the development board to vary the rate and frequency of a repetitive beep from the piezo buzzer. Turning the knob in one direction will result in slower beeps at lower frequency, while turning it the other direction will result in faster beeps at a higher frequency. The potentiometer setting along with the tone “note” is displayed on the LCD, and a log of the readings is output on the UART at 115,200, 8-n-1. The push button can be used to turn the beeping noise on and off; when off the LCD and UART still show the setting.

SSI (ssi_atmel)

This example application uses the SSI master to communicate with the Atmel AT25F1024A EEPROM that is on the development board. The first 256 bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the SSI interrupt; since a 256-byte

read at a 1 MHz SSI bus speed takes around 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own GPIO (port B0 and B1) on each interrupt; the attached LED will indicate the occurrence and rate of interrupts.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (the SER0 connector on the Stellaris Family Development Board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED connected to port B0 is inverted so that it is easy to see that it is being fed, which occurs once every second.

32 DK-LM3S811 Example Applications

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32.1 Introduction

The DK-LM3S811 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the Peripheral Device Controller on the Stellaris Family Development Kit board. The PDC is used to access the character LCD, eight user LEDs, eight user DIP switches, and twenty-four GPIOs.

There is an IAR workspace file (`dk-lm3s811.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`dk-lm3s811.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/dk-lm3s811` subdirectory of the peripheral driver library source distribution.

32.2 API Functions

Functions

- unsigned char [PDCDIPRead](#) (void)
- unsigned char [PDCGPIODirRead](#) (unsigned char ucIdx)
- void [PDCGPIODirWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- unsigned char [PDCGPIORead](#) (unsigned char ucIdx)
- void [PDCGPIOWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- void [PDCInit](#) (void)
- void [PDCLCDBacklightOff](#) (void)
- void [PDCLCDBacklightOn](#) (void)
- void [PDCLCDClear](#) (void)
- void [PDCLCDCreateChar](#) (unsigned char ucChar, unsigned char *pucData)
- void [PDCLCDInit](#) (void)
- void [PDCLCDSetPos](#) (unsigned char ucX, unsigned char ucY)
- void [PDCLCDWrite](#) (const char *pcStr, unsigned long ulCount)
- unsigned char [PDCLEDRead](#) (void)
- void [PDCLEDWrite](#) (unsigned char ucLED)

- unsigned char **PDCRead** (unsigned char ucAddr)
- void **PDCWrite** (unsigned char ucAddr, unsigned char ucData)

32.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

32.2.2 Function Documentation

32.2.2.1 PDCDIPRead

Read the current value of the PDC DIP switches.

Prototype:

```
unsigned char  
PDCDIPRead(void)
```

Description:

This function will read the current value of the DIP switches attached to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The current state of the DIP switches.

32.2.2.2 PDCGPIODirRead

Reads a GPIO direction register.

Prototype:

```
unsigned char  
PDCGPIODirRead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO direction registers in the PDC. The direction bit is set for pins that are outputs and clear for pins that are inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the direction register.

32.2.2.3 PDCGPIODirWrite

Write a GPIO direction register.

Prototype:

```
void  
PDCGPIODirWrite(unsigned char ucIdx,  
                 unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO direction register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO direction register.

Description:

This function writes ones of the GPIO direction registers in the PDC. The direction bit should be set for pins that are to be outputs and clear for pins that are to be inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

32.2.2.4 PDCGPIORead

Reads a GPIO data register.

Prototype:

```
unsigned char  
PDCGPIORead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO data registers in the PDC. The value returned for a pin is the value being driven out for outputs or the value being read for inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the data register.

32.2.2.5 PDCGPIOWrite

Write a GPIO data register.

Prototype:

```
void  
PDCGPIOWrite(unsigned char ucIdx,  
              unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO data register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO data register.

Description:

This function writes one of the GPIO direction registers in the PDC. The written to a pin is driven out for output pins and ignored for input pins.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

32.2.2.6 PDCInit

Initializes the connection to the PDC.

Prototype:

```
void  
PDCInit(void)
```

Description:

This function will enable clocking to the SSI and GPIO A modules, configure the GPIO pins to be used for an SSI interface, and it will configure the SSI as a 1 Mbps master device, operating in MOTO mode. It will also enable the SSI module, and will enable the chip select for the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

32.2.2.7 PDCLCDBacklightOff

Turn off the backlight.

Prototype:

```
void  
PDCLCDBacklightOff(void)
```

Description:

This function turns off the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

32.2.2.8 PDCLCDBacklightOn

Turns on the backlight.

Prototype:

```
void  
PDCLCDBacklightOn(void)
```

Description:

This function turns on the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

32.2.2.9 PDCLCDClear

Clear the screen.

Prototype:

```
void  
PDCLCDClear(void)
```

Description:

This function clears the contents of the LCD screen. The cursor will be returned to the upper left corner.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

32.2.2.10 PDCLCDCreateChar

Write a character pattern to the LCD.

Prototype:

```
void  
PDCLCDCreateChar(unsigned char ucChar,  
                  unsigned char *pucData)
```

Parameters:

ucChar is the character index to create. Valid values are zero through seven.

pucData is the data for the character pattern. It contains eight bytes, with the first byte being the top row of the pattern. In each byte, the LSB is the right pixel of the pattern.

Description:

This function will write a character pattern into the LCD for use as a character to be displayed. After writing the pattern, it can be used on the LCD by writing the corresponding character index to the display.

This function is contained in `pdclcd.c`, with `pdclcd.h` containing the API definition for use by applications.

Returns:

None.

32.2.2.11 PDCLCDInit

Initializes the LCD display.

Prototype:

```
void  
PDCLCDInit(void)
```

Description:

This function will set up the LCD display for writing. It will set the data bus to 8 bits, set the number of lines to 2, and the font size to 5x10. It will also turn the display off, clear the display, turn the display back on, and enable the backlight.

This function is contained in `pdclcd.c`, with `pdclcd.h` containing the API definition for use by applications.

Note:

The PDC must be initialized via the [PDCInit\(\)](#) function before this function can be called. Also, it may be necessary to adjust the contrast potentiometer in order to discern any output on the LCD display.

Returns:

None.

32.2.2.12 PDCLCDSetPos

Set the position of the cursor.

Prototype:

```
void  
PDCLCDSetPos(unsigned char ucX,  
              unsigned char ucY)
```

Parameters:

ucX is the horizontal position. Valid values are zero through fifteen.

ucY is the vertical position.. Valid values are zero and one.

Description:

This function will move the cursor to the specified position. All characters written to the LCD are placed at the current cursor position, which is automatically advanced.

This function is contained in `pdclcd.c`, with `pdclcd.h` containing the API definition for use by applications.

Returns:

None.

32.2.2.13 PDCLCDWrite

Writes a string to the LCD display.

Prototype:

```
void
PDCLCDWrite(const char *pcStr,
            unsigned long ulCount)
```

Parameters:

pcStr pointer to the string to be displayed.

ulCount is the number of characters to be displayed.

Description:

This function will display a string on the LCD at the current cursor position. It is the caller's responsibility to position the cursor to the place where the string should be displayed (either explicitly via [PDCLCDSetPos\(\)](#) or implicitly from where the cursor was left after a previous call to [PDCLCDWrite\(\)](#)), and to properly account for the LCD boundary (line wrapping is not automatically performed). Null characters are not treated special and are written to the LCD, which interprets it as a special programmable character glyph (see [PDCLCDCreateChar\(\)](#)).

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

32.2.2.14 PDCLEDRead

Read the current status of the PDC LEDs.

Prototype:

```
unsigned char
PDCLEDRead(void)
```

Description:

This function will read the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The value currently displayed by the LEDs.

32.2.2.15 PDCLEDWrite

Write to the PDC LEDs.

Prototype:

```
void
PDCLEDWrite(unsigned char ucLED)
```

Parameters:

ucLED value to write to the LEDs.

Description:

This function set the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

32.2.2.16 PDCRead

Read a PDC register.

Prototype:

```
unsigned char  
PDCRead(unsigned char ucAddr)
```

Parameters:

ucAddr specifies the PDC register to read.

Description:

This function will perform the SSI transfers required to read a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

Returns the value read from the PDC.

32.2.2.17 PDCWrite

Write a PDC register.

Prototype:

```
void  
PDCWrite(unsigned char ucAddr,  
          unsigned char ucData)
```

Parameters:

ucAddr specifies the PDC register to write.

ucData specifies the data to write.

Description:

This function will perform the SSI transfers required to write a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

32.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo2 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Comparator (comparator)

This example application demonstrates the operation of the analog comparator(s). Comparator zero (which is present on all devices that have analog comparators) is configured to compare its negative input to an internally generated 1.65 V reference and toggle the state of the LED on port B0 based on comparator change interrupts. The LED will be turned on by the interrupt handler when a rising edge on the comparator output is detected, and will be turned off when a falling edge is detected.

In order for this example to work properly, the ULED0 (JP22) jumper must be installed on the board.

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the user push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO. Note that because of errata in Rev Bx and Rev C0 of Sandstorm-class Stellaris microcontrollers, JTAG and SWD will not function if PB7 is configured as a GPIO. This errata is fixed in Rev C2 of Sandstorm-class Stellaris microcontrollers.

GPIO (gpio_led)

This example application uses LEDs connected to GPIO pins to create a “roving eye” display. Port B0-B3 are driven in a sequential manner to give the illusion of an eye looking back and forth.

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), ULED2 (JP24), and ULED3 (JP25) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the LCD and is a starting point for more complicated applications.

I2C (i2c_atmel)

This example application uses the I2C master to communicate with the Atmel AT24C08A EEPROM that is on the development board. The first sixteen bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the I2C interrupt; since a sixteen-byte read at a 100 kHz I2C bus speed takes almost 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

In order for this example to work properly, the I2C_SCL (JP14), I2C_SDA (JP13), and I2CM_A2 (JP11) jumpers must be installed on the board, and the I2CM_WP (JP12) jumper must be removed.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the LCD; individual LEDs connected to port B0-B2 will be turned on upon interrupt handler entry and off before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), and ULED2 (JP24) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 50 kHz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

DK-LM3S811 Quickstart Application (qs_dk-lm3s811)

This example uses the potentiometer on the development board to vary the rate of a repetitive beep from the piezo buzzer, while the light sensor will vary the frequency of the beep. Turning the knob in one direction will result in slower beeps while turning it in the other direction will result in faster beeps. The amount of light falling on the light sensor affects the frequency of the beep. The more light falling on the sensor the higher the pitch of the beep. The potentiometer setting along with the “note” representing the pitch of the beep is displayed on the LCD, and a log of the readings is output on the UART at 115,200, 8-n-1. The push button can be used to turn the beeping noise on and off; when off the LCD and UART still provide the settings.

In the default jumper configuration of the development board, the push button will not actually mute the beep. In order for this example to fully work, the following jumper wire connections must be made: JP19 pin 2 to J6 pin 6.

SSI (ssi_atmel)

This example application uses the SSI master to communicate with the Atmel AT25F1024A EEPROM that is on the development board. The first 256 bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the SSI interrupt; since a 256-byte read at a 1 MHz SSI bus speed takes around 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own GPIO (port B0 and B1) on each interrupt; the attached LED will indicate the occurrence and rate of interrupts.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (the SER0 connector on the Stellaris Family Development Board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED connected to port B0 is inverted so that it is easy to see that it is being fed, which occurs once every second.

33 DK-LM3S815 Example Applications

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33.1 Introduction

The DK-LM3S815 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the Peripheral Device Controller on the Stellaris Family Development Kit board. The PDC is used to access the character LCD, eight user LEDs, eight user DIP switches, and twenty-four GPIOs.

There is an IAR workspace file (`dk-lm3s815.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`dk-lm3s815.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/dk-lm3s815` subdirectory of the peripheral driver library source distribution.

33.2 API Functions

Functions

- unsigned char [PDCDIPRead](#) (void)
- unsigned char [PDCGPIODirRead](#) (unsigned char ucIdx)
- void [PDCGPIODirWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- unsigned char [PDCGPIORead](#) (unsigned char ucIdx)
- void [PDCGPIOWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- void [PDCInit](#) (void)
- void [PDCLCDBacklightOff](#) (void)
- void [PDCLCDBacklightOn](#) (void)
- void [PDCLCDClear](#) (void)
- void [PDCLCDCreateChar](#) (unsigned char ucChar, unsigned char *pucData)
- void [PDCLCDInit](#) (void)
- void [PDCLCDSetPos](#) (unsigned char ucX, unsigned char ucY)
- void [PDCLCDWrite](#) (const char *pcStr, unsigned long ulCount)
- unsigned char [PDCLEDRead](#) (void)
- void [PDCLEDWrite](#) (unsigned char ucLED)

- unsigned char **PDCRead** (unsigned char ucAddr)
- void **PDCWrite** (unsigned char ucAddr, unsigned char ucData)

33.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

33.2.2 Function Documentation

33.2.2.1 PDCDIPRead

Read the current value of the PDC DIP switches.

Prototype:

```
unsigned char  
PDCDIPRead(void)
```

Description:

This function will read the current value of the DIP switches attached to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The current state of the DIP switches.

33.2.2.2 PDCGPIODirRead

Reads a GPIO direction register.

Prototype:

```
unsigned char  
PDCGPIODirRead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO direction registers in the PDC. The direction bit is set for pins that are outputs and clear for pins that are inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the direction register.

33.2.2.3 PDCGPIODirWrite

Write a GPIO direction register.

Prototype:

```
void  
PDCGPIODirWrite(unsigned char ucIdx,  
                 unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO direction register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO direction register.

Description:

This function writes ones of the GPIO direction registers in the PDC. The direction bit should be set for pins that are to be outputs and clear for pins that are to be inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

33.2.2.4 PDCGPIORead

Reads a GPIO data register.

Prototype:

```
unsigned char  
PDCGPIORead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO data registers in the PDC. The value returned for a pin is the value being driven out for outputs or the value being read for inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the data register.

33.2.2.5 PDCGPIOWrite

Write a GPIO data register.

Prototype:

```
void  
PDCGPIOWrite(unsigned char ucIdx,  
              unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO data register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO data register.

Description:

This function writes one of the GPIO direction registers in the PDC. The written to a pin is driven out for output pins and ignored for input pins.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

33.2.2.6 PDCInit

Initializes the connection to the PDC.

Prototype:

```
void  
PDCInit(void)
```

Description:

This function will enable clocking to the SSI and GPIO A modules, configure the GPIO pins to be used for an SSI interface, and it will configure the SSI as a 1 Mbps master device, operating in MOTO mode. It will also enable the SSI module, and will enable the chip select for the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

33.2.2.7 PDCLCDBacklightOff

Turn off the backlight.

Prototype:

```
void  
PDCLCDBacklightOff(void)
```

Description:

This function turns off the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

33.2.2.8 PDCLCDBacklightOn

Turns on the backlight.

Prototype:

```
void  
PDCLCDBacklightOn(void)
```

Description:

This function turns on the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

33.2.2.9 PDCLCDClear

Clear the screen.

Prototype:

```
void  
PDCLCDClear(void)
```

Description:

This function clears the contents of the LCD screen. The cursor will be returned to the upper left corner.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

33.2.2.10 PDCLCDCreateChar

Write a character pattern to the LCD.

Prototype:

```
void  
PDCLCDCreateChar(unsigned char ucChar,  
                 unsigned char *pucData)
```

Parameters:

ucChar is the character index to create. Valid values are zero through seven.

pucData is the data for the character pattern. It contains eight bytes, with the first byte being the top row of the pattern. In each byte, the LSB is the right pixel of the pattern.

Description:

This function will write a character pattern into the LCD for use as a character to be displayed. After writing the pattern, it can be used on the LCD by writing the corresponding character index to the display.

This function is contained in `pdclcd.c`, with `pdclcd.h` containing the API definition for use by applications.

Returns:

None.

33.2.2.11 PDCLCDInit

Initializes the LCD display.

Prototype:

```
void  
PDCLCDInit(void)
```

Description:

This function will set up the LCD display for writing. It will set the data bus to 8 bits, set the number of lines to 2, and the font size to 5x10. It will also turn the display off, clear the display, turn the display back on, and enable the backlight.

This function is contained in `pdclcd.c`, with `pdclcd.h` containing the API definition for use by applications.

Note:

The PDC must be initialized via the [PDCInit\(\)](#) function before this function can be called. Also, it may be necessary to adjust the contrast potentiometer in order to discern any output on the LCD display.

Returns:

None.

33.2.2.12 PDCLCDSetPos

Set the position of the cursor.

Prototype:

```
void  
PDCLCDSetPos(unsigned char ucX,  
              unsigned char ucY)
```

Parameters:

ucX is the horizontal position. Valid values are zero through fifteen.

ucY is the vertical position.. Valid values are zero and one.

Description:

This function will move the cursor to the specified position. All characters written to the LCD are placed at the current cursor position, which is automatically advanced.

This function is contained in `pdclcd.c`, with `pdclcd.h` containing the API definition for use by applications.

Returns:

None.

33.2.2.13 PDCLCDWrite

Writes a string to the LCD display.

Prototype:

```
void
PDCLCDWrite(const char *pcStr,
            unsigned long ulCount)
```

Parameters:

pcStr pointer to the string to be displayed.

ulCount is the number of characters to be displayed.

Description:

This function will display a string on the LCD at the current cursor position. It is the caller's responsibility to position the cursor to the place where the string should be displayed (either explicitly via [PDCLCDSetPos\(\)](#) or implicitly from where the cursor was left after a previous call to [PDCLCDWrite\(\)](#)), and to properly account for the LCD boundary (line wrapping is not automatically performed). Null characters are not treated special and are written to the LCD, which interprets it as a special programmable character glyph (see [PDCLCDCreateChar\(\)](#)).

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

33.2.2.14 PDCLEDRead

Read the current status of the PDC LEDs.

Prototype:

```
unsigned char
PDCLEDRead(void)
```

Description:

This function will read the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The value currently displayed by the LEDs.

33.2.2.15 PDCLEDWrite

Write to the PDC LEDs.

Prototype:

```
void
PDCLEDWrite(unsigned char ucLED)
```

Parameters:

ucLED value to write to the LEDs.

Description:

This function set the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

33.2.2.16 PDCRead

Read a PDC register.

Prototype:

```
unsigned char  
PDCRead(unsigned char ucAddr)
```

Parameters:

ucAddr specifies the PDC register to read.

Description:

This function will perform the SSI transfers required to read a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

Returns the value read from the PDC.

33.2.2.17 PDCWrite

Write a PDC register.

Prototype:

```
void  
PDCWrite(unsigned char ucAddr,  
          unsigned char ucData)
```

Parameters:

ucAddr specifies the PDC register to write.

ucData specifies the data to write.

Description:

This function will perform the SSI transfers required to write a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

33.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo2 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Comparator (comparator)

This example application demonstrates the operation of the analog comparator(s). Comparator zero (which is present on all devices that have analog comparators) is configured to compare its negative input to an internally generated 1.65 V reference and toggle the state of the LED on port B0 based on comparator change interrupts. The LED will be turned on by the interrupt handler when a rising edge on the comparator output is detected, and will be turned off when a falling edge is detected.

In order for this example to work properly, the ULED0 (JP22) jumper must be installed on the board.

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This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the user push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO. Note that because of errata in Rev Bx and Rev C0 of Sandstorm-class Stellaris microcontrollers, JTAG and SWD will not function if PB7 is configured as a GPIO. This errata is fixed in Rev C2 of Sandstorm-class Stellaris microcontrollers.

GPIO (gpio_led)

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In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), ULED2 (JP24), and ULED3 (JP25) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the LCD and is a starting point for more complicated applications.

I2C (i2c_atmel)

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In order for this example to work properly, the I2C_SCL (JP14), I2C_SDA (JP13), and I2CM_A2 (JP11) jumpers must be installed on the board, and the I2CM_WP (JP12) jumper must be removed.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the LCD; individual LEDs connected to port B0-B2 will be turned on upon interrupt handler entry and off before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), and ULED2 (JP24) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 50 kHz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

DK-LM3S815 Quickstart Application (qs_dk-lm3s815)

This example uses the potentiometer on the development board to vary the rate of a repetitive beep from the piezo buzzer, while the light sensor will vary the frequency of the beep. Turning the knob in one direction will result in slower beeps while turning it in the other direction will result in faster beeps. The amount of light falling on the light sensor affects the frequency of the beep. The more light falling on the sensor the higher the pitch of the beep. The potentiometer setting along with the “note” representing the pitch of the beep is displayed on the LCD, and a log of the readings is output on the UART at 115,200, 8-n-1. The push button can be used to turn the beeping noise on and off; when off the LCD and UART still provide the settings.

In the default jumper configuration of the development board, the push button will not actually mute the beep. In order for this example to fully work, the following jumper wire connections must be made: JP19 pin 2 to J6 pin 6.

SSI (ssi_atmel)

This example application uses the SSI master to communicate with the Atmel AT25F1024A EEPROM that is on the development board. The first 256 bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the SSI interrupt; since a 256-byte read at a 1 MHz SSI bus speed takes around 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own GPIO (port B0 and B1) on each interrupt; the attached LED will indicate the occurrence and rate of interrupts.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (the SER0 connector on the Stellaris Family Development Board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED connected to port B0 is inverted so that it is easy to see that it is being fed, which occurs once every second.

34 DK-LM3S817 Example Applications

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34.1 Introduction

The DK-LM3S817 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the Peripheral Device Controller on the Stellaris Family Development Kit board. The PDC is used to access the character LCD, eight user LEDs, eight user DIP switches, and twenty-four GPIOs.

There is an IAR workspace file (`dk-lm3s817.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`dk-lm3s817.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/dk-lm3s817` subdirectory of the peripheral driver library source distribution.

34.2 API Functions

Functions

- unsigned char [PDCDIPRead](#) (void)
- unsigned char [PDCGPIODirRead](#) (unsigned char ucIdx)
- void [PDCGPIODirWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- unsigned char [PDCGPIORead](#) (unsigned char ucIdx)
- void [PDCGPIOWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- void [PDCInit](#) (void)
- void [PDCLCDBacklightOff](#) (void)
- void [PDCLCDBacklightOn](#) (void)
- void [PDCLCDClear](#) (void)
- void [PDCLCDCreateChar](#) (unsigned char ucChar, unsigned char *pucData)
- void [PDCLCDInit](#) (void)
- void [PDCLCDSetPos](#) (unsigned char ucX, unsigned char ucY)
- void [PDCLCDWrite](#) (const char *pcStr, unsigned long ulCount)
- unsigned char [PDCLEDRead](#) (void)
- void [PDCLEDWrite](#) (unsigned char ucLED)

- unsigned char **PDCRead** (unsigned char ucAddr)
- void **PDCWrite** (unsigned char ucAddr, unsigned char ucData)

34.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

34.2.2 Function Documentation

34.2.2.1 PDCDIPRead

Read the current value of the PDC DIP switches.

Prototype:

```
unsigned char  
PDCDIPRead(void)
```

Description:

This function will read the current value of the DIP switches attached to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The current state of the DIP switches.

34.2.2.2 PDCGPIODirRead

Reads a GPIO direction register.

Prototype:

```
unsigned char  
PDCGPIODirRead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO direction registers in the PDC. The direction bit is set for pins that are outputs and clear for pins that are inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the direction register.

34.2.2.3 PDCGPIODirWrite

Write a GPIO direction register.

Prototype:

```
void  
PDCGPIODirWrite(unsigned char ucIdx,  
                 unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO direction register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO direction register.

Description:

This function writes ones of the GPIO direction registers in the PDC. The direction bit should be set for pins that are to be outputs and clear for pins that are to be inputs.

This function is contained in `pdcc.c`, with `pdcc.h` containing the API definition for use by applications.

Returns:

None.

34.2.2.4 PDCGPIORead

Reads a GPIO data register.

Prototype:

```
unsigned char  
PDCGPIORead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO data registers in the PDC. The value returned for a pin is the value being driven out for outputs or the value being read for inputs.

This function is contained in `pdcc.c`, with `pdcc.h` containing the API definition for use by applications.

Returns:

The contents of the data register.

34.2.2.5 PDCGPIOWrite

Write a GPIO data register.

Prototype:

```
void  
PDCGPIOWrite(unsigned char ucIdx,  
              unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO data register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO data register.

Description:

This function writes one of the GPIO direction registers in the PDC. The written to a pin is driven out for output pins and ignored for input pins.

This function is contained in `pd.c`, with `pd.h` containing the API definition for use by applications.

Returns:

None.

34.2.2.6 PDCInit

Initializes the connection to the PDC.

Prototype:

```
void  
PDCInit(void)
```

Description:

This function will enable clocking to the SSI and GPIO A modules, configure the GPIO pins to be used for an SSI interface, and it will configure the SSI as a 1 Mbps master device, operating in MOTO mode. It will also enable the SSI module, and will enable the chip select for the PDC on the Stellaris development board.

This function is contained in `pd.c`, with `pd.h` containing the API definition for use by applications.

Returns:

None.

34.2.2.7 PDCLCDBacklightOff

Turn off the backlight.

Prototype:

```
void  
PDCLCDBacklightOff(void)
```

Description:

This function turns off the backlight on the LCD.

This function is contained in `pd.c`, with `pd.h` containing the API definition for use by applications.

Returns:

None.

34.2.2.8 PDCLCDBacklightOn

Turns on the backlight.

Prototype:

```
void  
PDCLCDBacklightOn(void)
```

Description:

This function turns on the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

34.2.2.9 PDCLCDClear

Clear the screen.

Prototype:

```
void  
PDCLCDClear(void)
```

Description:

This function clears the contents of the LCD screen. The cursor will be returned to the upper left corner.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

34.2.2.10 PDCLCDCreateChar

Write a character pattern to the LCD.

Prototype:

```
void  
PDCLCDCreateChar(unsigned char ucChar,  
                  unsigned char *pucData)
```

Parameters:

ucChar is the character index to create. Valid values are zero through seven.

pucData is the data for the character pattern. It contains eight bytes, with the first byte being the top row of the pattern. In each byte, the LSB is the right pixel of the pattern.

Description:

This function will write a character pattern into the LCD for use as a character to be displayed. After writing the pattern, it can be used on the LCD by writing the corresponding character index to the display.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

34.2.2.11 PDCLCDInit

Initializes the LCD display.

Prototype:

```
void  
PDCLCDInit(void)
```

Description:

This function will set up the LCD display for writing. It will set the data bus to 8 bits, set the number of lines to 2, and the font size to 5x10. It will also turn the display off, clear the display, turn the display back on, and enable the backlight.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Note:

The PDC must be initialized via the [PDCInit\(\)](#) function before this function can be called. Also, it may be necessary to adjust the contrast potentiometer in order to discern any output on the LCD display.

Returns:

None.

34.2.2.12 PDCLCDSetPos

Set the position of the cursor.

Prototype:

```
void  
PDCLCDSetPos(unsigned char ucX,  
              unsigned char ucY)
```

Parameters:

ucX is the horizontal position. Valid values are zero through fifteen.

ucY is the vertical position.. Valid values are zero and one.

Description:

This function will move the cursor to the specified position. All characters written to the LCD are placed at the current cursor position, which is automatically advanced.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

34.2.2.13 PDCLCDWrite

Writes a string to the LCD display.

Prototype:

```
void
PDCLCDWrite(const char *pcStr,
            unsigned long ulCount)
```

Parameters:

pcStr pointer to the string to be displayed.

ulCount is the number of characters to be displayed.

Description:

This function will display a string on the LCD at the current cursor position. It is the caller's responsibility to position the cursor to the place where the string should be displayed (either explicitly via [PDCLCDSetPos\(\)](#) or implicitly from where the cursor was left after a previous call to [PDCLCDWrite\(\)](#)), and to properly account for the LCD boundary (line wrapping is not automatically performed). Null characters are not treated special and are written to the LCD, which interprets it as a special programmable character glyph (see [PDCLCDCreateChar\(\)](#)).

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

34.2.2.14 PDCLEDRead

Read the current status of the PDC LEDs.

Prototype:

```
unsigned char
PDCLEDRead(void)
```

Description:

This function will read the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The value currently displayed by the LEDs.

34.2.2.15 PDCLEDWrite

Write to the PDC LEDs.

Prototype:

```
void
PDCLEDWrite(unsigned char ucLED)
```

Parameters:

ucLED value to write to the LEDs.

Description:

This function set the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

34.2.2.16 PDCRead

Read a PDC register.

Prototype:

```
unsigned char  
PDCRead(unsigned char ucAddr)
```

Parameters:

ucAddr specifies the PDC register to read.

Description:

This function will perform the SSI transfers required to read a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

Returns the value read from the PDC.

34.2.2.17 PDCWrite

Write a PDC register.

Prototype:

```
void  
PDCWrite(unsigned char ucAddr,  
          unsigned char ucData)
```

Parameters:

ucAddr specifies the PDC register to write.

ucData specifies the data to write.

Description:

This function will perform the SSI transfers required to write a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

34.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo2 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Comparator (comparator)

This example application demonstrates the operation of the analog comparator(s). Comparator zero (which is present on all devices that have analog comparators) is configured to compare its negative input to an internally generated 1.65 V reference and toggle the state of the LED on port B0 based on comparator change interrupts. The LED will be turned on by the interrupt handler when a rising edge on the comparator output is detected, and will be turned off when a falling edge is detected.

In order for this example to work properly, the ULED0 (JP22) jumper must be installed on the board.

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the user push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO. Note that because of errata in Rev Bx and Rev C0 of Sandstorm-class Stellaris microcontrollers, JTAG and SWD will not function if PB7 is configured as a GPIO. This errata is fixed in Rev C2 of Sandstorm-class Stellaris microcontrollers.

GPIO (gpio_led)

This example application uses LEDs connected to GPIO pins to create a “roving eye” display. Port B0-B3 are driven in a sequential manner to give the illusion of an eye looking back and forth.

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), ULED2 (JP24), and ULED3 (JP25) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the LCD and is a starting point for more complicated applications.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the LCD; individual LEDs connected to port B0-B2 will be turned on upon interrupt handler entry and off before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), and ULED2 (JP24) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 50 kHz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

DK-LM3S817 Quickstart Application (qs_dk-lm3s817)

This example uses the potentiometer on the development board to vary the rate of a repetitive beep from the piezo buzzer, while the light sensor will vary the frequency of the beep. Turning the knob in one direction will result in slower beeps while turning it in the other direction will result in faster beeps. The amount of light falling on the light sensor affects the frequency of the beep. The more light falling on the sensor the higher the pitch of the beep. The potentiometer setting along with the “note” representing the pitch of the beep is displayed on the LCD, and a log of the readings is output on the UART at 115,200, 8-n-1. The push button can be used to turn the beeping noise on and off; when off the LCD and UART still provide the settings.

In the default jumper configuration of the development board, the push button will not actually mute the beep. In order for this example to fully work, the following jumper wire connections must be made: JP19 pin 2 to J6 pin 6.

SSI (ssi_atmel)

This example application uses the SSI master to communicate with the Atmel AT25F1024A EEPROM that is on the development board. The first 256 bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the SSI interrupt; since a 256-byte read at a 1 MHz SSI bus speed takes around 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own GPIO (port B0 and B1) on each interrupt; the attached LED will indicate the occurrence and rate of interrupts.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (the SER0 connector on the Stellaris Family Development Board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED connected to port B0 is inverted so that it is easy to see that it is being fed, which occurs once every second.

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35.1 Introduction

The DK-LM3S818 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the Peripheral Device Controller on the Stellaris Family Development Kit board. The PDC is used to access the character LCD, eight user LEDs, eight user DIP switches, and twenty-four GPIOs.

There is an IAR workspace file (`dk-lm3s818.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`dk-lm3s818.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/dk-lm3s818` subdirectory of the peripheral driver library source distribution.

35.2 API Functions

Functions

- unsigned char [PDCDIPRead](#) (void)
- unsigned char [PDCGPIODirRead](#) (unsigned char ucIdx)
- void [PDCGPIODirWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- unsigned char [PDCGPIORead](#) (unsigned char ucIdx)
- void [PDCGPIOWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- void [PDCInit](#) (void)
- void [PDCLCDBacklightOff](#) (void)
- void [PDCLCDBacklightOn](#) (void)
- void [PDCLCDClear](#) (void)
- void [PDCLCDCreateChar](#) (unsigned char ucChar, unsigned char *pucData)
- void [PDCLCDInit](#) (void)
- void [PDCLCDSetPos](#) (unsigned char ucX, unsigned char ucY)
- void [PDCLCDWrite](#) (const char *pcStr, unsigned long ulCount)
- unsigned char [PDCLEDRead](#) (void)
- void [PDCLEDWrite](#) (unsigned char ucLED)

- unsigned char **PDCRead** (unsigned char ucAddr)
- void **PDCWrite** (unsigned char ucAddr, unsigned char ucData)

35.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

35.2.2 Function Documentation

35.2.2.1 PDCDIPRead

Read the current value of the PDC DIP switches.

Prototype:

```
unsigned char  
PDCDIPRead(void)
```

Description:

This function will read the current value of the DIP switches attached to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The current state of the DIP switches.

35.2.2.2 PDCGPIODirRead

Reads a GPIO direction register.

Prototype:

```
unsigned char  
PDCGPIODirRead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO direction registers in the PDC. The direction bit is set for pins that are outputs and clear for pins that are inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the direction register.

35.2.2.3 PDCGPIODirWrite

Write a GPIO direction register.

Prototype:

```
void
PDCGPIODirWrite(unsigned char ucIdx,
                 unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO direction register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO direction register.

Description:

This function writes ones of the GPIO direction registers in the PDC. The direction bit should be set for pins that are to be outputs and clear for pins that are to be inputs.

This function is contained in `pdcc.c`, with `pdcc.h` containing the API definition for use by applications.

Returns:

None.

35.2.2.4 PDCGPIORead

Reads a GPIO data register.

Prototype:

```
unsigned char
PDCGPIORead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO data registers in the PDC. The value returned for a pin is the value being driven out for outputs or the value being read for inputs.

This function is contained in `pdcc.c`, with `pdcc.h` containing the API definition for use by applications.

Returns:

The contents of the data register.

35.2.2.5 PDCGPIOWrite

Write a GPIO data register.

Prototype:

```
void
PDCGPIOWrite(unsigned char ucIdx,
              unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO data register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO data register.

Description:

This function writes one of the GPIO direction registers in the PDC. The written to a pin is driven out for output pins and ignored for input pins.

This function is contained in `pd.c`, with `pd.h` containing the API definition for use by applications.

Returns:

None.

35.2.2.6 PDCInit

Initializes the connection to the PDC.

Prototype:

```
void  
PDCInit(void)
```

Description:

This function will enable clocking to the SSI and GPIO A modules, configure the GPIO pins to be used for an SSI interface, and it will configure the SSI as a 1 Mbps master device, operating in MOTO mode. It will also enable the SSI module, and will enable the chip select for the PDC on the Stellaris development board.

This function is contained in `pd.c`, with `pd.h` containing the API definition for use by applications.

Returns:

None.

35.2.2.7 PDCLCDBacklightOff

Turn off the backlight.

Prototype:

```
void  
PDCLCDBacklightOff(void)
```

Description:

This function turns off the backlight on the LCD.

This function is contained in `pd.c`, with `pd.h` containing the API definition for use by applications.

Returns:

None.

35.2.2.8 PDCLCDBacklightOn

Turns on the backlight.

Prototype:

```
void  
PDCLCDBacklightOn(void)
```

Description:

This function turns on the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

35.2.2.9 PDCLCDClear

Clear the screen.

Prototype:

```
void  
PDCLCDClear(void)
```

Description:

This function clears the contents of the LCD screen. The cursor will be returned to the upper left corner.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

35.2.2.10 PDCLCDCreateChar

Write a character pattern to the LCD.

Prototype:

```
void  
PDCLCDCreateChar(unsigned char ucChar,  
                  unsigned char *pucData)
```

Parameters:

ucChar is the character index to create. Valid values are zero through seven.

pucData is the data for the character pattern. It contains eight bytes, with the first byte being the top row of the pattern. In each byte, the LSB is the right pixel of the pattern.

Description:

This function will write a character pattern into the LCD for use as a character to be displayed. After writing the pattern, it can be used on the LCD by writing the corresponding character index to the display.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

35.2.2.11 PDCLCDInit

Initializes the LCD display.

Prototype:

```
void  
PDCLCDInit(void)
```

Description:

This function will set up the LCD display for writing. It will set the data bus to 8 bits, set the number of lines to 2, and the font size to 5x10. It will also turn the display off, clear the display, turn the display back on, and enable the backlight.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Note:

The PDC must be initialized via the [PDCInit\(\)](#) function before this function can be called. Also, it may be necessary to adjust the contrast potentiometer in order to discern any output on the LCD display.

Returns:

None.

35.2.2.12 PDCLCDSetPos

Set the position of the cursor.

Prototype:

```
void  
PDCLCDSetPos(unsigned char ucX,  
              unsigned char ucY)
```

Parameters:

ucX is the horizontal position. Valid values are zero through fifteen.

ucY is the vertical position.. Valid values are zero and one.

Description:

This function will move the cursor to the specified position. All characters written to the LCD are placed at the current cursor position, which is automatically advanced.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

35.2.2.13 PDCLCDWrite

Writes a string to the LCD display.

Prototype:

```
void
PDCLCDWrite(const char *pcStr,
            unsigned long ulCount)
```

Parameters:

pcStr pointer to the string to be displayed.

ulCount is the number of characters to be displayed.

Description:

This function will display a string on the LCD at the current cursor position. It is the caller's responsibility to position the cursor to the place where the string should be displayed (either explicitly via [PDCLCDSetPos\(\)](#) or implicitly from where the cursor was left after a previous call to [PDCLCDWrite\(\)](#)), and to properly account for the LCD boundary (line wrapping is not automatically performed). Null characters are not treated special and are written to the LCD, which interprets it as a special programmable character glyph (see [PDCLCDCreateChar\(\)](#)).

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

35.2.2.14 PDCLEDRead

Read the current status of the PDC LEDs.

Prototype:

```
unsigned char
PDCLEDRead(void)
```

Description:

This function will read the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The value currently displayed by the LEDs.

35.2.2.15 PDCLEDWrite

Write to the PDC LEDs.

Prototype:

```
void
PDCLEDWrite(unsigned char ucLED)
```

Parameters:

ucLED value to write to the LEDs.

Description:

This function set the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

35.2.2.16 PDCRead

Read a PDC register.

Prototype:

```
unsigned char
PDCRead(unsigned char ucAddr)
```

Parameters:

ucAddr specifies the PDC register to read.

Description:

This function will perform the SSI transfers required to read a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

Returns the value read from the PDC.

35.2.2.17 PDCWrite

Write a PDC register.

Prototype:

```
void
PDCWrite(unsigned char ucAddr,
         unsigned char ucData)
```

Parameters:

ucAddr specifies the PDC register to write.

ucData specifies the data to write.

Description:

This function will perform the SSI transfers required to write a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

35.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo2 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Comparator (comparator)

This example application demonstrates the operation of the analog comparator(s). Comparator zero (which is present on all devices that have analog comparators) is configured to compare its negative input to an internally generated 1.65 V reference and toggle the state of the LED on port B0 based on comparator change interrupts. The LED will be turned on by the interrupt handler when a rising edge on the comparator output is detected, and will be turned off when a falling edge is detected.

In order for this example to work properly, the ULED0 (JP22) jumper must be installed on the board.

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the user push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO. Note that because of errata in Rev Bx and Rev C0 of Sandstorm-class Stellaris microcontrollers, JTAG and SWD will not function if PB7 is configured as a GPIO. This errata is fixed in Rev C2 of Sandstorm-class Stellaris microcontrollers.

GPIO (gpio_led)

This example application uses LEDs connected to GPIO pins to create a “roving eye” display. Port B0-B3 are driven in a sequential manner to give the illusion of an eye looking back and forth.

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), ULED2 (JP24), and ULED3 (JP25) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the LCD and is a starting point for more complicated applications.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the LCD; individual LEDs connected to port B0-B2 will be turned on upon interrupt handler entry and off before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), and ULED2 (JP24) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 50 kHz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

DK-LM3S818 Quickstart Application (qs_dk-lm3s818)

This example uses the potentiometer on the development board to vary the rate of a repetitive beep from the piezo buzzer, while the light sensor will vary the frequency of the beep. Turning the knob in one direction will result in slower beeps while turning it in the other direction will result in faster beeps. The amount of light falling on the light sensor affects the frequency of the beep. The more light falling on the sensor the higher the pitch of the beep. The potentiometer setting along with the “note” representing the pitch of the beep is displayed on the LCD, and a log of the readings is output on the UART at 115,200, 8-n-1. The push button can be used to turn the beeping noise on and off; when off the LCD and UART still provide the settings.

In the default jumper configuration of the development board, the push button will not actually mute the beep. In order for this example to fully work, the following jumper wire connections must be made: JP19 pin 2 to J6 pin 6.

SSI (ssi_atmel)

This example application uses the SSI master to communicate with the Atmel AT25F1024A EEPROM that is on the development board. The first 256 bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the SSI interrupt; since a 256-byte read at a 1 MHz SSI bus speed takes around 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own GPIO (port B0 and B1) on each interrupt; the attached LED will indicate the occurrence and rate of interrupts.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (the SER0 connector on the Stellaris Family Development Board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED connected to port B0 is inverted so that it is easy to see that it is being fed, which occurs once every second.

36 DK-LM3S828 Example Applications

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36.1 Introduction

The DK-LM3S828 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the Peripheral Device Controller on the Stellaris Family Development Kit board. The PDC is used to access the character LCD, eight user LEDs, eight user DIP switches, and twenty-four GPIOs.

There is an IAR workspace file (`dk-lm3s828.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`dk-lm3s828.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/dk-lm3s828` subdirectory of the peripheral driver library source distribution.

36.2 API Functions

Functions

- unsigned char [PDCDIPRead](#) (void)
- unsigned char [PDCGPIODirRead](#) (unsigned char ucIdx)
- void [PDCGPIODirWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- unsigned char [PDCGPIORead](#) (unsigned char ucIdx)
- void [PDCGPIOWrite](#) (unsigned char ucIdx, unsigned char ucValue)
- void [PDCInit](#) (void)
- void [PDCLCDBacklightOff](#) (void)
- void [PDCLCDBacklightOn](#) (void)
- void [PDCLCDClear](#) (void)
- void [PDCLCDCreateChar](#) (unsigned char ucChar, unsigned char *pucData)
- void [PDCLCDInit](#) (void)
- void [PDCLCDSetsPos](#) (unsigned char ucX, unsigned char ucY)
- void [PDCLCDWrite](#) (const char *pcStr, unsigned long ulCount)
- unsigned char [PDCLEDRead](#) (void)
- void [PDCLEDWrite](#) (unsigned char ucLED)

- unsigned char **PDCRead** (unsigned char ucAddr)
- void **PDCWrite** (unsigned char ucAddr, unsigned char ucData)

36.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

36.2.2 Function Documentation

36.2.2.1 PDCDIPRead

Read the current value of the PDC DIP switches.

Prototype:

```
unsigned char  
PDCDIPRead(void)
```

Description:

This function will read the current value of the DIP switches attached to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The current state of the DIP switches.

36.2.2.2 PDCGPIODirRead

Reads a GPIO direction register.

Prototype:

```
unsigned char  
PDCGPIODirRead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO direction registers in the PDC. The direction bit is set for pins that are outputs and clear for pins that are inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the direction register.

36.2.2.3 PDCGPIODirWrite

Write a GPIO direction register.

Prototype:

```
void  
PDCGPIODirWrite(unsigned char ucIdx,  
                 unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO direction register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO direction register.

Description:

This function writes ones of the GPIO direction registers in the PDC. The direction bit should be set for pins that are to be outputs and clear for pins that are to be inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

36.2.2.4 PDCGPIORead

Reads a GPIO data register.

Prototype:

```
unsigned char  
PDCGPIORead(unsigned char ucIdx)
```

Parameters:

ucIdx is the index of the GPIO direction register to read; valid values are 0, 1, and 2.

Description:

This function reads one of the GPIO data registers in the PDC. The value returned for a pin is the value being driven out for outputs or the value being read for inputs.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The contents of the data register.

36.2.2.5 PDCGPIOWrite

Write a GPIO data register.

Prototype:

```
void  
PDCGPIOWrite(unsigned char ucIdx,  
              unsigned char ucValue)
```

Parameters:

ucIdx is the index of the GPIO data register to write; valid values are 0, 1, and 2.

ucValue is the value to write to the GPIO data register.

Description:

This function writes one of the GPIO direction registers in the PDC. The written to a pin is driven out for output pins and ignored for input pins.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

36.2.2.6 PDCInit

Initializes the connection to the PDC.

Prototype:

```
void  
PDCInit(void)
```

Description:

This function will enable clocking to the SSI and GPIO A modules, configure the GPIO pins to be used for an SSI interface, and it will configure the SSI as a 1 Mbps master device, operating in MOTO mode. It will also enable the SSI module, and will enable the chip select for the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

36.2.2.7 PDCLCDBacklightOff

Turn off the backlight.

Prototype:

```
void  
PDCLCDBacklightOff(void)
```

Description:

This function turns off the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

36.2.2.8 PDCLCDBacklightOn

Turns on the backlight.

Prototype:

```
void  
PDCLCDBacklightOn(void)
```

Description:

This function turns on the backlight on the LCD.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

36.2.2.9 PDCLCDClear

Clear the screen.

Prototype:

```
void  
PDCLCDClear(void)
```

Description:

This function clears the contents of the LCD screen. The cursor will be returned to the upper left corner.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

36.2.2.10 PDCLCDCreateChar

Write a character pattern to the LCD.

Prototype:

```
void  
PDCLCDCreateChar(unsigned char ucChar,  
                  unsigned char *pucData)
```

Parameters:

ucChar is the character index to create. Valid values are zero through seven.

pucData is the data for the character pattern. It contains eight bytes, with the first byte being the top row of the pattern. In each byte, the LSB is the right pixel of the pattern.

Description:

This function will write a character pattern into the LCD for use as a character to be displayed. After writing the pattern, it can be used on the LCD by writing the corresponding character index to the display.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

36.2.2.11 PDCLCDInit

Initializes the LCD display.

Prototype:

```
void  
PDCLCDInit(void)
```

Description:

This function will set up the LCD display for writing. It will set the data bus to 8 bits, set the number of lines to 2, and the font size to 5x10. It will also turn the display off, clear the display, turn the display back on, and enable the backlight.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Note:

The PDC must be initialized via the [PDCInit\(\)](#) function before this function can be called. Also, it may be necessary to adjust the contrast potentiometer in order to discern any output on the LCD display.

Returns:

None.

36.2.2.12 PDCLCDSetPos

Set the position of the cursor.

Prototype:

```
void  
PDCLCDSetPos(unsigned char ucX,  
              unsigned char ucY)
```

Parameters:

ucX is the horizontal position. Valid values are zero through fifteen.

ucY is the vertical position.. Valid values are zero and one.

Description:

This function will move the cursor to the specified position. All characters written to the LCD are placed at the current cursor position, which is automatically advanced.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

36.2.2.13 PDCLCDWrite

Writes a string to the LCD display.

Prototype:

```
void
PDCLCDWrite(const char *pcStr,
            unsigned long ulCount)
```

Parameters:

pcStr pointer to the string to be displayed.

ulCount is the number of characters to be displayed.

Description:

This function will display a string on the LCD at the current cursor position. It is the caller's responsibility to position the cursor to the place where the string should be displayed (either explicitly via [PDCLCDSetPos\(\)](#) or implicitly from where the cursor was left after a previous call to [PDCLCDWrite\(\)](#)), and to properly account for the LCD boundary (line wrapping is not automatically performed). Null characters are not treated special and are written to the LCD, which interprets it as a special programmable character glyph (see [PDCLCDCreateChar\(\)](#)).

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

36.2.2.14 PDCLEDRead

Read the current status of the PDC LEDs.

Prototype:

```
unsigned char
PDCLEDRead(void)
```

Description:

This function will read the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

The value currently displayed by the LEDs.

36.2.2.15 PDCLEDWrite

Write to the PDC LEDs.

Prototype:

```
void
PDCLEDWrite(unsigned char ucLED)
```

Parameters:

ucLED value to write to the LEDs.

Description:

This function set the state of the LEDs connected to the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

36.2.2.16 PDCRead

Read a PDC register.

Prototype:

```
unsigned char  
PDCRead(unsigned char ucAddr)
```

Parameters:

ucAddr specifies the PDC register to read.

Description:

This function will perform the SSI transfers required to read a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

Returns the value read from the PDC.

36.2.2.17 PDCWrite

Write a PDC register.

Prototype:

```
void  
PDCWrite(unsigned char ucAddr,  
          unsigned char ucData)
```

Parameters:

ucAddr specifies the PDC register to write.

ucData specifies the data to write.

Description:

This function will perform the SSI transfers required to write a register in the PDC on the Stellaris development board.

This function is contained in `pdc.c`, with `pdc.h` containing the API definition for use by applications.

Returns:

None.

36.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo2 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the user push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO. Note that because of errata in Rev Bx and Rev C0 of Sandstorm-class Stellaris microcontrollers, JTAG and SWD will not function if PB7 is configured as a GPIO. This errata is fixed in Rev C2 of Sandstorm-class Stellaris microcontrollers.

GPIO (gpio_led)

This example application uses LEDs connected to GPIO pins to create a “roving eye” display. Port B0-B3 are driven in a sequential manner to give the illusion of an eye looking back and forth.

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), ULED2 (JP24), and ULED3 (JP25) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the LCD and is a starting point for more complicated applications.

I2C (i2c_atmel)

This example application uses the I2C master to communicate with the Atmel AT24C08A EEPROM that is on the development board. The first sixteen bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the I2C interrupt; since a sixteen-byte read at a 100 kHz I2C bus speed takes almost 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

In order for this example to work properly, the I2C_SCL (JP14), I2C_SDA (JP13), and I2CM_A2 (JP11) jumpers must be installed on the board, and the I2CM_WP (JP12) jumper must be removed.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the LCD; individual LEDs connected to port B0-B2 will be turned on upon interrupt handler entry and off before interrupt handler exit so that the

off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

In order for this example to work properly, the ULED0 (JP22), ULED1 (JP23), and ULED2 (JP24) jumpers must be installed on the board, and the PB1 (JP1) jumper on the daughtercard must be set to pins 2 & 3.

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

DK-LM3S828 Quickstart Application (qs_dk-lm3s828)

This example uses the potentiometer on the development board to vary the rate of a click sound from the piezo buzzer. Turning the knob in one direction will result in slower clicks while turning it in the other direction will result in faster clicks. The potentiometer setting is displayed on the LCD, and a log of the readings is output on the UART at 115,200, 8-n-1. The push button can be used to turn the clicking noise on and off; when off the LCD and UART still provide the settings.

SSI (ssi_atmel)

This example application uses the SSI master to communicate with the Atmel AT25F1024A EEPROM that is on the development board. The first 256 bytes of the EEPROM are erased and then programmed with an incrementing sequence. The data is then read back to verify its correctness. The transfer is managed by an interrupt handler in response to the SSI interrupt; since a 256-byte read at a 1 MHz SSI bus speed takes around 2 ms, this allows a lot of other processing to occur during the transfer (though that time is not utilized by this example).

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own GPIO (port B0 and B1) on each interrupt; the attached LED will indicate the occurrence and rate of interrupts.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (the SER0 connector on the Stellaris Family Development Board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED connected to port B0 is inverted so that it is easy to see that it is being fed, which occurs once every second.

37 EK-LM3S1968 Example Applications

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37.1 Introduction

The EK-LM3S1968 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the RiTdisplay 128x96 4-bit gray-scale OLED graphical display on the Stellaris LM3S1968 Evaluation Kit board.

There is also a board specific driver for the Class-D audio amplifier and speaker on the board. In order to use this driver, the system clock should be as high as possible and must be at least 256 KHz; increasing the system clock rate result in higher quality audio. This driver will play both 8-bit PCM data and 4-bit ADPCM data; the `converter` application (`converter.c` is the source code, and `converter.exe` is a pre-built binary) will take raw 16-bit signed PCM data and convert it into a C array that can be included in an application for playback purposes. For example, to encode `voice.pcm` with ADPCM and produce a C array called `g_pucVoice`:

```
converter -a -n g_pucVoice -o voice.h voice.pcm
```

To do the same, but encode to 8-bit PCM:

```
converter -p -n g_pucVoice -o voice.h voice.pcm
```

Since the Class-D audio driver will only play 8 KHz mono streams, and the `converter` application will only handle raw PCM input, an application such as `sox` will be needed to convert arbitrary wave files to the required format. To convert `voice.wav` to the required format for `converter`:

```
sox voice.wav -t raw -r 8000 -c 1 -s -w voice.pcm polyphase
```

The `polyphase` at the end selects a higher quality sample rate conversion algorithm. It may be helpful (and/or necessary) to also include `vol {factor}` before `polyphase` in order to increase the volume of the waveform. If `sox` complains of clipping, the volume needs to be reduced.

`sox` can be found at <http://sox.sourceforge.net>. There are numerous other audio applications (both open source and commercial) that can be used instead of `sox`.

There is an IAR workspace file (`ek-lm3s1968.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`ek-lm3s1968.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/ek-lm3s1968` subdirectory of the peripheral driver library source distribution.

37.2 API Functions

Functions

- tBoolean [ClassDBusy](#) (void)
- void [ClassDInit](#) (unsigned long ulPWMClock)
- void [ClassDPlayADPCM](#) (const unsigned char *pucBuffer, unsigned long ulLength)
- void [ClassDPlayPCM](#) (const unsigned char *pucBuffer, unsigned long ulLength)
- void [ClassDPWMHandler](#) (void)
- void [ClassDStop](#) (void)
- void [ClassDVolumeDown](#) (unsigned long ulVolume)
- void [ClassDVolumeSet](#) (unsigned long ulVolume)
- void [ClassDVolumeUp](#) (unsigned long ulVolume)
- void [RIT128x96x4Clear](#) (void)
- void [RIT128x96x4Disable](#) (void)
- void [RIT128x96x4DisplayOff](#) (void)
- void [RIT128x96x4DisplayOn](#) (void)
- void [RIT128x96x4Enable](#) (unsigned long ulFrequency)
- void [RIT128x96x4ImageDraw](#) (const unsigned char *pucImage, unsigned long ulX, unsigned long ulY, unsigned long ulWidth, unsigned long ulHeight)
- void [RIT128x96x4Init](#) (unsigned long ulFrequency)
- void [RIT128x96x4StringDraw](#) (const char *pcStr, unsigned long ulX, unsigned long ulY, unsigned char ucLevel)

37.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

37.2.2 Function Documentation

37.2.2.1 ClassDBusy

Determines if the Class-D audio driver is busy.

Prototype:

```
tBoolean
ClassDBusy(void)
```

Description:

This function determines if the Class-D audio driver is busy, either performing the startup ramp for the speaker or playing a stream.

This function is contained in `class-d.c`, with `class-d.h` containing the API definition for use by applications.

Returns:

Returns **true** if the Class-D audio driver is busy and **false** otherwise.

37.2.2.2 ClassDInit

Initializes the Class-D audio driver.

Prototype:

```
void  
ClassDInit(unsigned long ulPWMClock)
```

Parameters:

ulPWMClock is the rate of the clock supplied to the PWM module.

Description:

This function initializes the Class-D audio driver, preparing it to output audio data to the speaker. The startup ramp of the speaker is started but will not complete until after this function returns (use [ClassDBusy\(\)](#) to determine when it has completed).

The PWM module clock should be as high as possible; lower clock rates reduces the quality of the produced audio. For the best quality audio, the PWM module should be clocked at 50 MHz.

This function is contained in `class-d.c`, with `class-d.h` containing the API definition for use by applications.

Note:

In order for the Class-D audio driver to function properly, the Class-D audio driver interrupt handler ([ClassDPWMHandler\(\)](#)) must be installed into the vector table for the PWM1 interrupt.

Returns:

None.

37.2.2.3 ClassDPlayADPCM

Plays a buffer of 8 KHz IMA ADPCM data.

Prototype:

```
void  
ClassDPlayADPCM(const unsigned char *pucBuffer,  
                unsigned long ulLength)
```

Parameters:

pucBuffer is a pointer to the buffer containing the IMA ADPCM encoded data.

ulLength is the number of bytes in the buffer.

Description:

This function starts playback of a stream of IMA ADPCM encoded data. The data is decoded as needed and therefore does not require a large buffer in SRAM. This provides a 2:1 compression ratio relative to raw 8-bit PCM with little to no loss in audio quality.

This function is contained in `class-d.c`, with `class-d.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.4 ClassDPlayPCM

Plays a buffer of 8 KHz, 8-bit, unsigned PCM data.

Prototype:

```
void  
ClassDPlayPCM(const unsigned char *pucBuffer,  
              unsigned long ulLength)
```

Parameters:

pucBuffer is a pointer to the buffer containing 8-bit, unsigned PCM data.

ulLength is the number of bytes in the buffer.

Description:

This function starts playback of a stream of 8-bit, unsigned PCM data. Since the data is unsigned, a value of 128 represents the mid-point of the speaker's travel (that is, corresponds to no DC offset).

This function is contained in `class-d.c`, with `class-d.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.5 ClassDPWMHandler

Handles the PWM1 interrupt.

Prototype:

```
void  
ClassDPWMHandler(void)
```

Description:

This function responds to the PWM1 interrupt, updating the duty cycle of the output waveform in order to produce sound. It is the application's responsibility to ensure that this function is called in response to the PWM1 interrupt, typically by installing it in the vector table as the handler for the PWM1 interrupt.

This function is contained in `class-d.c`, with `class-d.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.6 ClassDStop

Stops playback of the current audio stream.

Prototype:

```
void  
ClassDStop(void)
```

Description:

This function immediately stops playback of the current audio stream. As a result, the output is changed directly to the mid-point, possibly resulting in a pop or click.

This function is contained in `class-d.c`, with `class-d.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.7 ClassDVolumeDown

Decreases the volume of the audio playback.

Prototype:

```
void  
ClassDVolumeDown(unsigned long ulVolume)
```

Parameters:

ulVolume is the amount by which to decrease the volume of the audio playback, specified as a value between 0 (for no adjustment) and 256 maximum adjustment).

Description:

This function decreases the volume of the audio playback relative to the current volume.

This function is contained in `class-d.c`, with `class-d.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.8 ClassDVolumeSet

Sets the volume of the audio playback.

Prototype:

```
void  
ClassDVolumeSet(unsigned long ulVolume)
```

Parameters:

ulVolume is the volume of the audio playback, specified as a value between 0 (for silence) and 256 (for full volume).

Description:

This function sets the volume of the audio playback. Setting the volume to 0 will mute the output, while setting the volume to 256 will play the audio stream without any volume adjustment (that is, full volume).

This function is contained in `class-d.c`, with `class-d.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.9 ClassDVolumeUp

Increases the volume of the audio playback.

Prototype:

```
void  
ClassDVolumeUp(unsigned long ulVolume)
```

Parameters:

ulVolume is the amount by which to increase the volume of the audio playback, specified as a value between 0 (for no adjustment) and 256 maximum adjustment).

Description:

This function increases the volume of the audio playback relative to the current volume.

This function is contained in `class-d.c`, with `class-d.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.10 RIT128x96x4Clear

Clears the OLED display.

Prototype:

```
void  
RIT128x96x4Clear(void)
```

Description:

This function will clear the display RAM. All pixels in the display will be turned off.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.11 RIT128x96x4Disable

Enable the SSI component of the OLED display driver.

Prototype:

```
void  
RIT128x96x4Disable(void)
```

Description:

This function initializes the SSI interface to the OLED display.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.12 RIT128x96x4DisplayOff

Turns off the OLED display.

Prototype:

```
void  
RIT128x96x4DisplayOff(void)
```

Description:

This function will turn off the OLED display. This will stop the scanning of the panel and turn off the on-chip DC-DC converter, preventing damage to the panel due to burn-in (it has similar characters to a CRT in this respect).

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.13 RIT128x96x4DisplayOn

Turns on the OLED display.

Prototype:

```
void  
RIT128x96x4DisplayOn(void)
```

Description:

This function will turn on the OLED display, causing it to display the contents of its internal frame buffer.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.14 RIT128x96x4Enable

Enable the SSI component of the OLED display driver.

Prototype:

```
void  
RIT128x96x4Enable(unsigned long ulFrequency)
```

Parameters:

ulFrequency specifies the SSI Clock Frequency to be used.

Description:

This function initializes the SSI interface to the OLED display.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.15 RIT128x96x4ImageDraw

Displays an image on the OLED display.

Prototype:

```
void
RIT128x96x4ImageDraw(const unsigned char *pucImage,
                      unsigned long ulX,
                      unsigned long ulY,
                      unsigned long ulWidth,
                      unsigned long ulHeight)
```

Parameters:

pucImage is a pointer to the image data.

ulX is the horizontal position to display this image, specified in columns from the left edge of the display.

ulY is the vertical position to display this image, specified in rows from the top of the display.

ulWidth is the width of the image, specified in columns.

ulHeight is the height of the image, specified in rows.

Description:

This function will display a bitmap graphic on the display. Because of the format of the display RAM, the starting column (*ulX*) and the number of columns (*ulWidth*) must be an integer multiple of two.

The image data is organized with the first row of image data appearing left to right, followed immediately by the second row of image data. Each byte contains the data for two columns in the current row, with the leftmost column being contained in bits 7:4 and the rightmost column being contained in bits 3:0.

For example, an image six columns wide and seven scan lines tall would be arranged as follows (showing how the twenty one bytes of the image would appear on the display):

+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+			
Byte 0				Byte 1				Byte 2							
+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+			
7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0			
+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+			
Byte 3				Byte 4				Byte 5							
+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+			
7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0			
+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+			
Byte 6				Byte 7				Byte 8							
+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+			
7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0			
+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+			
Byte 9				Byte 10				Byte 11							
+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+			
7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0			
+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+			
Byte 12				Byte 13				Byte 14							
+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+				+-----+-----+-----+			
7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0			

+-----+-----+-----+-----+																														
	Byte 15					Byte 16					Byte 17																			
+-----+-----+-----+-----+																														
	7	6	5	4		3	2	1	0		7	6	5	4		3	2	1	0		7	6	5	4		3	2	1	0	
+-----+-----+-----+-----+																														
	Byte 18					Byte 19					Byte 20																			
+-----+-----+-----+-----+																														
	7	6	5	4		3	2	1	0		7	6	5	4		3	2	1	0		7	6	5	4		3	2	1	0	
+-----+-----+-----+-----+																														

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.16 RIT128x96x4Init

Initialize the OLED display.

Prototype:

```
void
RIT128x96x4Init(unsigned long ulFrequency)
```

Parameters:

ulFrequency specifies the SSI Clock Frequency to be used.

Description:

This function initializes the SSI interface to the OLED display and configures the SSD1329 controller on the panel.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

37.2.2.17 RIT128x96x4StringDraw

Displays a string on the OLED display.

Prototype:

```
void
RIT128x96x4StringDraw(const char *pcStr,
                      unsigned long ulX,
                      unsigned long ulY,
                      unsigned char ucLevel)
```

Parameters:

pcStr is a pointer to the string to display.

ulX is the horizontal position to display the string, specified in columns from the left edge of the display.

u/Y is the vertical position to display the string, specified in rows from the top edge of the display.

ucLevel is the 4-bit gray scale value to be used for displayed text.

Description:

This function will draw a string on the display. Only the ASCII characters between 32 (space) and 126 (tilde) are supported; other characters will result in random data being draw on the display (based on whatever appears before/after the font in memory). The font is mono-spaced, so characters such as “i” and “l” have more white space around them than characters such as “m” or “w”.

If the drawing of the string reaches the right edge of the display, no more characters will be drawn. Therefore, special care is not required to avoid supplying a string that is “too long” to display.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Note:

Because the OLED display packs 2 pixels of data in a single byte, the parameter *u/X* must be an even column number (for example, 0, 2, 4, and so on).

Returns:

None.

37.3 Examples

Audio Playback (audio)

This example application plays audio via the Class-D amplifier and speaker. The audio is provided in both PCM and ADPCM format so that the audio quality can be compared.

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo2 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the select push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO.

Graphics Example (graphics)

A simple application that displays scrolling text on the top line of the OLED display, along with a 4-bit gray scale image.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the OLED and is a starting point for more complicated applications.

Hibernate Example (hibernate)

An example to demonstrate the use of the Hibernation module. The user can put the microcontroller in hibernation by pressing the select button. The microcontroller will then wake on its own after 5 seconds, or immediately if the user presses the select button again. The program keeps a count of the number of times it has entered hibernation. The value of the counter is stored in the battery backed memory of the Hibernation module so that it can be retrieved when the microcontroller wakes.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, pre-emption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the OLED; GPIO pins B0, B1 and B2 will be asserted upon interrupt handler entry and de-asserted before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 440 Hz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

EK-LM3S1968 Quickstart Application (qs_ek-lm3s1968)

A game in which a blob-like character tries to find its way out of a maze. The character starts in the middle of the maze and must find the exit, which will always be located at one of the four corners of the maze. Once the exit to the maze is located, the character is placed into the middle of a new maze and must find the exit to that maze; this repeats endlessly.

The game is started by pressing the select push button on the right side of the board. During game play, the select push button will fire a bullet in the direction the character is currently facing, and the navigation push buttons on the left side of the board will cause the character to walk in the corresponding direction.

Populating the maze are a hundred spinning stars that mindlessly attack the character. Contact with one of these stars results in the game ending, but the stars go away when shot.

Score is accumulated for shooting the stars and for finding the exit to the maze. The game lasts for only one character, and the score is displayed on the virtual UART at 115,200, 8-N-1 during game play and will be displayed on the screen at the end of the game.

Since the OLED display on the evaluation board has burn-in characteristics similar to a CRT, the application also contains a screen saver. The screen saver will only become active if two minutes have passed without the user push button being pressed while waiting to start the game (that is, it will never come on during game play). Qix-style bouncing lines are drawn on the display by the screen saver.

After two minutes of running the screen saver, the processor will enter hibernation mode, and the red LED will turn on. Hibernation mode will be exited by pressing the select push button. The select push button will then need to be pressed again to start the game.

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own indicator on the display.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (connected to the FTDI virtual serial port on the evaluation board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED is inverted so that it is easy to see that it is being fed, which occurs once every second.

38 EK-LM3S2965 Example Applications

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38.1 Introduction

The EK-LM3S2965 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the OSRAM 128x64 4-bit gray-scale OLED graphical display on the Stellaris LM3S2965 Evaluation Kit boards.

These examples and display driver are for the EK-LM3S2965 Rev A boards, which utilize the 128x64 OSRAM display. The Rev A boards can be identified by looking on the back of the circuit board opposite the JTAG header. The board part number is located there and will end with an "A". If the board part number ends with a "C", then refer instead to the examples chapter for the [EK-LM3S2965 Rev C Example Applications](#).

There is an IAR workspace file (`ek-lm3s2965.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`ek-lm3s2965.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/ek-lm3s2965` subdirectory of the peripheral driver library source distribution.

38.2 API Functions

Functions

- void [OSRAM128x64x4Clear](#) (void)
- void [OSRAM128x64x4Disable](#) (void)
- void [OSRAM128x64x4DisplayOff](#) (void)
- void [OSRAM128x64x4DisplayOn](#) (void)
- void [OSRAM128x64x4Enable](#) (unsigned long ulFrequency)
- void [OSRAM128x64x4ImageDraw](#) (const unsigned char *puclImage, unsigned long ulX, unsigned long ulY, unsigned long ulWidth, unsigned long ulHeight)
- void [OSRAM128x64x4Init](#) (unsigned long ulFrequency)
- void [OSRAM128x64x4StringDraw](#) (const char *pcStr, unsigned long ulX, unsigned long ulY, unsigned char ucLevel)

38.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

38.2.2 Function Documentation

38.2.2.1 OSRAM128x64x4Clear

Clears the OLED display.

Prototype:

```
void  
OSRAM128x64x4Clear(void)
```

Description:

This function will clear the display RAM. All pixels in the display will be turned off.

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

38.2.2.2 OSRAM128x64x4Disable

Enable the SSI component of the OLED display driver.

Prototype:

```
void  
OSRAM128x64x4Disable(void)
```

Description:

This function initializes the SSI interface to the OLED display.

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

38.2.2.3 OSRAM128x64x4DisplayOff

Turns off the OLED display.

Prototype:

```
void  
OSRAM128x64x4DisplayOff(void)
```

Description:

This function will turn off the OLED display. This will stop the scanning of the panel and turn off the on-chip DC-DC converter, preventing damage to the panel due to burn-in (it has similar characters to a CRT in this respect).

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

38.2.2.4 OSRAM128x64x4DisplayOn

Turns on the OLED display.

Prototype:

```
void  
OSRAM128x64x4DisplayOn(void)
```

Description:

This function will turn on the OLED display, causing it to display the contents of its internal frame buffer.

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

38.2.2.5 OSRAM128x64x4Enable

Enable the SSI component of the OLED display driver.

Prototype:

```
void  
OSRAM128x64x4Enable(unsigned long ulFrequency)
```

Parameters:

ulFrequency specifies the SSI Clock Frequency to be used.

Description:

This function initializes the SSI interface to the OLED display.

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

38.2.2.6 OSRAM128x64x4ImageDraw

Displays an image on the OLED display.

Prototype:

```
void
OSRAM128x64x4ImageDraw(const unsigned char *pucImage,
                        unsigned long ulX,
                        unsigned long ulY,
                        unsigned long ulWidth,
                        unsigned long ulHeight)
```

Parameters:

pucImage is a pointer to the image data.

ulX is the horizontal position to display this image, specified in columns from the left edge of the display.

ulY is the vertical position to display this image, specified in rows from the top of the display.

ulWidth is the width of the image, specified in columns.

ulHeight is the height of the image, specified in rows.

Description:

This function will display a bitmap graphic on the display. Because of the format of the display RAM, the starting column (*ulX*) and the number of columns (*ulWidth*) must be an integer multiple of two.

The image data is organized with the first row of image data appearing left to right, followed immediately by the second row of image data. Each byte contains the data for two columns in the current row, with the leftmost column being contained in bits 7:4 and the rightmost column being contained in bits 3:0.

For example, an image six columns wide and seven scan lines tall would be arranged as follows (showing how the twenty one bytes of the image would appear on the display):

+-----+-----+-----+						
	Byte 0		Byte 1		Byte 2	
+-----+-----+-----+						
	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	
+-----+-----+-----+						
	Byte 3		Byte 4		Byte 5	
+-----+-----+-----+						
	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	
+-----+-----+-----+						
	Byte 6		Byte 7		Byte 8	
+-----+-----+-----+						
	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	
+-----+-----+-----+						
	Byte 9		Byte 10		Byte 11	
+-----+-----+-----+						
	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	
+-----+-----+-----+						
	Byte 12		Byte 13		Byte 14	
+-----+-----+-----+						
	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	
+-----+-----+-----+						
	Byte 15		Byte 16		Byte 17	
+-----+-----+-----+						
	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	
+-----+-----+-----+						
	Byte 18		Byte 19		Byte 20	


```
+-----+-----+-----+-----+-----+-----+
| 7 6 5 4 | 3 2 1 0 | 7 6 5 4 | 3 2 1 0 | 7 6 5 4 | 3 2 1 0 |
+-----+-----+-----+-----+-----+-----+
```

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

38.2.2.7 OSRAM128x64x4Init

Initialize the OLED display.

Prototype:

```
void
OSRAM128x64x4Init(unsigned long ulFrequency)
```

Parameters:

ulFrequency specifies the SSI Clock Frequency to be used.

Description:

This function initializes the SSI interface to the OLED display and configures the SSD0323 controller on the panel.

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

38.2.2.8 OSRAM128x64x4StringDraw

Displays a string on the OLED display.

Prototype:

```
void
OSRAM128x64x4StringDraw(const char *pcStr,
                        unsigned long ulX,
                        unsigned long ulY,
                        unsigned char ucLevel)
```

Parameters:

pcStr is a pointer to the string to display.

ulX is the horizontal position to display the string, specified in columns from the left edge of the display.

ulY is the vertical position to display the string, specified in rows from the top edge of the display.

ucLevel is the 4-bit gray scale value to be used for displayed text.

Description:

This function will draw a string on the display. Only the ASCII characters between 32 (space) and 126 (tilde) are supported; other characters will result in random data being drawn on the display (based on whatever appears before/after the font in memory). The font is mono-spaced, so characters such as “i” and “l” have more white space around them than characters such as “m” or “w”.

If the drawing of the string reaches the right edge of the display, no more characters will be drawn. Therefore, special care is not required to avoid supplying a string that is “too long” to display.

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Note:

Because the OLED display packs 2 pixels of data in a single byte, the parameter *ulX* must be an even column number (for example, 0, 2, 4, and so on).

Returns:

None.

38.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The `boot_demo2` application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

CAN Device Board LED Application (can_device_led)

This simple application uses the two buttons on the board as a light switch. When the “up” button is pressed the status LED will turn on. When the “down” button is pressed, the status LED will turn off.

CAN Device Board Quickstart Application (can_device_qs)

This application uses the CAN controller to communicate with the evaluation board that is running the example game. It receives messages over CAN to turn on, turn off, or to pulse the LED on the device board. It also sends CAN messages when either of the up and down buttons are pressed or released.

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the select push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO.

Graphics Example (graphics)

A simple application that displays scrolling text on the top line of the OLED display, along with a 4-bit gray scale image.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the OLED and is a starting point for more complicated applications.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the OLED; GPIO pins B0, B1 and B2 will be asserted upon interrupt handler entry and de-asserted before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 440 Hz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

EK-LM3S2965 Quickstart Application (qs_ek-lm3s2965)

A game in which a blob-like character tries to find its way out of a maze. The character starts in the middle of the maze and must find the exit, which will always be located at one of the four corners of the maze. Once the exit to the maze is located, the character is placed into the middle of a new maze and must find the exit to that maze; this repeats endlessly.

The game is started by pressing the select push button on the right side of the board. During game play, the select push button will fire a bullet in the direction the character is currently facing, and the navigation push buttons on the left side of the board will cause the character to walk in the corresponding direction.

Populating the maze are a hundred spinning stars that mindlessly attack the character. Contact with one of these stars results in the game ending, but the stars go away when shot.

Score is accumulated for shooting the stars and for finding the exit to the maze. The game lasts for only one character, and the score is displayed on the virtual UART at 115,200, 8-N-1 during game play and will be displayed on the screen at the end of the game.

If the CAN device board is attached and is running the can_device_qs application, the volume of the music and sound effects can be adjusted over CAN with the two push buttons on the target

board. The LED on the CAN device board will track the state of the LED on the main board via CAN messages. The operation of the game will not be affected by the absence of the CAN device board.

Since the OLED display on the evaluation board has burn-in characteristics similar to a CRT, the application also contains a screen saver. The screen saver will only become active if two minutes have passed without the user push button being pressed while waiting to start the game (that is, it will never come on during game play). Qix-style bouncing lines are drawn on the display by the screen saver.

After two minutes of running the screen saver, the display will be turned off and the user LED will blink. Either mode of screen saver (bouncing lines or blank display) will be exited by pressing the select push button. The select push button will then need to be pressed again to start the game.

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own indicator on the display.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (connected to the FTDI virtual serial port on the evaluation board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED is inverted so that it is easy to see that it is being fed, which occurs once every second.

39 EK-LM3S2965 Rev C Example Applications

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39.1 Introduction

The EK-LM3S2965 Rev C example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the RiTdisplay 128x96 4-bit gray-scale OLED graphical display on the Stellaris LM3S2965 Rev C Evaluation Kit boards.

These examples and display driver are for the EK-LM3S2965 Rev C boards, which utilize the 128x96 RiTdisplay display. The Rev C boards can be identified by looking on the back of the circuit board opposite the JTAG header. The board part number is located there and will end with an "C". If the board part number ends with a "A", then refer instead to the examples chapter for the [EK-LM3S2965 Example Applications](#).

There is an IAR workspace file (`ek-lm3s2965_rev.c.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`ek-lm3s2965_rev.c.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/ek-lm3s2965_rev.c` subdirectory of the peripheral driver library source distribution.

39.2 API Functions

Functions

- void [RIT128x96x4Clear](#) (void)
- void [RIT128x96x4Disable](#) (void)
- void [RIT128x96x4DisplayOff](#) (void)
- void [RIT128x96x4DisplayOn](#) (void)
- void [RIT128x96x4Enable](#) (unsigned long ulFrequency)
- void [RIT128x96x4ImageDraw](#) (const unsigned char *puclImage, unsigned long ulX, unsigned long ulY, unsigned long ulWidth, unsigned long ulHeight)
- void [RIT128x96x4Init](#) (unsigned long ulFrequency)
- void [RIT128x96x4StringDraw](#) (const char *pcStr, unsigned long ulX, unsigned long ulY, unsigned char ucLevel)

39.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

39.2.2 Function Documentation

39.2.2.1 RIT128x96x4Clear

Clears the OLED display.

Prototype:

```
void  
RIT128x96x4Clear(void)
```

Description:

This function will clear the display RAM. All pixels in the display will be turned off.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

39.2.2.2 RIT128x96x4Disable

Enable the SSI component of the OLED display driver.

Prototype:

```
void  
RIT128x96x4Disable(void)
```

Description:

This function initializes the SSI interface to the OLED display.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

39.2.2.3 RIT128x96x4DisplayOff

Turns off the OLED display.

Prototype:

```
void  
RIT128x96x4DisplayOff(void)
```


Description:

This function will turn off the OLED display. This will stop the scanning of the panel and turn off the on-chip DC-DC converter, preventing damage to the panel due to burn-in (it has similar characters to a CRT in this respect).

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

39.2.2.4 RIT128x96x4DisplayOn

Turns on the OLED display.

Prototype:

```
void  
RIT128x96x4DisplayOn(void)
```

Description:

This function will turn on the OLED display, causing it to display the contents of its internal frame buffer.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

39.2.2.5 RIT128x96x4Enable

Enable the SSI component of the OLED display driver.

Prototype:

```
void  
RIT128x96x4Enable(unsigned long ulFrequency)
```

Parameters:

ulFrequency specifies the SSI Clock Frequency to be used.

Description:

This function initializes the SSI interface to the OLED display.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

39.2.2.6 RIT128x96x4ImageDraw

Displays an image on the OLED display.

Prototype:

```
void
RIT128x96x4ImageDraw(const unsigned char *pucImage,
                      unsigned long ulX,
                      unsigned long ulY,
                      unsigned long ulWidth,
                      unsigned long ulHeight)
```

Parameters:

pucImage is a pointer to the image data.

ulX is the horizontal position to display this image, specified in columns from the left edge of the display.

ulY is the vertical position to display this image, specified in rows from the top of the display.

ulWidth is the width of the image, specified in columns.

ulHeight is the height of the image, specified in rows.

Description:

This function will display a bitmap graphic on the display. Because of the format of the display RAM, the starting column (*ulX*) and the number of columns (*ulWidth*) must be an integer multiple of two.

The image data is organized with the first row of image data appearing left to right, followed immediately by the second row of image data. Each byte contains the data for two columns in the current row, with the leftmost column being contained in bits 7:4 and the rightmost column being contained in bits 3:0.

For example, an image six columns wide and seven scan lines tall would be arranged as follows (showing how the twenty one bytes of the image would appear on the display):

+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
Byte 0	Byte 1	Byte 2		Byte 3	Byte 4	Byte 5
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
Byte 6	Byte 7	Byte 8		Byte 9	Byte 10	Byte 11
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
Byte 12	Byte 13	Byte 14		Byte 15	Byte 16	Byte 17
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
Byte 18	Byte 19	Byte 20				
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+

```

+-----+-----+-----+-----+-----+-----+
| 7 6 5 4 | 3 2 1 0 | 7 6 5 4 | 3 2 1 0 | 7 6 5 4 | 3 2 1 0 |
+-----+-----+-----+-----+-----+-----+

```

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

39.2.2.7 RIT128x96x4Init

Initialize the OLED display.

Prototype:

```

void
RIT128x96x4Init(unsigned long ulFrequency)

```

Parameters:

ulFrequency specifies the SSI Clock Frequency to be used.

Description:

This function initializes the SSI interface to the OLED display and configures the SSD1329 controller on the panel.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

39.2.2.8 RIT128x96x4StringDraw

Displays a string on the OLED display.

Prototype:

```

void
RIT128x96x4StringDraw(const char *pcStr,
                      unsigned long ulX,
                      unsigned long ulY,
                      unsigned char ucLevel)

```

Parameters:

pcStr is a pointer to the string to display.

ulX is the horizontal position to display the string, specified in columns from the left edge of the display.

ulY is the vertical position to display the string, specified in rows from the top edge of the display.

ucLevel is the 4-bit gray scale value to be used for displayed text.

Description:

This function will draw a string on the display. Only the ASCII characters between 32 (space) and 126 (tilde) are supported; other characters will result in random data being drawn on the display (based on whatever appears before/after the font in memory). The font is mono-spaced, so characters such as “i” and “l” have more white space around them than characters such as “m” or “w”.

If the drawing of the string reaches the right edge of the display, no more characters will be drawn. Therefore, special care is not required to avoid supplying a string that is “too long” to display.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Note:

Because the OLED display packs 2 pixels of data in a single byte, the parameter *uIX* must be an even column number (for example, 0, 2, 4, and so on).

Returns:

None.

39.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The `boot_demo2` application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

CAN Device Board LED Application (can_device_led)

This simple application uses the two buttons on the board as a light switch. When the “up” button is pressed the status LED will turn on. When the “down” button is pressed, the status LED will turn off.

CAN Device Board Quickstart Application (can_device_qs)

This application uses the CAN controller to communicate with the evaluation board that is running the example game. It receives messages over CAN to turn on, turn off, or to pulse the LED on the device board. It also sends CAN messages when either of the up and down buttons are pressed or released.

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the select push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO.

Graphics Example (graphics)

A simple application that displays scrolling text on the top line of the OLED display, along with a 4-bit gray scale image.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the OLED and is a starting point for more complicated applications.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the OLED; GPIO pins B0, B1 and B2 will be asserted upon interrupt handler entry and de-asserted before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 440 Hz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

EK-LM3S2965 Rev C Quickstart Application (qs_ek-lm3s2965_revc)

A game in which a blob-like character tries to find its way out of a maze. The character starts in the middle of the maze and must find the exit, which will always be located at one of the four corners of the maze. Once the exit to the maze is located, the character is placed into the middle of a new maze and must find the exit to that maze; this repeats endlessly.

The game is started by pressing the select push button on the right side of the board. During game play, the select push button will fire a bullet in the direction the character is currently facing, and the navigation push buttons on the left side of the board will cause the character to walk in the corresponding direction.

Populating the maze are a hundred spinning stars that mindlessly attack the character. Contact with one of these stars results in the game ending, but the stars go away when shot.

Score is accumulated for shooting the stars and for finding the exit to the maze. The game lasts for only one character, and the score is displayed on the virtual UART at 115,200, 8-N-1 during game play and will be displayed on the screen at the end of the game.

If the CAN device board is attached and is running the can_device_qs application, the volume of the music and sound effects can be adjusted over CAN with the two push buttons on the target

board. The LED on the CAN device board will track the state of the LED on the main board via CAN messages. The operation of the game will not be affected by the absence of the CAN device board.

Since the OLED display on the evaluation board has burn-in characteristics similar to a CRT, the application also contains a screen saver. The screen saver will only become active if two minutes have passed without the user push button being pressed while waiting to start the game (that is, it will never come on during game play). Qix-style bouncing lines are drawn on the display by the screen saver.

After two minutes of running the screen saver, the display will be turned off and the user LED will blink. Either mode of screen saver (bouncing lines or blank display) will be exited by pressing the select push button. The select push button will then need to be pressed again to start the game.

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own indicator on the display.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (connected to the FTDI virtual serial port on the evaluation board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED is inverted so that it is easy to see that it is being fed, which occurs once every second.

40 EK-LM3S6965 Example Applications

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40.1 Introduction

The EK-LM3S6965 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the OSRAM 128x64 4-bit gray-scale OLED graphical display on the Stellaris LM3S6965 Evaluation Kit boards.

These examples and display driver are for the EK-LM3S6965 Rev A boards, which utilize the 128x64 OSRAM display. The Rev A boards can be identified by looking on the back of the circuit board opposite the JTAG header. The board part number is located there and will end with an "A". If the board part number ends with a "C", then refer instead to the examples chapter for the [EK-LM3S6965 Rev C Example Applications](#).

There is an IAR workspace file (`ek-lm3s6965.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`ek-lm3s6965.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/ek-lm3s6965` subdirectory of the peripheral driver library source distribution.

40.2 API Functions

Functions

- void [OSRAM128x64x4Clear](#) (void)
- void [OSRAM128x64x4Disable](#) (void)
- void [OSRAM128x64x4DisplayOff](#) (void)
- void [OSRAM128x64x4DisplayOn](#) (void)
- void [OSRAM128x64x4Enable](#) (unsigned long ulFrequency)
- void [OSRAM128x64x4ImageDraw](#) (const unsigned char *puclImage, unsigned long ulX, unsigned long ulY, unsigned long ulWidth, unsigned long ulHeight)
- void [OSRAM128x64x4Init](#) (unsigned long ulFrequency)
- void [OSRAM128x64x4StringDraw](#) (const char *pcStr, unsigned long ulX, unsigned long ulY, unsigned char ucLevel)

40.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

40.2.2 Function Documentation

40.2.2.1 OSRAM128x64x4Clear

Clears the OLED display.

Prototype:

```
void  
OSRAM128x64x4Clear(void)
```

Description:

This function will clear the display RAM. All pixels in the display will be turned off.

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

40.2.2.2 OSRAM128x64x4Disable

Enable the SSI component of the OLED display driver.

Prototype:

```
void  
OSRAM128x64x4Disable(void)
```

Description:

This function initializes the SSI interface to the OLED display.

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

40.2.2.3 OSRAM128x64x4DisplayOff

Turns off the OLED display.

Prototype:

```
void  
OSRAM128x64x4DisplayOff(void)
```

Description:

This function will turn off the OLED display. This will stop the scanning of the panel and turn off the on-chip DC-DC converter, preventing damage to the panel due to burn-in (it has similar characters to a CRT in this respect).

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

40.2.2.4 OSRAM128x64x4DisplayOn

Turns on the OLED display.

Prototype:

```
void  
OSRAM128x64x4DisplayOn(void)
```

Description:

This function will turn on the OLED display, causing it to display the contents of its internal frame buffer.

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

40.2.2.5 OSRAM128x64x4Enable

Enable the SSI component of the OLED display driver.

Prototype:

```
void  
OSRAM128x64x4Enable(unsigned long ulFrequency)
```

Parameters:

ulFrequency specifies the SSI Clock Frequency to be used.

Description:

This function initializes the SSI interface to the OLED display.

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

40.2.2.6 OSRAM128x64x4ImageDraw

Displays an image on the OLED display.

Prototype:

```
void
OSRAM128x64x4ImageDraw(const unsigned char *pucImage,
                        unsigned long ulX,
                        unsigned long ulY,
                        unsigned long ulWidth,
                        unsigned long ulHeight)
```

Parameters:

pucImage is a pointer to the image data.

ulX is the horizontal position to display this image, specified in columns from the left edge of the display.

ulY is the vertical position to display this image, specified in rows from the top of the display.

ulWidth is the width of the image, specified in columns.

ulHeight is the height of the image, specified in rows.

Description:

This function will display a bitmap graphic on the display. Because of the format of the display RAM, the starting column (*ulX*) and the number of columns (*ulWidth*) must be an integer multiple of two.

The image data is organized with the first row of image data appearing left to right, followed immediately by the second row of image data. Each byte contains the data for two columns in the current row, with the leftmost column being contained in bits 7:4 and the rightmost column being contained in bits 3:0.

For example, an image six columns wide and seven scan lines tall would be arranged as follows (showing how the twenty one bytes of the image would appear on the display):

+-----+-----+-----+						
	Byte 0		Byte 1		Byte 2	
+-----+-----+-----+						
	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	
+-----+-----+-----+						
	Byte 3		Byte 4		Byte 5	
+-----+-----+-----+						
	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	
+-----+-----+-----+						
	Byte 6		Byte 7		Byte 8	
+-----+-----+-----+						
	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	
+-----+-----+-----+						
	Byte 9		Byte 10		Byte 11	
+-----+-----+-----+						
	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	
+-----+-----+-----+						
	Byte 12		Byte 13		Byte 14	
+-----+-----+-----+						
	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	
+-----+-----+-----+						
	Byte 15		Byte 16		Byte 17	
+-----+-----+-----+						
	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	
+-----+-----+-----+						
	Byte 18		Byte 19		Byte 20	

```
+-----+-----+-----+-----+-----+-----+
| 7 6 5 4 | 3 2 1 0 | 7 6 5 4 | 3 2 1 0 | 7 6 5 4 | 3 2 1 0 |
+-----+-----+-----+-----+-----+-----+
```

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

40.2.2.7 OSRAM128x64x4Init

Initialize the OLED display.

Prototype:

```
void
OSRAM128x64x4Init(unsigned long ulFrequency)
```

Parameters:

ulFrequency specifies the SSI Clock Frequency to be used.

Description:

This function initializes the SSI interface to the OLED display and configures the SSD0323 controller on the panel.

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Returns:

None.

40.2.2.8 OSRAM128x64x4StringDraw

Displays a string on the OLED display.

Prototype:

```
void
OSRAM128x64x4StringDraw(const char *pcStr,
                        unsigned long ulX,
                        unsigned long ulY,
                        unsigned char ucLevel)
```

Parameters:

pcStr is a pointer to the string to display.

ulX is the horizontal position to display the string, specified in columns from the left edge of the display.

ulY is the vertical position to display the string, specified in rows from the top edge of the display.

ucLevel is the 4-bit gray scale value to be used for displayed text.

Description:

This function will draw a string on the display. Only the ASCII characters between 32 (space) and 126 (tilde) are supported; other characters will result in random data being drawn on the display (based on whatever appears before/after the font in memory). The font is mono-spaced, so characters such as “i” and “l” have more white space around them than characters such as “m” or “w”.

If the drawing of the string reaches the right edge of the display, no more characters will be drawn. Therefore, special care is not required to avoid supplying a string that is “too long” to display.

This function is contained in `osram128x64x4.c`, with `osram128x64x4.h` containing the API definition for use by applications.

Note:

Because the OLED display packs 2 pixels of data in a single byte, the parameter *uIX* must be an even column number (for example, 0, 2, 4, and so on).

Returns:

None.

40.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The `boot_demo2` application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Ethernet with lwIP (enet_lwip)

This example application demonstrates the operation of the Stellaris Ethernet controller using the lwIP TCP/IP Stack. DHCP is used to obtain an Ethernet address. If DHCP times out without obtaining an address, a static IP address will be used. The DHCP timeout and the default static IP are easily configurable using macros. The address that is selected will be shown on the OLED display.

The file system code will first check to see if an SD card has been plugged into the microSD slot. If so, all file requests from the web server will be directed to the SD card. Otherwise, a default set of pages served up by an internal file system will be used.

For additional details on lwIP, refer to the lwIP web page at:
<http://www.sics.se/~adam/lwip/>

Ethernet IEEE 1588 (PTPd) with lwIP (enet_ptpd)

This example application demonstrates the operation of the Stellaris Ethernet controller using the lwIP TCP/IP Stack. DHCP is used to obtain an Ethernet address. If DHCP times out without obtaining an address, a static IP address will be used. The DHCP timeout and the default static IP are easily configurable using macros. The address that is selected will be shown on the OLED display.

A default set of pages will be served up by an internal file system and the httpd server.

The IEEE 1588 (PTP) software has been enabled in this code to synchronize the internal clock to a network master clock source.

For additional details on lwIP, refer to the lwIP web page at:
<http://www.sics.se/~adam/lwip/>

For additional details on the PTPd software, refer to the PTPd web page at:
<http://ptpd.sourceforge.net>

Ethernet with uIP (enet_uip)

This example application demonstrates the operation of the Stellaris Ethernet controller using the uIP TCP/IP Stack. A basic web site is served over the Ethernet port, located at link local address

169.254.19.63. If a node on the network has already chosen this link local address, nothing is done by the application to choose another address and a conflict will occur. The web site displays a few lines of text, and a counter that increments each time the page is sent.

For additional details on uIP, refer to the uIP web page at: <http://www.sics.se/~adam/uip/>

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the select push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO.

Graphics Example (graphics)

A simple application that displays scrolling text on the top line of the OLED display, along with a 4-bit gray scale image.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the OLED and is a starting point for more complicated applications.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the OLED; GPIO pins B0, B1 and B2 will be asserted upon interrupt handler entry and de-asserted before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 440 Hz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

EK-LM3S6965 Quickstart Application (qs_ek-lm3s6965)

A game in which a blob-like character tries to find its way out of a maze. The character starts in the middle of the maze and must find the exit, which will always be located at one of the four corners of the maze. Once the exit to the maze is located, the character is placed into the middle of a new maze and must find the exit to that maze; this repeats endlessly.

The game is started by pressing the select push button on the right side of the board. During game play, the select push button will fire a bullet in the direction the character is currently facing, and the navigation push buttons on the left side of the board will cause the character to walk in the corresponding direction.

Populating the maze are a hundred spinning stars that mindlessly attack the character. Contact with one of these stars results in the game ending, but the stars go away when shot.

Score is accumulated for shooting the stars and for finding the exit to the maze. The game lasts for only one character, and the score is displayed on the virtual UART at 115,200, 8-N-1 during game play and will be displayed on the screen at the end of the game.

A small web site is provided by the game over the Ethernet port. DHCP is used to obtain an Ethernet address. If DHCP times out without obtaining an address, a static IP address will be used. The DHCP timeout and the default static IP are easily configurable using macros. The address that is selected will be shown on the OLED display before the game starts. The web pages allow the entire game maze to be viewed, along with the character and stars; the display is generated by a Java applet that is downloaded from the game (therefore requiring that Java be installed in the web browser). The volume of the game music and sound effects can also be adjusted.

Since the OLED display on the evaluation board has burn-in characteristics similar to a CRT, the application also contains a screen saver. The screen saver will only become active if two minutes have passed without the user push button being pressed while waiting to start the game (that is, it will never come on during game play). Qix-style bouncing lines are drawn on the display by the screen saver.

After two minutes of running the screen saver, the display will be turned off and the user LED will blink. Either mode of screen saver (bouncing lines or blank display) will be exited by pressing the select push button. The select push button will then need to be pressed again to start the game.

SD card using FAT file system (sd_card)

This example application demonstrates reading a file system from an SD card. It makes use of FatFs, a FAT file system driver. It provides a simple command console via a serial port for issuing commands to view and navigate the file system on the SD card.

The first UART, which is connected to the FTDI virtual serial port on the Stellaris LM3S6965 Evaluation Board, is configured for 115,200 bits per second, and 8-n-1 mode. When the program is started a message will be printed to the terminal. Type "help" for command help.

For additional details about FatFs, see the following site:
http://elm-chan.org/fsw/ff/00index_e.html

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own indicator on the display.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (connected to the FTDI virtual serial port on the evaluation board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED is inverted so that it is easy to see that it is being fed, which occurs once every second.

41 EK-LM3S6965 Rev C Example Applications

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41.1 Introduction

The EK-LM3S6965 Rev C example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the RiTdisplay 128x96 4-bit gray-scale OLED graphical display on the Stellaris LM3S6965 Rev C Evaluation Kit boards.

These examples and display driver are for the EK-LM3S6965 Rev C boards, which utilize the 128x96 RiTdisplay display. The Rev C boards can be identified by looking on the back of the circuit board opposite the JTAG header. The board part number is located there and will end with an "C". If the board part number ends with a "A", then refer instead to the examples chapter for the [EK-LM3S6965 Example Applications](#).

There is an IAR workspace file (`ek-lm3s6965_rev.c.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`ek-lm3s6965_rev.c.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/ek-lm3s6965_rev.c` subdirectory of the peripheral driver library source distribution.

41.2 API Functions

Functions

- void [RIT128x96x4Clear](#) (void)
- void [RIT128x96x4Disable](#) (void)
- void [RIT128x96x4DisplayOff](#) (void)
- void [RIT128x96x4DisplayOn](#) (void)
- void [RIT128x96x4Enable](#) (unsigned long ulFrequency)
- void [RIT128x96x4ImageDraw](#) (const unsigned char *puclImage, unsigned long ulX, unsigned long ulY, unsigned long ulWidth, unsigned long ulHeight)
- void [RIT128x96x4Init](#) (unsigned long ulFrequency)
- void [RIT128x96x4StringDraw](#) (const char *pcStr, unsigned long ulX, unsigned long ulY, unsigned char ucLevel)

41.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

41.2.2 Function Documentation

41.2.2.1 RIT128x96x4Clear

Clears the OLED display.

Prototype:

```
void  
RIT128x96x4Clear(void)
```

Description:

This function will clear the display RAM. All pixels in the display will be turned off.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

41.2.2.2 RIT128x96x4Disable

Enable the SSI component of the OLED display driver.

Prototype:

```
void  
RIT128x96x4Disable(void)
```

Description:

This function initializes the SSI interface to the OLED display.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

41.2.2.3 RIT128x96x4DisplayOff

Turns off the OLED display.

Prototype:

```
void  
RIT128x96x4DisplayOff(void)
```

Description:

This function will turn off the OLED display. This will stop the scanning of the panel and turn off the on-chip DC-DC converter, preventing damage to the panel due to burn-in (it has similar characters to a CRT in this respect).

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

41.2.2.4 RIT128x96x4DisplayOn

Turns on the OLED display.

Prototype:

```
void  
RIT128x96x4DisplayOn(void)
```

Description:

This function will turn on the OLED display, causing it to display the contents of its internal frame buffer.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

41.2.2.5 RIT128x96x4Enable

Enable the SSI component of the OLED display driver.

Prototype:

```
void  
RIT128x96x4Enable(unsigned long ulFrequency)
```

Parameters:

ulFrequency specifies the SSI Clock Frequency to be used.

Description:

This function initializes the SSI interface to the OLED display.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

41.2.2.6 RIT128x96x4ImageDraw

Displays an image on the OLED display.

Prototype:

```
void
RIT128x96x4ImageDraw(const unsigned char *pucImage,
                      unsigned long ulX,
                      unsigned long ulY,
                      unsigned long ulWidth,
                      unsigned long ulHeight)
```

Parameters:

pucImage is a pointer to the image data.

ulX is the horizontal position to display this image, specified in columns from the left edge of the display.

ulY is the vertical position to display this image, specified in rows from the top of the display.

ulWidth is the width of the image, specified in columns.

ulHeight is the height of the image, specified in rows.

Description:

This function will display a bitmap graphic on the display. Because of the format of the display RAM, the starting column (*ulX*) and the number of columns (*ulWidth*) must be an integer multiple of two.

The image data is organized with the first row of image data appearing left to right, followed immediately by the second row of image data. Each byte contains the data for two columns in the current row, with the leftmost column being contained in bits 7:4 and the rightmost column being contained in bits 3:0.

For example, an image six columns wide and seven scan lines tall would be arranged as follows (showing how the twenty one bytes of the image would appear on the display):

+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
Byte 0	Byte 1	Byte 2		Byte 3	Byte 4	Byte 5
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
Byte 6	Byte 7	Byte 8		Byte 9	Byte 10	Byte 11
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
Byte 12	Byte 13	Byte 14		Byte 15	Byte 16	Byte 17
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0		7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0	7 6 5 4 3 2 1 0
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+
Byte 18	Byte 19	Byte 20				
+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+		+-----+-----+-----+

```

+-----+-----+-----+-----+-----+-----+
| 7 6 5 4 | 3 2 1 0 | 7 6 5 4 | 3 2 1 0 | 7 6 5 4 | 3 2 1 0 |
+-----+-----+-----+-----+-----+-----+

```

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

41.2.2.7 RIT128x96x4Init

Initialize the OLED display.

Prototype:

```

void
RIT128x96x4Init(unsigned long ulFrequency)

```

Parameters:

ulFrequency specifies the SSI Clock Frequency to be used.

Description:

This function initializes the SSI interface to the OLED display and configures the SSD1329 controller on the panel.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

41.2.2.8 RIT128x96x4StringDraw

Displays a string on the OLED display.

Prototype:

```

void
RIT128x96x4StringDraw(const char *pcStr,
                      unsigned long ulX,
                      unsigned long ulY,
                      unsigned char ucLevel)

```

Parameters:

pcStr is a pointer to the string to display.

ulX is the horizontal position to display the string, specified in columns from the left edge of the display.

ulY is the vertical position to display the string, specified in rows from the top edge of the display.

ucLevel is the 4-bit gray scale value to be used for displayed text.

Description:

This function will draw a string on the display. Only the ASCII characters between 32 (space) and 126 (tilde) are supported; other characters will result in random data being drawn on the display (based on whatever appears before/after the font in memory). The font is mono-spaced, so characters such as “i” and “l” have more white space around them than characters such as “m” or “w”.

If the drawing of the string reaches the right edge of the display, no more characters will be drawn. Therefore, special care is not required to avoid supplying a string that is “too long” to display.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Note:

Because the OLED display packs 2 pixels of data in a single byte, the parameter *uIX* must be an even column number (for example, 0, 2, 4, and so on).

Returns:

None.

41.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The `boot_demo2` application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Ethernet with lwIP (enet_lwip)

This example application demonstrates the operation of the Stellaris Ethernet controller using the lwIP TCP/IP Stack. DHCP is used to obtain an Ethernet address. If DHCP times out without obtaining an address, a static IP address will be used. The DHCP timeout and the default static IP are easily configurable using macros. The address that is selected will be shown on the OLED display.

The file system code will first check to see if an SD card has been plugged into the microSD slot. If so, all file requests from the web server will be directed to the SD card. Otherwise, a default set of pages served up by an internal file system will be used.

For additional details on lwIP, refer to the lwIP web page at:
<http://www.sics.se/~adam/lwip/>

Ethernet IEEE 1588 (PTPd) with lwIP (enet_ptpd)

This example application demonstrates the operation of the Stellaris Ethernet controller using the lwIP TCP/IP Stack. DHCP is used to obtain an Ethernet address. If DHCP times out without obtaining an address, a static IP address will be used. The DHCP timeout and the default static IP are easily configurable using macros. The address that is selected will be shown on the OLED display.

A default set of pages will be served up by an internal file system and the httpd server.

The IEEE 1588 (PTP) software has been enabled in this code to synchronize the internal clock to a network master clock source.

For additional details on lwIP, refer to the lwIP web page at:
<http://www.sics.se/~adam/lwip/>

For additional details on the PTPd software, refer to the PTPd web page at:
<http://ptpd.sourceforge.net>

Ethernet with uIP (enet_uip)

This example application demonstrates the operation of the Stellaris Ethernet controller using the uIP TCP/IP Stack. A basic web site is served over the Ethernet port, located at link local address

169.254.19.63. If a node on the network has already chosen this link local address, nothing is done by the application to choose another address and a conflict will occur. The web site displays a few lines of text, and a counter that increments each time the page is sent.

For additional details on uIP, refer to the uIP web page at: <http://www.sics.se/~adam/uip/>

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the select push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO.

Graphics Example (graphics)

A simple application that displays scrolling text on the top line of the OLED display, along with a 4-bit gray scale image.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the OLED and is a starting point for more complicated applications.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the OLED; GPIO pins B0, B1 and B2 will be asserted upon interrupt handler entry and de-asserted before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 440 Hz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

EK-LM3S6965 Rev C Quickstart Application (qs_ek-lm3s6965_revC)

A game in which a blob-like character tries to find its way out of a maze. The character starts in the middle of the maze and must find the exit, which will always be located at one of the four corners of the maze. Once the exit to the maze is located, the character is placed into the middle of a new maze and must find the exit to that maze; this repeats endlessly.

The game is started by pressing the select push button on the right side of the board. During game play, the select push button will fire a bullet in the direction the character is currently facing, and the navigation push buttons on the left side of the board will cause the character to walk in the corresponding direction.

Populating the maze are a hundred spinning stars that mindlessly attack the character. Contact with one of these stars results in the game ending, but the stars go away when shot.

Score is accumulated for shooting the stars and for finding the exit to the maze. The game lasts for only one character, and the score is displayed on the virtual UART at 115,200, 8-N-1 during game play and will be displayed on the screen at the end of the game.

A small web site is provided by the game over the Ethernet port. DHCP is used to obtain an Ethernet address. If DHCP times out without obtaining an address, a static IP address will be used. The DHCP timeout and the default static IP are easily configurable using macros. The address that is selected will be shown on the OLED display before the game starts. The web pages allow the entire game maze to be viewed, along with the character and stars; the display is generated by a Java applet that is downloaded from the game (therefore requiring that Java be installed in the web browser). The volume of the game music and sound effects can also be adjusted.

Since the OLED display on the evaluation board has burn-in characteristics similar to a CRT, the application also contains a screen saver. The screen saver will only become active if two minutes have passed without the user push button being pressed while waiting to start the game (that is, it will never come on during game play). Qix-style bouncing lines are drawn on the display by the screen saver.

After two minutes of running the screen saver, the display will be turned off and the user LED will blink. Either mode of screen saver (bouncing lines or blank display) will be exited by pressing the select push button. The select push button will then need to be pressed again to start the game.

SD card using FAT file system (sd_card)

This example application demonstrates reading a file system from an SD card. It makes use of FatFs, a FAT file system driver. It provides a simple command console via a serial port for issuing commands to view and navigate the file system on the SD card.

The first UART, which is connected to the FTDI virtual serial port on the Stellaris LM3S6965 Evaluation Board, is configured for 115,200 bits per second, and 8-n-1 mode. When the program is started a message will be printed to the terminal. Type "help" for command help.

For additional details about FatFs, see the following site:
http://elm-chan.org/fsw/ff/00index_e.html

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own indicator on the display.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (connected to the FTDI virtual serial port on the evaluation board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED is inverted so that it is easy to see that it is being fed, which occurs once every second.

42 EK-LM3S811 Example Applications

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42.1 Introduction

The EK-LM3S811 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the OSRAM 96x16 OLED graphical display on the Stellaris LM3S811 Evaluation Kit board.

There is an IAR workspace file (`ek-lm3s811.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`ek-lm3s811.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/ek-lm3s811` subdirectory of the peripheral driver library source distribution.

42.2 API Functions

Functions

- void [OSRAM96x16x1Clear](#) (void)
- void [OSRAM96x16x1DisplayOff](#) (void)
- void [OSRAM96x16x1DisplayOn](#) (void)
- void [OSRAM96x16x1ImageDraw](#) (const unsigned char *puclImage, unsigned long ulX, unsigned long ulY, unsigned long ulWidth, unsigned long ulHeight)
- void [OSRAM96x16x1Init](#) (tBoolean bFast)
- void [OSRAM96x16x1StringDraw](#) (const char *pcStr, unsigned long ulX, unsigned long ulY)

42.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

There are macros to map the old function names for the OSRAM driver to the new function names (such as `OSRAMInit` to `OSRAM96x16x1Init`). The new names are more descriptive of the panel type in use; the macros for the old names are provided for backward compatibility.

42.2.2 Function Documentation

42.2.2.1 OSRAM96x16x1Clear

Clears the OLED display.

Prototype:

```
void  
OSRAM96x16x1Clear(void)
```

Description:

This function will clear the display. All pixels in the display will be turned off.

This function is contained in `osram96x16x1.c`, with `osram96x16x1.h` containing the API definition for use by applications.

Returns:

None.

42.2.2.2 OSRAM96x16x1DisplayOff

Turns off the OLED display.

Prototype:

```
void  
OSRAM96x16x1DisplayOff(void)
```

Description:

This function will turn off the OLED display. This will stop the scanning of the panel and turn off the on-chip DC-DC converter, preventing damage to the panel due to burn-in (it has similar characters to a CRT in this respect).

This function is contained in `osram96x16x1.c`, with `osram96x16x1.h` containing the API definition for use by applications.

Returns:

None.

42.2.2.3 OSRAM96x16x1DisplayOn

Turns on the OLED display.

Prototype:

```
void  
OSRAM96x16x1DisplayOn(void)
```

Description:

This function will turn on the OLED display, causing it to display the contents of its internal frame buffer.

This function is contained in `osram96x16x1.c`, with `osram96x16x1.h` containing the API definition for use by applications.

Returns:

None.

42.2.2.4 OSRAM96x16x1ImageDraw

Displays an image on the OLED display.

Prototype:

```
void
OSRAM96x16x1ImageDraw(const unsigned char *pucImage,
                        unsigned long ulX,
                        unsigned long ulY,
                        unsigned long ulWidth,
                        unsigned long ulHeight)
```

Parameters:***pucImage*** is a pointer to the image data.***ulX*** is the horizontal position to display this image, specified in columns from the left edge of the display.***ulY*** is the vertical position to display this image, specified in eight scan line blocks from the top of the display (that is, only 0 and 1 are valid).***ulWidth*** is the width of the image, specified in columns.***ulHeight*** is the height of the image, specified in eight row blocks (that is, only 1 and 2 are valid).**Description:**

This function will display a bitmap graphic on the display. The image to be displayed must be a multiple of eight scan lines high (that is, one row) and will be drawn at a vertical position that is a multiple of eight scan lines (that is, scan line zero or scan line eight, corresponding to row zero or row one).

The image data is organized with the first row of image data appearing left to right, followed immediately by the second row of image data. Each byte contains the data for the eight scan lines of the column, with the top scan line being in the least significant bit of the byte and the bottom scan line being in the most significant bit of the byte.

For example, an image four columns wide and sixteen scan lines tall would be arranged as follows (showing how the eight bytes of the image would appear on the display):

```
+-----+ +-----+ +-----+ +-----+
| 0 | 0 | 0 | 0 | | | | |
| B | 1 | B | 1 | B | 1 | B | 1 |
| y | 2 | y | 2 | y | 2 | y | 2 |
| t | 3 | t | 3 | t | 3 | t | 3 |
| e | 4 | e | 4 | e | 4 | e | 4 |
|   | 5 |   | 5 |   | 5 |   | 5 |
| 0 | 6 | 1 | 6 | 2 | 6 | 3 | 6 |
|   | 7 |   | 7 |   | 7 |   | 7 |
+-----+ +-----+ +-----+ +-----+

+-----+ +-----+ +-----+ +-----+
| 0 | 0 | 0 | 0 | | | | |
| B | 1 | B | 1 | B | 1 | B | 1 |
| y | 2 | y | 2 | y | 2 | y | 2 |
| t | 3 | t | 3 | t | 3 | t | 3 |
| e | 4 | e | 4 | e | 4 | e | 4 |
```

```

|   | 5 |   |   | 5 |   |   | 5 |   |   | 5 |
| 4 | 6 |   | 5 | 6 |   | 6 | 6 |   | 7 | 6 |
|   | 7 |   |   | 7 |   |   | 7 |   |   | 7 |
+-----+ +-----+ +-----+ +-----+

```

This function is contained in `osram96x16x1.c`, with `osram96x16x1.h` containing the API definition for use by applications.

Returns:

None.

42.2.2.5 OSRAM96x16x1Init

Initialize the OLED display.

Prototype:

```

void
OSRAM96x16x1Init(tBoolean bFast)

```

Parameters:

bFast is a boolean that is *true* if the I2C interface should be run at 400 kbps and *false* if it should be run at 100 kbps.

Description:

This function initializes the I2C interface to the OLED display and configures the SSD0303 controller on the panel.

This function is contained in `osram96x16x1.c`, with `osram96x16x1.h` containing the API definition for use by applications.

Returns:

None.

42.2.2.6 OSRAM96x16x1StringDraw

Displays a string on the OLED display.

Prototype:

```

void
OSRAM96x16x1StringDraw(const char *pcStr,
                        unsigned long ulX,
                        unsigned long ulY)

```

Parameters:

pcStr is a pointer to the string to display.

ulX is the horizontal position to display the string, specified in columns from the left edge of the display.

ulY is the vertical position to display the string, specified in eight scan line blocks from the top of the display (that is, only 0 and 1 are valid).

Description:

This function will draw a string on the display. Only the ASCII characters between 32 (space) and 126 (tilde) are supported; other characters will result in random data being drawn on the display (based on whatever appears before/after the font in memory). The font is mono-spaced, so characters such as “i” and “l” have more white space around them than characters such as “m” or “w”.

If the drawing of the string reaches the right edge of the display, no more characters will be drawn. Therefore, special care is not required to avoid supplying a string that is “too long” to display.

This function is contained in `osram96x16x1.c`, with `osram96x16x1.h` containing the API definition for use by applications.

Returns:

None.

42.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The `boot_demo2` application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the user push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO. Note that because of errata in Rev Bx and Rev C0 of Sandstorm-class Stellaris microcontrollers, JTAG and SWD will not function if PB7 is configured as a GPIO. This errata is fixed in Rev C2 of Sandstorm-class Stellaris microcontrollers.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the LCD and is a starting point for more complicated applications.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the LCD; GPIO pins D0 through D2 will be asserted upon interrupt handler entry and de-asserted before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 50 kHz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

EK-LM3S811 Quickstart Application (qs_ek-lm3s811)

A game in which a ship is navigated through an endless tunnel. The potentiometer is used to move the ship up and down, and the user push button is used to fire a missile to destroy obstacles in the tunnel. Score accumulates for survival and for destroying obstacles. The game lasts for only one ship; the score is displayed on the virtual UART at 115,200, 8-N-1 during game play and will be displayed on the screen at the end of the game.

Since the OLED display on the evaluation board has burn-in characteristics similar to a CRT, the application also contains a screen saver. The screen saver will only become active if two minutes have passed without the user push button being pressed while waiting to start the game (that is, it will never come on during game play). An implementation of the Game of Life is run with a field of random data as the seed value.

After two minutes of running the screen saver, the display will be turned off and the user LED will blink. Either mode of screen saver (Game of Life or blank display) will be exited by pressing the user push button. The button will then need to be pressed again to start the game.

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own indicator on the display.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (connected to the FTDI virtual serial port on the Stellaris LM3S811 Evaluation Board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED connected to port C5 is inverted so that it is easy to see that it is being fed, which occurs once every second.

43 EK-LM3S8962 Example Applications

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43.1 Introduction

The EK-LM3S8962 example applications show how to utilize features of the Cortex-M3 microprocessor, the peripherals on the Stellaris microcontroller, and the drivers provided by the peripheral driver library. These applications are intended for demonstration and as a starting point for new applications.

There is a board specific driver for the RiTdisplay 128x96 4-bit gray-scale OLED graphical display on the Stellaris LM3S8962 Evaluation Kit board.

There is an IAR workspace file (`ek-lm3s8962.eww`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with Embedded Workbench.

There is a Keil multi-project workspace file (`ek-lm3s8962.mpw`) that contains the peripheral driver library project, along with all of the board example projects, in a single, easy to use workspace for use with uVision.

All of these examples reside in the `boards/ek-lm3s8962` subdirectory of the peripheral driver library source distribution.

43.2 API Functions

Functions

- void [RIT128x96x4Clear](#) (void)
- void [RIT128x96x4Disable](#) (void)
- void [RIT128x96x4DisplayOff](#) (void)
- void [RIT128x96x4DisplayOn](#) (void)
- void [RIT128x96x4Enable](#) (unsigned long ulFrequency)
- void [RIT128x96x4ImageDraw](#) (const unsigned char *puclImage, unsigned long ulX, unsigned long ulY, unsigned long ulWidth, unsigned long ulHeight)
- void [RIT128x96x4Init](#) (unsigned long ulFrequency)
- void [RIT128x96x4StringDraw](#) (const char *pcStr, unsigned long ulX, unsigned long ulY, unsigned char ucLevel)

43.2.1 Detailed Description

Each API specifies the source file that contains it and the header file that provides the prototype for application use.

43.2.2 Function Documentation

43.2.2.1 RIT128x96x4Clear

Clears the OLED display.

Prototype:

```
void  
RIT128x96x4Clear(void)
```

Description:

This function will clear the display RAM. All pixels in the display will be turned off.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

43.2.2.2 RIT128x96x4Disable

Enable the SSI component of the OLED display driver.

Prototype:

```
void  
RIT128x96x4Disable(void)
```

Description:

This function initializes the SSI interface to the OLED display.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

43.2.2.3 RIT128x96x4DisplayOff

Turns off the OLED display.

Prototype:

```
void  
RIT128x96x4DisplayOff(void)
```

Description:

This function will turn off the OLED display. This will stop the scanning of the panel and turn off the on-chip DC-DC converter, preventing damage to the panel due to burn-in (it has similar characters to a CRT in this respect).

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

43.2.2.4 RIT128x96x4DisplayOn

Turns on the OLED display.

Prototype:

```
void  
RIT128x96x4DisplayOn(void)
```

Description:

This function will turn on the OLED display, causing it to display the contents of its internal frame buffer.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

43.2.2.5 RIT128x96x4Enable

Enable the SSI component of the OLED display driver.

Prototype:

```
void  
RIT128x96x4Enable(unsigned long ulFrequency)
```

Parameters:

ulFrequency specifies the SSI Clock Frequency to be used.

Description:

This function initializes the SSI interface to the OLED display.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

43.2.2.6 RIT128x96x4ImageDraw

Displays an image on the OLED display.

Prototype:

```
void  
RIT128x96x4ImageDraw(const unsigned char *pucImage,  
                      unsigned long ulX,  
                      unsigned long ulY,
```

```
unsigned long ulWidth,  
unsigned long ulHeight)
```

Parameters:

pucImage is a pointer to the image data.

ulX is the horizontal position to display this image, specified in columns from the left edge of the display.

ulY is the vertical position to display this image, specified in rows from the top of the display.

ulWidth is the width of the image, specified in columns.

ulHeight is the height of the image, specified in rows.

Description:

This function will display a bitmap graphic on the display. Because of the format of the display RAM, the starting column (*ulX*) and the number of columns (*ulWidth*) must be an integer multiple of two.

The image data is organized with the first row of image data appearing left to right, followed immediately by the second row of image data. Each byte contains the data for two columns in the current row, with the leftmost column being contained in bits 7:4 and the rightmost column being contained in bits 3:0.

For example, an image six columns wide and seven scan lines tall would be arranged as follows (showing how the twenty one bytes of the image would appear on the display):

+-----+				+-----+				+-----+				+-----+			
Byte 0				Byte 1				Byte 2							
+-----+				+-----+				+-----+				+-----+			
7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0							
+-----+				+-----+				+-----+				+-----+			
Byte 3				Byte 4				Byte 5							
+-----+				+-----+				+-----+				+-----+			
7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0							
+-----+				+-----+				+-----+				+-----+			
Byte 6				Byte 7				Byte 8							
+-----+				+-----+				+-----+				+-----+			
7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0							
+-----+				+-----+				+-----+				+-----+			
Byte 9				Byte 10				Byte 11							
+-----+				+-----+				+-----+				+-----+			
7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0							
+-----+				+-----+				+-----+				+-----+			
Byte 12				Byte 13				Byte 14							
+-----+				+-----+				+-----+				+-----+			
7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0							
+-----+				+-----+				+-----+				+-----+			
Byte 15				Byte 16				Byte 17							
+-----+				+-----+				+-----+				+-----+			
7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0							
+-----+				+-----+				+-----+				+-----+			
Byte 18				Byte 19				Byte 20							
+-----+				+-----+				+-----+				+-----+			
7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0				7 6 5 4 3 2 1 0							
+-----+				+-----+				+-----+				+-----+			

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

43.2.2.7 RIT128x96x4Init

Initialize the OLED display.

Prototype:

```
void  
RIT128x96x4Init(unsigned long ulFrequency)
```

Parameters:

ulFrequency specifies the SSI Clock Frequency to be used.

Description:

This function initializes the SSI interface to the OLED display and configures the SSD1329 controller on the panel.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Returns:

None.

43.2.2.8 RIT128x96x4StringDraw

Displays a string on the OLED display.

Prototype:

```
void  
RIT128x96x4StringDraw(const char *pcStr,  
                        unsigned long ulX,  
                        unsigned long ulY,  
                        unsigned char ucLevel)
```

Parameters:

pcStr is a pointer to the string to display.

ulX is the horizontal position to display the string, specified in columns from the left edge of the display.

ulY is the vertical position to display the string, specified in rows from the top edge of the display.

ucLevel is the 4-bit gray scale value to be used for displayed text.

Description:

This function will draw a string on the display. Only the ASCII characters between 32 (space) and 126 (tilde) are supported; other characters will result in random data being drawn on the display (based on whatever appears before/after the font in memory). The font is mono-spaced, so characters such as “i” and “l” have more white space around them than characters such as “m” or “w”.

If the drawing of the string reaches the right edge of the display, no more characters will be drawn. Therefore, special care is not required to avoid supplying a string that is “too long” to display.

This function is contained in `rit128x96x4.c`, with `rit128x96x4.h` containing the API definition for use by applications.

Note:

Because the OLED display packs 2 pixels of data in a single byte, the parameter *u/X* must be an even column number (for example, 0, 2, 4, and so on).

Returns:

None.

43.3 Examples

Bit-Banding (bitband)

This example application demonstrates the use of the bit-banding capabilities of the Cortex-M3 microprocessor. All of SRAM and all of the peripherals reside within bit-band regions, meaning that bit-banding operations can be applied to any of them. In this example, a variable in SRAM is set to a particular value one bit at a time using bit-banding operations (it would be more efficient to do a single non-bit-banded write; this simply demonstrates the operation of bit-banding).

Blinky (blinky)

A very simple example that blinks the on-board LED.

Boot Loader Demo 1 (boot_demo1)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART and branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo2 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

Boot Loader Demo 2 (boot_demo2)

An example to demonstrate the use of the boot loader. After being started by the boot loader, the application will configure the UART, wait for select button to be pressed, and then branch back to the boot loader to await the start of an update. The UART will always be configured at 115,200 baud and does not require the use of auto-bauding.

Both the boot loader and the application must be placed into flash. Once the boot loader is in flash, it can be used to program the application into flash as well. Then, the boot loader can be used to replace the application with another.

The boot_demo1 application can be used along with this application to easily demonstrate that the boot loader is actually updating the on-chip flash.

CAN Device Board LED Application (can_device_led)

This simple application uses the two buttons on the board as a light switch. When the “up” button is pressed the status LED will turn on. When the “down” button is pressed, the status LED will turn off.

CAN Device Board Quickstart Application (can_device_qs)

This application uses the CAN controller to communicate with the evaluation board that is running the example game. It receives messages over CAN to turn on, turn off, or to pulse the LED on the device board. It also sends CAN messages when either of the up and down buttons are pressed or released.

Ethernet with lwIP (enet_lwip)

This example application demonstrates the operation of the Stellaris Ethernet controller using the lwIP TCP/IP Stack. DHCP is used to obtain an Ethernet address. If DHCP times out without obtaining an address, a static IP address will be used. The DHCP timeout and the default static IP are easily configurable using macros. The address that is selected will be shown on the OLED display.

The file system code will first check to see if an SD card has been plugged into the microSD slot. If so, all file requests from the web server will be directed to the SD card. Otherwise, a default set of pages served up by an internal file system will be used.

For additional details on lwIP, refer to the lwIP web page at:
<http://www.sics.se/~adam/lwip/>

Ethernet IEEE 1588 (PTPd) with lwIP (enet_ptpd)

This example application demonstrates the operation of the Stellaris Ethernet controller using the lwIP TCP/IP Stack. DHCP is used to obtain an Ethernet address. If DHCP times out without obtaining an address, a static IP address will be used. The DHCP timeout and the default static IP are easily configurable using macros. The address that is selected will be shown on the OLED display.

A default set of pages will be served up by an internal file system and the httpd server.

The IEEE 1588 (PTP) software has been enabled in this code to synchronize the internal clock to a network master clock source.

Two methods of receive packet timestamping are implemented. The default mode uses the Stellaris hardware timestamp mechanism to capture Ethernet packet reception time using timer 3B. On parts which do not support hardware timestamping or if the application is started up with the Evaluation Kit "Select" button pressed, software time stamping is used.

For additional details on lwIP, refer to the lwIP web page at:
<http://www.sics.se/~adam/lwip/>

For additional details on the PTPd software, refer to the PTPd web page at:
<http://ptpd.sourceforge.net>

Ethernet with uIP (enet_uip)

This example application demonstrates the operation of the Stellaris Ethernet controller using the uIP TCP/IP Stack. A basic web site is served over the Ethernet port, located at link local address 169.254.19.63. If a node on the network has already chosen this link local address, nothing is done by the application to choose another address and a conflict will occur. The web site displays a few lines of text, and a counter that increments each time the page is sent.

For additional details on uIP, refer to the uIP web page at: <http://www.sics.se/~adam/uip/>

GPIO JTAG Recovery (gpio_jtag)

This example demonstrates changing the JTAG pins into GPIOs, along with a mechanism to revert them to JTAG pins. When first run, the pins remain in JTAG mode. Pressing the select push button will toggle the pins between JTAG mode and GPIO mode. Because there is no debouncing of the push button (either in hardware or software), a button press will occasionally result in more than one mode change.

In this example, all five pins (PB7, PC0, PC1, PC2, and PC3) are switched, though the more typical use would be to change PB7 into a GPIO.

Graphics Example (graphics)

A simple application that displays scrolling text on the top line of the OLED display, along with a 4-bit gray scale image.

Hello World (hello)

A very simple “hello world” example. It simply displays “hello world” on the OLED and is a starting point for more complicated applications.

Interrupts (interrupts)

This example application demonstrates the interrupt preemption and tail-chaining capabilities of Cortex-M3 microprocessor and NVIC. Nested interrupts are synthesized when the interrupts have the same priority, increasing priorities, and decreasing priorities. With increasing priorities, preemption will occur; in the other two cases tail-chaining will occur. The currently pending interrupts and the currently executing interrupt will be displayed on the OLED; GPIO pins B0, B1 and B2 will be asserted upon interrupt handler entry and de-asserted before interrupt handler exit so that the off-to-on time can be observed with a scope or logic analyzer to see the speed of tail-chaining (for the two cases where tail-chaining is occurring).

MPU (mpu_fault)

This example application demonstrates the use of the MPU to protect a region of memory from access, and to generate a memory management fault when there is an access violation.

PWM (pwmgen)

This example application utilizes the PWM peripheral to output a 25% duty cycle PWM signal and a 75% duty cycle PWM signal, both at 440 Hz. Once configured, the application enters an infinite loop, doing nothing while the PWM peripheral continues to output its signals.

EK-LM3S8962 Quickstart Application (qs_ek-lm3s8962)

A game in which a blob-like character tries to find its way out of a maze. The character starts in the middle of the maze and must find the exit, which will always be located at one of the four corners of the maze. Once the exit to the maze is located, the character is placed into the middle of a new maze and must find the exit to that maze; this repeats endlessly.

The game is started by pressing the select push button on the right side of the board. During game play, the select push button will fire a bullet in the direction the character is currently facing, and the navigation push buttons on the left side of the board will cause the character to walk in the corresponding direction.

Populating the maze are a hundred spinning stars that mindlessly attack the character. Contact with one of these stars results in the game ending, but the stars go away when shot.

Score is accumulated for shooting the stars and for finding the exit to the maze. The game lasts for only one character, and the score is displayed on the virtual UART at 115,200, 8-N-1 during game play and will be displayed on the screen at the end of the game.

A small web site is provided by the game over the Ethernet port. DHCP is used to obtain an Ethernet address. If DHCP times out without obtaining an address, a static IP address will be used. The DHCP timeout and the default static IP are easily configurable using macros. The address that is selected will be shown on the OLED display before the game starts. The web pages allow the entire game maze to be viewed, along with the character and stars; the display is generated by a Java applet that is downloaded from the game (therefore requiring that Java be installed in the web browser). The volume of the game music and sound effects can also be adjusted.

If the CAN device board is attached and is running the `can_device_qs` application, the volume of the music and sound effects can be adjusted over CAN with the two push buttons on the target board. The LED on the CAN device board will track the state of the LED on the main board via CAN messages. The operation of the game will not be affected by the absence of the CAN device board.

Since the OLED display on the evaluation board has burn-in characteristics similar to a CRT, the application also contains a screen saver. The screen saver will only become active if two minutes have passed without the user push button being pressed while waiting to start the game (that is, it will never come on during game play). Qix-style bouncing lines are drawn on the display by the screen saver.

After two minutes of running the screen saver, the display will be turned off and the user LED will blink. Either mode of screen saver (bouncing lines or blank display) will be exited by pressing the select push button. The select push button will then need to be pressed again to start the game.

SD card using FAT file system (sd_card)

This example application demonstrates reading a file system from an SD card. It makes use of FatFs, a FAT file system driver. It provides a simple command console via a serial port for issuing

commands to view and navigate the file system on the SD card.

The first UART, which is connected to the FTDI virtual serial port on the Stellaris LM3S6965 Evaluation Board, is configured for 115,200 bits per second, and 8-n-1 mode. When the program is started a message will be printed to the terminal. Type “help” for command help.

For additional details about FatFs, see the following site:
http://elm-chan.org/fsw/ff/00index_e.html

Timer (timers)

This example application demonstrates the use of the timers to generate periodic interrupts. One timer is set up to interrupt once per second and the other to interrupt twice per second; each interrupt handler will toggle its own indicator on the display.

UART (uart_echo)

This example application utilizes the UART to echo text. The first UART (connected to the FTDI virtual serial port on the evaluation board) will be configured in 115,200 baud, 8-n-1 mode. All characters received on the UART are transmitted back to the UART.

Watchdog (watchdog)

This example application demonstrates the use of the watchdog as a simple heartbeat for the system. If the watchdog is not periodically fed, it will reset the system. Each time the watchdog is fed, the LED is inverted so that it is easy to see that it is being fed, which occurs once every second.

Company Information

Founded in 2004, Luminary Micro, Inc. designs, markets, and sells ARM Cortex-M3-based microcontrollers (MCUs). Austin, Texas-based Luminary Micro is the lead partner for the Cortex-M3 processor, delivering the world's first silicon implementation of the Cortex-M3 processor. Luminary Micro's introduction of the Stellaris family of products provides 32-bit performance for the same price as current 8- and 16-bit microcontroller designs. With entry-level pricing at \$1.00 for an ARM technology-based MCU, Luminary Micro's Stellaris product line allows for standardization that eliminates future architectural upgrades or software tool changes.

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