



MCUXpresso SDK Documentation

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This documentation contains information specific to the frdmke15z board.

Chapter 1

FRDM-KE15Z

1.1 Overview

The FRDM-KE15Z Freedom Board is designed to work in standalone mode or as the main board of FRDM-TOUCH, FRDM-MC-LVBLDC, and Arduino boards. This Freedom board is compatible with DC 5v and 3.3v power supply, and features a KL15Z, a device boasting up to 256KB Flash and 32KB SRAM and numerous analog and digital peripherals. The on-board interfaces include an RGB LED, a 6-axis digital sensor, a 3-axis digital angular rate gyroscope, an ambient light sensor, and a capacitive touch slider.



MCU device and part on board is shown below:

- Device: MKE15Z7
- PartNumber: MKE15Z256VLL7

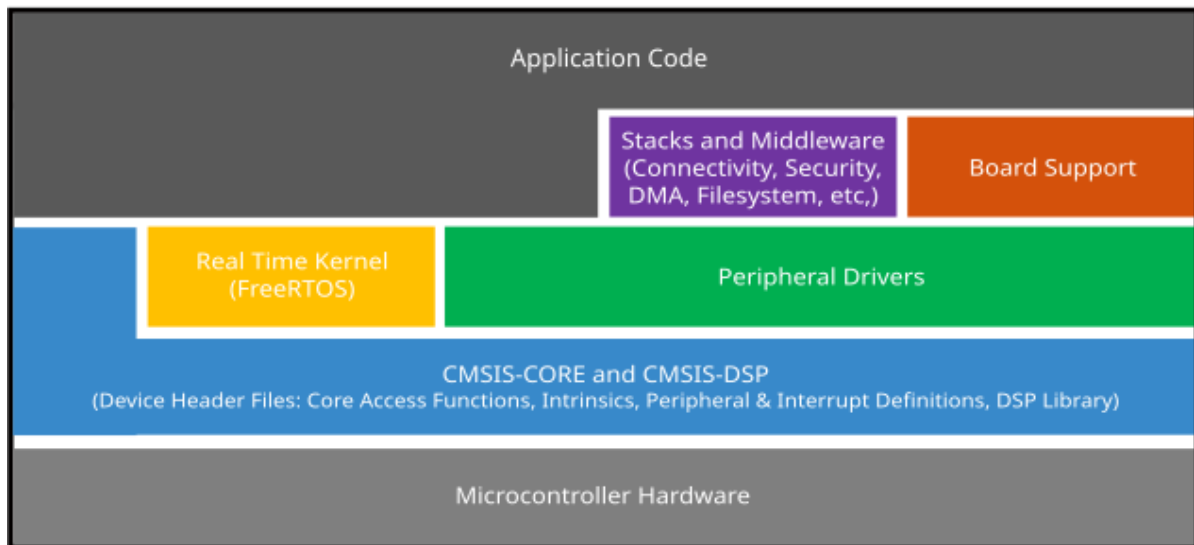
1.2 Getting Started with MCUXpresso SDK Package

1.2.1 Getting Started with MCUXpresso SDK Package

Overview

The NXP MCUXpresso software and tools offer comprehensive development solutions designed to optimize, ease, and help accelerate embedded system development of applications based on general purpose, crossover, and Bluetooth-enabled MCUs from NXP. The MCUXpresso SDK includes a flexible set of peripheral drivers designed to speed up and simplify development of embedded applications. Along with the peripheral drivers, the MCUXpresso SDK provides an extensive and rich set of example applications covering everything from basic peripheral use case examples to full demo applications. The MCUXpresso SDK contains optional RTOS integrations such as FreeRTOS and Azure RTOS, and various other middleware to support rapid development.

For supported toolchain versions, see *MCUXpresso SDK Release Notes* (document MCUXSDKRN).
 For more details about MCUXpresso SDK, see [MCUXpresso Software Development Kit \(SDK\)](#).



MCUXpresso SDK board support package folders

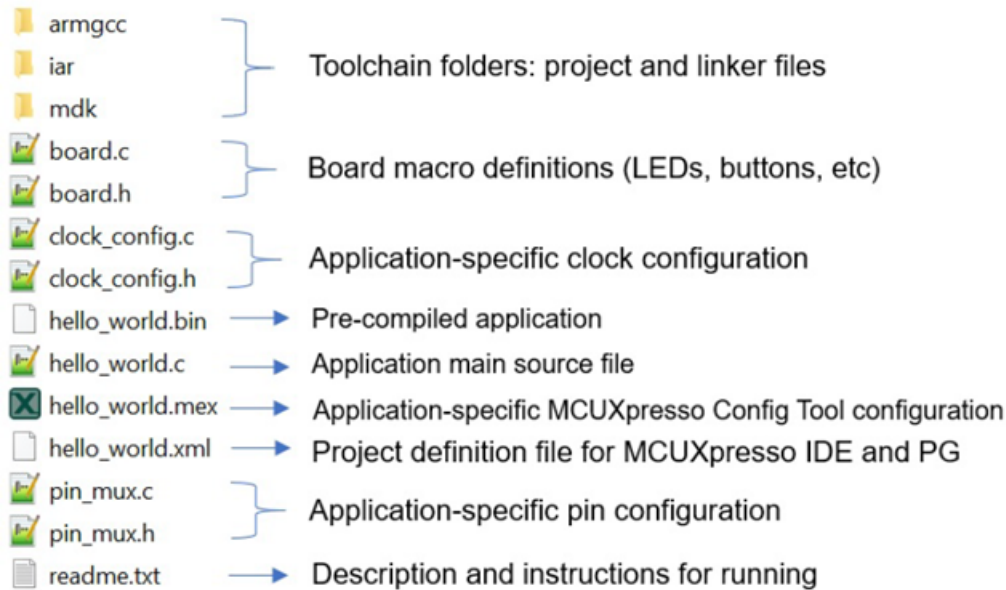
MCUXpresso SDK board support package provides example applications for NXP development and evaluation boards for Arm Cortex-M cores including Freedom, Tower System, and LPCXpresso boards. Board support packages are found inside the top-level boards folder and each supported board has its own folder (an MCUXpresso SDK package can support multiple boards). Within each `<board_name>` folder, there are various subfolders to classify the type of examples it contains. These include (but are not limited to):

- `cmsis_driver_examples`: Simple applications intended to show how to use CMSIS drivers.
- `demo_apps`: Full-featured applications that highlight key functionality and use cases of the target MCU. These applications typically use multiple MCU peripherals and may leverage stacks and middleware.
- `driver_examples`: Simple applications that show how to use the MCUXpresso SDK's peripheral drivers for a single use case. These applications typically only use a single peripheral but there are cases where multiple peripherals are used (for example, SPI conversion using DMA).
- `emwin_examples`: Applications that use the emWin GUI widgets.
- `rtos_examples`: Basic FreeRTOS OS examples that show the use of various RTOS objects (semaphores, queues, and so on) and interfaces with the MCUXpresso SDK's RTOS drivers
- `usb_examples`: Applications that use the USB host/device/OTG stack.

Example application structure This section describes how the various types of example applications interact with the other components in the MCUXpresso SDK. To get a comprehensive understanding of all MCUXpresso SDK components and folder structure, see *MCUXpresso SDK API Reference Manual*.

Each `<board_name>` folder in the boards directory contains a comprehensive set of examples that are relevant to that specific piece of hardware. Although we use the `hello_world` example (part of the `demo_apps` folder), the same general rules apply to any type of example in the `<board_name>` folder.

In the `hello_world` application folder you see the following contents:



All files in the application folder are specific to that example, so it is easy to copy and paste an existing example to start developing a custom application based on a project provided in the MCUXpresso SDK.

Locating example application source files When opening an example application in any of the supported IDEs, various source files are referenced. The MCUXpresso SDK devices folder is the central component to all example applications. It means that the examples reference the same source files and, if one of these files is modified, it could potentially impact the behavior of other examples.

The main areas of the MCUXpresso SDK tree used in all example applications are:

- `devices/<device_name>`: The device's CMSIS header file, MCUXpresso SDK feature file, and a few other files
- `devices/<device_name>/cmsis_drivers`: All the CMSIS drivers for your specific MCU
- `devices/<device_name>/drivers`: All of the peripheral drivers for your specific MCU
- `devices/<device_name>/<tool_name>`: Toolchain-specific startup code, including vector table definitions
- `devices/<device_name>/utilities`: Items such as the debug console that are used by many of the example applications
- `devices/<device_name>/project`: Project template used in CMSIS PACK new project creation

For examples containing middleware/stacks or an RTOS, there are references to the appropriate source code. Middleware source files are located in the `middleware` folder and RTOSes are in the `rtos` folder. The core files of each of these are shared, so modifying one could have potential impacts on other projects that depend on that file.

Run a demo using MCUXpresso IDE

Note: Ensure that the MCUXpresso IDE toolchain is included when generating the MCUXpresso SDK package.

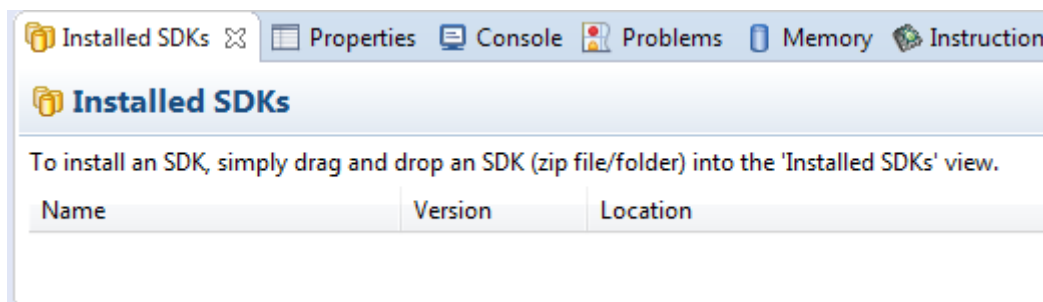
This section describes the steps required to configure MCUXpresso IDE to build, run, and debug example applications. The `hello_world` demo application targeted for the hardware platform is

used as an example, though these steps can be applied to any example application in the MCUXpresso SDK.

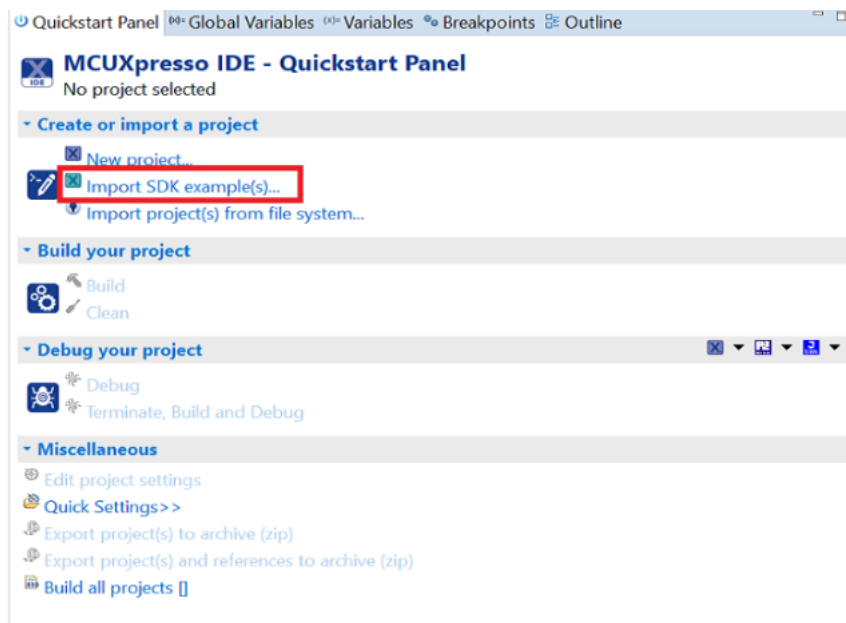
Select the workspace location Every time MCUXpresso IDE launches, it prompts the user to select a workspace location. MCUXpresso IDE is built on top of Eclipse which uses workspace to store information about its current configuration, and in some use cases, source files for the projects are in the workspace. The location of the workspace can be anywhere, but it is recommended that the workspace be located outside the MCUXpresso SDK tree.

Build an example application To build an example application, follow these steps.

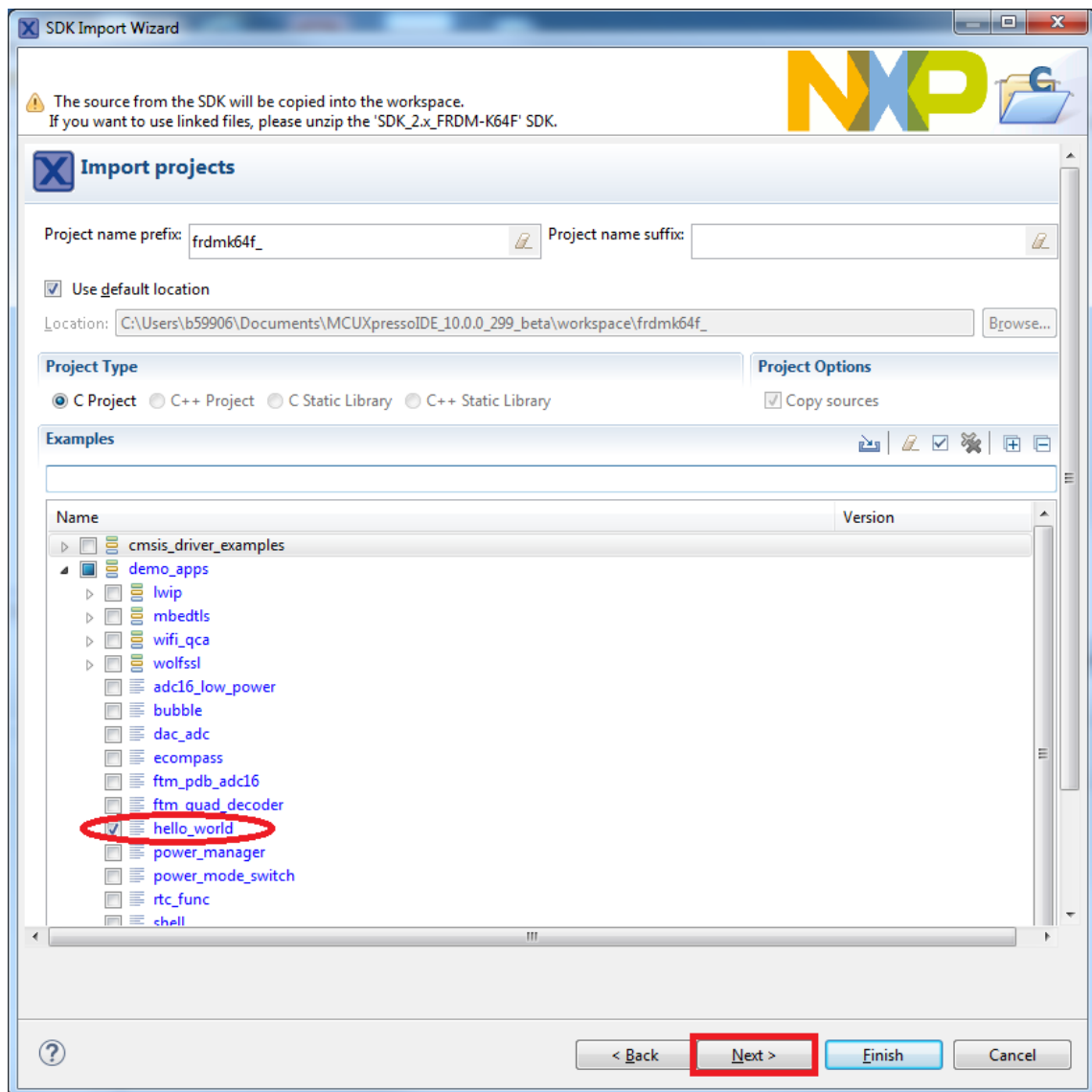
1. Drag and drop the SDK zip file into the **Installed SDKs** view to install an SDK. In the window that appears, click **OK** and wait until the import has finished.



2. On the **Quickstart Panel**, click **Import SDK example(s)...**



3. Expand the `demo_apps` folder and select `hello_world`.
4. Click **Next**.



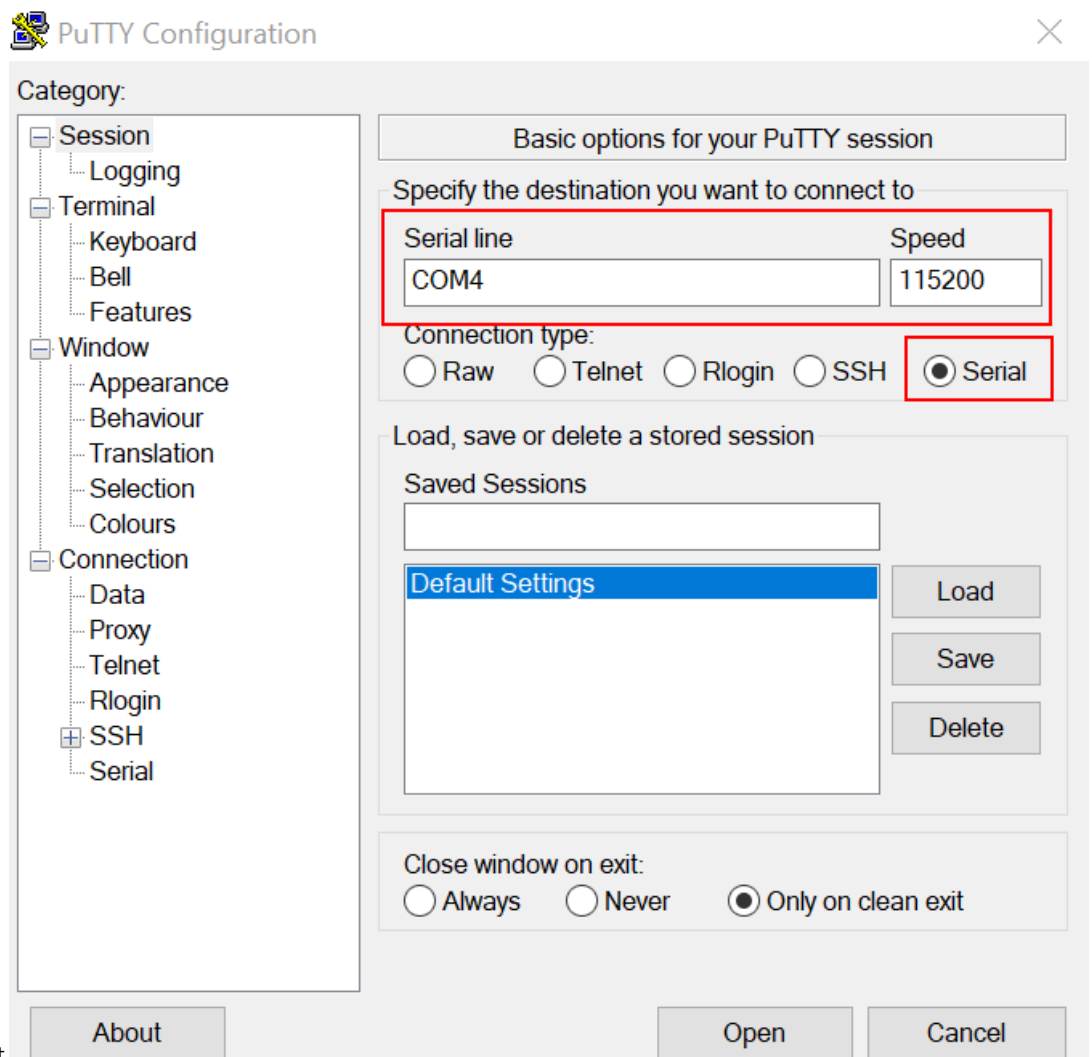
5. Ensure **Redlib: Use floating-point version of printf** is selected if the example prints floating-point numbers on the terminal for demo applications such as `adc_basic`, `adc_burst`, `adc_dma`, and `adc_interrupt`. Otherwise, it is not necessary to select this option. Then, click **Finish**.

Run an example application For more information on debug probe support in the MCUXpresso IDE, see community.nxp.com.

To download and run the application, perform the following steps:

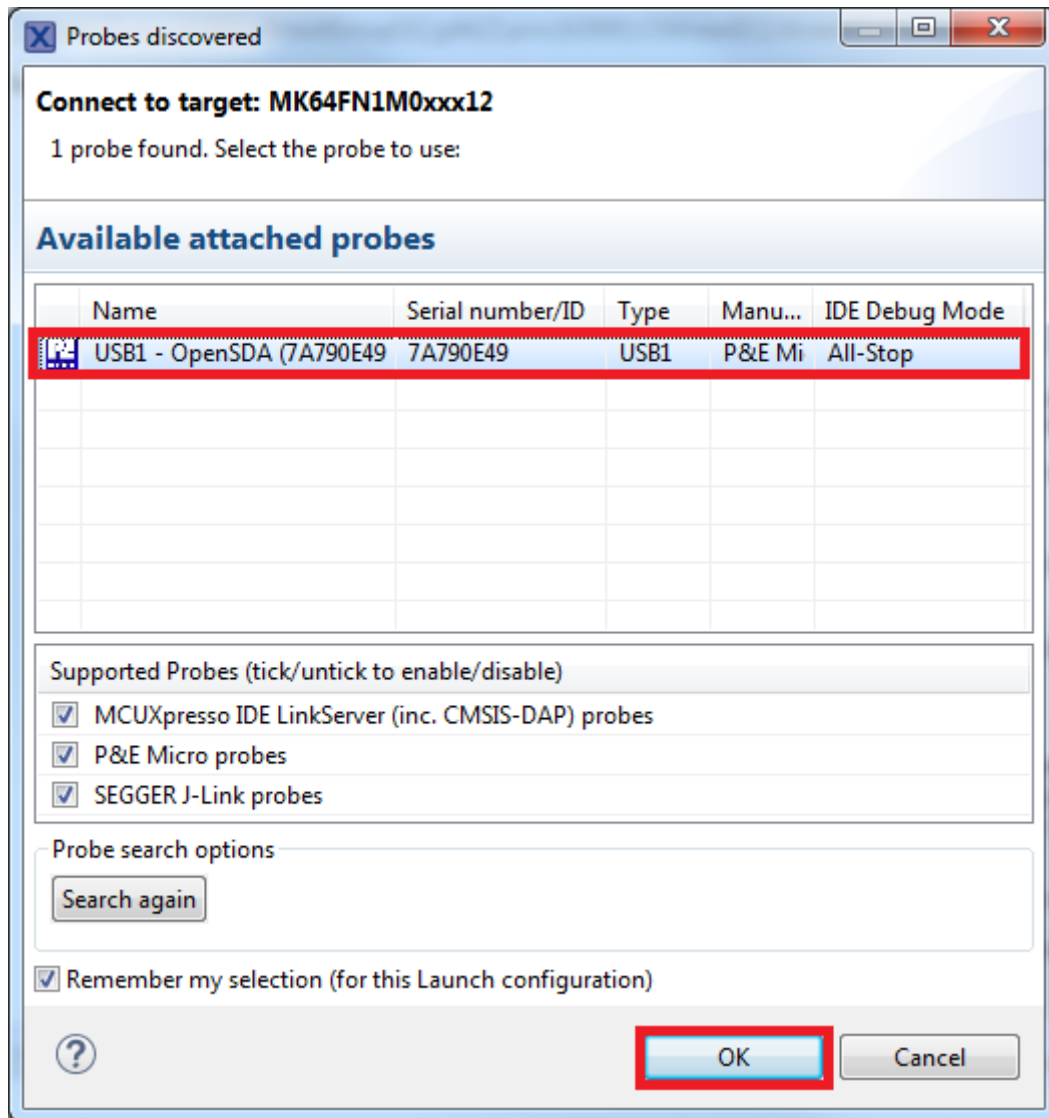
1. Ensure the host driver for the debugger firmware has been installed. See [On-board debugger](#).
2. Connect the development platform to your PC via a USB cable.
3. Open the terminal application on the PC, such as PuTTY or TeraTerm, and connect to the debug serial port number (to determine the COM port number, see [How to determine COM port](#)). Configure the terminal with these settings:
 1. 115200 or 9600 baud rate, depending on your board (reference `BOARD_DEBUG_UART_BAUDRATE` variable in `board.h` file)
 2. No parity

3. 8 data bits



4. 1 stop bit

4. On the **Quickstart Panel**, click **Debug** to launch the debug session.
5. The first time you debug a project, the **Debug Emulator Selection** dialog is displayed, showing all supported probes that are attached to your computer. Select the probe through which you want to debug and click **OK**. (For any future debug sessions, the stored probe selection is automatically used, unless the probe cannot be found.)



- The application is downloaded to the target and automatically runs to `main()`.
- Start the application by clicking **Resume**.

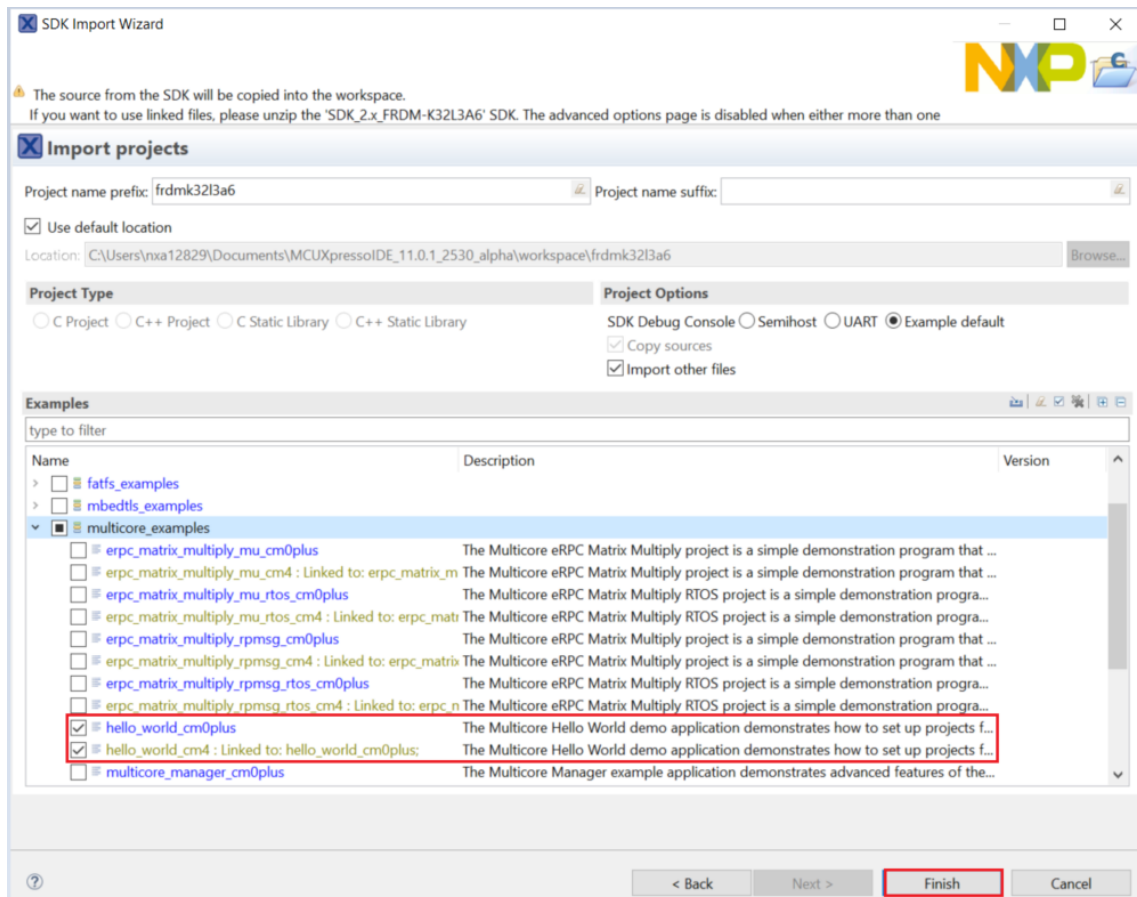


The `hello_world` application is now running and a banner is displayed on the terminal. If not, check your terminal settings and connections.

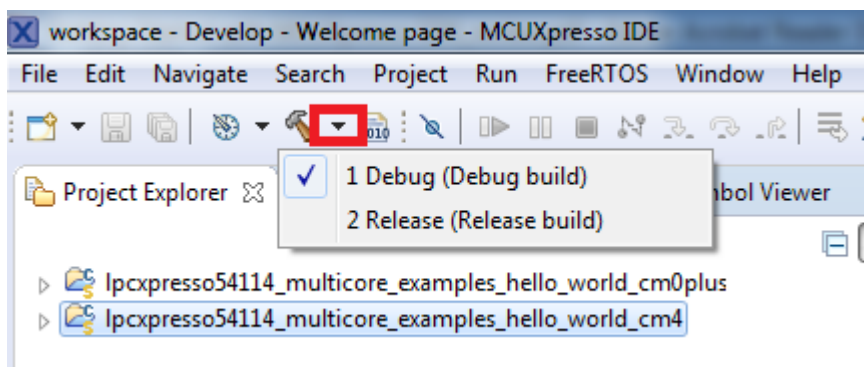


Build a multicore example application This section describes the steps required to configure MCUXpresso IDE to build, run, and debug multicore example applications. The following steps can be applied to any multicore example application in the MCUXpresso SDK. Here, the dual-core version of hello_world example application targeted for the LPCXpresso54114 hardware platform is used as an example.

1. Multicore examples are imported into the workspace in a similar way as single core applications, explained in **Build an example application**. When the SDK zip package for LPCXpresso54114 is installed and available in the **Installed SDKs** view, click **Import SDK example(s)...** on the Quickstart Panel. In the window that appears, expand the **LPCxx** folder and select **LPC54114J256**. Then, select **lpcxpresso54114** and click **Next**.
2. Expand the multicore_examples/hello_world folder and select **cm4**. The cm0plus counterpart project is automatically imported with the cm4 project, because the multicore examples are linked together and there is no need to select it explicitly. Click **Finish**.

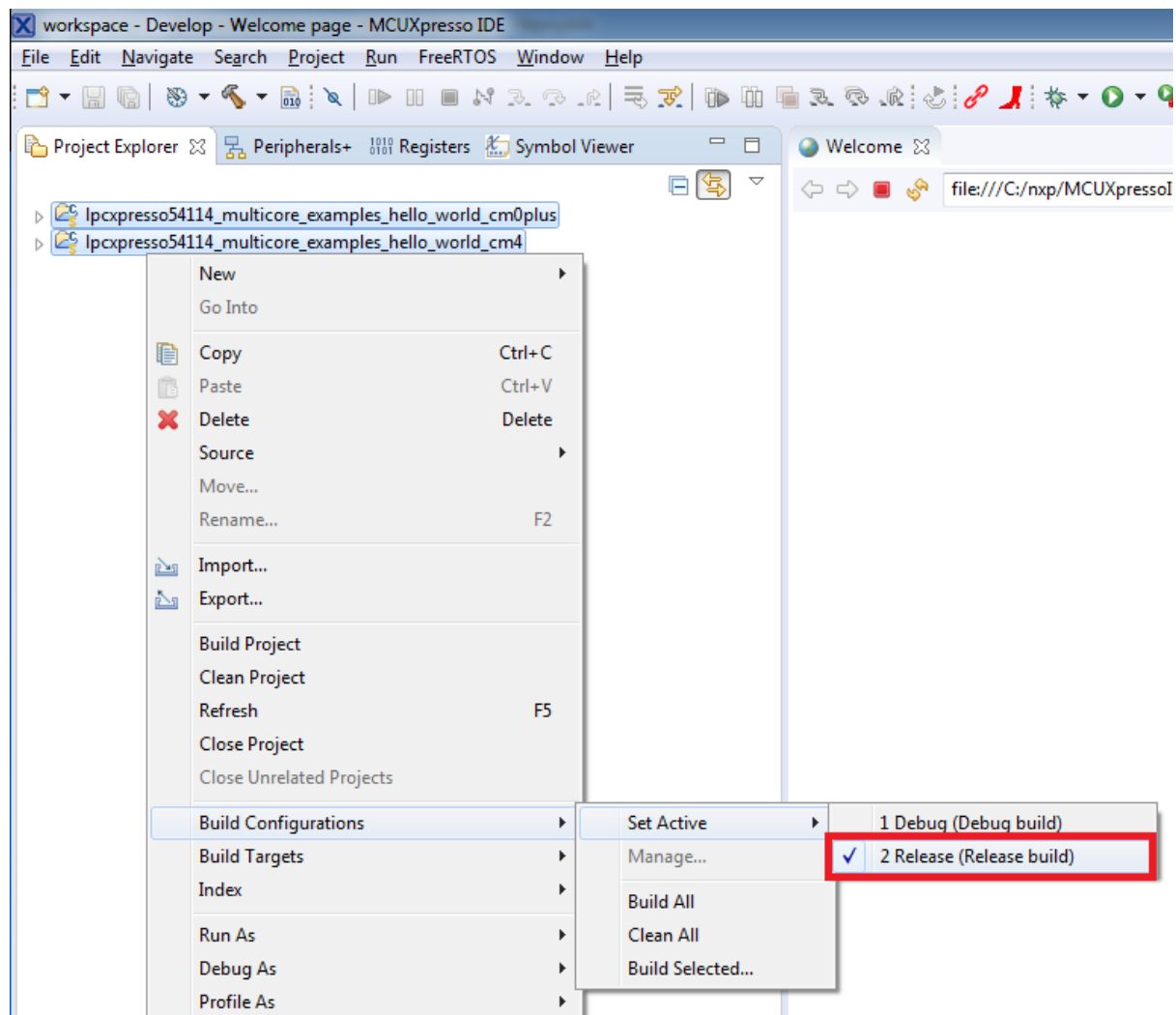


- Now, two projects should be imported into the workspace. To start building the multicore application, highlight the `lpcxpresso54114_multicore_examples_hello_world_cm4` project (multicore master project) in the Project Explorer. Then choose the appropriate build target, **Debug** or **Release**, by clicking the downward facing arrow next to the hammer icon, as shown in the figure. For this example, select **Debug**.

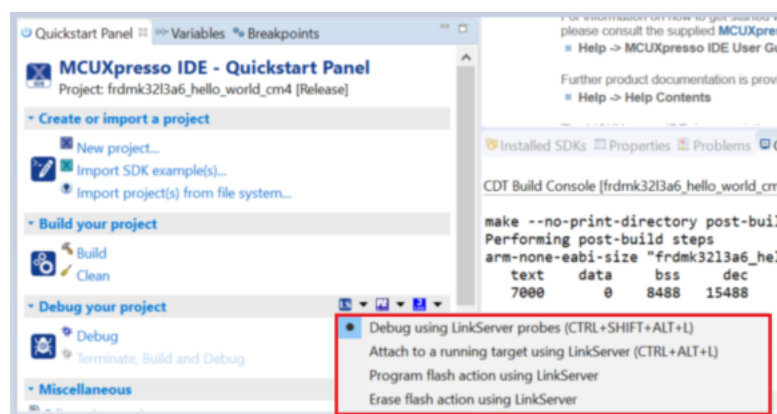


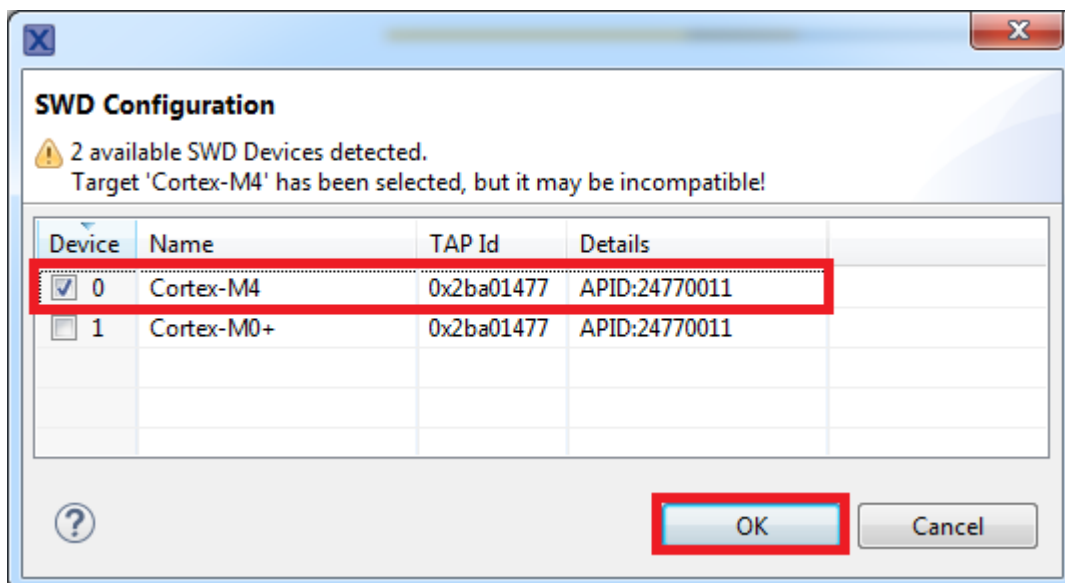
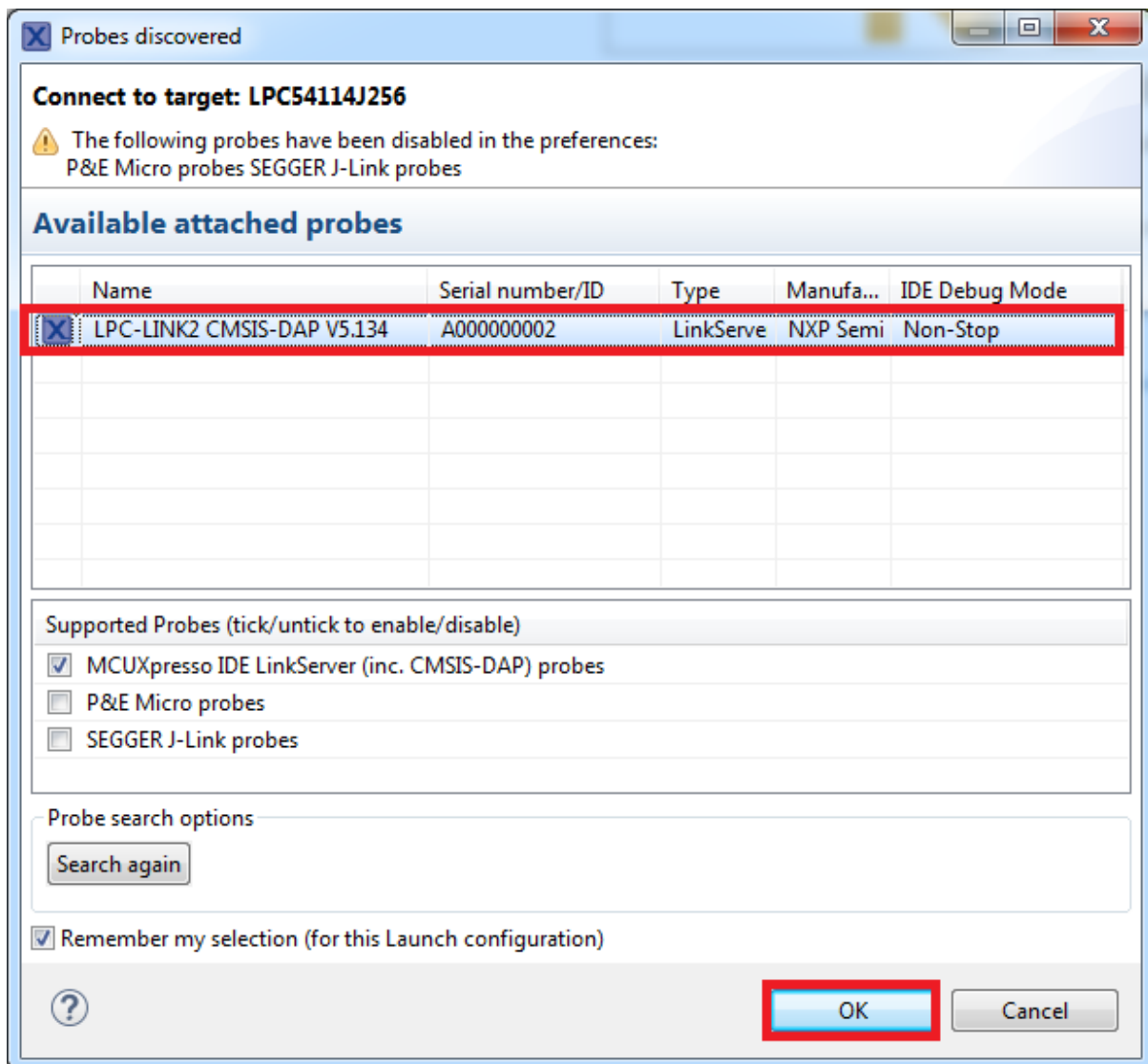
The project starts building after the build target is selected. Because of the project reference settings in multicore projects, triggering the build of the primary core application (cm4) also causes the referenced auxiliary core application (cm0plus) to build.

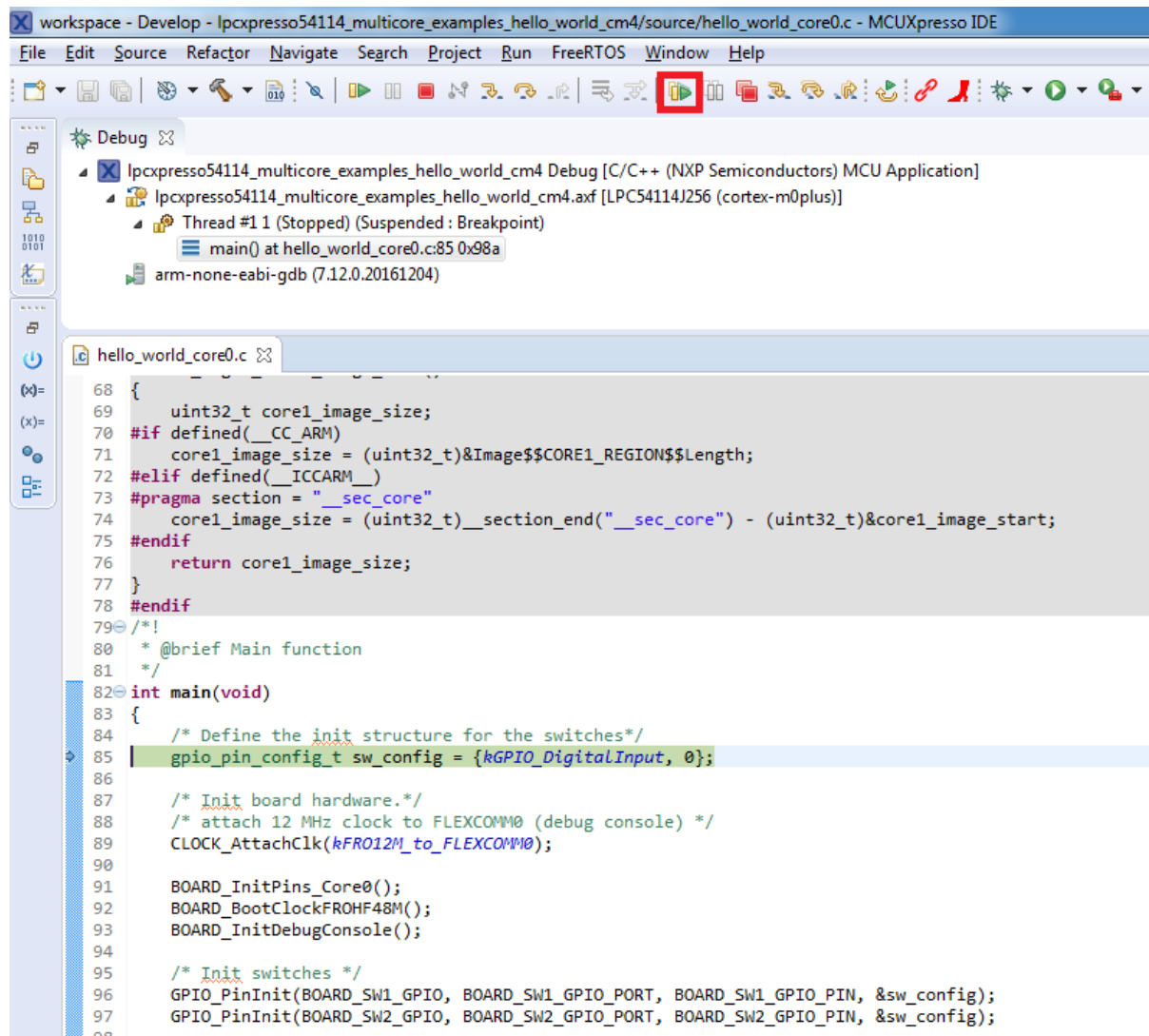
Note: When the **Release** build is requested, it is necessary to change the build configuration of both the primary and auxiliary core application projects first. To do this, select both projects in the Project Explorer view and then right click which displays the context-sensitive menu. Select **Build Configurations -> Set Active -> Release**. This alternate navigation using the menu item is **Project -> Build Configuration -> Set Active -> Release**. After switching to the **Release** build configuration, the build of the multicore example can be started by triggering the primary core application (cm4) build.



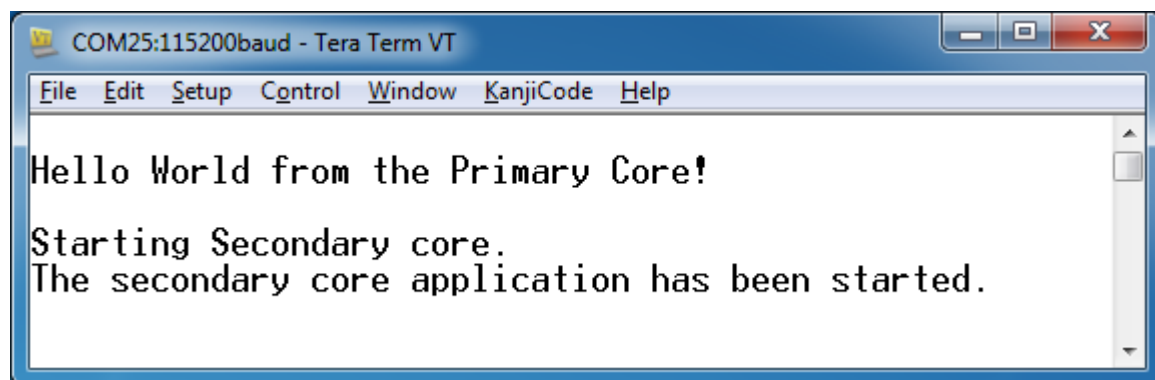
Run a multicore example application The primary core debugger handles flashing of both the primary and the auxiliary core applications into the SoC flash memory. To download and run the multicore application, switch to the primary core application project and perform all steps as described in **Run an example application**. These steps are common for both single-core applications and the primary side of dual-core applications, ensuring both sides of the multicore application are properly loaded and started. However, there is one additional dialogue that is specific to multicore examples which requires selecting the target core. See the following figures as reference.





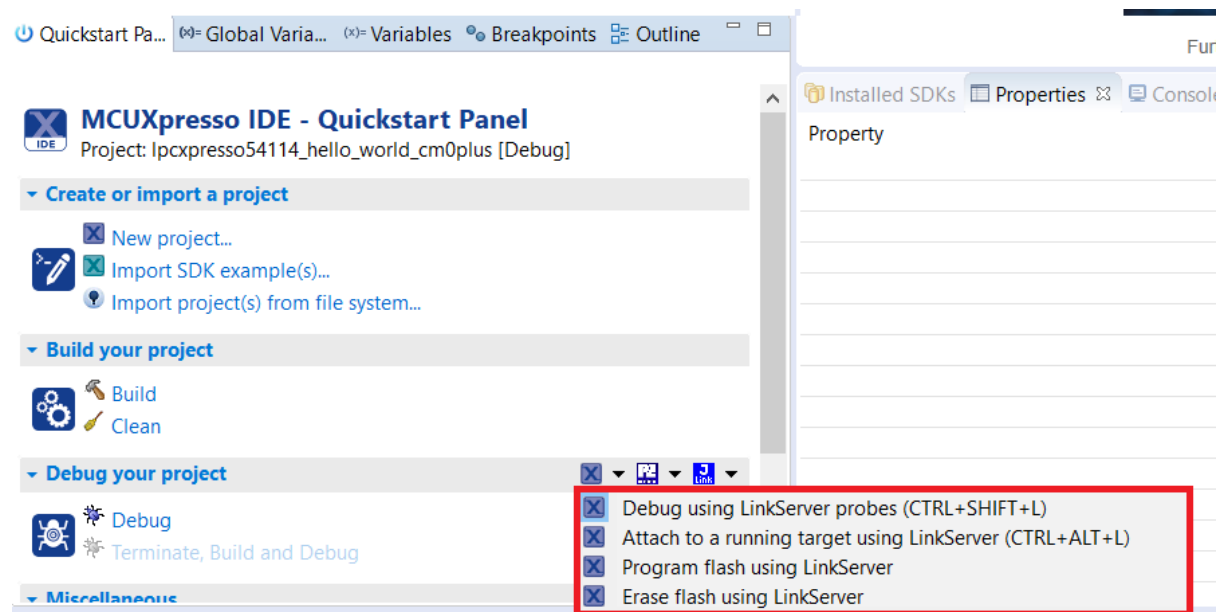


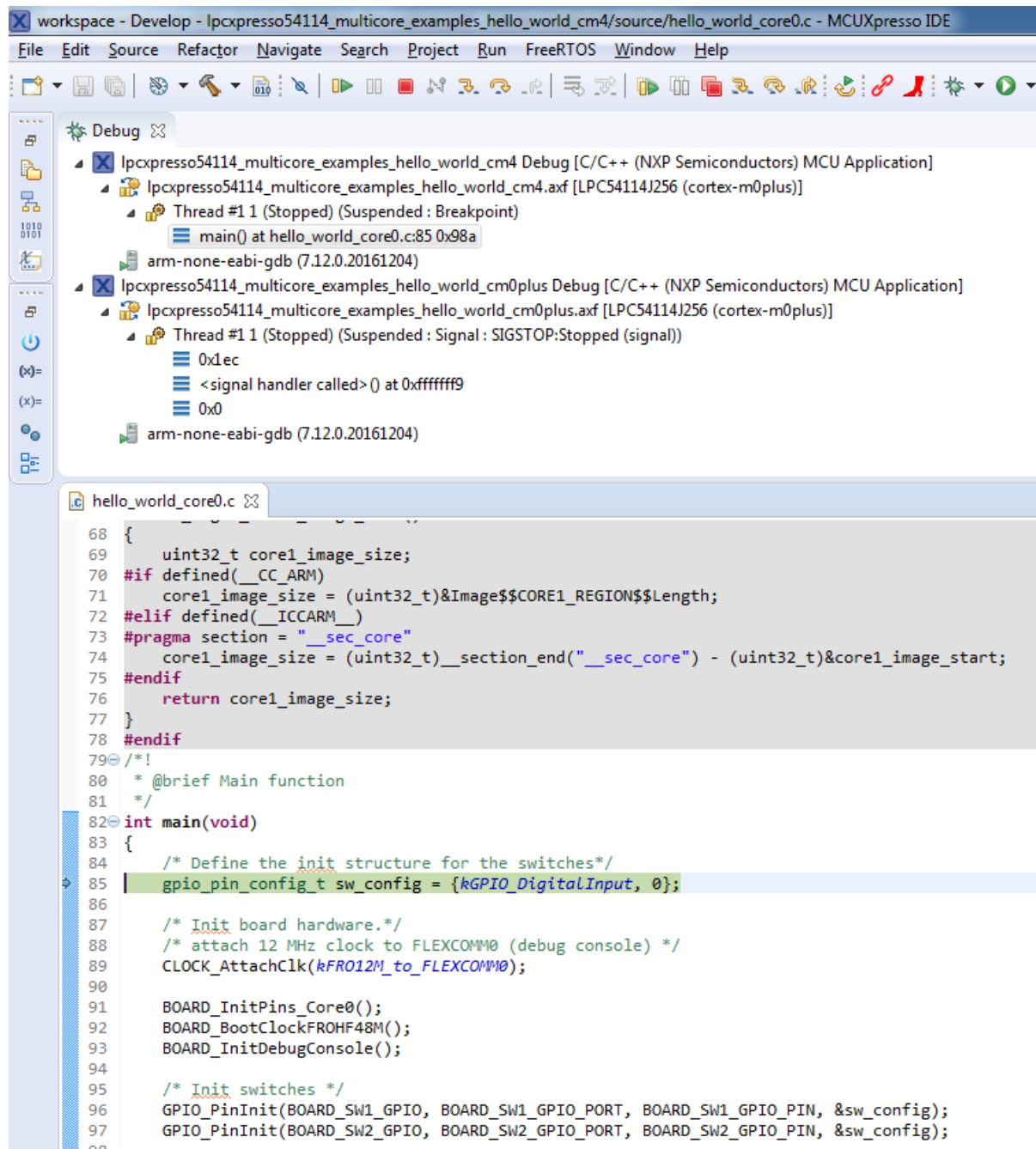
After clicking the “Resume All Debug sessions” button, the hello_world multicore application runs and a banner is displayed on the terminal. If this is not the case, check your terminal settings and connections.



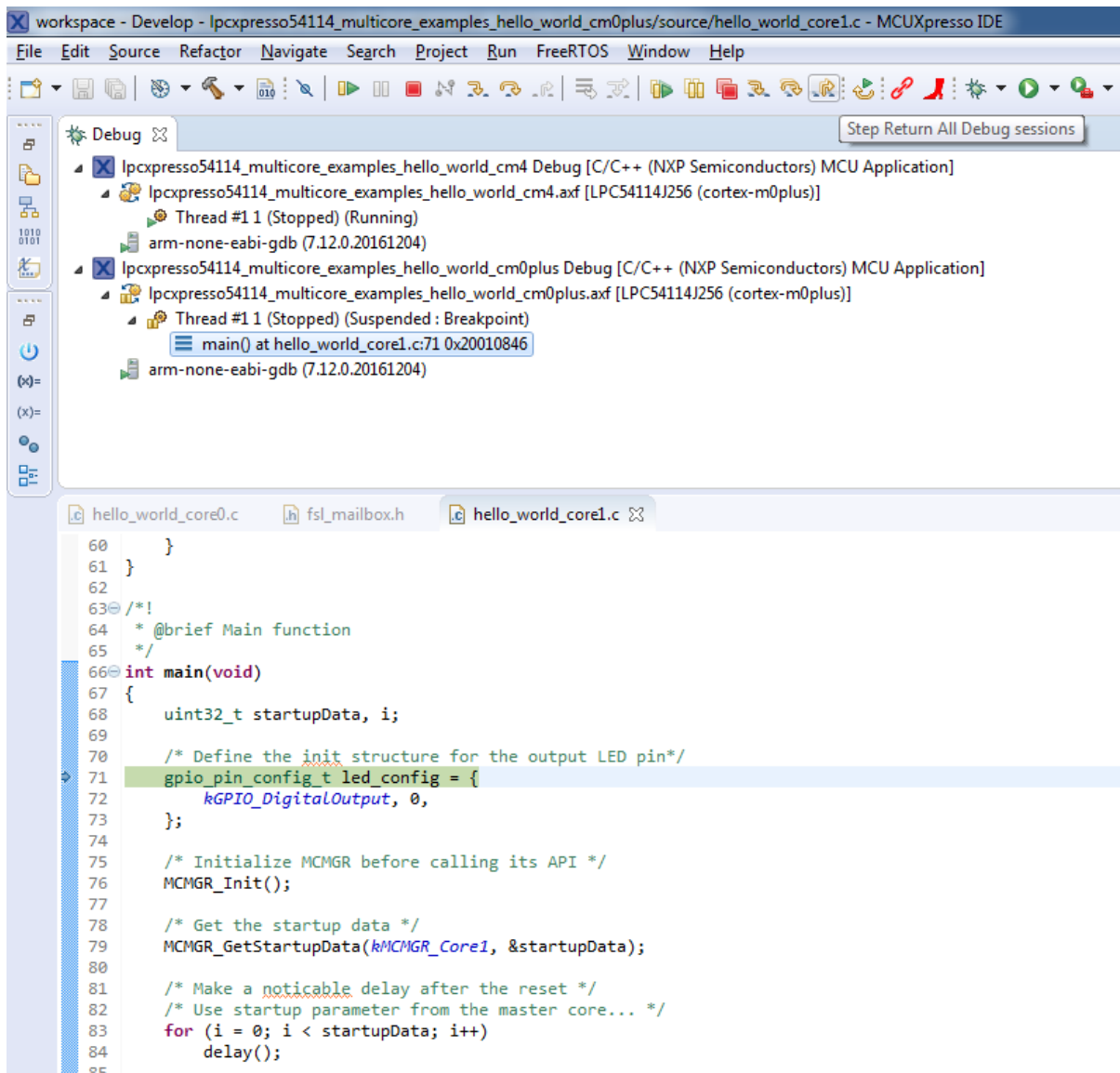
An LED controlled by the auxiliary core starts flashing, indicating that the auxiliary core has been released from the reset and running correctly. It is also possible to debug both sides of the multicore application in parallel. After creating the debug session for the primary core, perform same steps also for the auxiliary core application. Highlight the lpcxpresso54114_multicore_examples_hello_world_cm0plus project (multicore slave project) in the Project Explorer. On the Quickstart Panel, click “Debug ‘lpcxpresso54114_multicore_examples_hello_world_cm0plus’ [Debug]” to launch the second debug

session.

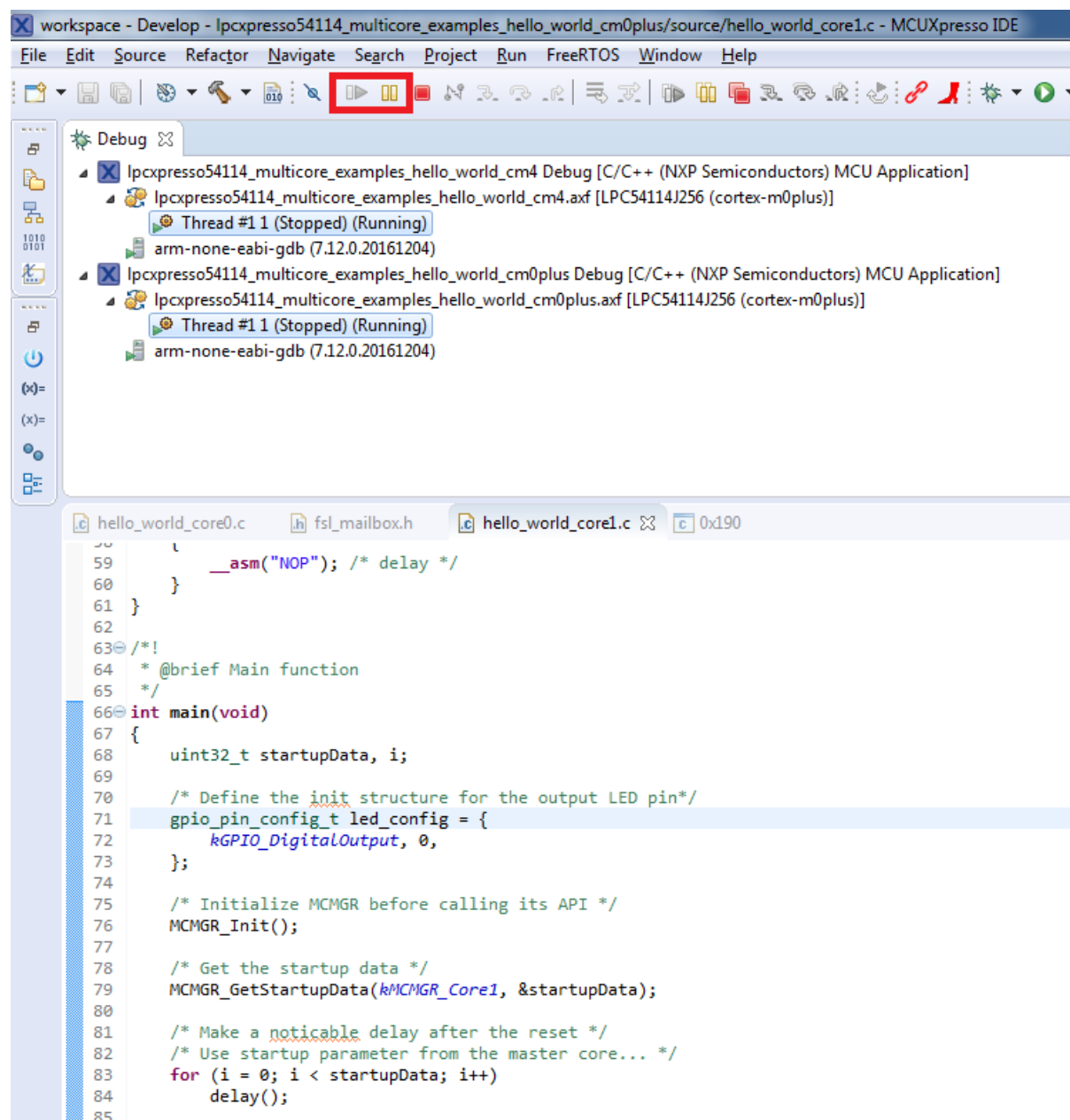


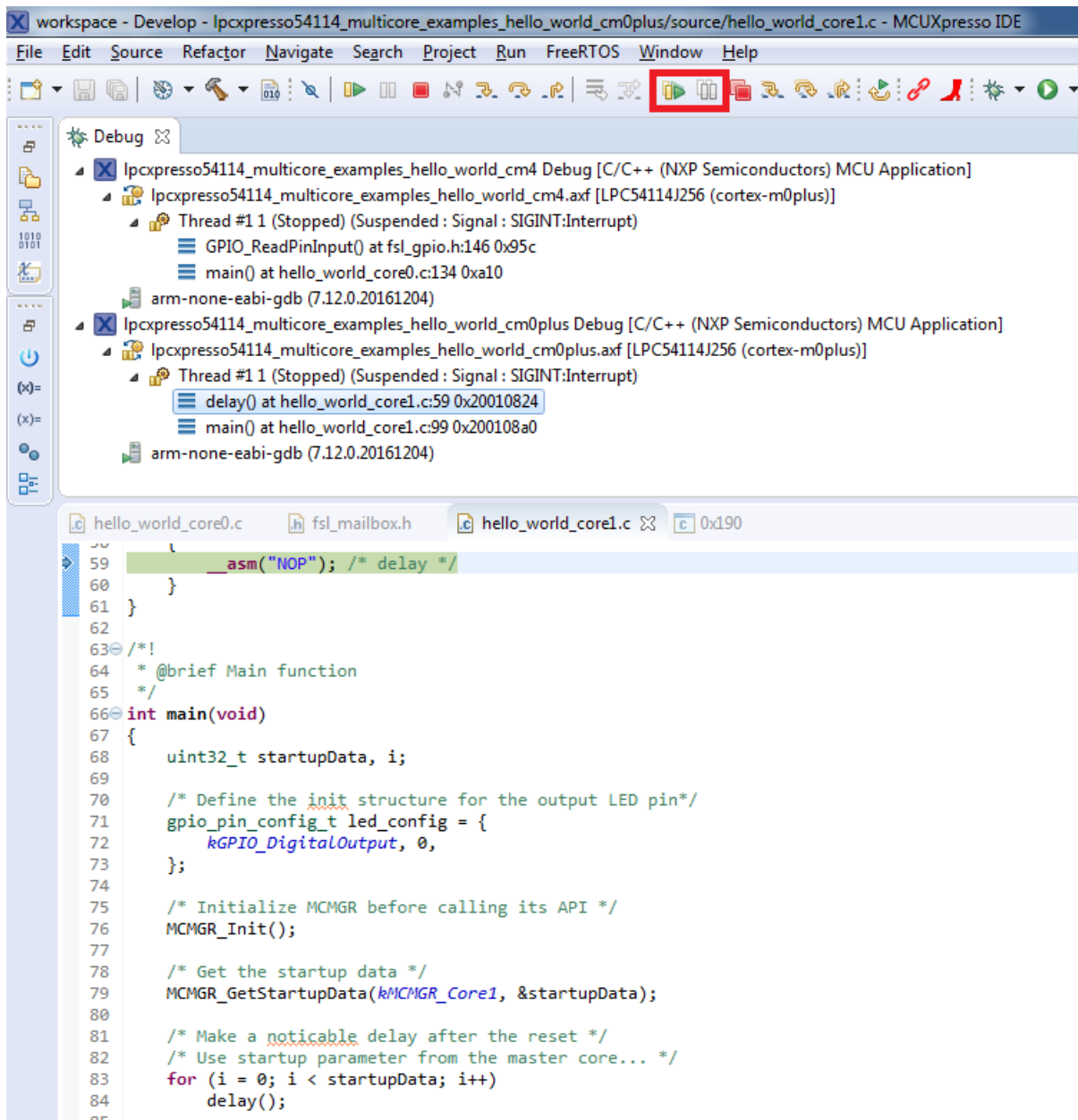


Now, the two debug sessions should be opened, and the debug controls can be used for both debug sessions depending on the debug session selection. Keep the primary core debug session selected by clicking the “Resume” button. The hello_world multicore application then starts running. The primary core application starts the auxiliary core application during runtime, and the auxiliary core application stops at the beginning of the main() function. The debug session of the auxiliary core application is highlighted. After clicking the “Resume” button, it is applied to the auxiliary core debug session. Therefore, the auxiliary core application continues its execution.



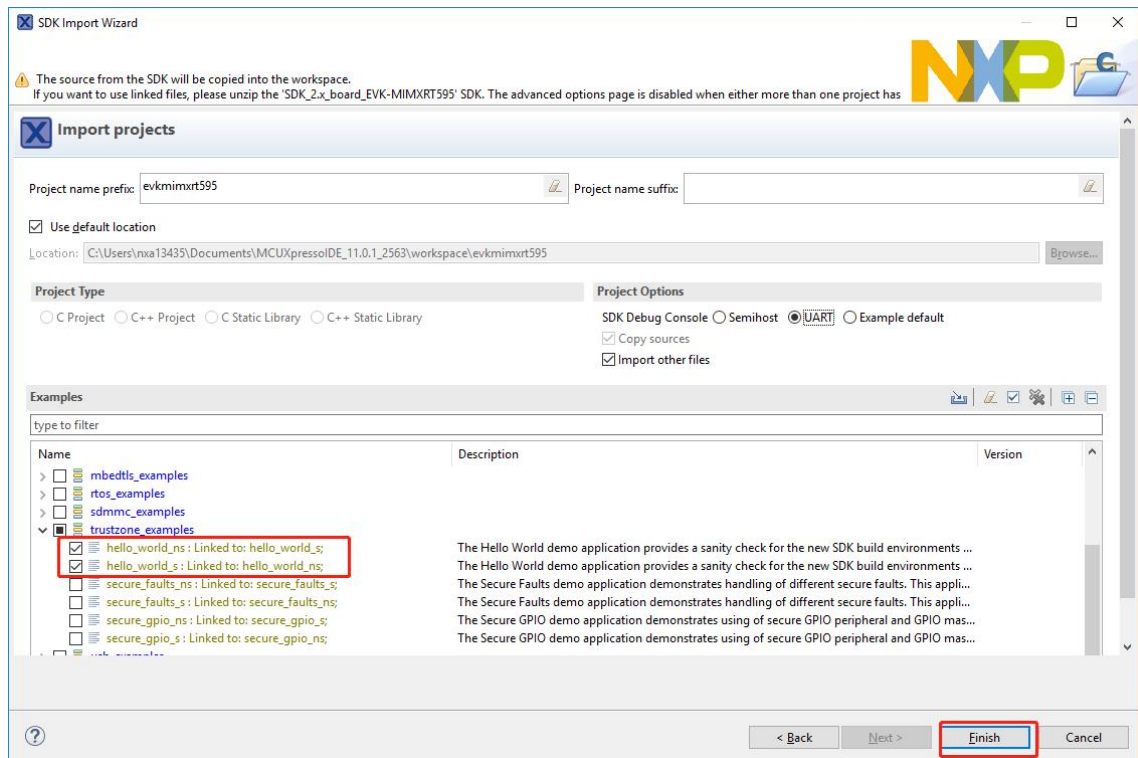
At this point, it is possible to suspend and resume individual cores independently. It is also possible to make synchronous suspension and resumption of both the cores. This is done either by selecting both opened debug sessions (multiple selections) and clicking the “Suspend” / “Resume” control button, or just using the “Suspend All Debug sessions” and the “Resume All Debug sessions” buttons.



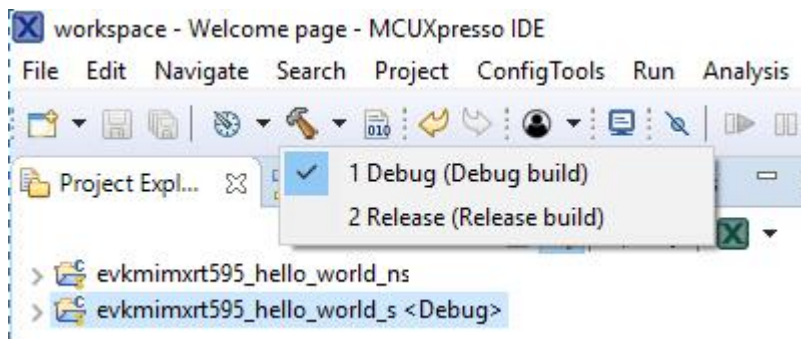


Build a TrustZone example application This section describes the steps required to configure MCUXpresso IDE to build, run, and debug TrustZone example applications. The TrustZone version of the `hello_world` example application targeted for the MIMXRT595-EVK hardware platform is used as an example, though these steps can be applied to any TrustZone example application in the MCUXpresso SDK.

1. TrustZone examples are imported into the workspace in a similar way as single core applications. When the SDK zip package for MIMXRT595-EVK is installed and available in the **Installed SDKs** view, click **Import SDK example(s)...** on the Quickstart Panel. In the window that appears, expand the **MIMXRT500** folder and select **MIMXRT595S**. Then, select **evkmimxrt595** and click **Next**.
2. Expand the `trustzone_examples/` folder and select `hello_world_s`. Because TrustZone examples are linked together, the non-secure project is automatically imported with the secure project, and there is no need to select it explicitly. Then, click **Finish**.

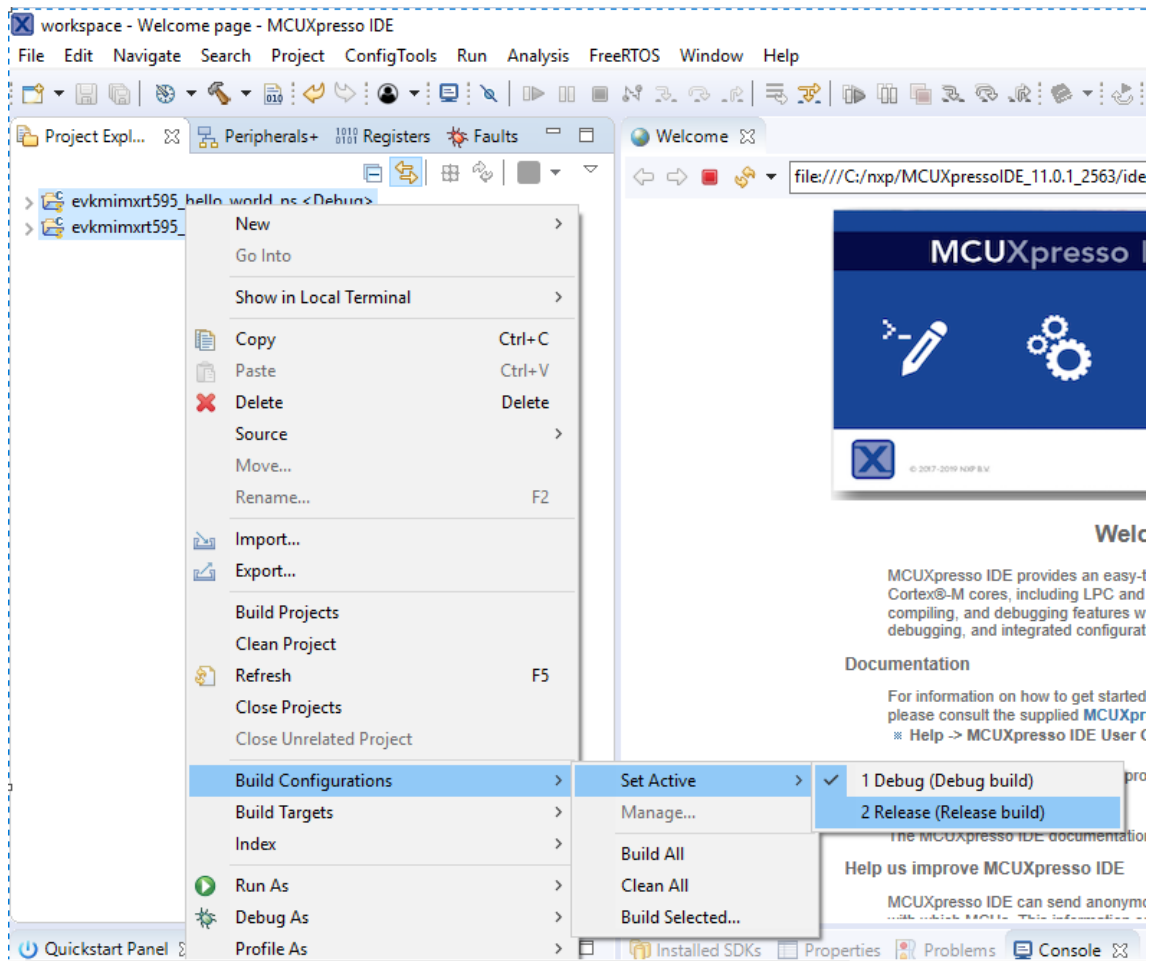


3. Now, two projects should be imported into the workspace. To start building the TrustZone application, highlight the `evkmimxrt595_hello_world_s` project (TrustZone master project) in the Project Explorer. Then, choose the appropriate build target, **Debug** or **Release**, by clicking the downward facing arrow next to the hammer icon, as shown in following figure. For this example, select the **Debug** target.



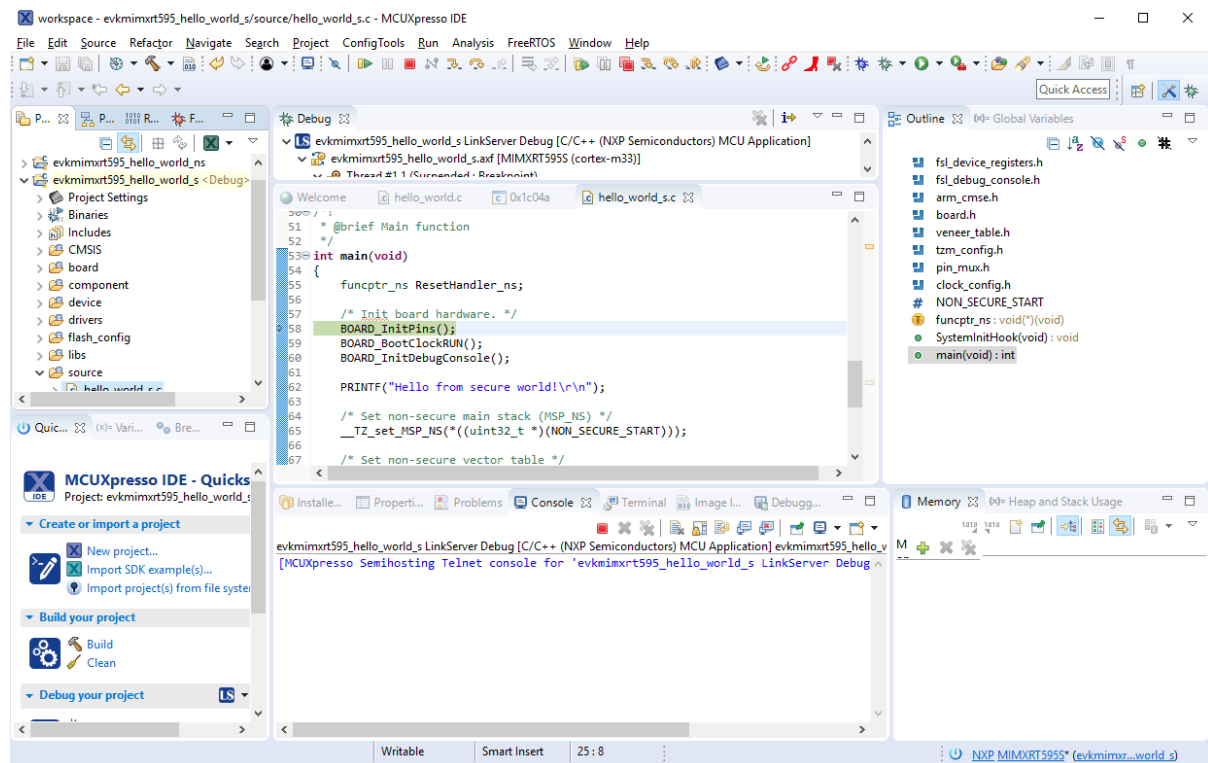
The project starts building after the build target is selected. It is requested to build the application for the secure project first, because the non-secure project must know the secure project since CMSE library when running the linker. It is not possible to finish the non-secure project linker when the secure project since CMSE library is not ready.

Note: When the **Release** build is requested, it is necessary to change the build configuration of both the secure and non-secure application projects first. To do this, select both projects in the Project Explorer view by clicking to select the first project, then using shift-click or control-click to select the second project. Right click in the Project Explorer view to display the context-sensitive menu and select **Build Configurations > Set Active > Release**. This is also possible by using the menu item of **Project > Build Configuration > Set Active > Release**. After switching to the **Release** build configuration. Build the application for the secure project first.



Run a TrustZone example application To download and run the application, perform all steps as described in **Run an example application**. These steps are common for single core, and TrustZone applications, ensuring <board_name>_hello_world_s is selected for debugging.

In the Quickstart Panel, click **Debug** to launch the second debug session.



Now, the TrustZone sessions should be opened. Click **Resume**. The `hello_world` TrustZone application then starts running, and the secure application starts the non-secure application during runtime.

Run a demo application using IAR

This section describes the steps required to build, run, and debug example applications provided in the MCUXpresso SDK.

Note: IAR Embedded Workbench for Arm version 8.32.3 is used in the following example, and the IAR toolchain should correspond to the latest supported version, as described in the *MCUXpresso SDK Release Notes*.

Build an example application Do the following steps to build the `hello_world` example application.

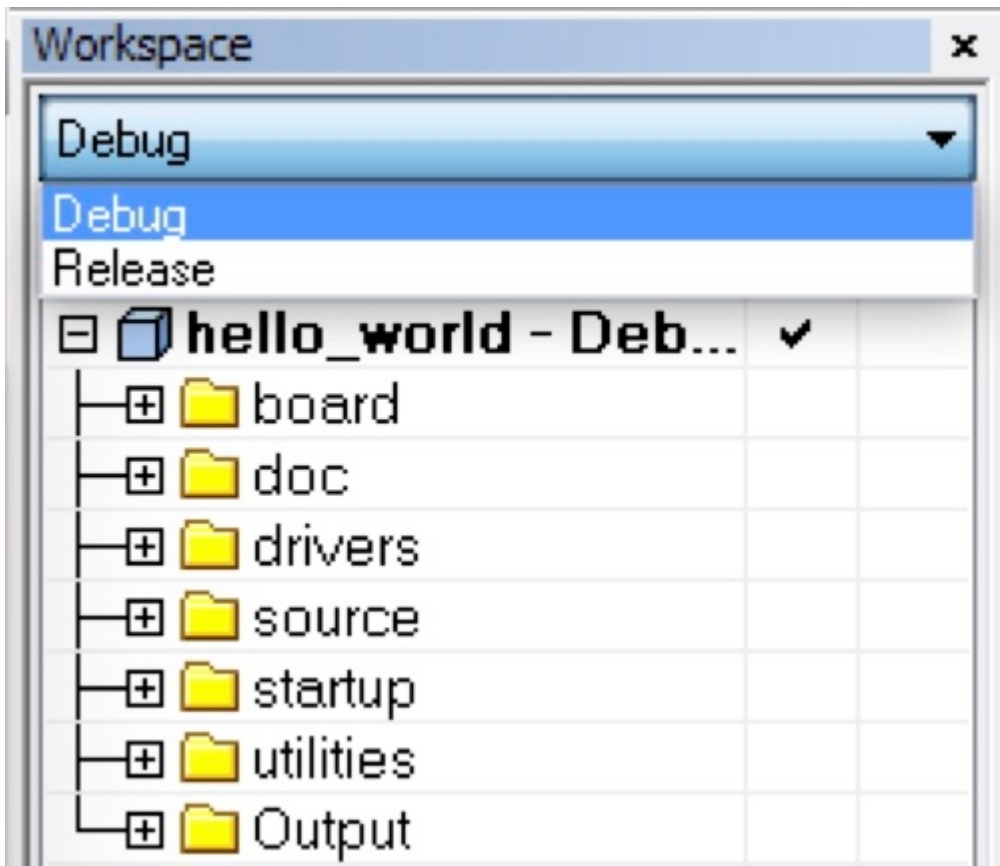
1. Open the desired demo application workspace. Most example application workspace files can be located using the following path:

```
<install_dir>/boards/<board_name>/<example_type>/<application_name>/iar
```

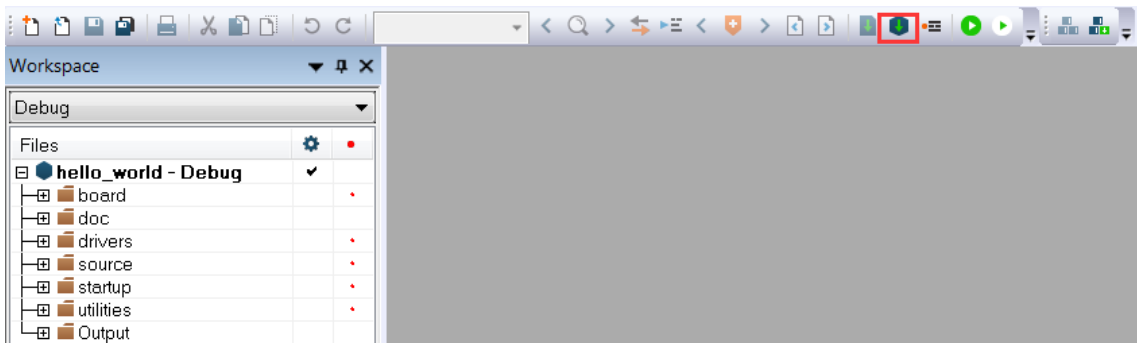
Other example applications may have additional folders in their path.

2. Select the desired build target from the drop-down menu.

For this example, select **hello_world – debug**.



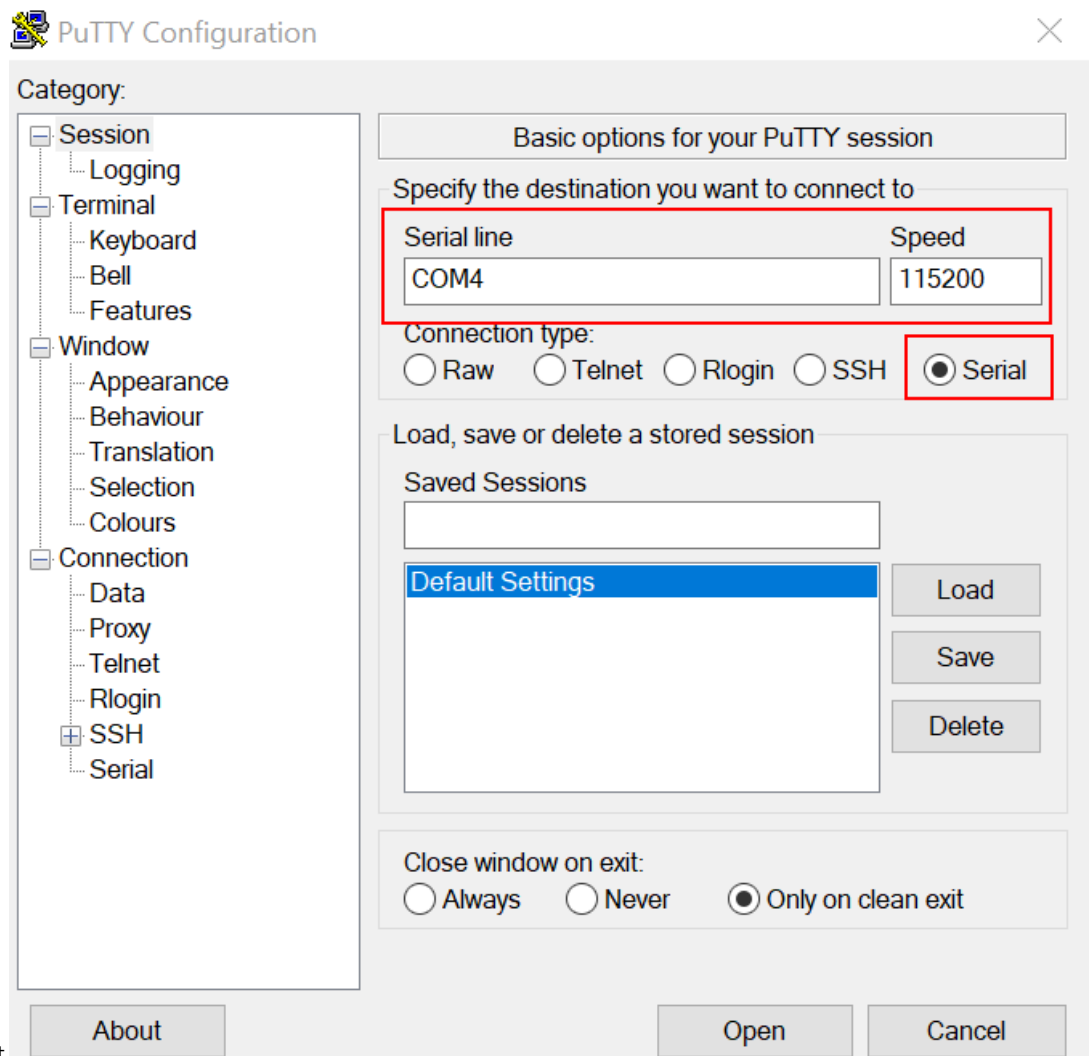
3. To build the demo application, click **Make**, highlighted in red in following figure.



4. The build completes without errors.

Run an example application To download and run the application, perform these steps:

1. Ensure the host driver for the debugger firmware has been installed. See [On-board debugger](#).
2. Connect the development platform to your PC via USB cable.
3. Open the terminal application on the PC, such as PuTTY or TeraTerm, and connect to the debug COM port (to determine the COM port number, see [How to determine COM port](#)). Configure the terminal with these settings:
 1. 115200 or 9600 baud rate, depending on your board (reference BOARD_DEBUG_UART_BAUDRATE variable in the board.h file)
 2. No parity
 3. 8 data bits

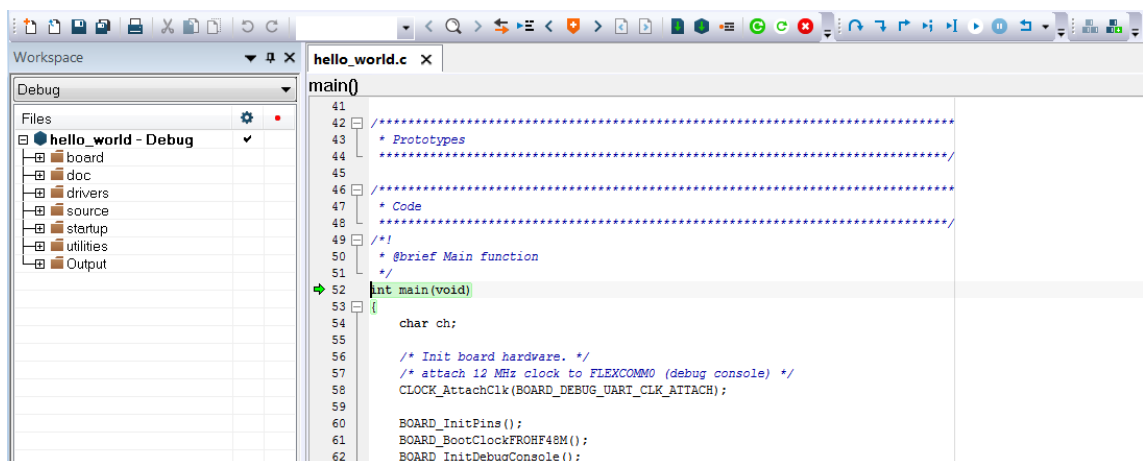


4. 1 stop bit

4. In IAR, click the **Download and Debug** button to download the application to the target.



5. The application is then downloaded to the target and automatically runs to the `main()` function.



6. Run the code by clicking the **Go** button.

7. The `hello_world` application is now running and a banner is displayed on the terminal. If it does not appear, check your terminal settings and connections.



Build a multicore example application This section describes the steps to build and run a dual-core application. The demo applications workspace files are located in this folder:

```
<install_dir>/boards/<board_name>/multicore_examples/<application_name>/<core_type>/iar
```

Begin with a simple dual-core version of the Hello World application. The multicore Hello World IAR workspaces are located in this folder:

```
<install_dir>/boards/lpcxpresso54114/multicore_examples/hello_world/cm0plus/iar/hello_world_cm0plus.  
→ eww
```

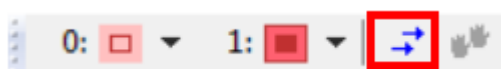
```
<install_dir>/boards/lpcxpresso54114/multicore_examples/hello_world/cm4/iar/hello_world_cm4.eww
```

Build both applications separately by clicking the **Make** button. Build the application for the auxiliary core (cm0plus) first, because the primary core application project (cm4) must know the auxiliary core application binary when running the linker. It is not possible to finish the primary core linker when the auxiliary core application binary is not ready.

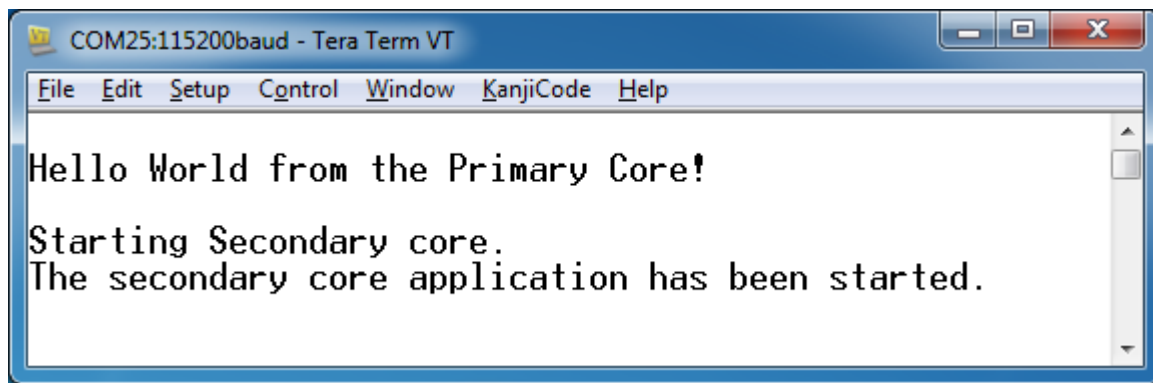
Run a multicore example application The primary core debugger handles flashing both primary and the auxiliary core applications into the SoC flash memory. To download and run the multicore application, switch to the primary core application project and perform steps 1 – 4 as described in **Run an example application**. These steps are common for both single core and dual-core applications in IAR.

After clicking the “Download and Debug” button, the auxiliary core project is opened in the separate EWARM instance. Both the primary and auxiliary images are loaded into the device flash memory and the primary core application is executed. It stops at the default C language entry point in the `*main()*function`.

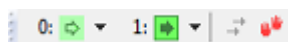
Run both cores by clicking the “Start all cores” button to start the multicore application.



During the primary core code execution, the auxiliary core is released from the reset. The `hello_world` multicore application is now running and a banner is displayed on the terminal. If this does not appear, check the terminal settings and connections.



An LED controlled by the auxiliary core starts flashing, indicating that the auxiliary core has been released from the reset and is running correctly. When both cores are running, use the “Stop all cores”, and “Start all cores” control buttons to stop or run both cores simultaneously.



Build a TrustZone example application This section describes the particular steps that must be done in order to build and run a TrustZone application. The demo applications workspace files are located in this folder:

```
<install_dir>/boards/<board_name>/trustzone_examples/<application_name>/[<core_type>]/iar/  
↪<application_name>_ns/iar
```

```
<install_dir>/boards/<board_name>/trustzone_examples/<application_name>/[<core_type>]/iar/  
↪<application_name>_s/iar
```

Begin with a simple TrustZone version of the Hello World application. The TrustZone Hello World IAR workspaces are located in this folder:

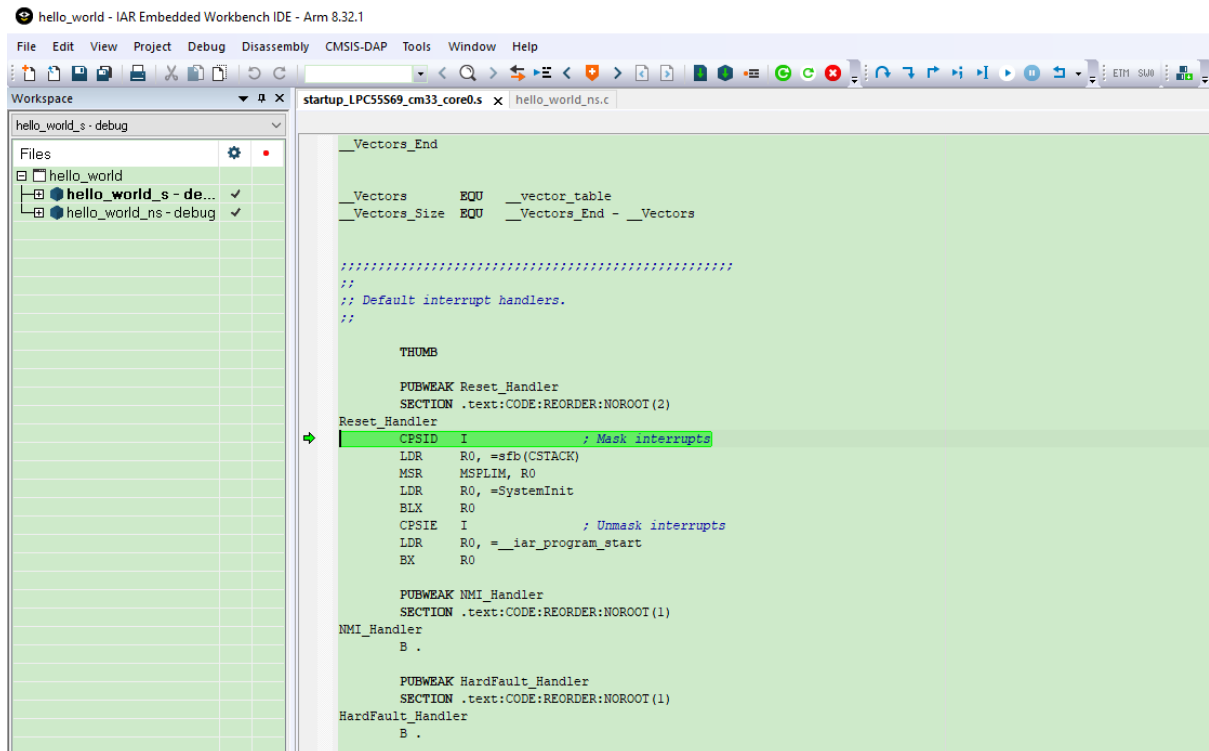
```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_ns/iar/hello_world_  
↪ns.eww
```

```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_s/iar/hello_world_s.  
↪eww
```

```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_s/iar/hello_world.eww
```

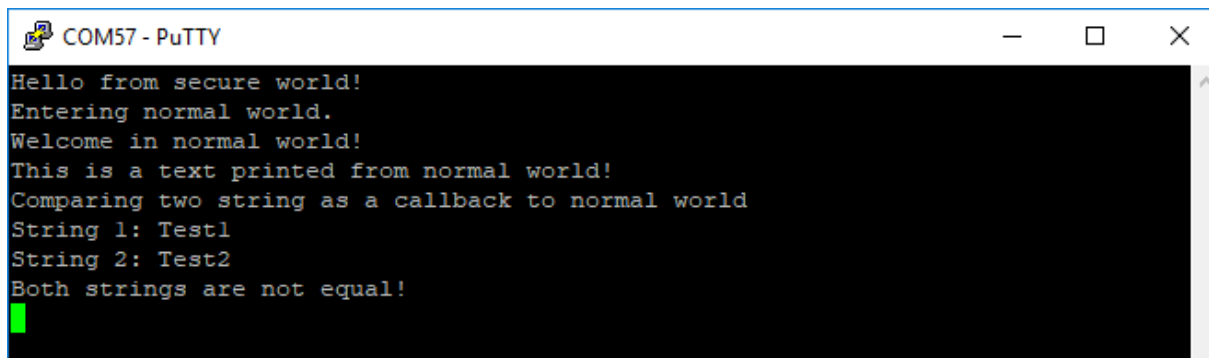
This project `hello_world.eww` contains both secure and non-secure projects in one workspace and it allows the user to easily transition from one project to another. Build both applications separately by clicking **Make**. It is requested to build the application for the secure project first, because the non-secure project must know the secure project, since the CMSE library is running the linker. It is not possible to finish the non-secure project linker with the secure project since CMSE library is not ready.

Run a TrustZone example application The secure project is configured to download both secure and non-secure output files, so debugging can be fully managed from the secure project. To download and run the TrustZone application, switch to the secure application project and perform steps 1 – 4 as described in **Run an example application**. These steps are common for both single core, and TrustZone applications in IAR. After clicking **Download and Debug**, both the secure and non-secure images are loaded into the device memory, and the secure application is executed. It stops at the `Reset_Handler` function.

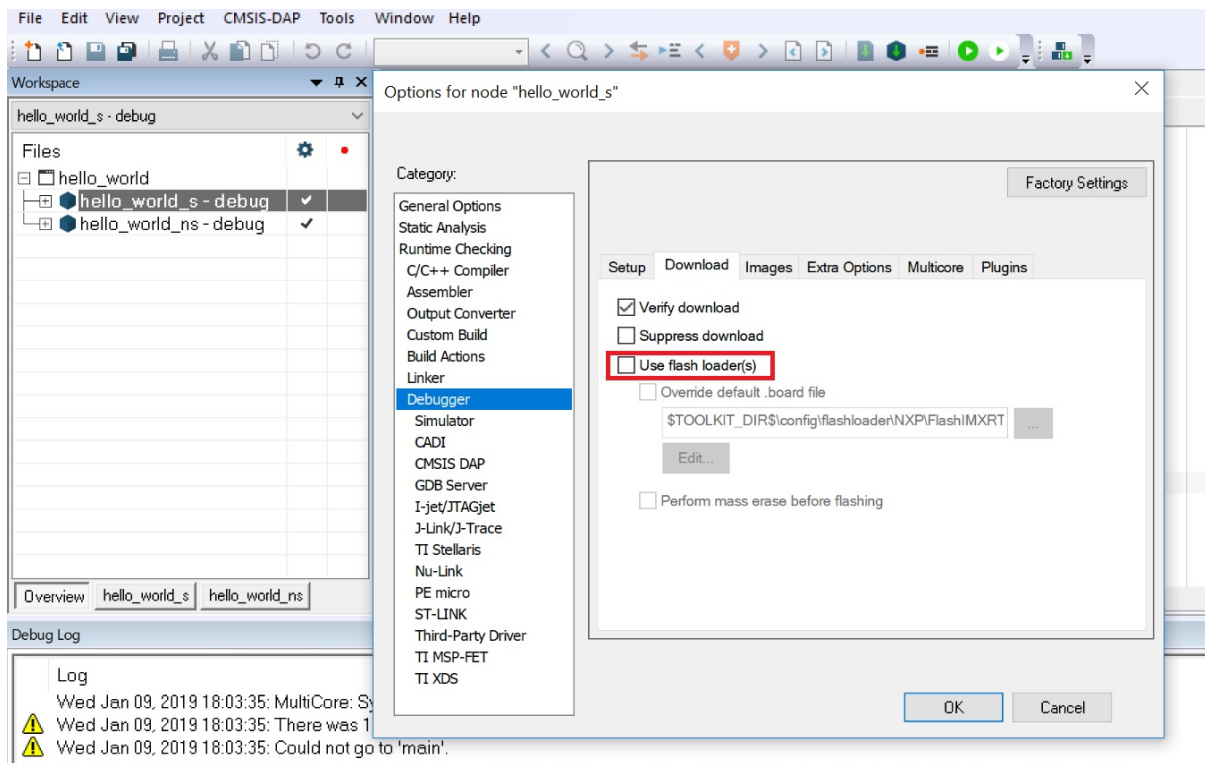


Run the code by clicking **Go** to start the application.

The TrustZone hello_world application is now running and a banner is displayed on the terminal. If this is not true, check your terminal settings and connections.



Note: If the application is running in RAM (debug/release build target), in **Options**>**Debugger > Download** tab, disable **Use flash loader(s)**. This can avoid the `__ns` download issue on i.MXRT500.

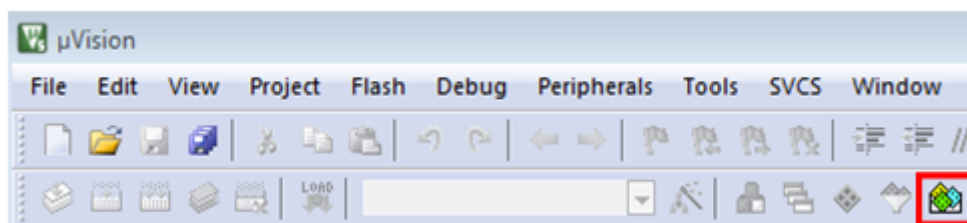


Run a demo using Keil MDK/μVision

This section describes the steps required to build, run, and debug example applications provided in the MCUXpresso SDK.

Install CMSIS device pack After the MDK tools are installed, Cortex Microcontroller Software Interface Standard (CMSIS) device packs must be installed to fully support the device from a debug perspective. These packs include things such as memory map information, register definitions, and flash programming algorithms. Follow these steps to install the appropriate CMSIS pack.

1. Open the MDK IDE, which is called μVision. In the IDE, select the **Pack Installer** icon.



2. After the installation finishes, close the Pack Installer window and return to the μVision IDE.

Build an example application

1. Open the desired example application workspace in:

```
<install_dir>/boards/<board_name>/<example_type>/<application_name>/mdk
```

The workspace file is named as <demo_name>.uvmpw. For this specific example, the actual path is:

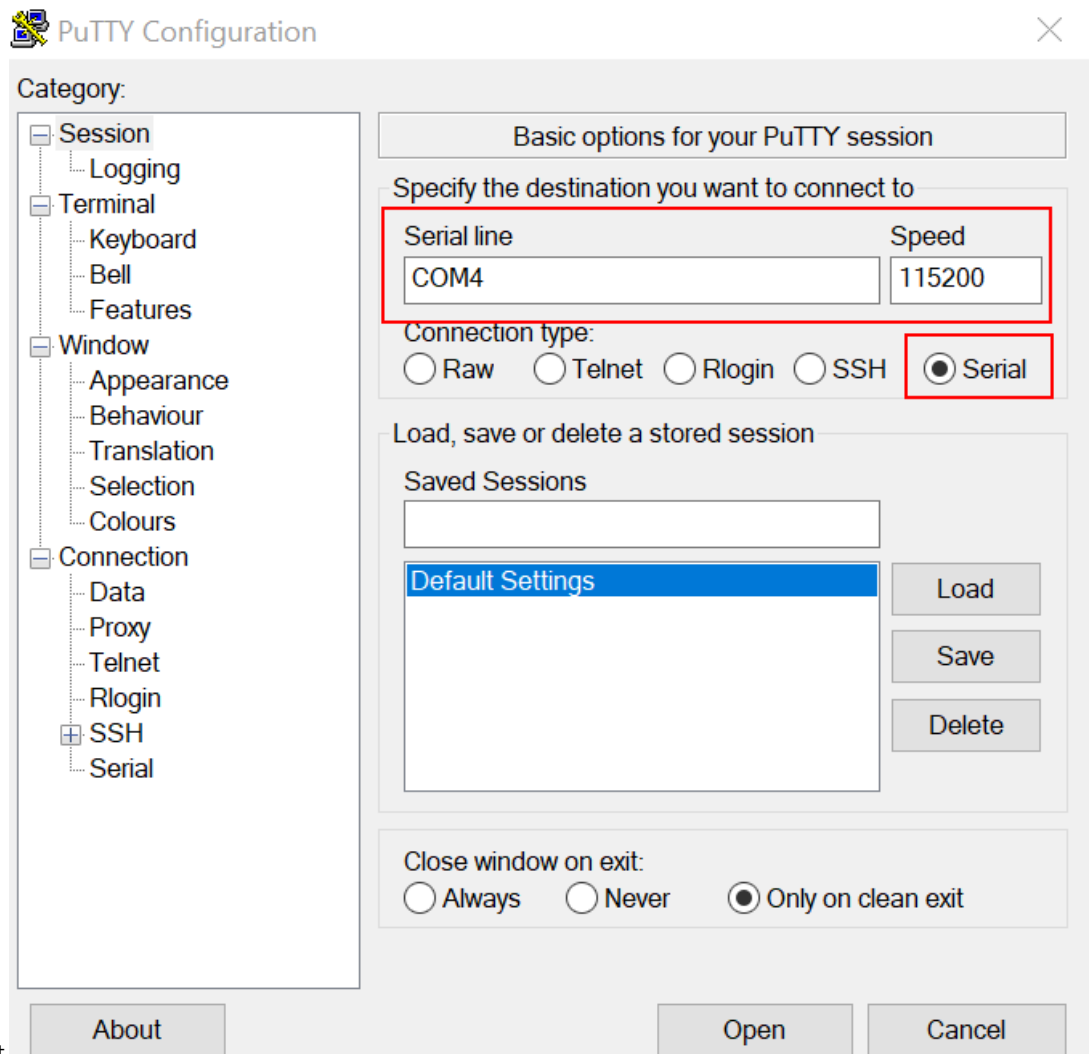
- To build the demo project, select **Rebuild**, highlighted in red.



- The build completes without errors.

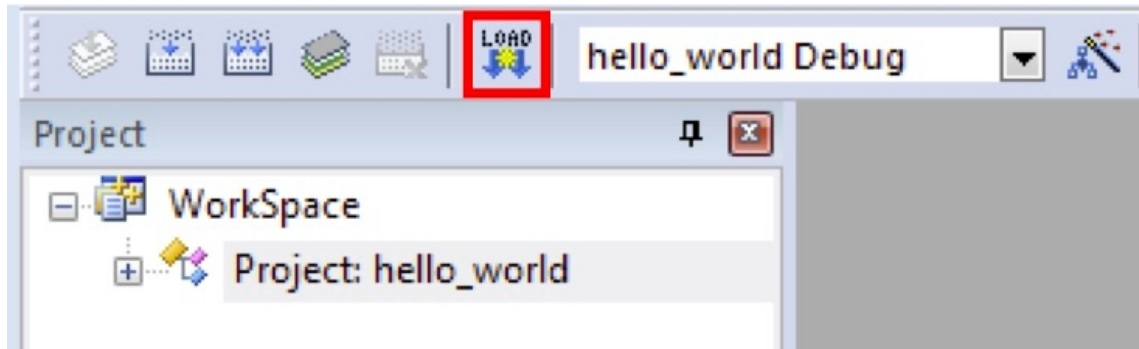
Run an example application To download and run the application, perform these steps:

- Ensure the host driver for the debugger firmware has been installed. See [On-board debugger](#).
- Connect the development platform to your PC via USB cable using USB connector.
- Open the terminal application on the PC, such as PuTTY or TeraTerm and connect to the debug serial port number (to determine the COM port number, see [How to determine COM port](#)). Configure the terminal with these settings:
 - 115200 or 9600 baud rate, depending on your board (reference BOARD_DEBUG_UART_BAUDRATE variable in the board.h file)
 - No parity
 - 8 data bits

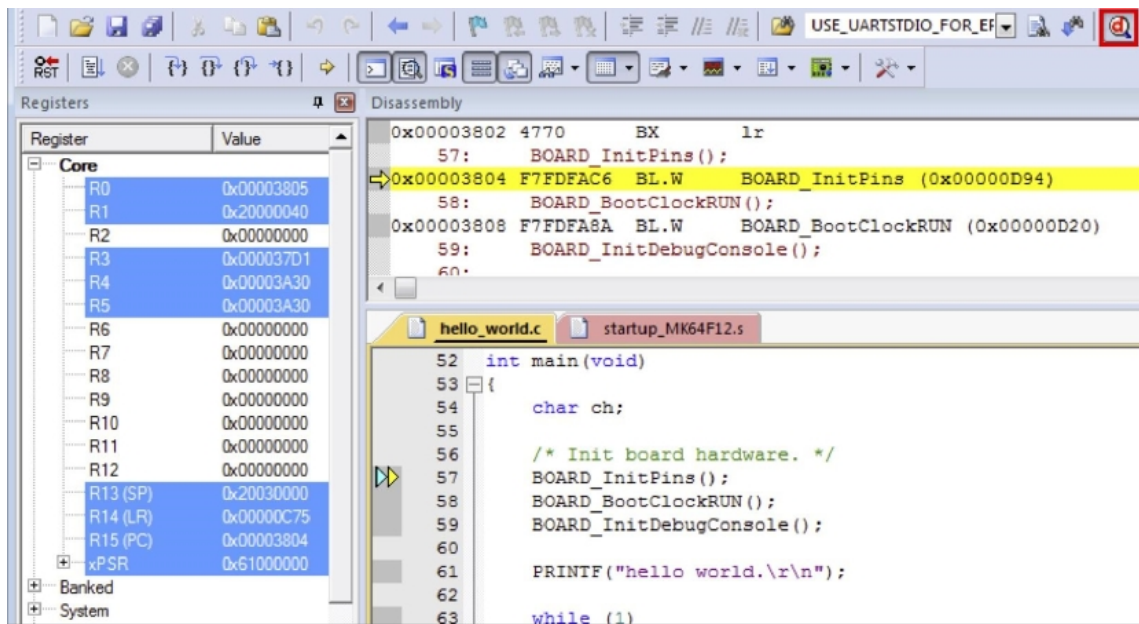


- 1 stop bit

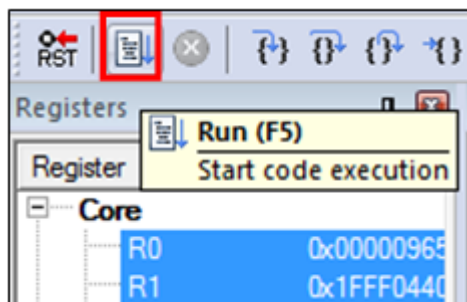
- In μ Vision, after the application is built, click the **Download** button to download the application to the target.



5. After clicking the **Download** button, the application downloads to the target and is running. To debug the application, click the **Start/Stop Debug Session** button, highlighted in red.



6. Run the code by clicking the **Run** button to start the application.



The `hello_world` application is now running and a banner is displayed on the terminal. If this does not appear, check your terminal settings and connections.



Build a multicore example application This section describes the steps to build and run a dual-core application. The demo applications workspace files are located in this folder:

```
<install_dir>/boards/<board_name>/multicore_examples/<application_name>/<core_type>/mdk
```

Begin with a simple dual-core version of the Hello World application. The multicore Hello World Keil MSDK/μVision workspaces are located in this folder:

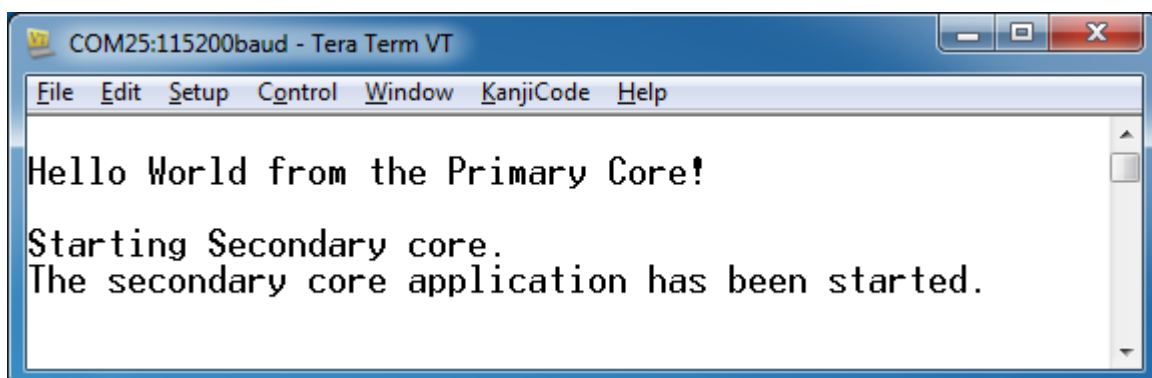
```
<install_dir>/boards/lpcxpresso54114/multicore_examples/hello_world/cm0plus/mdk/hello_world_
→cm0plus.uvmpw
```

```
<install_dir>/boards/lpcxpresso54114/multicore_examples/hello_world/cm4/mdk/hello_world_cm4.uvmpw
```

Build both applications separately by clicking the **Rebuild** button. Build the application for the auxiliary core (cm0plus) first because the primary core application project (cm4) must know the auxiliary core application binary when running the linker. It is not possible to finish the primary core linker when the auxiliary core application binary is not ready.

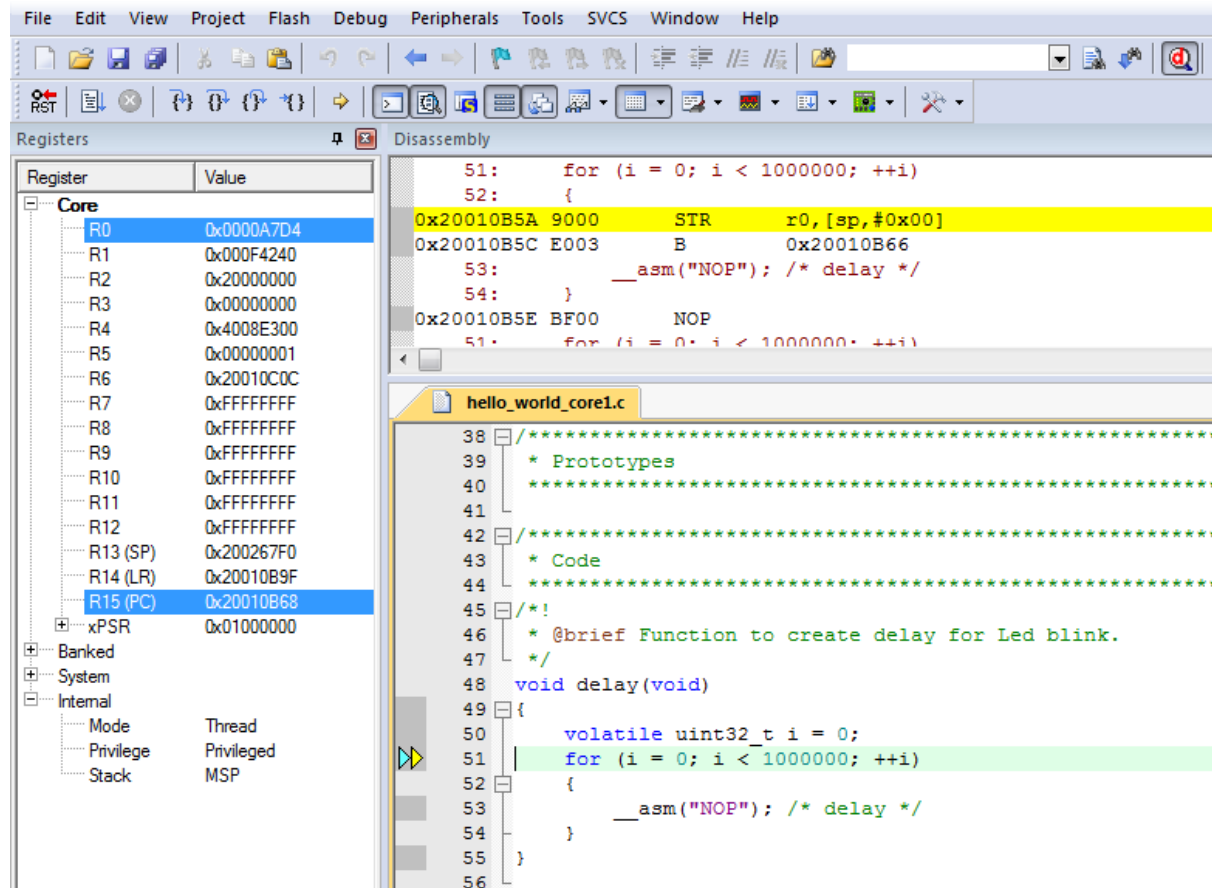
Run a multicore example application The primary core debugger flashes both the primary and the auxiliary core applications into the SoC flash memory. To download and run the multicore application, switch to the primary core application project and perform steps 1 – 5 as described in **Run an example application**. These steps are common for both single-core and dual-core applications in μVision.

Both the primary and the auxiliary image is loaded into the device flash memory. After clicking the “Run” button, the primary core application is executed. During the primary core code execution, the auxiliary core is released from the reset. The hello_world multicore application is now running and a banner is displayed on the terminal. If this does not appear, check your terminal settings and connections.



An LED controlled by the auxiliary core starts flashing indicating that the auxiliary core has been released from the reset and is running correctly.

Attach the running application of the auxiliary core by opening the auxiliary core project in the second μ Vision instance and clicking the “Start/Stop Debug Session” button. After this, the second debug session is opened and the auxiliary core application can be debugged.



Arm describes multicore debugging using the NXP LPC54114 Cortex-M4/M0+ dual-core processor and Keil uVision IDE in Application Note 318 at www.keil.com/appnotes/docs/apnt_318.asp. The associated video can be found [here](#).

Build a TrustZone example application This section describes the particular steps that must be done in order to build and run a TrustZone application. The demo applications workspace files are located in this folder:

```
<install_dir>/boards/<board_name>/trustzone_examples/<application_name>/<application_name>_ns/
↪ mdk
```

```
<install_dir>/boards/<board_name>/trustzone_examples/<application_name>/<application_name>_s/
↪ mdk
```

Begin with a simple TrustZone version of the Hello World application. The TrustZone Hello World Keil MSDK/ μ Vision workspaces are located in this folder:

```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_ns/mdk/hello_world_
↪ ns.uvmpw
```

```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_s/mdk/hello_world_s.
↪ uvmpw
```

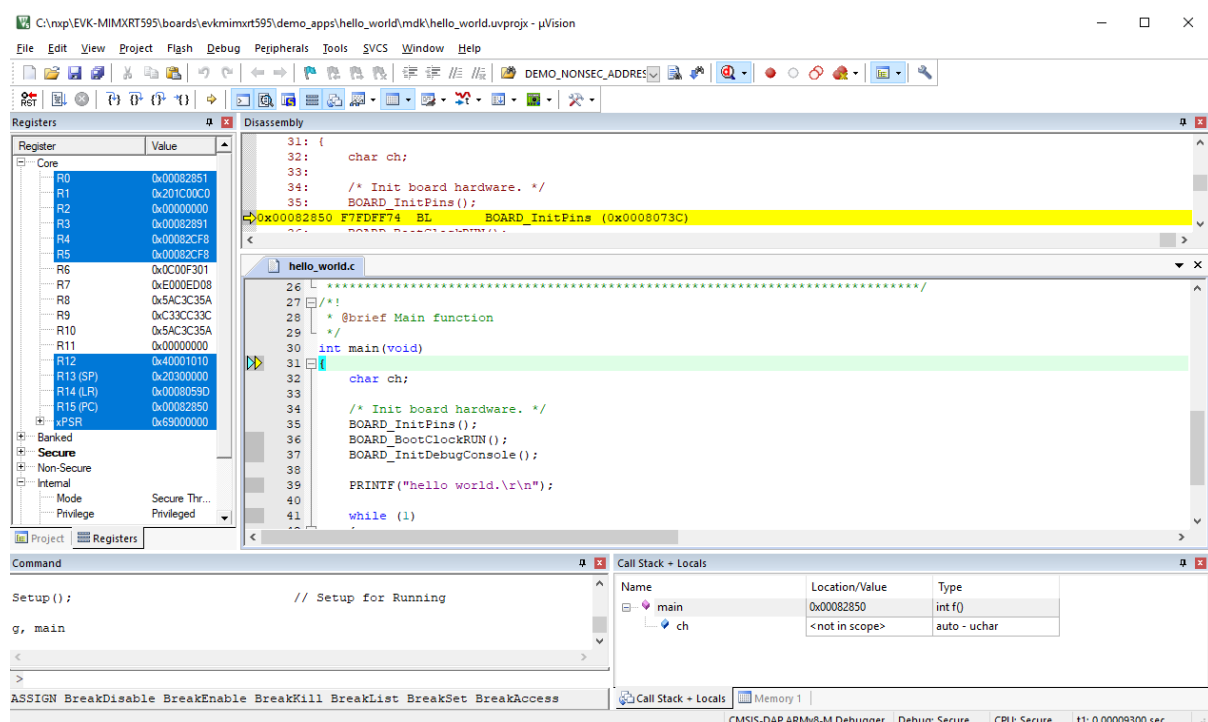
```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_s/mdk/hello_world.  
→ uvmpw
```

This project `hello_world.uvmpw` contains both secure and non-secure projects in one workspace and it allows the user to easily transition from one project to another.

Build both applications separately by clicking **Rebuild**. It is requested to build the application for the secure project first, because the non-secure project must know the secure project since CMSE library is running the linker. It is not possible to finish the non-secure project linker with the secure project because CMSE library is not ready.

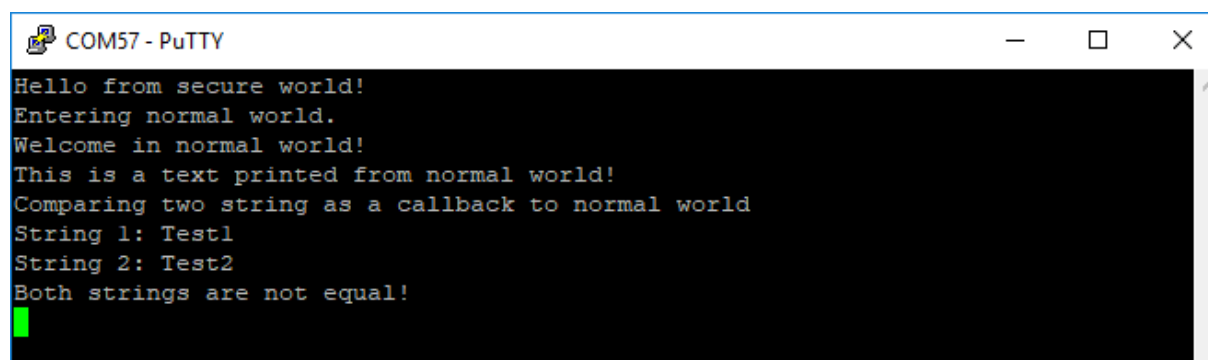
Run a TrustZone example application The secure project is configured to download both secure and non-secure output files so debugging can be fully managed from the secure project.

To download and run the TrustZone application, switch to the secure application project and perform steps as described in **Run an example application**. These steps are common for single core, dual-core, and TrustZone applications in μ Vision. After clicking **Download and Debug**, both the secure and non-secure images are loaded into the device flash memory, and the secure application is executed. It stops at the `main()` function.



Run the code by clicking **Run** to start the application.

The `hello_world` application is now running and a banner is displayed on the terminal. If not, check your terminal settings and connections.



Run a demo using Arm GCC

This section describes the steps to configure the command-line Arm GCC tools to build, run, and debug demo applications and necessary driver libraries provided in the MCUXpresso SDK. The `hello_world` demo application is targeted which is used as an example.

Set up toolchain This section contains the steps to install the necessary components required to build and run an MCUXpresso SDK demo application with the Arm GCC toolchain, as supported by the MCUXpresso SDK. There are many ways to use Arm GCC tools, but this example focuses on a Windows operating system environment.

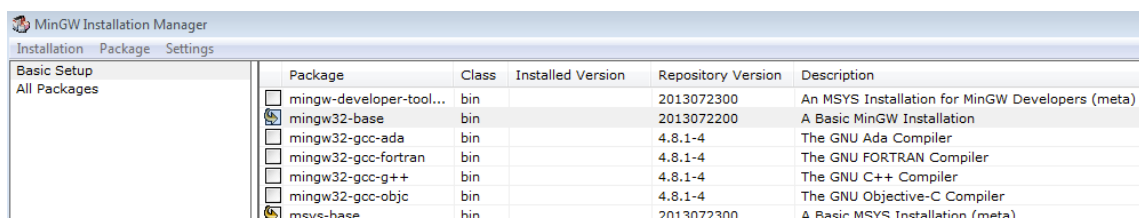
Install GCC Arm Embedded tool chain Download and run the installer from GNU Arm Embedded Toolchain. This is the actual toolset (in other words, compiler, linker, and so on). The GCC toolchain should correspond to the latest supported version, as described in **MCUXpresso SDK Release Notes**.

Install MinGW (only required on Windows OS) The Minimalist GNU for Windows (MinGW) development tools provide a set of tools that are not dependent on third-party C-Runtime DLLs (such as Cygwin). The build environment used by the MCUXpresso SDK does not use the MinGW build tools, but does leverage the base install of both MinGW and MSYS. MSYS provides a basic shell with a Unix-like interface and tools.

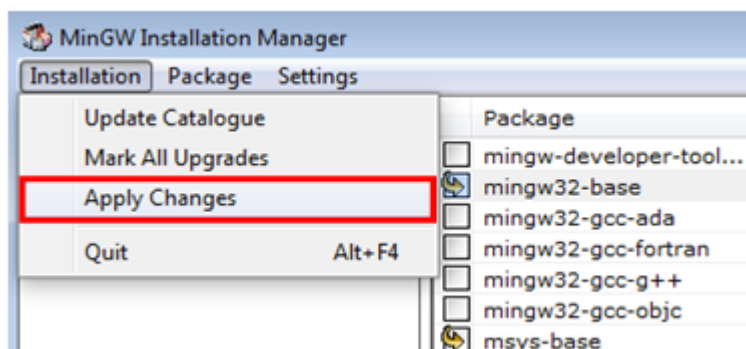
1. Download the latest MinGW mingw-get-setup installer from [MinGW](#).
2. Run the installer. The recommended installation path is `C:\MinGW`, however, you may install to any location.

Note: The installation path cannot contain any spaces.

3. Ensure that the **mingw32-base** and **msys-base** are selected under **Basic Setup**.



4. In the **Installation** menu, click **Apply Changes** and follow the remaining instructions to complete the installation.

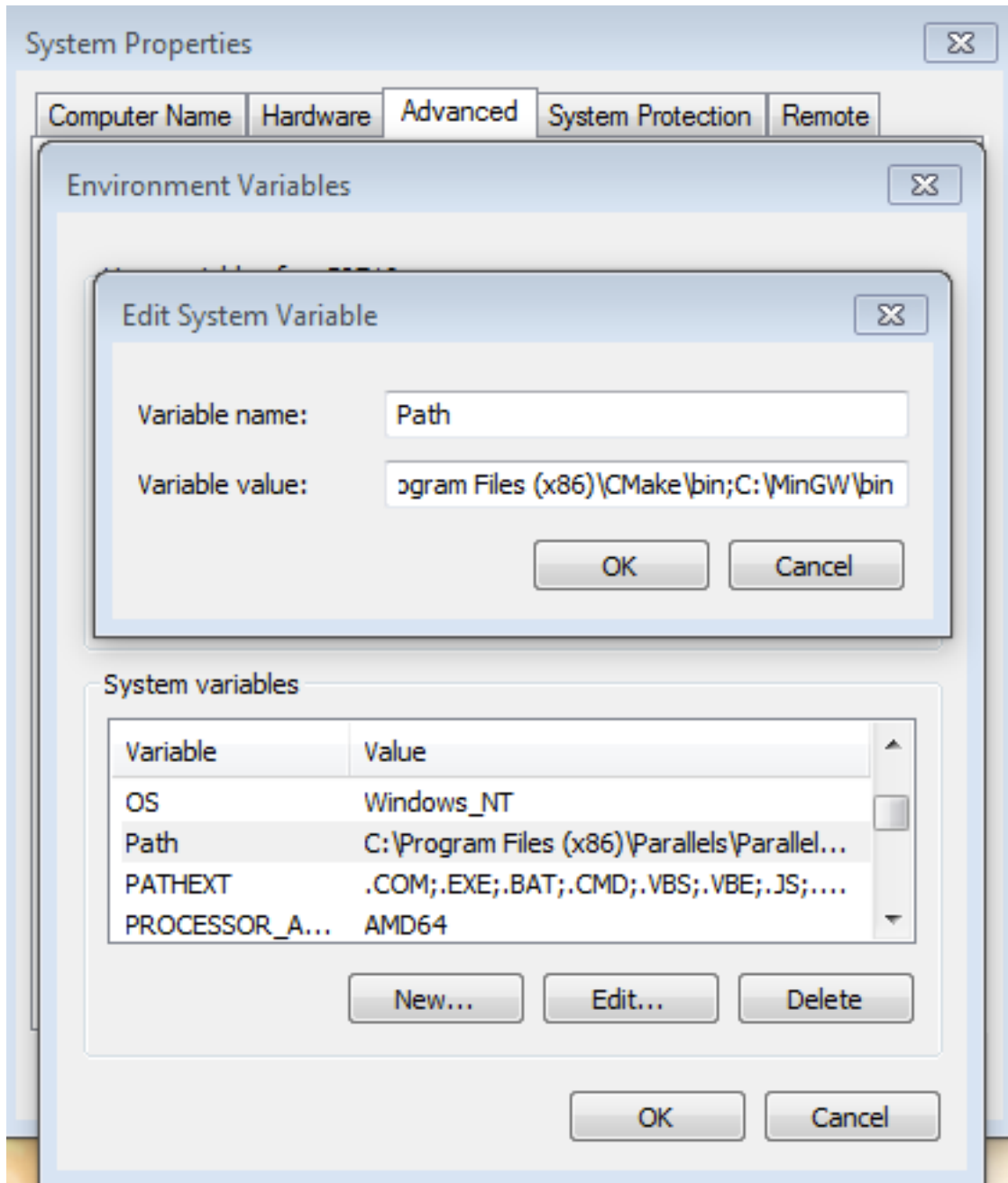


5. Add the appropriate item to the Windows operating system path environment variable. It can be found under **Control Panel->System and Security->System->Advanced System Settings** in the **Environment Variables...** section. The path is:


```
<mingw_install_dir>\bin
```

Assuming the default installation path, C:\MinGW, an example is shown below. If the path is not set correctly, the toolchain will not work.

Note: If you have C:\MinGW\msys\x.x\bin in your PATH variable (as required by Kinetis SDK 1.0.0), remove it to ensure that the new GCC build system works correctly.



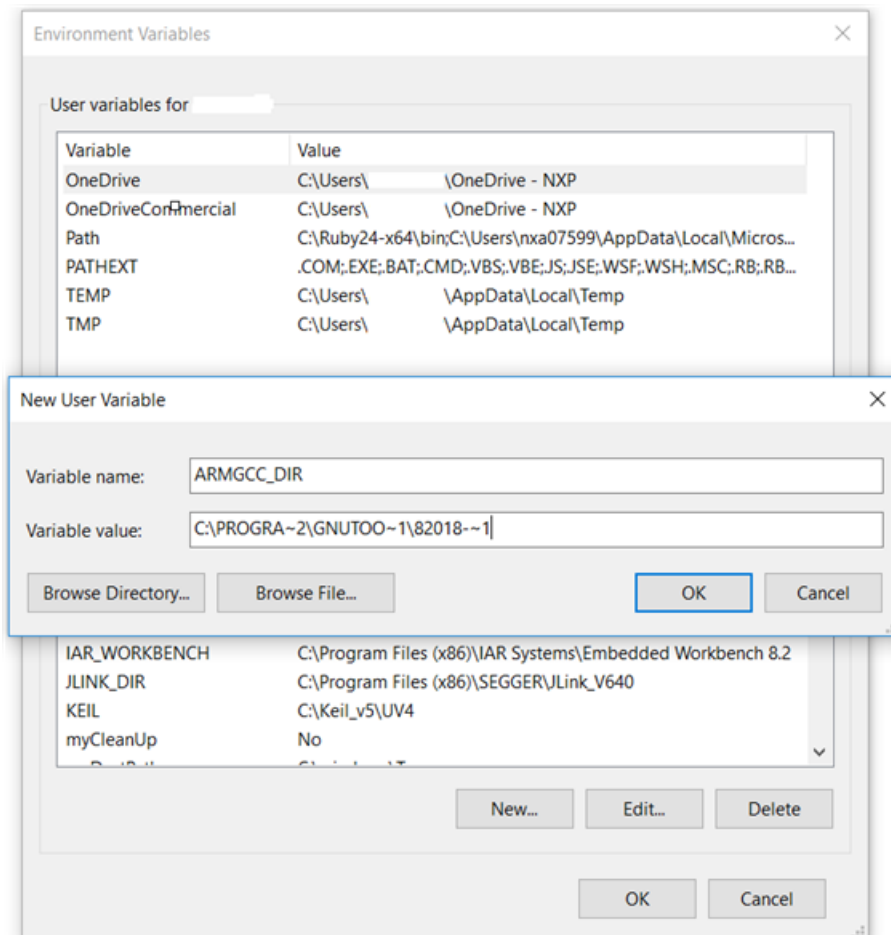
Add a new system environment variable for ARMGCC_DIR Create a new *system* environment variable and name it as ARMGCC_DIR. The value of this variable should point to the Arm GCC Embedded tool chain installation path. For this example, the path is:

```
C:\Program Files (x86)\GNU Tools Arm Embedded\8 2018-q4-major
```

See the installation folder of the GNU Arm GCC Embedded tools for the exact pathname of your installation.

Short path should be used for path setting, you could convert the path to short path by running command for %I in (.) do echo %~sI

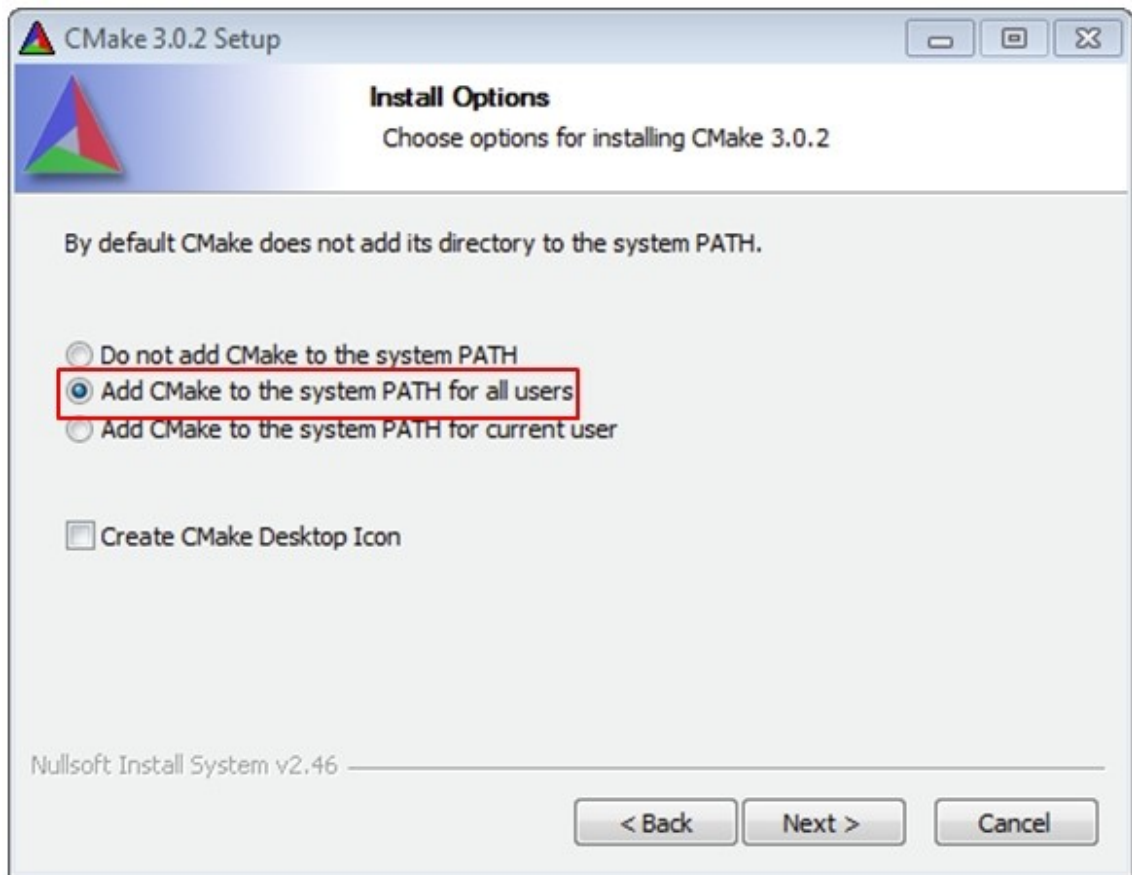
```
C:\Program Files (x86)\GNU Tools Arm Embedded\8 2018-q4-major>for %I in (.) do echo %~sI
C:\Program Files (x86)\GNU Tools Arm Embedded\8 2018-q4-major>echo C:\PROGRA~2\GNUTOO~1\82018~1
C:\PROGRA~2\GNUTOO~1\82018~1
```



Install CMake

Windows OS

1. Download CMake 3.0.x from www.cmake.org/cmake/resources/software.html.
2. Install CMake, ensuring that the option **Add CMake to system PATH** is selected when installing. The user chooses to select whether it is installed into the PATH for all users or just the current user. In this example, it is installed for all users.



3. Follow the remaining instructions of the installer.
4. You may need to reboot your system for the PATH changes to take effect.
5. Make sure `sh.exe` is not in the Environment Variable PATH. This is a limitation of mingw32-make.

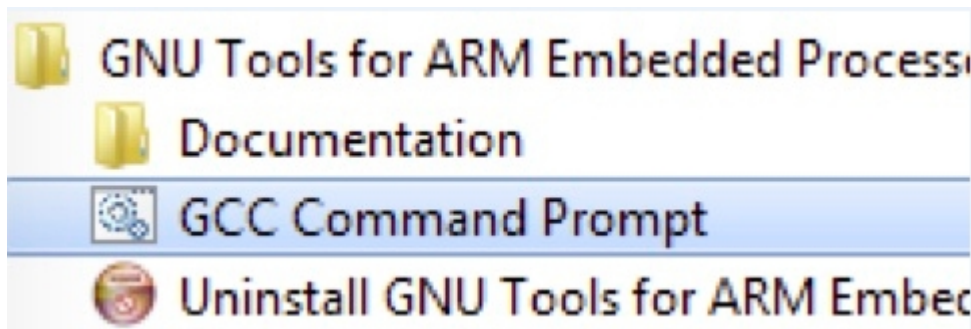
Linux OS It depends on the distributions of Linux Operation System. Here we use Ubuntu as an example.

Open shell and use following commands to install cmake and its version. Ensure the cmake version is above 3.0.x.

```
$ sudo apt-get install cmake
$ cmake --version
```

Build an example application To build an example application, follow these steps.

1. Open a GCC Arm Embedded tool chain command window. To launch the window, from the Windows operating system **Start** menu, go to **Programs > GNU Tools Arm Embedded <version>** and select **GCC Command Prompt**.



2. Change the directory to the example application project directory which has a path similar to the following:

```
<install_dir>/boards/<board_name>/<example_type>/<application_name>/armgcc
```

For this example, the exact path is:

Note: To change directories, use the `cd` command.

3. Type **build_debug.bat** on the command line or double click on **build_debug.bat** file in Windows Explorer to build it. The output is as shown in following figure.

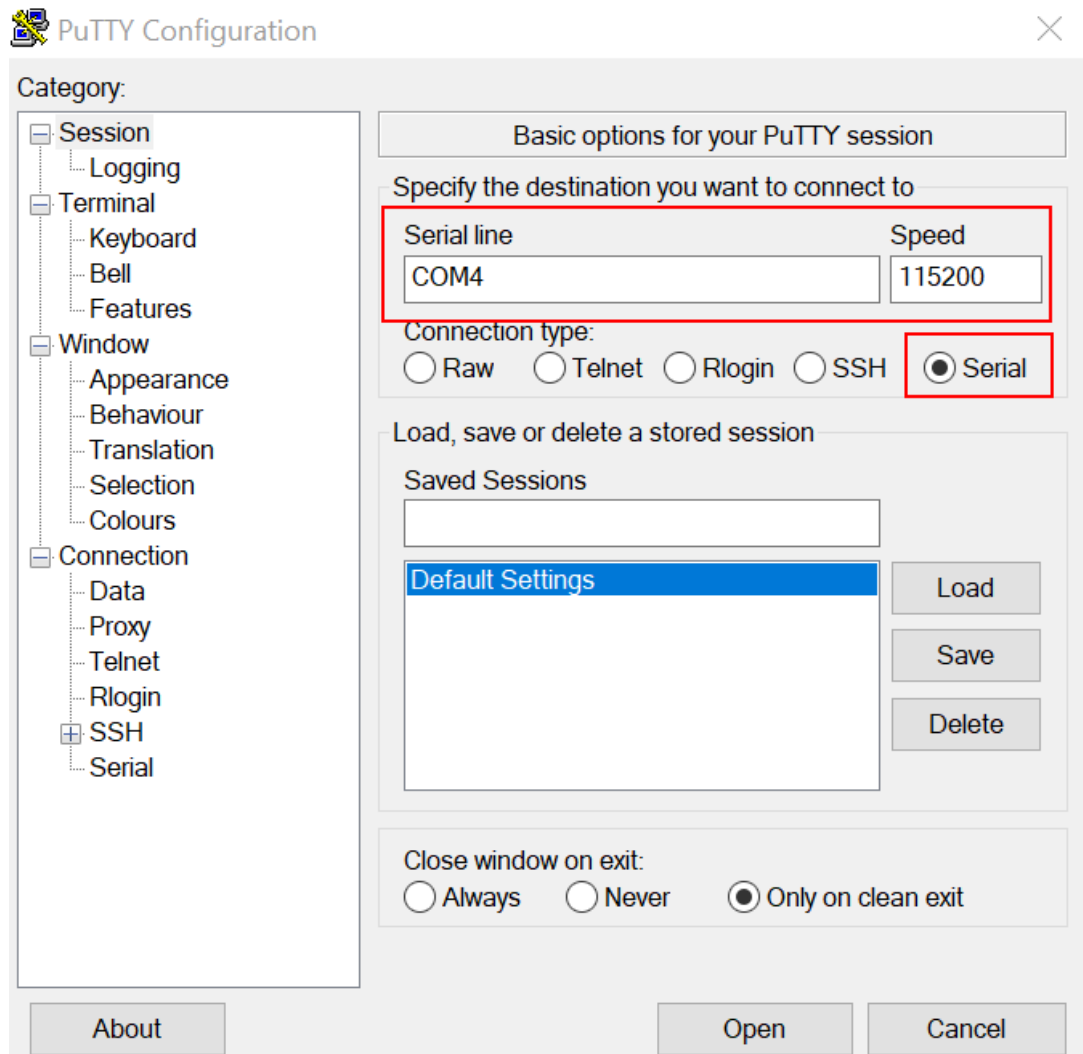
```
[ 84%] Building C object CMakeFiles/hello_world.elf.dir/C:/nxp/SDK_2.0_FRDM-K64F
/devices/MK64F12/drivers/fsl_smc.c.obj
[ 92%] Building C object CMakeFiles/hello_world.elf.dir/C:/nxp/SDK_2.0_FRDM-K64F
/devices/MK64F12/drivers/fsl_clock.c.obj
[100%] Linking C executable debug\hello_world.elf
[100%] Built target hello_world.elf

C:\nxp\SDK_2.0_FRDM-K64F\boards\frdmk64f\demo_apps\hello_world\armgcc>IF "" == "
" <pause >
Press any key to continue . . .
```

Run an example application This section describes steps to run a demo application using J-Link GDB Server application. To install J-Link host driver and update the on-board debugger firmware to Jlink firmware, see [On-board debugger](#).

After the J-Link interface is configured and connected, follow these steps to download and run the demo applications:

1. Connect the development platform to your PC via USB cable between the on-board debugger USB connector and the PC USB connector. If using a standalone J-Link debug pod, connect it to the SWD/JTAG connector of the board.
2. Open the terminal application on the PC, such as PuTTY or TeraTerm, and connect to the debug serial port number (to determine the COM port number, see [How to determine COM port](#)). Configure the terminal with these settings:
 1. 115200 or 9600 baud rate, depending on your board (reference BOARD_DEBUG_UART_BAUDRATE variable in board.h file)
 2. No parity
 3. 8 data bits
 4. 1 stop bit



3. To launch the application, open the Windows **Start** menu and select **Programs > SEGGER > J-Link <version> J-Link GDB Server**.

Note: It is assumed that the J-Link software is already installed.

The **SEGGER J-Link GDB Server Config** settings dialog appears.

4. Make sure to check the following options.
 1. **Target interface:** The debug connection on board uses internal SWD signaling. In case of a wrong setting J-Link is unable to communicate with device under test.
 2. **Script file:** If required, a J-Link init script file can be used for board initialization. The file with the ".jlinkscript" file extension is located in the <install_dir>/boards/<board_name>/ directory.
 3. Under the **Server settings**, check the GDB port for connection with the gdb target remote command. For more information, see step 9.
 4. There is a command line version of J-Link GDB server "JLinkGDBServerCL.exe". Typical path is C:\Program Files\SEGGER\JLink\. To start the J-Link GDB server with the same settings as are selected in the UI, you can use these command line options.

SEGGER J-Link GDB Server V7.94b Config

Connection to J-Link

☒ USB ☒ SN / Nickname 0

☐ TCP/IP

Target device

MIMXRT1021xxx4A ...

Little Endian

Flash banks

BaseAddr	Name	Loader
0x60000000	External QSPI flash	Default

Target interface a)

SWD

Speed

☐ Auto Selection

☐ Adaptive clocking

☒ Fixed 4000 kHz

Script file (optional) b)

...

Server settings

☐ Init registers

☒ Localhost only

☐ Generate logfile c)

GDB port 2331

SWO port 2332

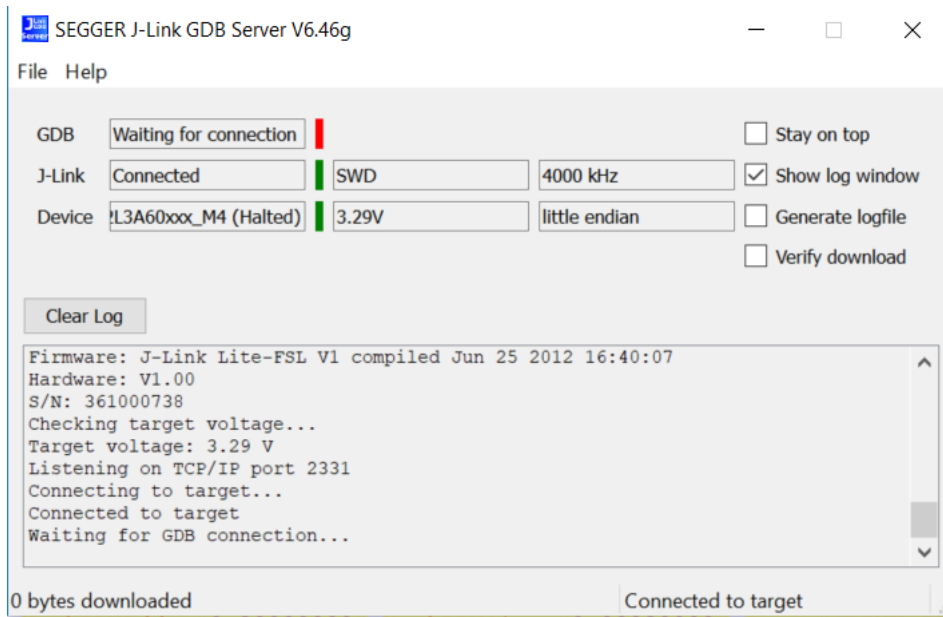
Telnet port 2333

Command line option d)

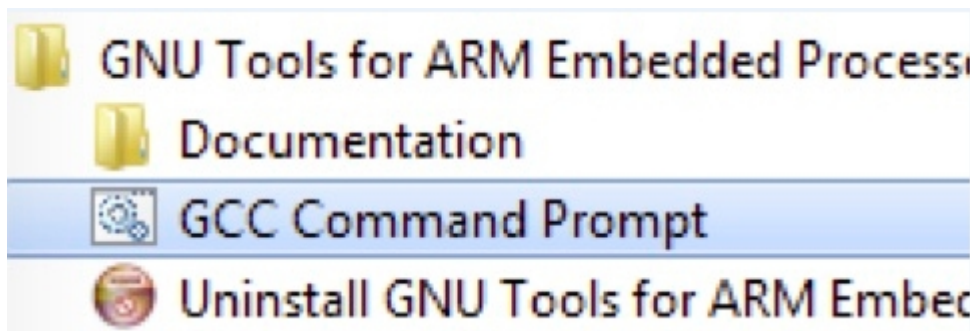
```
-select USB=0 -device MIMXRT1021xxx4A -endian little -if SWD -speed 4000 -noir -LocalhostOnly -nologtofile -port 2331 -SWOPort 2332 -TelnetPort 2333
```

OK Cancel

5. After it is connected, the screen should look like this figure:



6. If not already running, open a GCC Arm Embedded tool chain command window. To launch the window, from the Windows operating system Start menu, go to **Programs - GNU Tools Arm Embedded <version>** and select **GCC Command Prompt**.

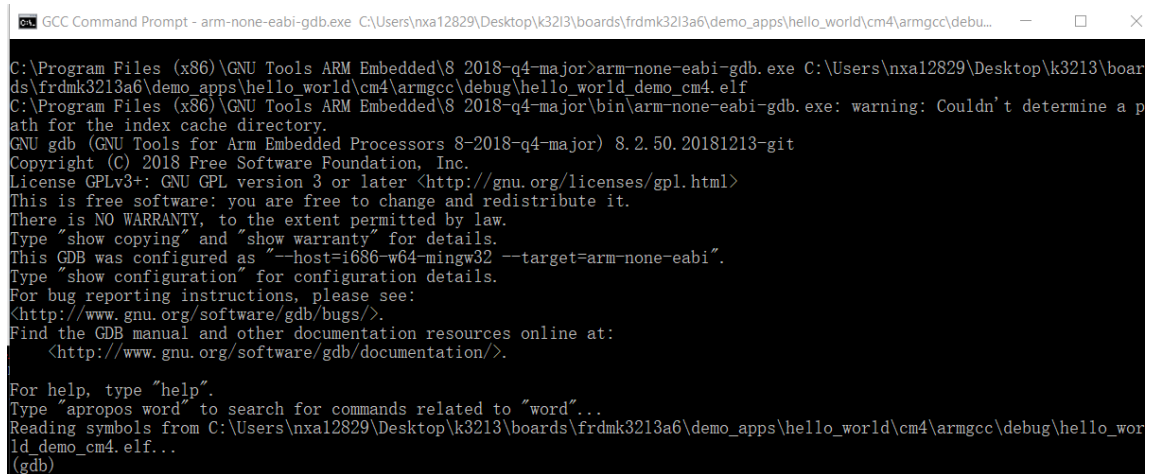


7. Change to the directory that contains the example application output. The output can be found in using one of these paths, depending on the build target selected:

```
<install_dir>/boards/<board_name>/<example_type>/<application_name>/armgcc/debug
```

```
<install_dir>/boards/<board_name>/<example_type>/<application_name>/armgcc/release
```

8. Run the `arm-none-eabi-gdb.exe <application_name>.elf` command. For this example, it is `arm-none-eabi-gdb.exe hello_world.elf`.



```

GCC Command Prompt - arm-none-eabi-gdb.exe C:\Users\nxa12829\Desktop\k3213\boards\frdmk3213a6\demo_apps\hello_world\cm4\armgcc\debug\hello_world_demo_cm4.elf
C:\Program Files (x86)\GNU Tools ARM Embedded\8 2018-q4-major>arm-none-eabi-gdb.exe C:\Users\nxa12829\Desktop\k3213\boards\frdmk3213a6\demo_apps\hello_world\cm4\armgcc\debug\hello_world_demo_cm4.elf
C:\Program Files (x86)\GNU Tools ARM Embedded\8 2018-q4-major\bin>arm-none-eabi-gdb.exe: warning: Couldn't determine a path for the index cache directory.
GNU gdb (GNU Tools for Arm Embedded Processors 8-2018-q4-major) 8.2.50.20181213-git
Copyright (C) 2018 Free Software Foundation, Inc.
License GPLv3+: GNU GPL version 3 or later <http://gnu.org/licenses/gpl.html>
This is free software: you are free to change and redistribute it.
There is NO WARRANTY, to the extent permitted by law.
Type "show copying" and "show warranty" for details.
This GDB was configured as "--host=i686-w64-mingw32 --target=arm-none-eabi".
Type "show configuration" for configuration details.
For bug reporting instructions, please see:
<http://www.gnu.org/software/gdb/bugs/>.
Find the GDB manual and other documentation resources online at:
<http://www.gnu.org/software/gdb/documentation/>.

For help, type "help".
Type "apropos word" to search for commands related to "word"...
Reading symbols from C:\Users\nxa12829\Desktop\k3213\boards\frdmk3213a6\demo_apps\hello_world\cm4\armgcc\debug\hello_world_demo_cm4.elf...
(gdb)

```

9. Run these commands:

1. target remote localhost:2331
2. monitor reset
3. monitor halt
4. load
5. monitor reset

10. The application is now downloaded and halted. Execute the `monitor go` command to start the demo application.

The `hello_world` application is now running and a banner is displayed on the terminal. If this does not appear, check your terminal settings and connections.



```

COM4 - PuTTY
hello world.

```

Build a multicore example application This section describes the steps to build and run a dual-core application. The demo application build scripts are located in this folder:

```
<install_dir>/boards/<board_name>/multicore_examples/<application_name>/<core_type>/armgcc
```

Begin with a simple dual-core version of the Hello World application. The multicore Hello World GCC build scripts are located in this folder:

```
<install_dir>/boards/lpcxpresso54114/multicore_examples/hello_world/cm0plus/armgcc/build_debug.bat
```

```
<install_dir>/boards/lpcxpresso54114/multicore_examples/hello_world/cm4/armgcc/build_debug.bat
```

Build both applications separately following steps for single core examples as described in **Build an example application**.

```

GCC Command Prompt - build_debug.bat

[ 47%] Building C object CMakeFiles/hello_world_cm0plus.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/drivers/fsl_common.c.obj
[ 52%] Building C object CMakeFiles/hello_world_cm0plus.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/drivers/fsl_msmc.c.obj
[ 56%] Building C object CMakeFiles/hello_world_cm0plus.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/utilities/debug_console/fsl_debug_console.c.obj
[ 60%] Building C object CMakeFiles/hello_world_cm0plus.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/utilities/fsl_assert.c.obj
[ 65%] Building C object CMakeFiles/hello_world_cm0plus.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/utilities/str/fsl_str.c.obj
[ 69%] Building C object CMakeFiles/hello_world_cm0plus.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/components/uart/lpuart_adapter.c.obj
[ 73%] Building C object CMakeFiles/hello_world_cm0plus.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/components/serial_manager/serial_manager.c.obj
[ 78%] Building C object CMakeFiles/hello_world_cm0plus.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/components/serial_manager/serial_port_uart.c.obj
[ 82%] Building C object CMakeFiles/hello_world_cm0plus.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/components/lists/generic_list.c.obj
[ 86%] Building C object CMakeFiles/hello_world_cm0plus.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/system_K32L3A60_cm0plus.c.obj
[ 91%] Building ASM object CMakeFiles/hello_world_cm0plus.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/gcc/startup_K32L3A60_cm0plus.S.obj
[ 95%] Building C object CMakeFiles/hello_world_cm0plus.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/middleware/multicore/mcmgr/src/mcmgr.c.obj
[100%] Linking C executable debug\hello_world_cm0plus.elf
[100%] Built target hello_world_cm0plus.elf

c:\packages\SDK_2.6.0_FRDM-K32L3A6_RC1\boards\frdmk32l3a6\multicore_examples\hello_world\cm0plus\armgcc>IF "" == "" (pause)
Press any key to continue . . .

GCC Command Prompt - build_debug.bat

[ 50%] Building C object CMakeFiles/hello_world_cm4.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/drivers/fsl_lpuart.c.obj
[ 54%] Building C object CMakeFiles/hello_world_cm4.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/drivers/fsl_common.c.obj
[ 58%] Building C object CMakeFiles/hello_world_cm4.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/drivers/fsl_msmc.c.obj
[ 62%] Building C object CMakeFiles/hello_world_cm4.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/utilities/str/fsl_str.c.obj
[ 66%] Building C object CMakeFiles/hello_world_cm4.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/utilities/fsl_assert.c.obj
[ 70%] Building C object CMakeFiles/hello_world_cm4.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/utilities/debug_console/fsl_debug_console.c.obj
[ 75%] Building C object CMakeFiles/hello_world_cm4.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/components/uart/lpuart_adapter.c.obj
[ 79%] Building C object CMakeFiles/hello_world_cm4.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/components/serial_manager/serial_port_uart.c.obj
[ 83%] Building C object CMakeFiles/hello_world_cm4.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/components/serial_manager/serial_manager.c.obj
[ 87%] Building C object CMakeFiles/hello_world_cm4.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/components/lists/generic_list.c.obj
[ 91%] Building C object CMakeFiles/hello_world_cm4.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/system_K32L3A60_cm4.c.obj
[ 95%] Building ASM object CMakeFiles/hello_world_cm4.elf.dir/C:/packages/SDK_2.6.0_FRDM-K32L3A6_RC1/devices/K32L3A60/gcc/startup_K32L3A60_cm4.S.obj
[100%] Linking C executable debug\hello_world_cm4.elf
[100%] Built target hello_world_cm4.elf

c:\packages\SDK_2.6.0_FRDM-K32L3A6_RC1\boards\frdmk32l3a6\multicore_examples\hello_world\cm4\armgcc>IF "" == "" (pause)
Press any key to continue . . .

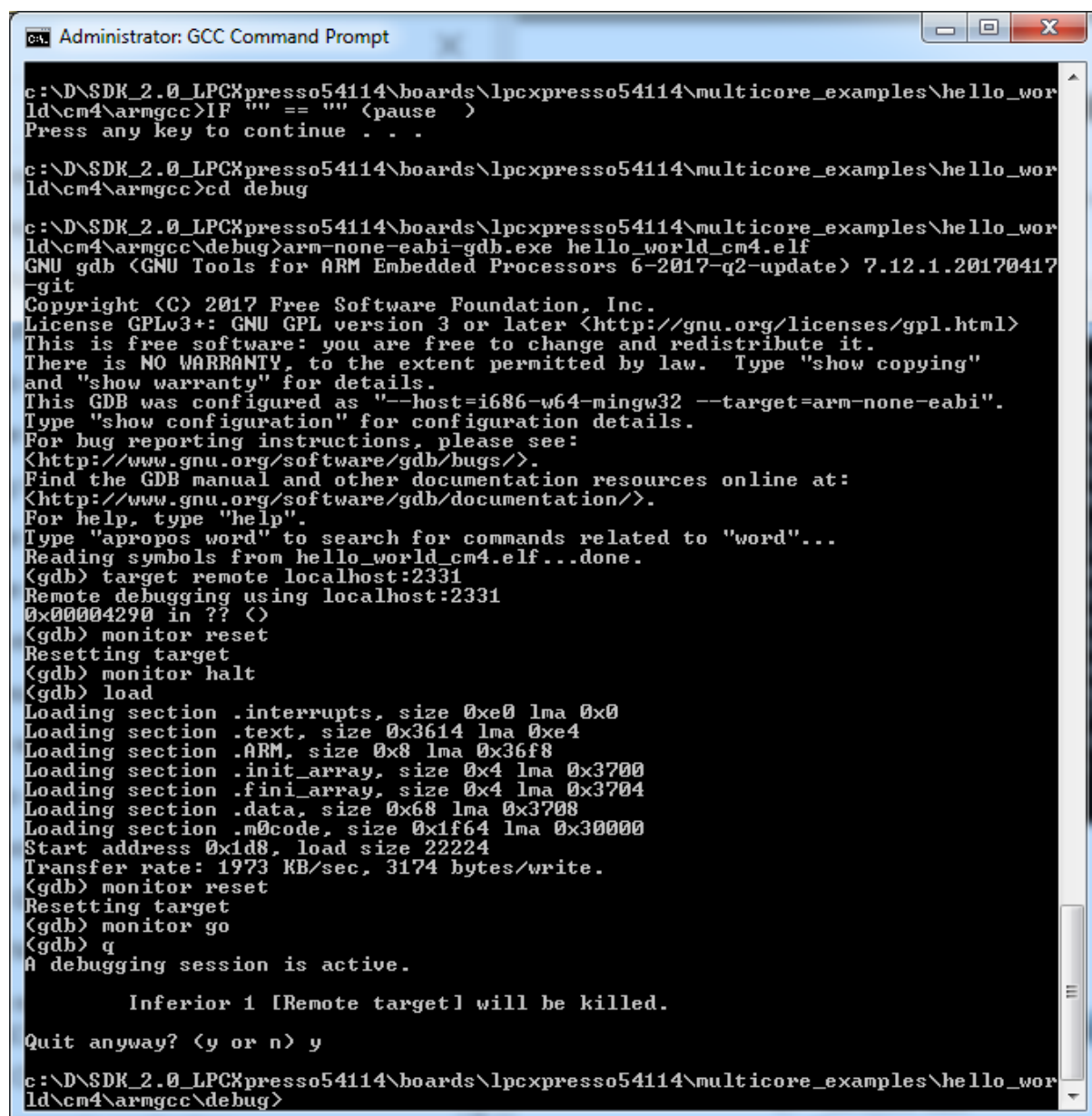
```

Run a multicore example application When running a multicore application, the same prerequisites for J-Link/J-Link OpenSDA firmware, and the serial console as for the single-core application, applies, as described in **Run an example application**.

The primary core debugger handles flashing of both the primary and the auxiliary core applications into the SoC flash memory. To download and run the multicore application, switch to the primary core application project and perform steps 1 to 10, as described in **Run an example application**. These steps are common for both single-core and dual-core applications in Arm GCC.

Both the primary and the auxiliary image is loaded into the SPI flash memory. After execution of the monitor go command, the primary core application is executed. During the primary core code execution, the auxiliary core code is reallocated from the flash memory to the RAM, and the auxiliary core is released from the reset. The hello_world multicore application is now running

and a banner is displayed on the terminal. If this is not true, check your terminal settings and connections.



```

Administrator: GCC Command Prompt

c:\D\SDK_2.0_LPCXpresso54114\boards\lpcxpresso54114\multicore_examples\hello_world_cm4\armgcc>IF "" == "" <pause >
Press any key to continue . . .

c:\D\SDK_2.0_LPCXpresso54114\boards\lpcxpresso54114\multicore_examples\hello_world_cm4\armgcc>cd debug

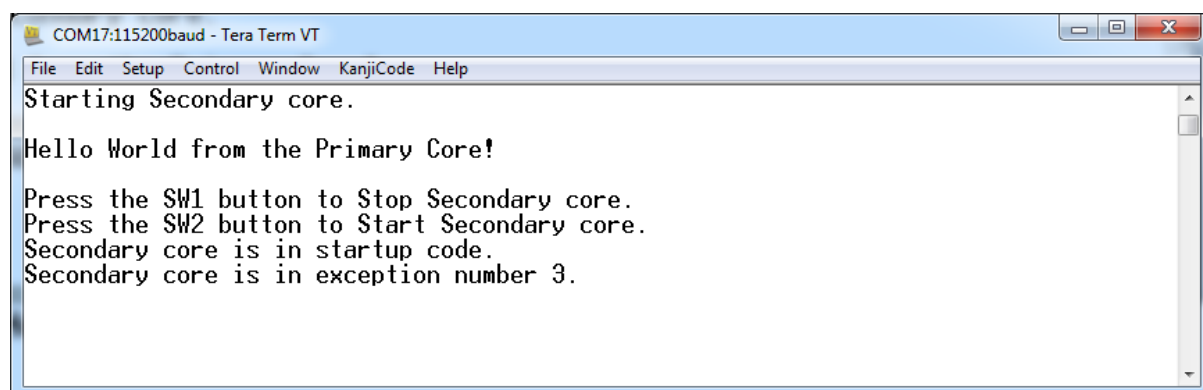
c:\D\SDK_2.0_LPCXpresso54114\boards\lpcxpresso54114\multicore_examples\hello_world_cm4\armgcc\debug>arm-none-eabi-gdb.exe hello_world_cm4.elf
GNU gdb (GNU Tools for ARM Embedded Processors 6-2017-q2-update) 7.12.1.20170417-git
Copyright (C) 2017 Free Software Foundation, Inc.
License GPLv3+: GNU GPL version 3 or later <http://gnu.org/licenses/gpl.html>
This is free software: you are free to change and redistribute it.
There is NO WARRANTY, to the extent permitted by law. Type "show copying"
and "show warranty" for details.
This GDB was configured as "--host=i686-w64-mingw32 --target=arm-none-eabi".
Type "show configuration" for configuration details.
For bug reporting instructions, please see:
<http://www.gnu.org/software/gdb/bugs/>.
Find the GDB manual and other documentation resources online at:
<http://www.gnu.org/software/gdb/documentation/>.
For help, type "help".
Type "apropos word" to search for commands related to "word"...
Reading symbols from hello_world_cm4.elf...done.
(gdb) target remote localhost:2331
Remote debugging using localhost:2331
0x00004290 in ?? ()
(gdb) monitor reset
Resetting target
(gdb) monitor halt
(gdb) load
Loading section .interrupts, size 0xe0 lma 0x0
Loading section .text, size 0x3614 lma 0xe4
Loading section .ARM, size 0x8 lma 0x36f8
Loading section .init_array, size 0x4 lma 0x3700
Loading section .fini_array, size 0x4 lma 0x3704
Loading section .data, size 0x68 lma 0x3708
Loading section .m0code, size 0x1f64 lma 0x30000
Start address 0x1d8, load size 22224
Transfer rate: 1973 KB/sec, 3174 bytes/write.
(gdb) monitor reset
Resetting target
(gdb) monitor go
(gdb) q
A debugging session is active.

    Inferior 1 [Remote target] will be killed.

Quit anyway? (y or n) y

c:\D\SDK_2.0_LPCXpresso54114\boards\lpcxpresso54114\multicore_examples\hello_world_cm4\armgcc\debug>

```



```

COM17:115200baud - Tera Term VT
File Edit Setup Control Window KanjiCode Help
Starting Secondary core.

Hello World from the Primary Core!

Press the SW1 button to Stop Secondary core.
Press the SW2 button to Start Secondary core.
Secondary core is in startup code.
Secondary core is in exception number 3.

```

Build a TrustZone example application This section describes the steps to build and run a TrustZone application. The demo application build scripts are located in this folder:


```
<install_dir>/boards/<board_name>/trustzone_examples/<application_name>/[<core_type>]/
↪<application_name>_ns/armgcc
```

```
<install_dir>/boards/<board_name>/trustzone_examples/<application_name>/[<core_type>]/
↪<application_name>_s/armgcc
```

Begin with a simple TrustZone version of the Hello World application. The TrustZone Hello World GCC build scripts are located in this folder:

```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_ns/armgcc/build_
↪debug.bat
```

```
<install_dir>/boards/<board_name>/trustzone_examples/hello_world/hello_world_s/armgcc/build_
↪debug.bat
```

Build both applications separately, following steps for single core examples as described in **Build an example application**. It is requested to build the application for the secure project first, because the non-secure project must know the secure project, since CMSE library is running the linker. It is not possible to finish the non-secure project linker with the secure project because the CMSE library is not ready.

```
C:\WINDOWS\system32\cmd.exe
[ 55%] Building C object CMakeFiles/hello_world_s.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/utilities/fsl_
l_assert.c.obj
[ 59%] Building C object CMakeFiles/hello_world_s.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/components/uart/usart_adapter.c
.obj
[ 62%] Building C object CMakeFiles/hello_world_s.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/drivers/fsl_
flexspi.c.obj
[ 66%] Building C object CMakeFiles/hello_world_s.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/drivers/fsl_
cache.c.obj
[ 70%] Building C object CMakeFiles/hello_world_s.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/components/serial_manager/seria
l_manager.c.obj
[ 74%] Building C object CMakeFiles/hello_world_s.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/components/serial_manager/seria
l_port_uart.c.obj
[ 77%] Building ASM object CMakeFiles/hello_world_s.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/gcc/startu
p_MIMXRT595S_cm33.S.obj
[ 81%] Building C object CMakeFiles/hello_world_s.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/components/lists/generic_list.c
.obj
[ 85%] Building C object CMakeFiles/hello_world_s.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/drivers/fsl_
uart.c.obj
[ 88%] Building C object CMakeFiles/hello_world_s.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/drivers/fsl_
flexcomm.c.obj
[ 92%] Building C object CMakeFiles/hello_world_s.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/drivers/fsl_
pio.c.obj
[ 96%] Building C object CMakeFiles/hello_world_s.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/drivers/fsl_
iap.c.obj
[100%] Linking C executable debug\hello_world_s.elf
[100%] Built target hello_world_s.elf
C:\npx\SDK_2.6.0_EVK-MIMXRT595\boards\evkmimxrt595\trustzone_examples\hello_world\hello_world_s\armgcc>IF "" == "" (paus
e)
Press any key to continue . . .
```

```

C:\WINDOWS\system32\cmd.exe
[ 52%] Building C object CMakeFiles/hello_world_ns.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/components/uart/usart_adapter.c.obj
[ 56%] Building C object CMakeFiles/hello_world_ns.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/utilities/flexspi_assert.c.obj
[ 60%] Building C object CMakeFiles/hello_world_ns.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/drivers/flexspi/flexspi.c.obj
[ 64%] Building C object CMakeFiles/hello_world_ns.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/drivers/flexspi/cache.c.obj
[ 68%] Building C object CMakeFiles/hello_world_ns.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/components/serial_manager/serial_manager.c.obj
[ 72%] Building C object CMakeFiles/hello_world_ns.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/components/serial_manager/serial_port_uart.c.obj
[ 76%] Building C object CMakeFiles/hello_world_ns.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/drivers/flexspi/usart.c.obj
[ 80%] Building C object CMakeFiles/hello_world_ns.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/components/lists/generic_list.c.obj
[ 84%] Building ASM object CMakeFiles/hello_world_ns.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/gcc/startup_MIMXRT595S_cm33.S.obj
[ 88%] Building C object CMakeFiles/hello_world_ns.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/drivers/flexcomm/flexcomm.c.obj
[ 92%] Building C object CMakeFiles/hello_world_ns.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/drivers/flexcomm/gpio.c.obj
[ 96%] Building C object CMakeFiles/hello_world_ns.elf.dir/C:/npx/SDK_2.6.0_EVK-MIMXRT595/devices/MIMXRT595S/drivers/flexcomm/iap.c.obj
[100%] Linking C executable debug\hello_world_ns.elf
[100%] Built target hello_world_ns.elf

C:\npx\SDK_2.6.0_EVK-MIMXRT595\boards\evkmimxrt595\trustzone_examples\hello_world\hello_world_ns\armgcc>IF "" == "" (pause)
Press any key to continue . . .

```

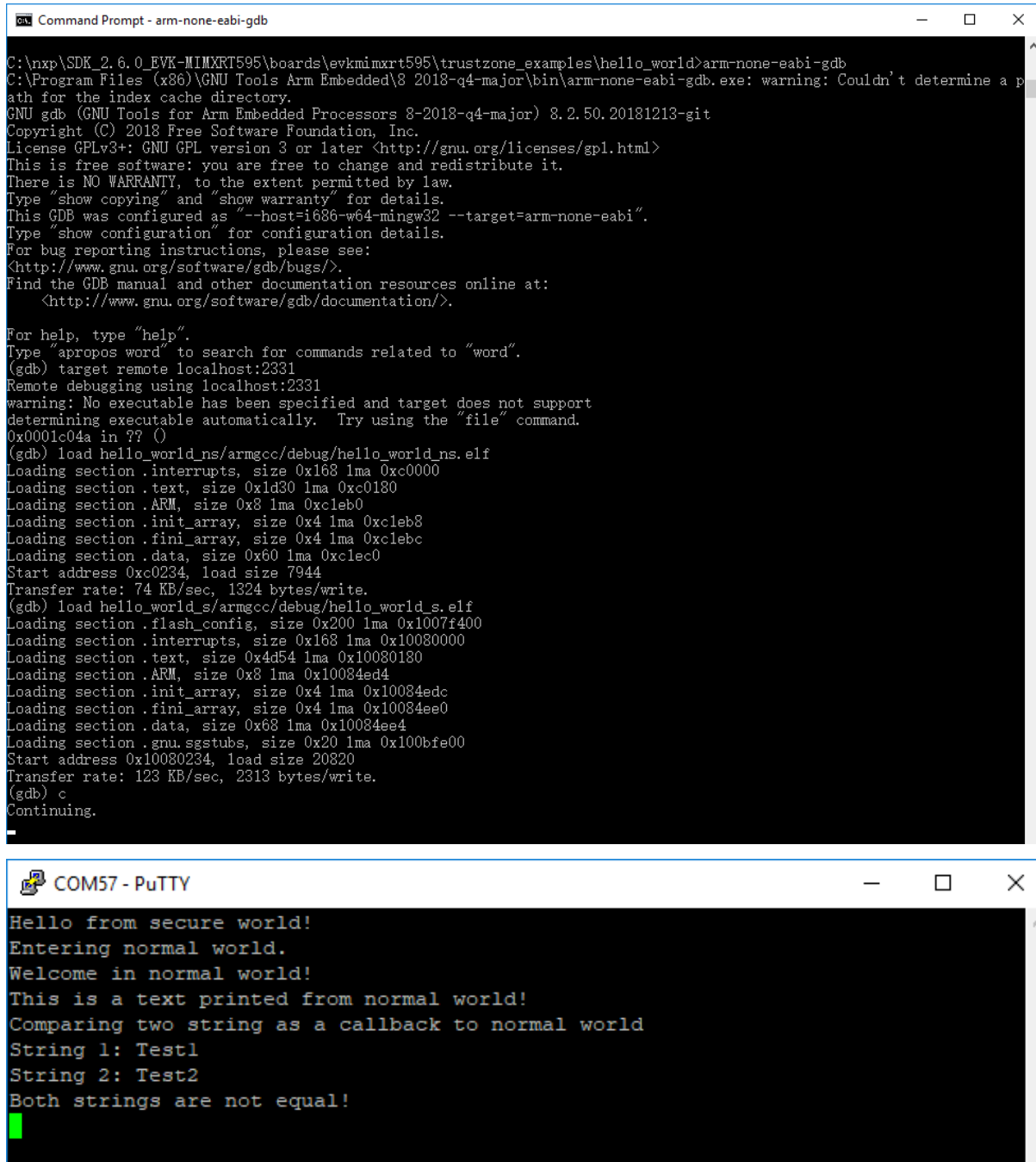
Run a TrustZone example application When running a TrustZone application, the same prerequisites for J-Link/J-Link OpenSDA firmware, and the serial console as for the single core application, apply, as described in **Run an example application**.

To download and run the TrustZone application, perform steps 1 to 10, as described in **Run an example application**. These steps are common for both single core and TrustZone applications in Arm GCC.

Then, run these commands:

1. arm-none-eabi-gdb.exe
2. target remote localhost:2331
3. monitor reset
4. monitor halt
5. monitor exec SetFlashDLNoRMWThreshold = 0x20000
6. load <install_dir>/boards/evkmimxrt595/trustzone_examples/hello_world/hello_world_ns/armgcc/debug/hello_world_ns.elf
7. load <install_dir>/boards/evkmimxrt595/trustzone_examples/hello_world/hello_world_s/armgcc/debug/hello_world_s.elf
8. monitor reset

The application is now downloaded and halted. Execute the `c` command to start the demo application.



```

Command Prompt - arm-none-eabi-gdb
C:\nxp\SDK_2.6.0_EVK-MIMXRT595\boards\evkmimxrt595\trustzone_examples\hello_world>arm-none-eabi-gdb
C:\Program Files (x86)\GNU Tools Arm Embedded\8 2018-q4-major\bin\arm-none-eabi-gdb.exe: warning: Couldn't determine a p
ath for the index cache directory.
GNU gdb (GNU Tools for Arm Embedded Processors 8-2018-q4-major) 8.2.50.20181213-git
Copyright (C) 2018 Free Software Foundation, Inc.
License GPLv3+: GNU GPL version 3 or later <http://gnu.org/licenses/gpl.html>
This is free software; you are free to change and redistribute it.
There is NO WARRANTY, to the extent permitted by law.
Type "show copying" and "show warranty" for details.
This GDB was configured as "--host=i686-w64-mingw32 --target=arm-none-eabi".
Type "show configuration" for configuration details.
For bug reporting instructions, please see:
<http://www.gnu.org/software/gdb/bugs/>.
Find the GDB manual and other documentation resources online at:
<http://www.gnu.org/software/gdb/documentation/>.

For help, type "help".
Type "apropos word" to search for commands related to "word".
(gdb) target remote localhost:2331
Remote debugging using localhost:2331
warning: No executable has been specified and target does not support
determining executable automatically. Try using the "file" command.
0x0001c04a in ?? ()
(gdb) load hello_world_ns/armgcc/debug/hello_world_ns.elf
Loading section .interrupts, size 0x168 lma 0xc0000
Loading section .text, size 0x1d30 lma 0xc0180
Loading section .ARM, size 0x8 lma 0xc1eb0
Loading section .init_array, size 0x4 lma 0xc1eb8
Loading section .fini_array, size 0x4 lma 0xc1ebc
Loading section .data, size 0x60 lma 0xc1ec0
Start address 0xc0234, load size 7944
Transfer rate: 74 KB/sec, 1324 bytes/write.
(gdb) load hello_world_s/armgcc/debug/hello_world_s.elf
Loading section .flash_config, size 0x200 lma 0x1007f400
Loading section .interrupts, size 0x168 lma 0x10080000
Loading section .text, size 0x4d54 lma 0x10080180
Loading section .ARM, size 0x8 lma 0x10084ed4
Loading section .init_array, size 0x4 lma 0x10084edc
Loading section .fini_array, size 0x4 lma 0x10084ee0
Loading section .data, size 0x68 lma 0x10084ee4
Loading section .gnu.sgstubs, size 0x20 lma 0x100bfe00
Start address 0x10080234, load size 20820
Transfer rate: 123 KB/sec, 2313 bytes/write.
(gdb) c
Continuing.

```

```

COM57 - PuTTY
Hello from secure world!
Entering normal world.
Welcome in normal world!
This is a text printed from normal world!
Comparing two string as a callback to normal world
String 1: Test1
String 2: Test2
Both strings are not equal!

```

MCUXpresso Config Tools

MCUXpresso Config Tools can help configure the processor and generate initialization code for the on chip peripherals. The tools are able to modify any existing example project, or create a new configuration for the selected board or processor. The generated code is designed to be used with MCUXpresso SDK version 24.12.00 or later.

Following table describes the tools included in the MCUXpresso Config Tools.

Config Tool	Description	Image
Pins tool	For configuration of pin routing and pin electrical properties.	
Clock tool	For system clock configuration	
Peripherals tools	For configuration of other peripherals	
TEE tool	Configures access policies for memory area and peripherals helping to protect and isolate sensitive parts of the application.	
Device Configuration tool	Configures Device Configuration Data (DCD) contained in the program image that the Boot ROM code interprets to set up various on-chip peripherals prior to the program launch.	

MCUXpresso Config Tools can be accessed in the following products:

- **Integrated** in the MCUXpresso IDE. Config tools are integrated with both compiler and debugger which makes it the easiest way to begin the development.
- **Standalone version** available for download from www.nxp.com/mcuxpresso. Recommended for customers using IAR Embedded Workbench, Keil MDK μ Vision, or Arm GCC.
- **Online version** available on mcuxpresso.nxp.com. Recommended doing a quick evaluation of the processor or use the tool without installation.

Each version of the product contains a specific *Quick Start Guide* document MCUXpresso IDE Config Tools installation folder that can help start your work.

How to determine COM port

This section describes the steps necessary to determine the debug COM port number of your NXP hardware development platform. All NXP boards ship with a factory programmed, onboard debug interface, whether it is based on MCU-Link or the legacy OpenSDA, LPC-Link2, P&E Micro OSJTAG interface. To determine what your specific board ships with, see [Default debug interfaces](#).

1. **Linux:** The serial port can be determined by running the following command after the USB Serial is connected to the host:

```
$ dmesg | grep "ttyUSB"
[503175.307873] usb 3-12: cp210x converter now attached to ttyUSB0
[503175.309372] usb 3-12: cp210x converter now attached to ttyUSB1
```

There are two ports, one is for core0 debug console and the other is for core1.

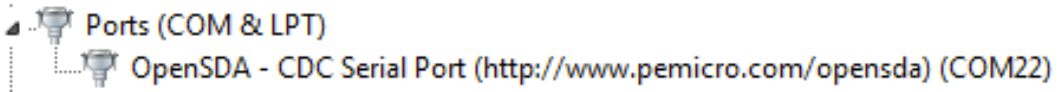
2. **Windows:** To determine the COM port open Device Manager in the Windows operating system. Click the **Start** menu and type **Device Manager** in the search bar.

In the Device Manager, expand the **Ports (COM & LPT)** section to view the available ports. The COM port names are different for all the NXP boards.

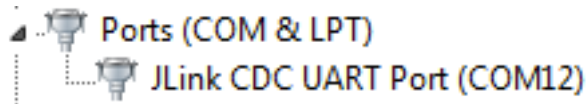
1. **CMSIS-DAP/mbed/DAPLink** interface:



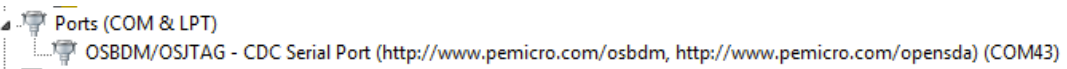
2. P&E Micro:



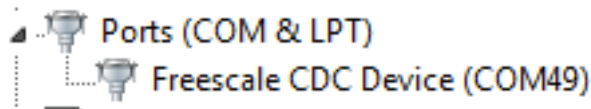
3. J-Link:



4. P&E Micro OSJTAG:



5. MRB-KW01:



On-board Debugger

This section describes the on-board debuggers used on NXP development boards.

On-board debugger MCU-Link MCU-Link is a powerful and cost effective debug probe that can be used seamlessly with MCUXpresso IDE, and is also compatible with 3rd party IDEs that support CMSIS-DAP protocol. MCU-Link also includes a USB to UART bridge feature (VCOM) that can be used to provide a serial connection between the target MCU and a host computer. MCU-Link features a high-speed USB interface for high performance debug. MCU-Link is compatible with Windows, MacOS and Linux. A free utility from NXP provides an easy way to install firmware updates.

On-board MCU-Link debugger supports CMSIS-DAP and J-Link firmware. See the table in [Default debug interfaces](#) to determine the default debug interface that comes loaded on your specific hardware platform.

The corresponding host driver must be installed before debugging.

- For boards with CMSIS-DAP firmware, visit developer.mbed.org/handbook/Windows-serial-configuration and follow the instructions to install the Windows operating system serial driver. If running on Linux OS, this step is not required.
- If using J-Link with either a standalone debug pod or MCU-Link, install the J-Link software (drivers and utilities) from www.segger.com/jlink-software.html.

Updating MCU-Link firmware This firmware in this debug interface may be updated using the host computer utility called MCU-Link. This typically used when switching between the default debugger protocol (CMSIS-DAP) to SEGGER J-Link, or for updating this firmware with new releases of these. This section contains the steps to reprogram the debug probe firmware.

Note: If MCUXpresso IDE is used and the jumper making DFUlink is installed on the board (JP5 on some boards, but consult the board user manual or schematic for specific jumper number), MCU-Link debug probe boots to DFU mode, and MCUXpresso IDE automatically downloads the

CMSIS-DAP firmware to the probe before flash memory programming (after clicking **Debug**). Using DFU mode ensures that most up-to-date/compatible firmware is used with MCUXpresso IDE.

NXP provides the MCU-Link utility, which is the recommended tool for programming the latest versions of CMSIS-DAP and J-Link firmware onto MCU-Link or NXP boards. The utility can be downloaded from [MCU-Link](#).

These steps show how to update the debugger firmware on your board for Windows operating system.

1. Install the MCU-Link utility.
2. Unplug the board's USB cable.
3. Make the DFU link (install the jumper labeled DFUlink).
4. Connect the probe to the host via USB (use Link USB connector).
5. Open a command shell and call the appropriate script located in the MCU-Link installation directory (<MCU-Link install dir>).
 1. To program CMSIS-DAP debug firmware: <MCU-Link install dir>/scripts/program_CMSIS
 2. To program J-Link debug firmware: <MCU-Link install dir>/scripts/program_JLINK
6. Remove DFU link (remove the jumper installed in Step 3).
7. Repower the board by removing the USB cable and plugging it in again.

On-board debugger LPC-Link LPC-Link 2 is an extensible debug probe that can be used seamlessly with MCUXpresso IDE, and is also compatible with 3rd party IDEs that support CMSIS-DAP protocol. MCU-Link also includes a USB to UART bridge feature (VCOM) that can be used to provide a serial connection between the target MCU and a host computer. LPC-Link 2 is compatible with Windows, MacOS and Linux. A free utility from NXP provides an easy way to install firmware updates.

On-board LPC-Link 2 debugger supports CMSIS-DAP and J-Link firmware. See the table in [Default debug interfaces](#) to determine the default debug interface that comes loaded on your specific hardware platform.

The corresponding host driver must be installed before debugging.

- For boards with CMSIS-DAP firmware, visit developer.mbed.org/handbook/Windows-serial-configuration and follow the instructions to install the Windows operating system serial driver. If running on Linux OS, this step is not required.
- If using J-Link with either a standalone debug pod or MCU-Link, install the J-Link software (drivers and utilities) from www.segger.com/jlink-software.html.

Updating LPC-Link firmware The LPCXpresso hardware platform comes with a CMSIS-DAP-compatible debug interface (known as LPC-Link2). This firmware in this debug interface may be updated using the host computer utility called LPCScript. This typically used when switching between the default debugger protocol (CMSIS-DAP) to SEGGER J-Link, or for updating this firmware with new releases of these. This section contains the steps to reprogram the debug probe firmware.

Note: If MCUXpresso IDE is used and the jumper making DFUlink is installed on the board (JP5 on some boards, but consult the board user manual or schematic for specific jumper number), LPC-Link2 debug probe boots to DFU mode, and MCUXpresso IDE automatically downloads the CMSIS-DAP firmware to the probe before flash memory programming (after clicking **Debug**). Using DFU mode ensures that most up-to-date/compatible firmware is used with MCUXpresso IDE.

NXP provides the LPCScript utility, which is the recommended tool for programming the latest versions of CMSIS-DAP and J-Link firmware onto LPC-Link2 or LPCXpresso boards. The utility can be downloaded from [LPCScript](#).

These steps show how to update the debugger firmware on your board for Windows operating system. For Linux OS, follow the instructions described in LPCScript user guide ([LPCScript](#), select **LPCScript**, and then the documentation tab).

1. Install the LPCScript utility.
2. Unplug the board's USB cable.
3. Make the DFU link (install the jumper labeled DFUlink).
4. Connect the probe to the host via USB (use Link USB connector).
5. Open a command shell and call the appropriate script located in the LPCScript installation directory (<LPCScript install dir>).
 1. To program CMSIS-DAP debug firmware: <LPCScript install dir>/scripts/program_CMSIS
 2. To program J-Link debug firmware: <LPCScript install dir>/scripts/program_JLINK
6. Remove DFU link (remove the jumper installed in Step 3).
7. Repower the board by removing the USB cable and plugging it in again.

On-board debugger OpenSDA OpenSDA/OpenSDAv2 is a serial and debug adapter that is built into several NXP evaluation boards. It provides a bridge between your computer (or other USB host) and the embedded target processor, which can be used for debugging, flash programming, and serial communication, all over a simple USB cable.

The difference is the firmware implementation: OpenSDA: Programmed with the proprietary P&E Micro developed bootloader. P&E Micro is the default debug interface app. OpenSDAv2: Programmed with the open-sourced CMSIS-DAP/mbd bootloader. CMSIS-DAP is the default debug interface app.

See the table in [Default debug interfaces](#) to determine the default debug interface that comes loaded on your specific hardware platform.

The corresponding host driver must be installed before debugging.

- For boards with CMSIS-DAP firmware, visit developer.mbed.org/handbook/Windows-serial-configuration and follow the instructions to install the Windows operating system serial driver. If running on Linux OS, this step is not required.
- For boards with a P&E Micro interface, see [PE micro](#) to download and install the P&E Micro Hardware Interface Drivers package.

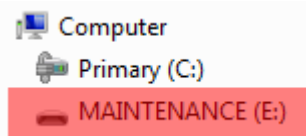
Updating OpenSDA firmware Any NXP hardware platform that comes with an OpenSDA-compatible debug interface has the ability to update the OpenSDA firmware. This typically means to switch from the default application (either CMSIS-DAP or P&E Micro) to a SEGGER J-Link. This section contains the steps to switch the OpenSDA firmware to a J-Link interface. However, the steps can be applied to restoring the original image also. For reference, OpenSDA firmware files can be found at the links below:

- J-Link: Download appropriate image from www.segger.com/opensda.html. Choose the appropriate J-Link binary based on the table in [Default debug interfaces](#). Any OpenSDA v1.0 interface should use the standard OpenSDA download (in other words, the one with no version). For OpenSDA 2.0 or 2.1, select the corresponding binary.
- CMSIS-DAP: CMSIS-DAP OpenSDA firmware is available at www.nxp.com/opensda.

- P&E Micro: Downloading P&E Micro OpenSDA firmware images requires registration with P&E Micro (www.pemicro.com).

Perform the following steps to update the OpenSDA firmware on your board for Windows and Linux OS users:

1. Unplug the board's USB cable.
2. Press the **Reset** button on the board. While still holding the button, plug the USB cable back into the board.
3. When the board re-enumerates, it shows up as a disk drive called **MAINTENANCE**.



4. Drag and drop the new firmware image onto the MAINTENANCE drive.

Note: If for any reason the firmware update fails, the board can always reenter maintenance mode by holding down **Reset** button and power cycling.

These steps show how to update the OpenSDA firmware on your board for Mac OS users.

1. Unplug the board's USB cable.
2. Press the **Reset** button of the board. While still holding the button, plug the USB cable back into the board.
3. For boards with OpenSDA v2.0 or v2.1, it shows up as a disk drive called **BOOTLOADER** in **Finder**. Boards with OpenSDA v1.0 may or may not show up depending on the bootloader version. If you see the drive in **Finder**, proceed to the next step. If you do not see the drive in **Finder**, use a PC with Windows OS 7 or an earlier version to either update the OpenSDA firmware, or update the OpenSDA bootloader to version 1.11 or later. The bootloader update instructions and image can be obtained from P&E Microcomputer website.
4. For OpenSDA v2.1 and OpenSDA v1.0 (with bootloader 1.11 or later) users, drag the new firmware image onto the BOOTLOADER drive in **Finder**.
5. For OpenSDA v2.0 users, type these commands in a Terminal window:

```
> sudo mount -u -w -o sync /Volumes/BOOTLOADER  
> cp -X <path to update file> /Volumes/BOOTLOADER
```

Note: If for any reason the firmware update fails, the board can always reenter bootloader mode by holding down the **Reset** button and power cycling.

On-board debugger Multilink An on-board Multilink debug circuit provides a JTAG interface and a power supply input through a single micro-USB connector. It is a hardware interface that allows PC software to debug and program a target processor through its debug port.

The host driver must be installed before debugging.

- See [PE micro](#) to download and install the P&E Micro Hardware Interface Drivers package.

On-board debugger OSJTAG An on-board OSJTAG debug circuit provides a JTAG interface and a power supply input through a single micro-USB connector. It is a hardware interface that allows PC software to debug and program a target processor through its debug port.

The host driver must be installed before debugging.

- See [PE micro](#) to download and install the P&E Micro Hardware Interface Drivers package.

Default debug interfaces

The MCUXpresso SDK supports various hardware platforms that come loaded with various factory programmed debug interface configurations. The following table lists the hardware platforms supported by the MCUXpresso SDK, their default debug firmware, and any version information that helps differentiate a specific interface configuration.

Hardware platform	Default debugger firmware	On-board debugger probe
EVK-MCIMX7ULP	N/A	N/A
EVK-MIMX8MM	N/A	N/A
EVK-MIMX8MN	N/A	N/A
EVK-MIMX8MNDDR3L	N/A	N/A
EVK-MIMX8MP	N/A	N/A
EVK-MIMX8MQ	N/A	N/A
EVK-MIMX8ULP	N/A	N/A
EVK-MIMXRT1010	CMSIS-DAP	LPC-Link2
EVK-MIMXRT1015	CMSIS-DAP	LPC-Link2
EVK-MIMXRT1020	CMSIS-DAP	LPC-Link2
EVK-MIMXRT1064	CMSIS-DAP	LPC-Link2
EVK-MIMXRT595	CMSIS-DAP	LPC-Link2
EVK-MIMXRT685	CMSIS-DAP	LPC-Link2
EVK9-MIMX8ULP	N/A	N/A
EVKB-IMXRT1050	CMSIS-DAP	LPC-Link2
FRDM-K22F	CMSIS-DAP	OpenSDA v2
FRDM-K32L2A4S	CMSIS-DAP	OpenSDA v2
FRDM-K32L2B	CMSIS-DAP	OpenSDA v2
FRDM-K32L3A6	CMSIS-DAP	OpenSDA v2
FRDM-KE02Z40M	P&E Micro	OpenSDA v1
FRDM-KE15Z	CMSIS-DAP	OpenSDA v2
FRDM-KE16Z	CMSIS-DAP	OpenSDA v2
FRDM-KE17Z	CMSIS-DAP	OpenSDA v2
FRDM-KE17Z512	CMSIS-DAP	MCU-Link
FRDM-MCXA153	CMSIS-DAP	MCU-Link
FRDM-MCXA156	CMSIS-DAP	MCU-Link
FRDM-MCXA346	CMSIS-DAP	MCU-Link
FRDM-MCXC041	CMSIS-DAP	MCU-Link
FRDM-MCXC242	CMSIS-DAP	MCU-Link
FRDM-MCXC444	CMSIS-DAP	MCU-Link
FRDM-MCXE247	CMSIS-DAP	MCU-Link
FRDM-MCXN236	CMSIS-DAP	MCU-Link
FRDM-MCXN947	CMSIS-DAP	MCU-Link
FRDM-MCXW23	CMSIS-DAP	MCU-Link
FRDM-MCXW71	CMSIS-DAP	MCU-Link
FRDM-MCXW72	CMSIS-DAP	MCU-Link
FRDM-RW612	CMSIS-DAP	MCU-Link
IMX943-EVK	N/A	N/A
IMX95LP4XEVK-15	N/A	N/A
IMX95LPD5EVK-19	N/A	N/A
IMX95VERDINEVK	N/A	N/A
KW45B41Z-EVK	CMSIS-DAP	MCU-Link
KW45B41Z-LOC	CMSIS-DAP	MCU-Link
KW47-EVK	CMSIS-DAP	MCU-Link
KW47-LOC	CMSIS-DAP	MCU-Link
LPC845BREAKOUT	CMSIS-DAP	LPC-Link2
LPCXpresso51U68	CMSIS-DAP	LPC-Link2
LPCXpresso54628	CMSIS-DAP	LPC-Link2

continues on next page

Table 1 – continued from previous page

Hardware platform	Default debugger firmware	On-board debugger probe
LPCXpresso54S018	CMSIS-DAP	LPC-Link2
LPCXpresso54S018M	CMSIS-DAP	LPC-Link2
LPCXpresso55S06	CMSIS-DAP	LPC-Link2
LPCXpresso55S16	CMSIS-DAP	LPC-Link2
LPCXpresso55S28	CMSIS-DAP	LPC-Link2
LPCXpresso55S36	CMSIS-DAP	MCU-Link
LPCXpresso55S69	CMSIS-DAP	LPC-Link2
LPCXpresso802	CMSIS-DAP	LPC-Link2
LPCXpresso804	CMSIS-DAP	LPC-Link2
LPCXpresso824MAX	CMSIS-DAP	LPC-Link2
LPCXpresso845MAX	CMSIS-DAP	LPC-Link2
LPCXpresso860MAX	CMSIS-DAP	LPC-Link2
MC56F80000-EVK	P&E Micro	Multilink
MC56F81000-EVK	P&E Micro	Multilink
MC56F83000-EVK	P&E Micro	OSJTAG
MCIMX93-EVK	N/A	N/A
MCIMX93-QSB	N/A	N/A
MCIMX93AUTO-EVK	N/A	N/A
MCX-N5XX-EVK	CMSIS-DAP	MCU-Link
MCX-N9XX-EVK	CMSIS-DAP	MCU-Link
MCX-W71-EVK	CMSIS-DAP	MCU-Link
MCX-W72-EVK	CMSIS-DAP	MCU-Link
MIMXRT1024-EVK	CMSIS-DAP	LPC-Link2
MIMXRT1040-EVK	CMSIS-DAP	LPC-Link2
MIMXRT1060-EVKB	CMSIS-DAP	LPC-Link2
MIMXRT1060-EVKC	CMSIS-DAP	MCU-Link
MIMXRT1160-EVK	CMSIS-DAP	LPC-Link2
MIMXRT1170-EVKB	CMSIS-DAP	MCU-Link
MIMXRT1180-EVK	CMSIS-DAP	MCU-Link
MIMXRT685-AUD-EVK	CMSIS-DAP	LPC-Link2
MIMXRT700-EVK	CMSIS-DAP	MCU-Link
RD-RW612-BGA	CMSIS-DAP	MCU-Link
TWR-KM34Z50MV3	P&E Micro	OpenSDA v1
TWR-KM34Z75M	P&E Micro	OpenSDA v1
TWR-KM35Z75M	CMSIS-DAP	OpenSDA v2
TWR-MC56F8200	P&E Micro	OSJTAG
TWR-MC56F8400	P&E Micro	OSJTAG

How to define IRQ handler in CPP files

With MCUXpresso SDK, users could define their own IRQ handler in application level to override the default IRQ handler. For example, to override the default PIT_IRQHandler define in startup_DEVICE.s, application code like app.c can be implement like:

```
// c
void PIT_IRQHandler(void)
{
    // Your code
}
```

When application file is CPP file, like app.cpp, then extern "C" should be used to ensure the function prototype alignment.

```
// cpp
extern "C" {
    void PIT_IRQHandler(void);
}
void PIT_IRQHandler(void)
{
    // Your code
}
```

1.3 Getting Started with MCUXpresso SDK GitHub

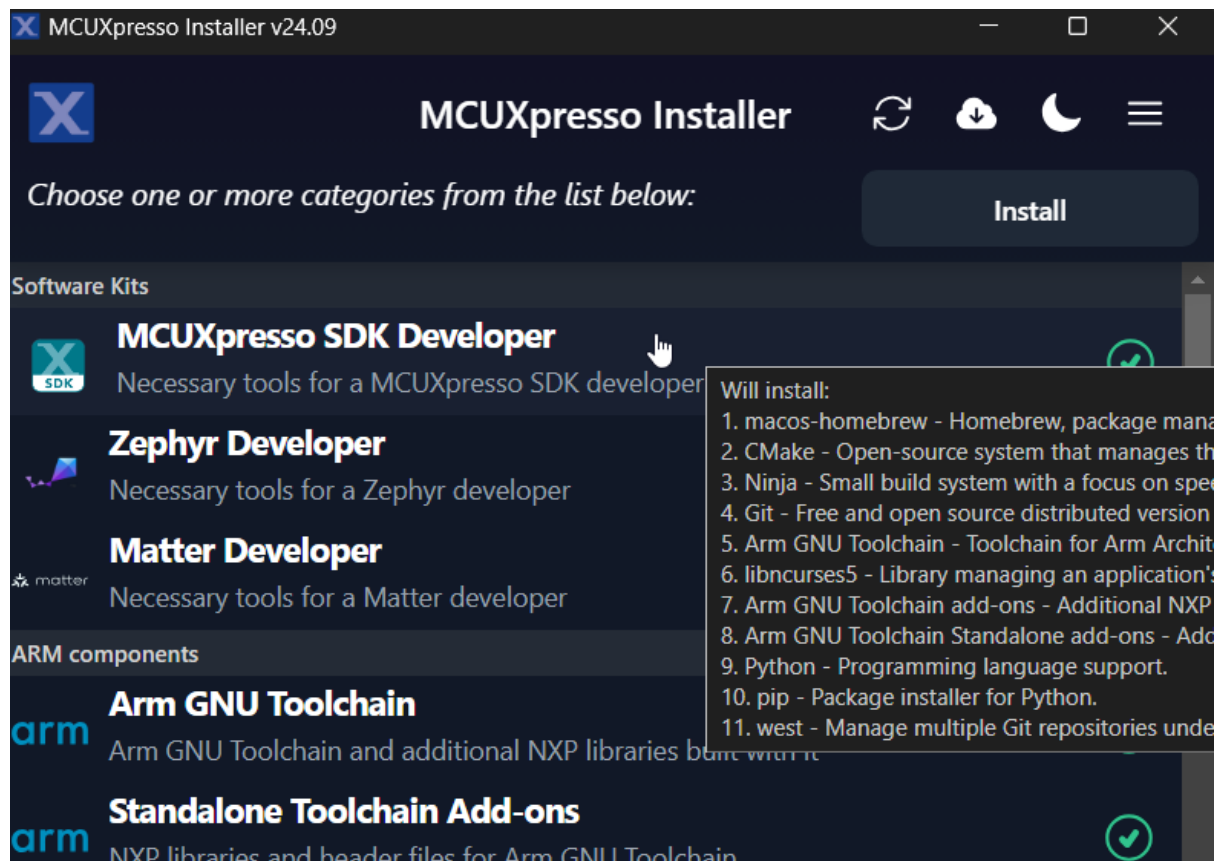
1.3.1 Getting Started with MCUXpresso SDK Repository

Installation

NOTE

If the installation instruction asks/selects whether to have the tool installation path added to the PATH variable, agree/select the choice. This option ensures that the tool can be used in any terminal in any path. *Verify the installation* after each tool installation.

Install Prerequisites with MCUXpresso Installer The MCUXpresso Installer offers a quick and easy way to install the basic tools needed. The MCUXpresso Installer can be obtained from <https://github.com/nxp-mcuxpresso/vscode-for-mcux/wiki/Dependency-Installation>. The MCUXpresso Installer is an automated installation process, simply select MCUXpresso SDK Developer from the menu and click install. If you prefer to install the basic tools manually, refer to the next section.



Alternative: Manual Installation

Basic tools

Git Git is a free and open source distributed version control system. Git is designed to handle everything from small to large projects with speed and efficiency. To install Git, visit the official [Git website](#). Download the appropriate version (you may use the latest one) for your operating system (Windows, macOS, Linux). Then run the installer and follow the installation instructions.

User `git --version` to check the version if you have a version installed.

Then configure your username and email using the commands:

```
git config --global user.name "Your Name"
git config --global user.email "youremail@example.com"
```

Python Install python 3.10 or latest. Follow the [Python Download](#) guide.

Use `python --version` to check the version if you have a version installed.

West Please use the west version equal or greater than 1.2.0

```
# Note: you can add option '--default-timeout=1000' if you meet connection issue. Or you may set a different
↪source using option '-i'.
# for example, in China you could try: pip install -U west -i https://pypi.tuna.tsinghua.edu.cn/simple
pip install -U west
```

Build And Configuration System

CMake It is strongly recommended to use CMake version equal or later than 3.30.0. You can get latest CMake distributions from [the official CMake download page](#).

For Windows, you can directly use the .msi installer like [cmake-3.31.4-windows-x86_64.msi](#) to install.

For Linux, CMake can be installed using the system package manager or by getting binaries from [the official CMake download page](#).

After installation, you can use `cmake --version` to check the version.

Ninja Please use the ninja version equal or later than 1.12.1.

By default, Windows comes with the Ninja program. If the default Ninja version is too old, you can directly download the [ninja binary](#) and register the ninja executor location path into your system path variable to work.

For Linux, you can use your [system package manager](#) or you can directly download the [ninja binary](#) to work.

After installation, you can use `ninja --version` to check the version.

Kconfig MCUXpresso SDK uses Kconfig python implementation. We customize it based on our needs and integrate it into our build and configuration system. The Kconfiglib sources are placed under `mcuxsdk/scripts/kconfig` folder.

Please make sure [python](#) environment is setup ready then you can use the Kconfig.

Ruby Our build system supports IDE project generation for iar, mdk, codewarrior and xtensa to provide OOB from build to debug. This feature is implemented with ruby. You can follow the guide ruby environment setup to setup the ruby environment. Since we provide a built-in portable ruby, it is just a simple one cmd installation.

If you only work with CLI, you can skip this step.

Toolchain MCUXpresso SDK supports all mainstream toolchains for embedded development. You can install your used or interested toolchains following the guides.

Toolchain	Download and Installation Guide	Note
Armgcc	Arm GNU Toolchain Install Guide	ARMGCC is default toolchain
IAR	IAR Installation and Licensing quick reference guide	
MDK	MDK Installation	
Armclang	Installing Arm Compiler for Embedded	
Zephyr	Zephyr SDK	
Codewarrior	NXP CodeWarrior	
Xtensa	Tensilica Tools	
NXP S32Compiler RISC-V Zen-V	NXP Website	

After you have installed the toolchains, register them in the system environment variables. This will allow the west build to recognize them:

Toolchain	Environment Variable	Example	Cmd Line Argument
Armgcc	AR-MGCC_DIR	C:\armgcc for windows/usr for Linux. Typically arm-none-eabi-* is installed under /usr/bin	– toolchain armgcc
IAR	IAR_DIR	C:\iar\ewarm-9.60.3 for Windows/opt/iarsystems/bxarm-9.60.3 for Linux	– toolchain iar
MDK	MDK_DIR	C:\Keil_v5 for Windows.MDK IDE is not officially supported with Linux.	– toolchain mdk
Armclang	ARM-CLANG_DIR	C:\ArmCompilerforEmbedded6.22 for Windows/opt/ArmCompilerforEmbedded6.21 for Linux	– toolchain mdk
Zephyr	ZEPHYR_DIR	c:\NXP\zephyr-sdk-<version> for windows/opt/zephyr-sdk-<version> for Linux	– toolchain zephyr
CodeWarrior	CW_DIR	C:\Freescall\CW MCU v11.2 for windowsCodeWarrior is not supported with Linux	– toolchain code-warrior
Xtensa	XCC_DIR	C:\xtensa\XtDevTools\install\tools\RI-2023.11-win32\XtensaTools for windows/opt/xtensa/XtDevTools/install/tools/RI-2023.11-Linux/XtensaTools for Linux	– toolchain xtensa
NXP S32Compiler RISC-V Zen-V	RISCV-LVM_DIR	C:\riscv-llvm-win32_b298_b298_2024.08.12 for Windows/opt/riscv-llvm-Linux-x64_b298_b298_2024.08.12 for Linux	– toolchain riscv-llvm

- The <toolchain>_DIR is the root installation folder, not the binary location folder. For IAR, it is directory containing following installation folders:

```

└─ arm
└─ common
└─ install-info

```

- MDK IDE using armclang toolchain only officially supports Windows. In Linux, please directly use armclang toolchain by setting ARMCLANG_DIR. In Windows, since most Keil users will install MDK IDE instead of standalone armclang toolchain, the MDK_DIR has higher priority than ARMCLANG_DIR.
- For Xtensa toolchain, please set the XTENSA_CORE environment variable. Here's an example list:

Device Core	XTENSA_CORE
RT500 fusion1	nxp_rt500_RI23_11_newlib
RT600 hifi4	nxp_rt600_RI23_11_newlib
RT700 hifi1	rt700_hifi1_RI23_11_nlib
RT700 hifi4	t700_hifi4_RI23_11_nlib
i.MX8ULP fusion1	fusion_nxp02_dsp_prod

- In Windows, the short path is used in environment variables. If any toolchain is using the long path, you can open a command window from the toolchain folder and use below command to get the short path: `for %i in (.) do echo %~fsi`

Tool installation check Once installed, open a terminal or command prompt and type the associated command to verify the installation.

If you see the version number, you have successfully installed the tool. Else, check whether the tool's installation path is added into the PATH variable. You can add the installation path to the PATH with the commands below:

- Windows: Open command prompt or powershell, run below command to show the user PATH variable.

```
reg query HKEY_CURRENT_USER\Environment /v PATH
```

The tool installation path should be `C:\Users\xxx\AppData\Local\Programs\Git\cmd`. If the path is not seen in the output from above, append the path value to the PATH variable with the command below:

```
reg add HKEY_CURRENT_USER\Environment /v PATH /d "%PATH%;C:\Users\xxx\AppData\
↪Local\Programs\Git\cmd"
```

Then close the command prompt or powershell and verify the tool command again.

- Linux:
 1. Open the `$HOME/.bashrc` file using a text editor, such as `vim`.
 2. Go to the end of the file.
 3. Add the line which appends the tool installation path to the PATH variable and export PATH at the end of the file. For example, `export PATH="/Directory1:$PATH"`.
 4. Save and exit.
 5. Execute the script with `source .bashrc` or reboot the system to make the changes live. To verify the changes, run `echo $PATH`.
- macOS:
 1. Open the `$HOME/.bash_profile` file using a text editor, such as `nano`.
 2. Go to the end of the file.
 3. Add the line which appends the tool installation path to the PATH variable and export PATH at the end of the file. For example, `export PATH="/Directory1:$PATH"`.
 4. Save and exit.
 5. Execute the script with `source .bash_profile` or reboot the system to make the changes live. To verify the changes, run `echo $PATH`.

Get MCUXpresso SDK Repo

Establish SDK Workspace To get the MCUXpresso SDK repository, use the `west` tool to clone the manifest repository and checkout all the west projects.

```
# Initialize west with the manifest repository
west init -m https://github.com/nxp-mcuxpresso/mcuxsdk-manifests/ mcuxpresso-sdk

# Update the west projects
cd mcuxpresso-sdk
west update

# Allow the usage of west extensions provided by MCUXpresso SDK
west config commands.allow_extensions true
```

Install Python Dependency(If do tool installation manually) To create a Python virtual environment in the west workspace core repo directory `mcuxsdk`, follow these steps:

1. Navigate to the core directory:

```
cd mcuxsdk
```

2. [Optional] Create and activate the virtual environment: If you don't want to use the python virtual environment, skip this step. **We strongly suggest you use `venv` to avoid conflicts with other projects using python.**

```
python -m venv .venv

# For Linux/MacOS
source .venv/bin/activate

# For Windows
.\.venv\Scripts\activate
# If you are using powershell and see the issue that the activate script cannot be run.
# You may fix the issue by opening the powershell as administrator and run below command:
powershell Set-ExecutionPolicy RemoteSigned
# then run above activate command again.
```

Once activated, your shell will be prefixed with `(.venv)`. The virtual environment can be deactivated at any time by running `deactivate` command.

Remember to activate the virtual environment every time you start working in this directory. If you are using some modern shell like `zsh`, there are some powerful plugins to help you auto switch `venv` among workspaces. For example, `zsh-autoswitch-virtualenv`.

3. Install the required Python packages:

```
# Note: you can add option '--default-timeout=1000' if you meet connection issue. Or you may set a
↪ different source using option '-i'.
# for example, in China you could try: pip3 install -r mcuxsdk/scripts/requirements.txt -i https://pypi.
↪ tuna.tsinghua.edu.cn/simple
pip install -r scripts/requirements.txt
```

Explore Contents

This section helps you build basic understanding of current fundamental project content and guides you how to build and run the provided example project in whole SDK delivery.

Folder View The whole MCUXpresso SDK project, after you have done the `west init` and `west update` operations follow the guideline at [Getting Started Guide](#), have below folder structure:

Folder	Description
manifests	Manifest repo, contains the manifest file to initialize and update the west workspace.
mcuxsdk	The MCUXpresso SDK source code, examples, middleware integration and script files.

All the projects record in the **Manifest repo** are checked out to the folder `mcuxsdk/`, the layout of `mcuxsdk` folder is shown as below:

Folder	Description
arch	Arch related files such as ARM CMSIS core files, RISC-V files and the build files related to the architecture.
cmake	The cmake modules, files which organize the build system.
components	Software components.
devices	Device support package which categorized by device series. For each device, header file, feature file, startup file and linker files are provided, also device specific drivers are included.
docs	Documentation source and build configuration for this sphinx built online documentation.
drivers	Peripheral drivers.
examples	Various demos and examples, support files on different supported boards. For each board support, there are board configuration files.
middleware	Middleware components integrated into SDK.
rtos	Rtos components integrated into SDK.
scripts	Script files for the west extension command and build system support.
svd	Svd files for devices, this is optional because of large size. Customers run <code>west manifest config group.filter +optional</code> and <code>west update mcux-soc-svd</code> to get this folder.

Examples Project The examples project is part of the whole SDK delivery, and locates in the folder `mcuxsdk/examples` of west workspace.

Examples files are placed in folder of `<example_category>`, these examples include (but are not limited to)

- `demo_apps`: Basic demo set to start using SDK, including `hello_world` and `led_blinky`.
- `driver_examples`: Simple applications that show how to use the peripheral drivers for a single use case. These applications typically only use a single peripheral but there are cases where multiple peripherals are used (for example, SPI transfer using DMA).

Board porting layers are placed in folder of `_boards/<board_name>` which aims at providing the board specific parts for examples code mentioned above.

Run a demo using MCUXpresso for VS Code

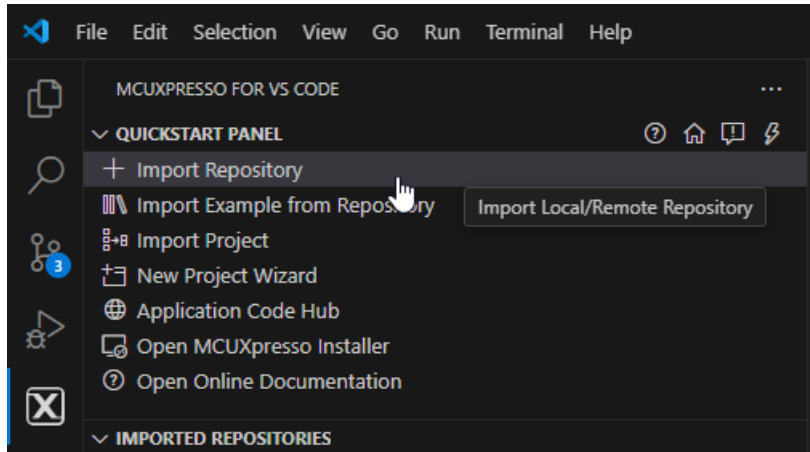
This section explains how to configure MCUXpresso for VS Code to build, run, and debug example applications. This guide uses the `hello_world` demo application as an example. However, these

steps can be applied to any example application in the MCUXpresso SDK.

Build an example application This section assumes that the user has already obtained the SDK as outlined in [Get MCUXpresso SDK Repo](#).

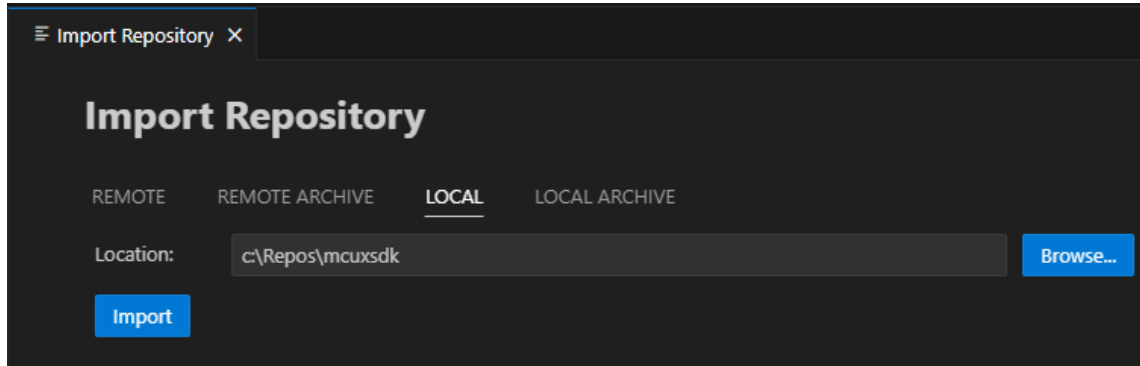
To build an example application:

1. Import the SDK into your workspace. Click **Import Repository** from the **QUICKSTART PANEL**.

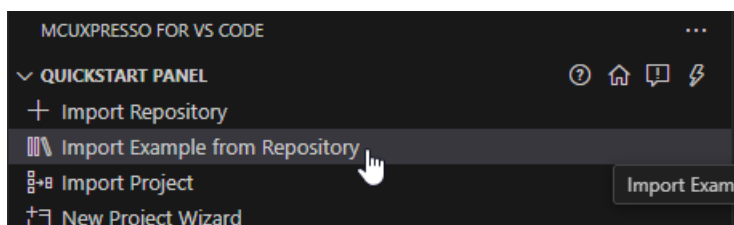


Note: You can import the SDK in several ways. Refer to [MCUXpresso for VS Code Wiki](#) for details.

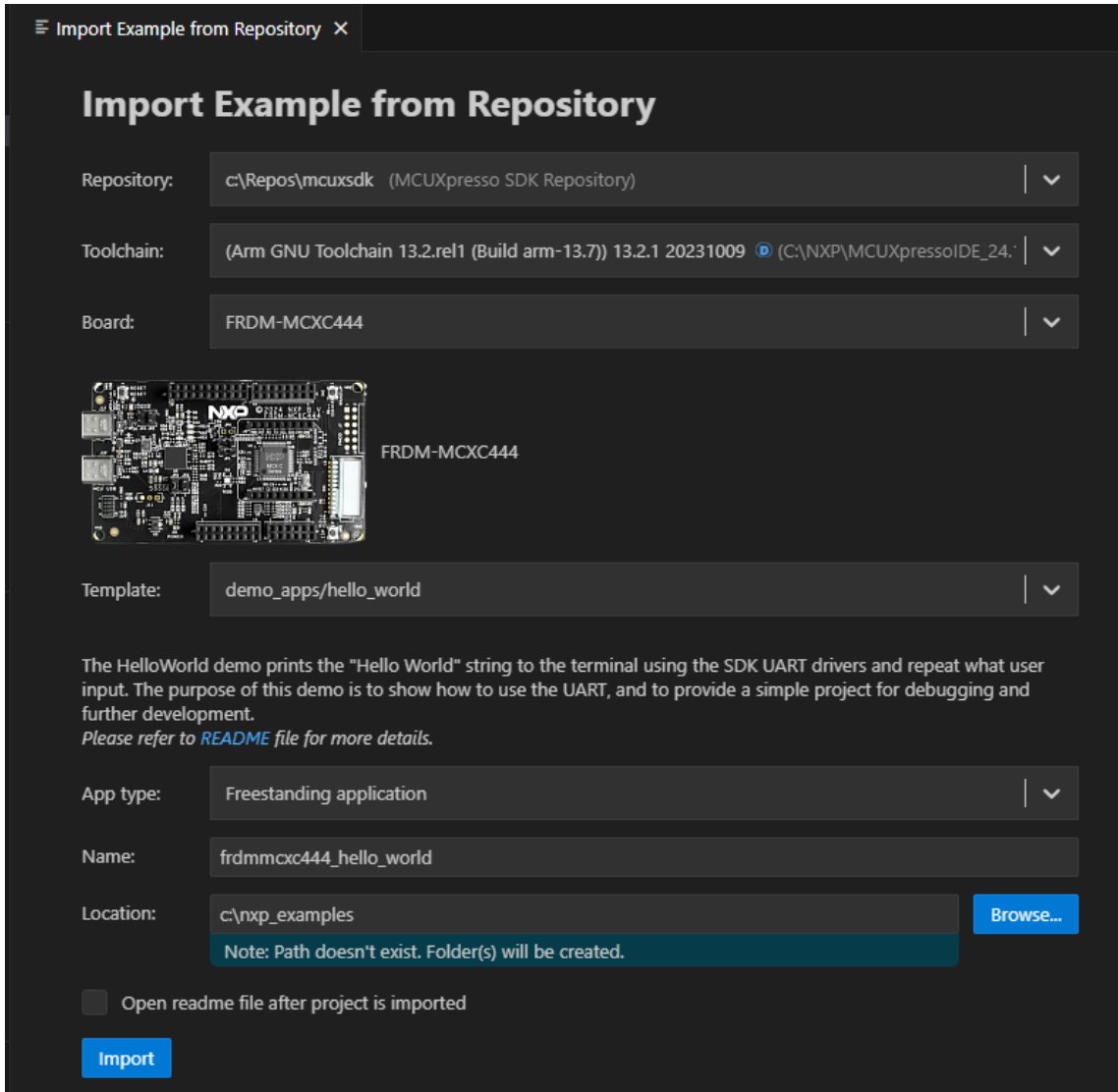
Select **Local** if you've already obtained the SDK as seen in [Get MCUXpresso SDK Repo](#). Select your location and click **Import**.



2. Click **Import Example from Repository** from the **QUICKSTART PANEL**.



In the dropdown menu, select the MCUXpresso SDK, the Arm GNU Toolchain, your board, template, and application type. Click **Import**.



Import Example from Repository X

Import Example from Repository

Repository: c:\Repos\mcuxsdk (MCUXpresso SDK Repository) | v

Toolchain: (Arm GNU Toolchain 13.2.rel1 (Build arm-13.7)) 13.2.1 20231009 | v

Board: FRDM-MCXC444 | v



FRDM-MCXC444

Template: demo_apps/hello_world | v

The HelloWorld demo prints the "Hello World" string to the terminal using the SDK UART drivers and repeat what user input. The purpose of this demo is to show how to use the UART, and to provide a simple project for debugging and further development.
Please refer to [README](#) file for more details.

App type: Freestanding application | v

Name: frdmmcxc444_hello_world

Location: c:\nxp_examples [Browse...](#)

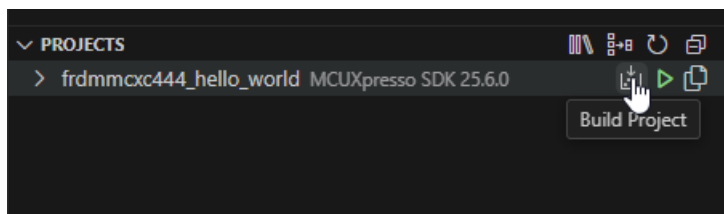
Note: Path doesn't exist. Folder(s) will be created.

☐ Open readme file after project is imported

[Import](#)

Note: The MCUXpresso SDK projects can be imported as **Repository applications** or **Freestanding applications**. The difference between the two is the import location. Projects imported as Repository examples will be located inside the MCUXpresso SDK, whereas Freestanding examples can be imported to a user-defined location. Select between these by designating your selection in the **App type** dropdown menu.

- VS Code will prompt you to confirm if the imported files are trusted. Click **Yes**.
- Navigate to the **PROJECTS** view. Find your project and click the **Build Project** icon.



The integrated terminal will open at the bottom and will display the build output.

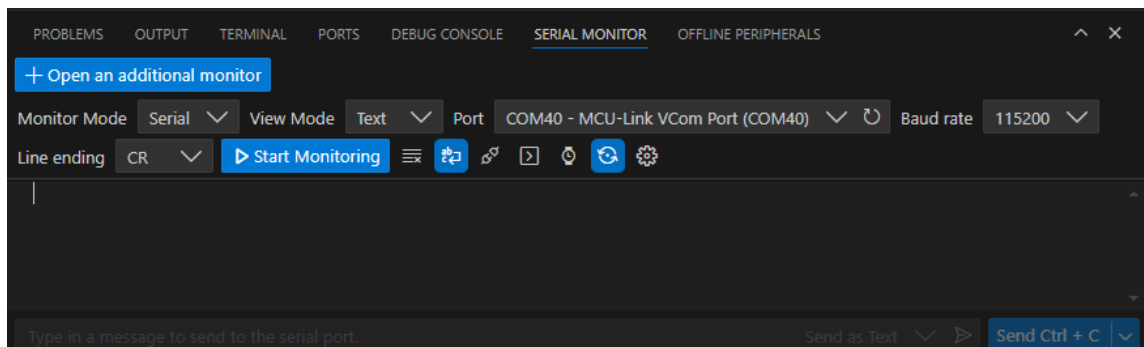
```

[17/21] Building C object CMakeFiles/hello_world.dir/C:/Repos/mcuxsdk/mcuxsdk/components/debug_console_lite/fsl_debug_console.c.obj
[18/21] Building C object CMakeFiles/hello_world.dir/C:/Repos/mcuxsdk/mcuxsdk/devices/MCXC/MCXC444/drivers/fsl_clock.c.obj
[19/21] Building C object CMakeFiles/hello_world.dir/C:/Repos/mcuxsdk/mcuxsdk/drivers/lpuart/fsl_lpuart.c.obj
[20/21] Building C object CMakeFiles/hello_world.dir/C:/Repos/mcuxsdk/mcuxsdk/drivers/uart/fsl_uart.c.obj
[21/21] Linking C executable hello_world.elf
Memory region      Used Size  Region Size  %age Used
  m_interrupts:     192 B      512 B      37.50%
  m_flash_config:    16 B       16 B     100.00%
  m_text:          7892 B    261104 B      3.02%
  m_data:          2128 B     32 KB      6.49%
build finished successfully.
Terminal will be reused by tasks, press any key to close it.

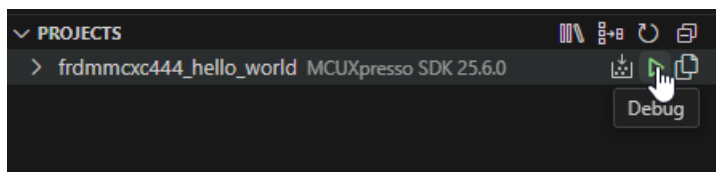
```

Run an example application **Note:** for full details on MCUXpresso for VS Code debug probe support, see [MCUXpresso for VS Code Wiki](#).

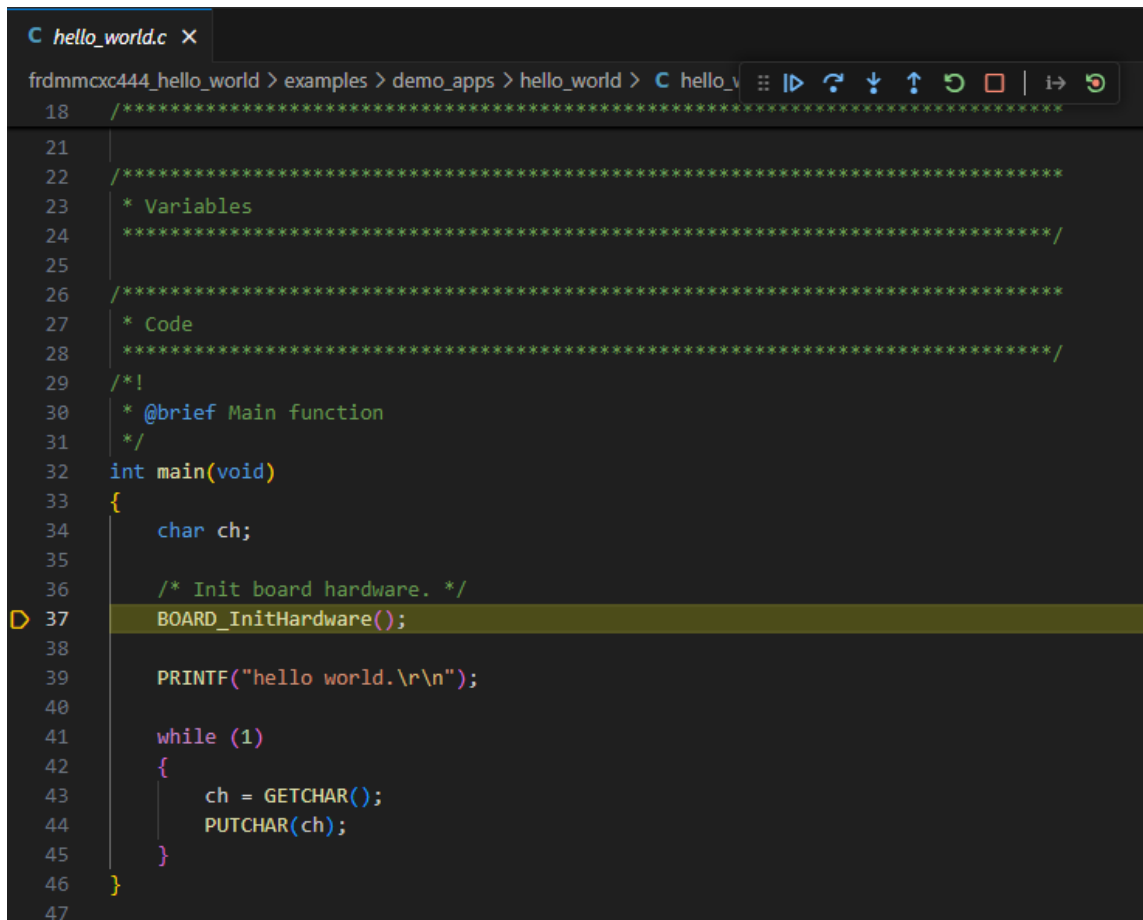
1. Open the **Serial Monitor** from the VS Code's integrated terminal. Select the VCom Port for your device and set the baud rate to 115200.



2. Navigate to the **PROJECTS** view and click the play button to initiate a debug session.



The debug session will begin. The debug controls are initially at the top.

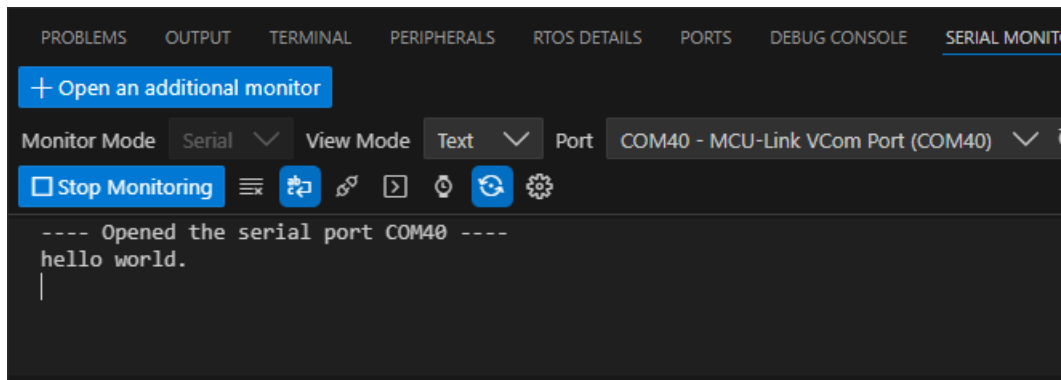


```

18  /*****
21
22  /*****
23  * Variables
24  *****/
25
26  /*****
27  * Code
28  *****/
29  /*!
30  * @brief Main function
31  */
32  int main(void)
33  {
34      char ch;
35
36      /* Init board hardware. */
37      BOARD_InitHardware();
38
39      PRINTF("hello world.\r\n");
40
41      while (1)
42      {
43          ch = GETCHAR();
44          PUTCHAR(ch);
45      }
46  }
47

```

3. Click **Continue** on the debug controls to resume execution of the code. Observe the output on the **Serial Monitor**.



```

PROBLEMS  OUTPUT  TERMINAL  PERIPHERALS  RTOS DETAILS  PORTS  DEBUG CONSOLE  SERIAL MONITOR
+ Open an additional monitor
Monitor Mode: Serial View Mode: Text Port: COM40 - MCU-Link VCom Port (COM40)
[Stop Monitoring] [Icons]
---- Opened the serial port COM40 ----
hello world.
|

```

Running a demo using ARMGCC CLI/IAR/MDK

Supported Boards Use the west extension `west list_project` to understand the board support scope for a specified example. All supported build command will be listed in output:

```
west list_project -p examples/demo_apps/hello_world [-t armgcc]
```

```
INFO: [ 1][west build -p always examples/demo_apps/hello_world --toolchain armgcc --config release -b_
↳ evk9mimx8ulp -Dcore_id=cm33]
```

```
INFO: [ 2][west build -p always examples/demo_apps/hello_world --toolchain armgcc --config release -b_
↳ evkbimxrt1050]
```

```
INFO: [ 3][west build -p always examples/demo_apps/hello_world --toolchain armgcc --config release -b_
```

(continues on next page)

(continued from previous page)

```

↪ evkbnimxrt1060]
INFO: [ 4][west build -p always examples/demo_apps/hello_world --toolchain armgcc --config release -b_
↪ evkbnimxrt1170 -Dcore_id=cm4]
INFO: [ 5][west build -p always examples/demo_apps/hello_world --toolchain armgcc --config release -b_
↪ evkbnimxrt1170 -Dcore_id=cm7]
INFO: [ 6][west build -p always examples/demo_apps/hello_world --toolchain armgcc --config release -b_
↪ evkbnimxrt1060]
INFO: [ 7][west build -p always examples/demo_apps/hello_world --toolchain armgcc --config release -b_
↪ evkbnimxrt7ulp]
...

```

The supported toolchains and build targets for an example are decided by the example-self example.yml and board example.yml, please refer Example Toolchains and Targets for more details.

Build the project Use west build -h to see help information for west build command. Compared to zephyr's west build, MCUXpresso SDK's west build command provides following additional options for mcux examples:

- --toolchain: specify the toolchain for this build, default armgcc.
- --config: value for CMAKE_BUILD_TYPE. If not provided, build system will get all the example supported build targets and use the first debug target as the default one. Please refer Example Toolchains and Targets for more details about example supported build targets.

Here are some typical usages for generating a SDK example:

```

# Generate example with default settings, default used device is the mainset MK22F51212
west build -b frdmk22f examples/demo_apps/hello_world

# Just print cmake commands, do not execute it
west build -b frdmk22f examples/demo_apps/hello_world --dry-run

# Generate example with other toolchain like iar, default armgcc
west build -b frdmk22f examples/demo_apps/hello_world --toolchain iar

# Generate example with other config type
west build -b frdmk22f examples/demo_apps/hello_world --config release

# Generate example with other devices with --device
west build -b frdmk22f examples/demo_apps/hello_world --device MK22F12810 --config release

```

For multicore devices, you shall specify the corresponding core id by passing the command line argument -Dcore_id. For example

```

west build -b evkbnimxrt1170 examples/demo_apps/hello_world --toolchain iar -Dcore_id=cm7 --config_
↪ flexspi_nor_debug

```

For shield, please use the --shield to specify the shield to run, like

```

west build -b mimxrt700evk --shield a8974 examples/issdk_examples/sensors/fxls8974cf/fxls8974cf_poll -
↪ Dcore_id=cm33_core0

```

Sysbuild(System build) To support multicore project building, we ported Sysbuild from Zephyr. It supports combine multiple projects for compilation. You can build all projects by adding --sysbuild for main application. For example:

```

west build -b evkbnimxrt1170 --sysbuild ./examples/multicore_examples/hello_world/primary -Dcore_
↪ id=cm7 --config flexspi_nor_debug --toolchain=armgcc -p always

```

For more details, please refer to System build.

Config a Project Example in MCUXpresso SDK is configured and tested with pre-defined configuration. You can follow steps blow to change the configuration.

1. Run cmake configuration

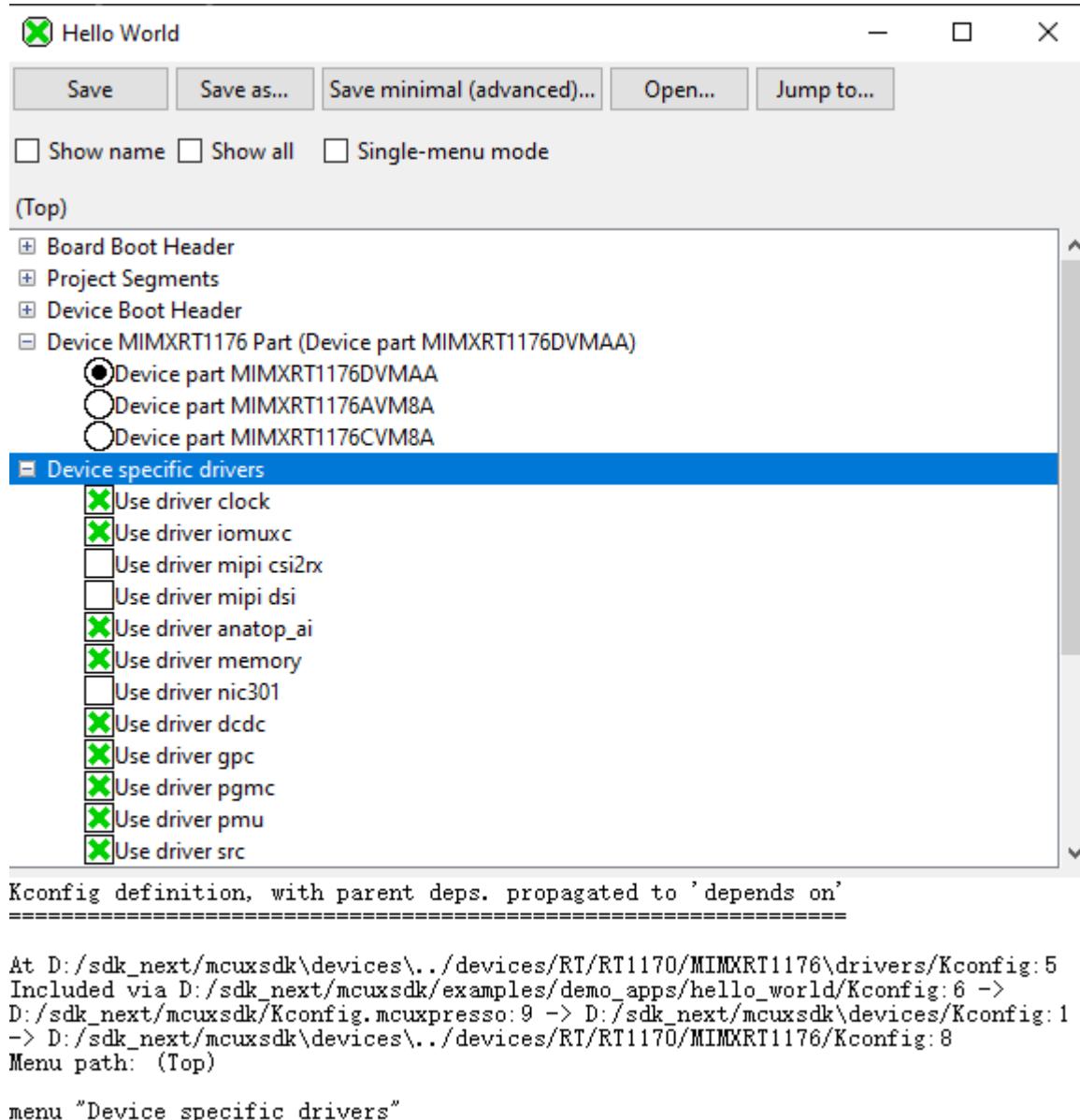
```
west build -b evkbnimxrt1170 examples/demo_apps/hello_world -Dcore_id=cm7 --cmake-only -p
```

Please note the project will be built without --cmake-only parameter.

2. Run guiconfig target

```
west build -t guiconfig
```

Then you will get the Kconfig GUI launched, like



You can reconfigure the project by selecting/deselecting Kconfig options.

After saving and closing the Kconfig GUI, you can directly run `west build` to build with the new configuration.

Flash *Note:* Please refer Flash and Debug The Example to enable west flash/debug support.
Flash the hello_world example:

```
west flash -r linkserver
```

Debug Start a gdb interface by following command:

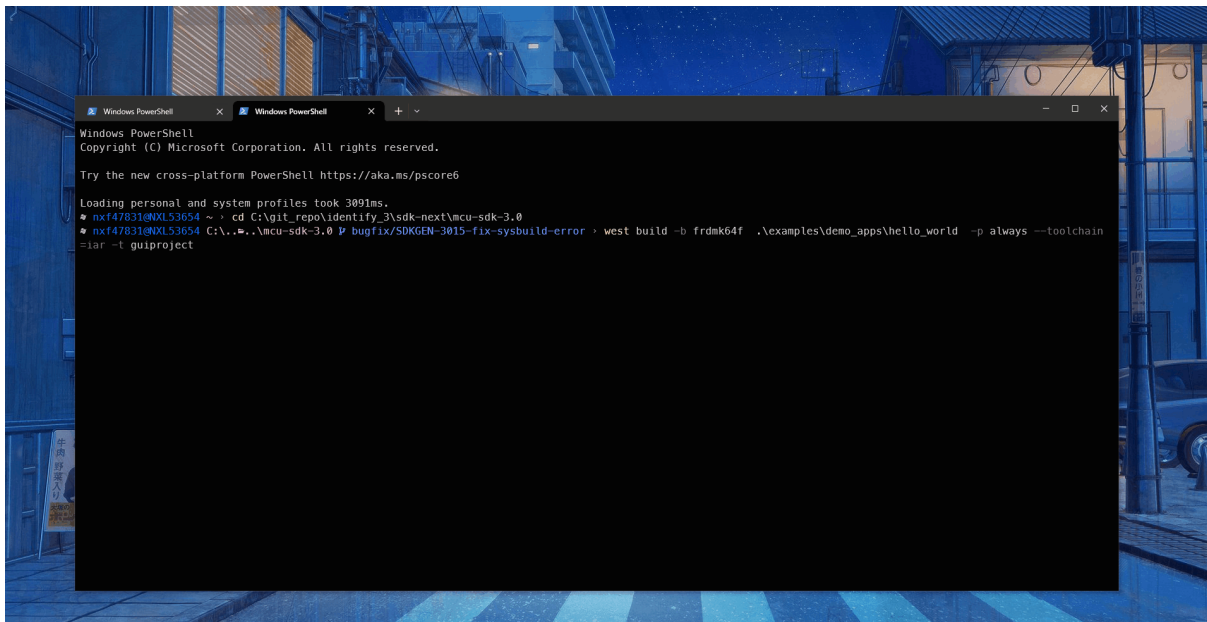
```
west debug -r linkserver
```

Work with IDE Project The above build functionalities are all with CLI. If you want to use the toolchain IDE to work to enjoy the better user experience especially for debugging or you are already used to develop with IDEs like IAR, MDK, Xtensa and CodeWarrior in the embedded world, you can play with our IDE project generation functionality.

This is the cmd to generate the evkbmimxrt1170 hello_world IAR IDE project files.

```
west build -b evkbmimxrt1170 examples/demo_apps/hello_world --toolchain iar -Dcore_id=cm7 --config_↵  
↵flexspi_nor_debug -p always -t guiproject
```

By default, the IDE project files are generated in mcuxsdk/build/<toolchain> folder, you can open the project file with the IDE tool to work:



Note, please follow the [Installation](#) to setup the environment especially make sure that [ruby](#) has been installed.

1.4 Release Notes

1.4.1 MCUXpresso SDK Release Notes

Overview

The MCUXpresso SDK is a comprehensive software enablement package designed to simplify and accelerate application development with Arm Cortex-M-based devices from NXP, including its general purpose, crossover and Bluetooth-enabled MCUs. MCUXpresso SW and Tools for DSC

further extends the SDK support to current 32-bit Digital Signal Controllers. The MCUXpresso SDK includes production-grade software with integrated RTOS (optional), integrated enabling software technologies (stacks and middleware), reference software, and more.

In addition to working seamlessly with the MCUXpresso IDE, the MCUXpresso SDK also supports and provides example projects for various toolchains. The Development tools chapter in the associated Release Notes provides details about toolchain support for your board. Support for the MCUXpresso Config Tools allows easy cloning of existing SDK examples and demos, allowing users to leverage the existing software examples provided by the SDK for their own projects.

Underscoring our commitment to high quality, the MCUXpresso SDK is MISRA compliant and checked with Coverity static analysis tools. For details on MCUXpresso SDK, see [MCUXpresso-SDK: Software Development Kit for MCUXpresso](#).

MCUXpresso SDK

As part of the MCUXpresso software and tools, MCUXpresso SDK is the evolution of Kinetis SDK, includes support for LPC, DSC, PN76, and i.MX System-on-Chip (SoC). The same drivers, APIs, and middleware are still available with support for Kinetis, LPC, DSC, and i.MX silicon. The MCUXpresso SDK adds support for the MCUXpresso IDE, an Eclipse-based toolchain that works with all MCUXpresso SDKs. Easily import your SDK into the new toolchain to access to all of the available components, examples, and demos for your target silicon. In addition to the MCUXpresso IDE, support for the MCUXpresso Config Tools allows easy cloning of existing SDK examples and demos, allowing users to leverage the existing software examples provided by the SDK for their own projects.

In order to maintain compatibility with legacy Freescale code, the filenames and source code in MCUXpresso SDK containing the legacy Freescale prefix FSL has been left as is. The FSL prefix has been redefined as the NXP Foundation Software Library.

Development tools

The MCUXpresso SDK was tested with following development tools. Same versions or above are recommended.

- MCUXpresso IDE, Rev. 25.06.xx
- IAR Embedded Workbench for Arm, version is 9.60.4
- Keil MDK, version is 5.41
- MCUXpresso for VS Code v25.06
- GCC Arm Embedded Toolchain 14.2.x

Supported development systems

This release supports board and devices listed in following table. The board and devices in bold were tested in this release.

Devel- opment boards	MCU devices
FRDM- KE15Z	MKE14Z128VLH7, MKE14Z128VLL7, MKE14Z256VLH7, MKE14Z256VLL7, MKE15Z128VLH7, MKE15Z128VLL7, MKE15Z256VLH7, MKE15Z256VLL7

MCUXpresso SDK release package

The MCUXpresso SDK release package content is aligned with the silicon subfamily it supports. This includes the boards, CMSIS, devices, middleware, and RTOS support.

Device support The device folder contains the whole software enablement available for the specific System-on-Chip (SoC) subfamily. This folder includes clock-specific implementation, device register header files, device register feature header files, and the system configuration source files. Included with the standard SoC support are folders containing peripheral drivers, toolchain support, and a standard debug console. The device-specific header files provide a direct access to the microcontroller peripheral registers. The device header file provides an overall SoC memory mapped register definition. The folder also includes the feature header file for each peripheral on the microcontroller. The toolchain folder contains the startup code and linker files for each supported toolchain. The startup code efficiently transfers the code execution to the `main()` function.

Board support The boards folder provides the board-specific demo applications, driver examples, and middleware examples.

Demo application and other examples The demo applications demonstrate the usage of the peripheral drivers to achieve a system level solution. Each demo application contains a readme file that describes the operation of the demo and required setup steps. The driver examples demonstrate the capabilities of the peripheral drivers. Each example implements a common use case to help demonstrate the driver functionality.

RTOS

FreeRTOS Real-time operating system for microcontrollers from Amazon

Middleware

CMSIS DSP Library The MCUXpresso SDK is shipped with the standard CMSIS development pack, including the prebuilt libraries.

NXP Touch Library NXP Touch Library

TinyCBOR Concise Binary Object Representation (CBOR) Library

PKCS#11 The PKCS#11 standard specifies an application programming interface (API), called “Cryptoki,” for devices that hold cryptographic information and perform cryptographic functions. Cryptoki follows a simple object based approach, addressing the goals of technology independence (any kind of device) and resource sharing (multiple applications accessing multiple devices), presenting to applications a common, logical view of the device called a “cryptographic token”.

llhttp HTTP parser llhttp

FreeMASTER FreeMASTER communication driver for 32-bit platforms.

File systemFatfs The FatFs file system is integrated with the MCUXpresso SDK and can be used to access either the SD card or the USB memory stick when the SD card driver or the USB Mass Storage Device class implementation is used.

Release contents

Provides an overview of the MCUXpresso SDK release package contents and locations.

Deliverable	Location
Boards	INSTALL_DIR/boards
Demo Applications	INSTALL_DIR/boards/<board_name>/demo_apps
Driver Examples	INSTALL_DIR/boards/<board_name>/driver_examples
eIQ examples	INSTALL_DIR/boards/<board_name>/eiq_examples
Board Project Template for MCUXpresso IDE NPW	INSTALL_DIR/boards/<board_name>/project_template
Driver, SoC header files, extension header files and feature header files, utilities	INSTALL_DIR/devices/<device_name>
CMSIS drivers	INSTALL_DIR/devices/<device_name>/cmsis_drivers
Peripheral drivers	INSTALL_DIR/devices/<device_name>/drivers
Toolchain linker files and startup code	INSTALL_DIR/devices/<device_name>/<toolchain_name>
Utilities such as debug console	INSTALL_DIR/devices/<device_name>/utilities
Device Project Template for MCUXpresso IDE NPW	INSTALL_DIR/devices/<device_name>/project_template
CMSIS Arm Cortex-M header files, DSP library source	INSTALL_DIR/CMSIS
Components and board device drivers	INSTALL_DIR/components
RTOS	INSTALL_DIR/rtos
Release Notes, Getting Started Document and other documents	INSTALL_DIR/docs
Tools such as shared cmake files	INSTALL_DIR/tools
Middleware	INSTALL_DIR/middleware

Known issues

This section lists the known issues, limitations, and/or workarounds.

Cannot add SDK components into FreeRTOS projects

It is not possible to add any SDK components into FreeRTOS project using the MCUXpresso IDE New Project wizard.

Importing FTM_PDB_ADC16 project into MCUXpresso Config tool reports FTM driver error

When you import the FTM_PDB_ADC16 project using the MCUXpresso Config Tool an error is prompted. The error prompts that the FTM driver is not aligned with the peripheral components. It is recommended not to import this project into the MCUXpresso Config Tool.

1.5 ChangeLog

1.5.1 MCUXpresso SDK Changelog

Board Support Files

board

[25.06.00]

- Initial version

clock_config

[25.06.00]

- Initial version

pin_mux

[25.06.00]

- Initial version
-

ACMP

[2.3.0]

- Improvements
 - Expose C0 register FILTER_CNT bitfield and FPR bitfield to the user.

[2.2.0]

- Improvements
 - Updated feature macros for roundrobin mode, window mode, filter mode, and 3V domain removes.

[2.1.0]

- New Feature
 - Supported the platforms which don't have hysteresis mode.

[2.0.6]

- Bug Fixes
 - Fixed the wrong comments, the DAC value should range from 0 to 255.

[2.0.5]

- Bug Fixes
 - Fixed the out-of-bounds error of Coverity caused by missing an assert sentence to avoid the return value of `ACMP_GetInstance()` exceeding the array bounds.
 - Fixed the violations of MISRA C-2012 rules:
 - * Rule 10.1, 14.4, 16.4, 17.7.

[2.0.4]

- Bug Fixes
 - Avoided changing w1c bit in `ACMP_SetRoundRobinPreState()`.

[2.0.3]

- New Features
 - Added feature functions for usage of different power domains(1.8 V and 3 V). These functions are first enabled in ULP1. They are about:
 - * `ACMP_EnableLinkToDAC()`
 - * `ACMP_SetDiscreteModeConfig()`
 - * `ACMP_GetDefaultDiscreteModeConfig()`

[2.0.2]

- Other Changes
 - Changed coding style of peripheral base address from “`s_acmpBases`” to “`s_acmpBase`”.

[2.0.1]

- Bug Fixes
 - Fixed bug regarding the function “`ACMP_SetRoundRobinConfig`”. It will not continue execution but returns directly after disabling round robin mode.
-

ADC12**[2.0.8]**

- Bug Fixes
 - Fix build warning when `FSL_SDK_DISABLE_DRIVER_CLOCK_CONTROL` is defined as 1.

[2.0.7]

- Improvements
 - Change the method for judging the end of calibration. Previously, it was judged based on the COCO bit of the SC1 register. After the update, it is judged based on the CAL bit of the SC3 register. In some cases, `SC1[COCO]` was already set to 1 before calibration was performed, which caused calibration to fail.

[2.0.6]

- Improvements
 - Removed useless comments of ADC12_DoAutoCalibration() function.

[2.0.5]

- Bug Fixes
 - Fixed the violations of MISRA C-2012 rule 10.4.

[2.0.4]

- Bug Fixes
 - Fixed the violations of MISRA C-2012 rules:
 - * Rule 4.7 10.1 10.3 10.4 10.8 12.2 16.4 17.7

[2.0.3]

- Improvements
 - Used conversion control feature macro instead of that in IO map.

[2.0.2]

- Bug Fixes
 - Set ADC clock frequency as half of the maximum value for calibration.

[2.0.1]

- New Features
 - Added a feature to control enablement of DMA.

[2.0.0]

- Initial version.
-

CLOCK

[2.4.0]

- Bug Fixes
 - Removed unimplemented kSCG_AsyncDiv1Clk.

[2.3.1]

- Bug Fixes
 - Fixed MISRA C-2012 rule 10.1, rule 10.4, rule 10.8, rule 15.5 and so on.

[2.3.0]

- New Features
 - Moved SDK_DelayAtLeastUs function from clock driver to common driver.

[2.2.0]

- New Features
 - Added new API CLOCK_DelayAtLeastUs() implemented by DWT to allow users set delay in unit of microsecond.

[2.1.2]

- Bug Fixes
 - Fixed OSC32 can not use EXTAL32 clock source issue.

[2.1.1]

- Improvements
 - Changed reserved bit fields in _scg_sys_clk_config struct into unnamed bit fields.

[2.1.0]

- Other Changes
 - Merged fsl_scg and fsl_osc into fsl_clock.

[2.0.0]

- Initial version.
-

COMMON**[2.6.0]**

- Bug Fixes
 - Fix CERT-C violations.

[2.5.0]

- New Features
 - Added new APIs InitCriticalSectionMeasurementContext, DisableGlobalIRQEx and EnableGlobalIRQEx so that user can measure the execution time of the protected sections.

[2.4.3]

- Improvements
 - Enable irqsteer that mount under irqsteer interrupt extender.

[2.4.2]

- Improvements
 - Add the macros to convert peripheral address to secure address or non-secure address.

[2.4.1]

- Improvements
 - Improve for the macro redefinition error when integrated with zephyr.

[2.4.0]

- New Features
 - Added EnableIRQWithPriority, IRQ_SetPriority, and IRQ_ClearPendingIRQ for ARM.
 - Added MSDK_EnableCpuCycleCounter, MSDK_GetCpuCycleCount for ARM.

[2.3.3]

- New Features
 - Added NETC into status group.

[2.3.2]

- Improvements
 - Make driver aarch64 compatible

[2.3.1]

- Bug Fixes
 - Fixed MAKE_VERSION overflow on 16-bit platforms.

[2.3.0]

- Improvements
 - Split the driver to common part and CPU architecture related part.

[2.2.10]

- Bug Fixes
 - Fixed the ATOMIC macros build error in cpp files.

[2.2.9]

- Bug Fixes
 - Fixed MISRA C-2012 issue, 5.6, 5.8, 8.4, 8.5, 8.6, 10.1, 10.4, 17.7, 21.3.
 - Fixed SDK_Malloc issue that not allocate memory with required size.

[2.2.8]

- Improvements
 - Included `stdint.h` header file for MDK tool chain.
- New Features:
 - Added atomic modification macros.

[2.2.7]

- Other Change
 - Added MECC status group definition.

[2.2.6]

- Other Change
 - Added more status group definition.
- Bug Fixes
 - Undef `__VECTOR_TABLE` to avoid duplicate definition in `cmsis_clang.h`

[2.2.5]

- Bug Fixes
 - Fixed MISRA C-2012 rule-15.5.

[2.2.4]

- Bug Fixes
 - Fixed MISRA C-2012 rule-10.4.

[2.2.3]

- New Features
 - Provided better accuracy of `SDK_DelayAtLeastUs` with DWT, use macro `SDK_DELAY_USE_DWT` to enable this feature.
 - Modified the Cortex-M7 delay count divisor based on latest tests on RT series boards, this setting lets result be closer to actual delay time.

[2.2.2]

- New Features
 - Added include `RTE_Components.h` for CMSIS pack RTE.

[2.2.1]

- Bug Fixes
 - Fixed violation of MISRA C-2012 Rule 3.1, 10.1, 10.3, 10.4, 11.6, 11.9.

[2.2.0]

- New Features
 - Moved SDK_DelayAtLeastUs function from clock driver to common driver.

[2.1.4]

- New Features
 - Added OTFAD into status group.

[2.1.3]

- Bug Fixes
 - MISRA C-2012 issue fixed.
 - * Fixed the rule: rule-10.3.

[2.1.2]

- Improvements
 - Add SUPPRESS_FALL_THROUGH_WARNING() macro for the usage of suppressing fallthrough warning.

[2.1.1]

- Bug Fixes
 - Deleted and optimized repeated macro.

[2.1.0]

- New Features
 - Added IRQ operation for XCC toolchain.
 - Added group IDs for newly supported drivers.

[2.0.2]

- Bug Fixes
 - MISRA C-2012 issue fixed.
 - * Fixed the rule: rule-10.4.

[2.0.1]

- Improvements
 - Removed the implementation of LPC8XX Enable/DisableDeepSleepIRQ() function.
 - Added new feature macro switch “FSL_FEATURE_HAS_NO_NONCACHEABLE_SECTION” for specific SoCs which have no noncacheable sections, that helps avoid an unnecessary complex in link file and the startup file.
 - Updated the align(x) to **attribute**(aligned(x)) to support MDK v6 armclang compiler.

[2.0.0]

- Initial version.
-

CRC**[2.0.4]**

- Improvements
 - Release peripheral from reset if necessary in init function.

[2.0.3]

- Bug fix:
 - Fix MISRA issues.

[2.0.2]

- Bug fix:
 - Fix MISRA issues.

[2.0.1]

- Bug fix:
 - DATA and DATALL macro definition moved from header file to source file.

[2.0.0]

- Initial version.
-

DMAMUX**[2.1.2]**

- Bug Fixes
 - Add macro FSL_DMAMUX_CHANNEL_NUM to calculat correct DMAMUX channel number when input EDAM channel number.

[2.1.1]

- Improvements
 - Add macro FSL_FEATURE_DMAMUX_CHANNEL_NEEDS_ENDIAN_CONVERT and DMAMUX_CHANNEL_ENDIAN_CONVERTn do channel endian convert.

[2.1.0]

- Improvements
 - Modify the type of parameter source from uint32_t to int32_t in the DMA-MUX_SetSource.

[2.0.5]

- Improvements
 - Added feature FSL_FEATURE_DMAMUX_CHCFG_REGISTER_WIDTH for the difference of CHCFG register width.

[2.0.4]

- Bug Fixes
 - Fixed violations of MISRA C-2012 rule 10.4.

[2.0.3]

- Bug Fixes
 - Fixed the issue for MISRA-2012 check.
 - * Fixed rule 10.4 and rule 10.3.

[2.0.2]

- New Features
 - Added an always-on enable feature to a DMA channel for ULP1 DMAMUX support.

[2.0.1]

- Bug Fixes
 - Fixed the build warning issue by changing the type of parameter source from uint8_t to uint32_t when setting DMA request source in DMAMUX_SetSourceChange.

[2.0.0]

- Initial version.
-

EDMA

[2.4.5]

- Bug Fixes
 - Fixed memory convert would convert NULL as zero address issue.

[2.4.4]

- Bug Fixes
 - Fixed comments by replacing STCD with TCD
 - Fixed the TCD overwrite issue when submit transfer request in the callback if there is a active TCD in hardware.
 - Fixed violations of MISRA C-2012 rule 10.8,5.6.

[2.4.3]

- Improvements
 - Added `FSL_FEATURE_MEMORY_HAS_ADDRESS_OFFSET` to convert the address between system mapped address and dma quick access address.
- Bug Fixes
 - Fixed the wrong tcd done count calculated in first TCD interrupt for the non scatter gather case.

[2.4.2]

- Bug Fixes
 - Fixed the wrong tcd done count calculated in first TCD interrupt by correct the initial value of the header.
 - Fixed violations of MISRA C-2012 rule 10.3, 10.4.

[2.4.1]

- Bug Fixes
 - Added clear CITER and BITER registers in `EDMA_AbortTransfer` to make sure the TCD registers in a correct state for next calling of `EDMA_SubmitTransfer`.
 - Removed the clear DONE status for ESG not enabled case to avoid DONE bit cleared unexpectedly.

[2.4.0]

- Improvements
 - Added api `EDMA_EnableContinuousChannelLinkMode` to support continuous link mode.
 - Added apis `EDMA_SetMajorOffsetConfig/EDMA_TcdSetMajorOffsetConfig` to support major loop address offset feature.
 - Added api `EDMA_EnableChannelMinorLoopMapping` for minor loop offset feature.
 - Removed the redundant IRQ Handler in edma driver.

[2.3.2]

- Improvements
 - Fixed HIS ccm issue in function `EDMA_PrepareTransferConfig`.
 - Fixed violations of MISRA C-2012 rule 11.6, 10.7, 10.3, 18.1.
- Bug Fixes
 - Added ACTIVE & BITER & CITER bitfields to determine the channel status to fixed the issue of the transfer request cannot submit by function `EDMA_SubmitTransfer` when channel is idle.

[2.3.1]

- Improvements
 - Added source/destination address alignment check.
 - Added driver IRQ handler support for multi DMA instance in one SOC.

[2.3.0]

- Improvements
 - Added new api `EDMA_PrepareTransferConfig` to allow different configurations of width and offset.
- Bug Fixes
 - Fixed violations of MISRA C-2012 rule 10.4, 10.1.
 - Fixed the Coverity issue regarding out-of-bounds write.

[2.2.0]

- Improvements
 - Added peripheral-to-peripheral support in EDMA driver.

[2.1.9]

- Bug Fixes
 - Fixed MISRA issue: Rule 10.7 and 10.8 in function `EDMA_DisableChannelInterrupts` and `EDMA_SubmitTransfer`.
 - Fixed MISRA issue: Rule 10.7 in function `EDMA_EnableAsyncRequest`.

[2.1.8]

- Bug Fixes
 - Fixed incorrect channel preemption base address used in `EDMA_SetChannelPreemptionConfig` API which causes incorrect configuration of the channel preemption register.

[2.1.7]

- Bug Fixes
 - Fixed incorrect transfer size setting.
 - * Added 8 bytes transfer configuration and feature for RT series;
 - * Added feature to support 16 bytes transfer for Kinetis.
 - Fixed the issue that `EDMA_HandleIRQ` would go to incorrect branch when TCD was not used and callback function not registered.

[2.1.6]

- Bug Fixes
 - Fixed KW3X MISRA Issue.
 - * Rule 14.4, 10.8, 10.4, 10.7, 10.1, 10.3, 13.5, and 13.2.
- Improvements
 - Cleared the IRQ handler unavailable for specific platform with macro `FSL_FEATURE_EDMA_MODULE_CHANNEL_IRQ_ENTRY_SHARED_OFFSET`.

[2.1.5]

- Improvements
 - Improved EDMA IRQ handler to support half interrupt feature.

[2.1.4]

- Bug Fixes
 - Cleared enabled request, status during `EDMA_Init` for the case that EDMA is halted before reinitialization.

[2.1.3]

- Bug Fixes
 - Added clear DONE bit in IRQ handler to avoid overwrite TCD issue.
 - Optimized above solution for the case that transfer request occurs in callback.

[2.1.2]

- Improvements
 - Added interface to get next TCD address.
 - Added interface to get the unused TCD number.

[2.1.1]

- Improvements
 - Added documentation for eDMA data flow when scatter/gather is implemented for the `EDMA_HandleIRQ` API.
 - Updated and corrected some related comments in the `EDMA_HandleIRQ` API and `edma_handle_t` struct.

[2.1.0]

- Improvements
 - Changed the `EDMA_GetRemainingBytes` API into `EDMA_GetRemainingMajorLoopCount` due to eDMA IP limitation (see API comments/note for further details).

[2.0.5]

- Improvements
 - Added pubweak DriverIRQHandler for K32H844P (16 channels shared).

[2.0.4]

- Improvements
 - Added support for SoCs with multiple eDMA instances.
 - Added pubweak DriverIRQHandler for KL28T DMA1 and MCIMX7U5_M4.

[2.0.3]

- Bug Fixes
 - Fixed the incorrect pubweak IRQHandler name issue, which caused re-definition build errors when client set his/her own IRQHandler, by changing the 32-channel IRQHandler name to DriverIRQHandler.

[2.0.2]

- Bug Fixes
 - Fixed incorrect minorLoopBytes type definition in `_edma_transfer_config` struct, and defined `minorLoopBytes` as `uint32_t` instead of `uint16_t`.

[2.0.1]

- Bug Fixes
 - Fixed the eDMA callback issue (which did not check valid status) in `EDMA_HandleIRQ` API.

[2.0.0]

- Initial version.
-

EWM

[2.0.4]

- Bug Fixes
 - Fixed CERT INT31-C violations.

[2.0.3]

- Bug Fixes
 - Fixed violation of MISRA C-2012 rules: 10.1, 10.3.

[2.0.2]

- Bug Fixes
 - Fixed violation of MISRA C-2012 rules: 10.3, 10.4.

[2.0.1]

- Bug Fixes
 - Fixed the hard fault in EWM_Deinit.

[2.0.0]

- Initial version.
-

FLASH

[3.2.0]

- New Feature
 - Basic support for FTFC

[3.1.3]

- New Feature
 - Support 512KB flash for Kinetis E serials.

[3.1.2]

- Bug Fixes — Remove redundant comments.

[3.1.1]

- Bug Fixes — MISRA C-2012 issue fixed: rule 10.3

[3.1.0]

- New Feature
 - Support erase flash asynchronously.

[3.0.2]

- Bug Fixes — MISRA C-2012 issue fixed: rule 8.4, 17.7, 10.4, 16.1, 21.15, 11.3, 10.7 — building warning -Wnull-dereference on arm compiler v6

[3.0.1]

- New Features
 - Added support FlexNVM alias for (kw37/38/39).

[3.0.0]

- Improvements
 - Reorganized FTFx flash driver source file.
 - Extracted flash cache driver from FTFx driver.
 - Extracted flexnvm flash driver from FTFx driver.

[2.3.1]

- Bug Fixes
 - Unified Flash IFR design from K3.
 - New encoding rule for K3 flash size.

[2.3.0]

- New Features
 - Added support for device with LP flash (K3S/G).
 - Added flash prefetch speculation APIs.
- Improvements
 - Refined flash_cache_clear function.
 - Reorganized the member of flash_config_t struct.

[2.2.0]

- New Features
 - Supported FTFL device in FLASH_Swap API.
 - Supported various pflash start addresses.
 - Added support for KV58 in cache clear function.
 - Added support for device with secondary flash (KW40).
- Bug Fixes
 - Compiled execute-in-ram functions as PIC binary code for driver use.
 - Added missed flexram properties.
 - Fixed unaligned variable issue for execute-in-ram function code array.

[2.1.0]

- Improvements
 - Updated coding style to align with KSDK 2.0.
 - Different-alignment-size support for pflash and flexnvm.
 - Improved the implementation of execute-in-ram functions.

[2.0.0]

- Initial version

FLEXIO

[2.3.0]

- Improvements
 - Supported platforms which don't have DOZE mode control.
 - Added more pin control functions.

[2.2.3]

- Improvements
 - Adapter the FLEXIO driver to platforms which don't have system level interrupt controller, such as NVIC.

[2.2.2]

- Improvements
 - Release peripheral from reset if necessary in init function.

[2.2.1]

- Improvements
 - Added doxygen index parameter comment in FLEXIO_SetClockMode.

[2.2.0]

- New Features
 - Added new APIs to support FlexIO pin register.

[2.1.0]

- Improvements
 - Added API FLEXIO_SetClockMode to set flexio channel counter and source clock.

[2.0.4]

- Bug Fixes
 - Fixed MISRA 8.4 issues.

[2.0.3]

- Bug Fixes
 - Fixed MISRA 10.4 issues.

[2.0.2]

- Improvements
 - Split FLEXIO component which combines all flexio/flexio_uart/flexio_i2c/flexio_i2s drivers into several components: FlexIO component, flexio_uart component, flexio_i2c_master component, and flexio_i2s component.
- Bug Fixes
 - Fixed MISRA issues
 - * Fixed rules 10.1, 10.3, 10.4, 10.7, 11.6, 11.9, 14.4, 17.7.

[2.0.1]

- Bug Fixes
 - Fixed the dozen mode configuration error in FLEXIO_Init API. For enableInDoze = true, the configuration should be 0; for enableInDoze = false, the configuration should be 1.
-

FLEXIO_I2C

[2.6.1]

- Bug Fixes
 - Fixed coverity issues

[2.6.0]

- Improvements
 - Supported platforms which don't have DOZE mode control.

[2.5.1]

- Improvements
 - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.5.0]

- Improvements
 - Split some functions, fixed CCM problem in file fsl_flexio_i2c_master.c.

[2.4.0]

- Improvements
 - Added delay of 1 clock cycle in FLEXIO_I2C_MasterTransferRunStateMachine to ensure that bus would be idle before next transfer if master is nacked.
 - Fixed issue that the restart setup time is less than the time in I2C spec by adding delay of 1 clock cycle before restart signal.

[2.3.0]

- Improvements
 - Used 3 timers instead of 2 to support transfer which is more than 14 bytes in single transfer.
 - Improved FLEXIO_I2C_MasterTransferGetCount so that the API can check whether the transfer is still in progress.
- Bug Fixes
 - Fixed MISRA 10.4 issues.

[2.2.0]

- New Features
 - Added timeout mechanism when waiting certain state in transfer API.
 - Added an API for checking bus pin status.
- Bug Fixes
 - Fixed COVERITY issue of useless call in FLEXIO_I2C_MasterTransferRunStateMachine.
 - Fixed MISRA issues
 - * Fixed rules 10.1, 10.3, 10.4, 10.7, 11.6, 11.9, 14.4, 17.7.
 - Added codes in FLEXIO_I2C_MasterTransferCreateHandle to clear pending NVIC IRQ, disable internal IRQs before enabling NVIC IRQ.
 - Modified code so that during master's nonblocking transfer the start and slave address are sent after interrupts being enabled, in order to avoid potential issue of sending the start and slave address twice.

[2.1.7]

- Bug Fixes
 - Fixed the issue that FLEXIO_I2C_MasterTransferBlocking did not wait for STOP bit sent.
 - Fixed COVERITY issue of useless call in FLEXIO_I2C_MasterTransferRunStateMachine.
 - Fixed the issue that I2C master did not check whether bus was busy before transfer.

[2.1.6]

- Bug Fixes
 - Fixed the issue that I2C Master transfer APIs(blocking/non-blocking) did not support the situation of master transfer with subaddress and transfer data size being zero, which means no data followed the subaddress.

[2.1.5]

- Improvements
 - Unified component full name to FLEXIO I2C Driver.

[2.1.4]

- Bug Fixes
 - The following modifications support FlexIO using multiple instances:
 - * Removed FLEXIO_Reset API in module Init APIs.
 - * Updated module Deinit APIs to reset the shifter/timer config instead of disabling module/clock.
 - * Updated module Enable APIs to only support enable operation.

[2.1.3]

- Improvements
 - Changed the prototype of FLEXIO_I2C_MasterInit to return kStatus_Success if initialized successfully or to return kStatus_InvalidArgument if “(srcClock_Hz / masterConfig->baudRate_Bps) / 2 - 1” exceeds 0xFFU.

[2.1.2]

- Bug Fixes
 - Fixed the FLEXIO I2C issue where the master could not receive data from I2C slave in high baudrate.
 - Fixed the FLEXIO I2C issue where the master could not receive NAK when master sent non-existent addr.
 - Fixed the FLEXIO I2C issue where the master could not get transfer count successfully.
 - Fixed the FLEXIO I2C issue where the master could not receive data successfully when sending data first.
 - Fixed the Dozen mode configuration error in FLEXIO_I2C_MasterInit API. For enableInDoze = true, the configuration should be 0; for enableInDoze = false, the configuration should be 1.
 - Fixed the issue that FLEXIO_I2C_MasterTransferBlocking API called FLEXIO_I2C_MasterTransferCreateHandle, which lead to the s_flexioHandle/s_flexioIsr/s_flexioType variable being written. Then, if calling FLEXIO_I2C_MasterTransferBlocking API multiple times, the s_flexioHandle/s_flexioIsr/s_flexioType variable would not be written any more due to it being out of range. This lead to the following situation: NonBlocking transfer APIs could not work due to the fail of register IRQ.

[2.1.1]

- Bug Fixes
 - Implemented the FLEXIO_I2C_MasterTransferBlocking API which is defined in header file but has no implementation in the C file.

[2.1.0]

- New Features
 - Added Transfer prefix in transactional APIs.
 - Added transferSize in handle structure to record the transfer size.

FLEXIO_I2S

[2.2.2]

- Bug Fixes
 - Fixed violations of MISRA C-2012 rule 12.4.

[2.2.1]

- Improvements
 - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.2.0]

- New Features
 - Added timeout mechanism when waiting certain state in transfer API.
- Bug Fixes
 - Fixed IAR Pa082 warnings.
 - Fixed violations of the MISRA C-2012 rules 10.4, 14.4, 11.8, 11.9, 10.1, 17.7, 11.6, 10.3, 10.7.

[2.1.6]

- Bug Fixes
 - Added reset flexio before flexio i2s init to make sure flexio status is normal.

[2.1.5]

- Bug Fixes
 - Fixed the issue that I2S driver used hard code for bitwidth setting.

[2.1.4]

- Improvements
 - Unified component's full name to FLEXIO I2S (DMA/EDMA) driver.

[2.1.3]

- Bug Fixes
 - The following modifications support FLEXIO using multiple instances:
 - * Removed FLEXIO_Reset API in module Init APIs.
 - * Updated module Deinit APIs to reset the shifter/timer config instead of disabling module/clock.
 - * Updated module Enable APIs to only support enable operation.

[2.1.2]

- New Features
 - Added configure items for all pin polarity and data valid polarity.
 - Added default configure for pin polarity and data valid polarity.

[2.1.1]

- Bug Fixes
 - Fixed FlexIO I2S RX data read error and eDMA address error.
 - Fixed FlexIO I2S slave timer compare setting error.

[2.1.0]

- New Features
 - Added Transfer prefix in transactional APIs.
 - Added transferSize in handle structure to record the transfer size.
-

FLEXIO_I2S_EDMA

[2.1.9]

- Bug Fixes
 - Fixed violations of MISRA C-2012 rule 12.4.

[2.1.8]

- Improvements
 - Applied EDMA ERRATA 51327.
-

FLEXIO_SPI

[2.4.2]

- Bug Fixes
 - Fixed FLEXIO_SPI_MasterTransferBlocking and FLEXIO_SPI_MasterTransferNonBlocking issue in CS continuous mode, the CS might not be continuous.

[2.4.1]

- Bug Fixes
 - Fixed coverity issues

[2.4.0]

- Improvements
 - Supported platforms which don't have DOZE mode control.

[2.3.5]

- Improvements
 - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.3.4]

- Bug Fixes
 - Fixed the txData from void * to const void * in transmit API

[2.3.3]

- Bugfixes
 - Fixed cs-continuous mode.

[2.3.2]

- Improvements
 - Changed FLEXIO_SPI_DUMMYDATA to 0x00.

[2.3.1]

- Bugfixes
 - Fixed IRQ SHIFTBUF overrun issue when one FLEXIO instance used as multiple SPIs.

[2.3.0]

- New Features
 - Supported FLEXIO_SPI slave transfer with continuous master CS signal and CPHA=0.
 - Supported FLEXIO_SPI master transfer with continuous CS signal.
 - Support 32 bit transfer width.
- Bug Fixes
 - Fixed wrong timer compare configuration for dma/edma transfer.
 - Fixed wrong byte order of rx data if transfer width is 16 bit, since the we use shifter buffer bit swapped/byte swapped register to read in received data, so the high byte should be read from the high bits of the register when MSB.

[2.2.1]

- Bug Fixes
 - Fixed bug in FLEXIO_SPI_MasterTransferAbortEDMA that when aborting EDMA transfer EDMA_AbortTransfer should be used rather than EDMA_StopTransfer.

[2.2.0]

- Improvements
 - Added timeout mechanism when waiting certain states in transfer driver.
- Bug Fixes
 - Fixed MISRA 10.4 issues.
 - Added codes in FLEXIO_SPI_MasterTransferCreateHandle and FLEXIO_SPI_SlaveTransferCreateHandle to clear pending NVIC IRQ before enabling NVIC IRQ, to fix issue of pending IRQ interfering the on-going process.

[2.1.3]

- Improvements
 - Unified component full name to FLEXIO SPI(DMA/EDMA) Driver.
- Bug Fixes
 - Fixed MISRA issues
 - * Fixed rules 10.1, 10.3, 10.4, 10.7, 11.6, 11.9, 14.4, 17.7.

[2.1.2]

- Bug Fixes
 - The following modification support FlexIO using multiple instances:
 - * Removed FLEXIO_Reset API in module Init APIs.
 - * Updated module Deinit APIs to reset the shifter/timer config instead of disabling module/clock.
 - * Updated module Enable APIs to only support enable operation.

[2.1.1]

- Bug Fixes
 - Fixed bug where FLEXIO SPI transfer data is in 16 bit per frame mode with eDMA.
 - Fixed bug when FLEXIO SPI works in eDMA and interrupt mode with 16-bit per frame and Lsbfirst.
 - Fixed the Dozen mode configuration error in FLEXIO_SPI_MasterInit/FLEXIO_SPI_SlaveInit API. For enableInDoze = true, the configuration should be 0; for enableInDoze = false, the configuration should be 1.
- Improvements
 - Added #ifndef/#endif to allow users to change the default TX value at compile time.

[2.1.0]

- New Features
 - Added Transfer prefix in transactional APIs.
 - Added transferSize in handle structure to record the transfer size.
- Bug Fixes

- Fixed the error register address return for 16-bit data write in FLEXIO_SPI_GetTxDataRegisterAddress.
 - Provided independent IRQHandler/transfer APIs for Master and slave to fix the baudrate limit issue.
-

FLEXIO_UART

[2.6.3]

- Bug Fixes
 - Fixed coverity issues

[2.6.2]

- Bug Fixes
 - Fixed coverity issues

[2.6.1]

- Improvements
 - Improve baudrate calculation method, to support higher frequency FlexIO clock source.

[2.6.0]

- Improvements
 - Supported platforms which don't have DOZE mode control.

[2.5.1]

- Improvements
 - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.5.0]

- Improvements
 - Added API FLEXIO_UART_FlushShifters to flush UART fifo.

[2.4.0]

- Improvements
 - Use separate data for TX and RX in flexio_uart_transfer_t.
- Bug Fixes
 - Fixed bug that when ring buffer is used, if some data is received in ring buffer first before calling FLEXIO_UART_TransferReceiveNonBlocking, the received data count returned by FLEXIO_UART_TransferGetReceiveCount is wrong.

[2.3.0]

- Improvements
 - Added check for baud rate's accuracy that returns `kStatus_FLEXIO_UART_BaudrateNotSupport` when the best achieved baud rate is not within 3% error of configured baud rate.
- Bug Fixes
 - Added codes in `FLEXIO_UART_TransferCreateHandle` to clear pending NVIC IRQ before enabling NVIC IRQ, to fix issue of pending IRQ interfering the on-going process.

[2.2.0]

- Improvements
 - Added timeout mechanism when waiting for certain states in transfer driver.
- Bug Fixes
 - Fixed MISRA 10.4 issues.

[2.1.6]

- Bug Fixes
 - Fixed IAR Pa082 warnings.
 - Fixed MISRA issues
 - * Fixed rules 10.1, 10.3, 10.4, 10.7, 11.6, 11.9, 14.4, 17.7.

[2.1.5]

- Improvements
 - Triggered user callback after all the data in ringbuffer were received in `FLEXIO_UART_TransferReceiveNonBlocking`.

[2.1.4]

- Improvements
 - Unified component full name to FLEXIO UART(DMA/EDMA) Driver.

[2.1.3]

- Bug Fixes
 - The following modifications support FLEXIO using multiple instances:
 - * Removed `FLEXIO_Reset` API in module Init APIs.
 - * Updated module Deinit APIs to reset the shifter/timer configuration instead of disabling module and clock.
 - * Updated module Enable APIs to only support enable operation.

[2.1.2]

- Bug Fixes
 - Fixed the transfer count calculation issue in FLEXIO_UART_TransferGetReceiveCount, FLEXIO_UART_TransferGetSendCount, FLEXIO_UART_TransferGetReceiveCountDMA, FLEXIO_UART_TransferGetSendCountDMA, FLEXIO_UART_TransferGetReceiveCountEDMA and FLEXIO_UART_TransferGetSendCountEDMA.
 - Fixed the Dozen mode configuration error in FLEXIO_UART_Init API. For enableInDoze = true, the configuration should be 0; for enableInDoze = false, the configuration should be 1.
 - Added code to report errors if the user sets a too-low-baudrate which FLEXIO cannot reach.
 - Disabled FLEXIO_UART receive interrupt instead of all NVICs when reading data from ring buffer. If ring buffer is used, receive nonblocking will disable all NVIC interrupts to protect the ring buffer. This had negative effects on other IPs using interrupt.

[2.1.1]

- Bug Fixes
 - Changed the API name FLEXIO_UART_StopRingBuffer to FLEXIO_UART_TransferStopRingBuffer to align with the definition in C file.

[2.1.0]

- New Features
 - Added Transfer prefix in transactional APIs.
 - Added txSize/rxSize in handle structure to record the transfer size.
 - Bug Fixes
 - Added an error handle to handle the situation that data count is zero or data buffer is NULL.
-

FLEXIO_UART_EDMA

[2.3.1]

- Bug Fixes
 - Fixed violations of the MISRA C-2012 rules.

[2.3.0]

- Refer FLEXIO_UART driver change log to 2.3.0
-

FTM

[2.7.2]

- Improvements
 - Add API FTM_ERRATA_010856 for ERR010856 workaround.

[2.7.1]

- Bug Fixes
 - Added function macro when accsee FLTCTRL register FSTATE bit to prevent access nonexistent register.
 - Added function macro to prevent access nonexistent FTM channel for API FTM_ConfigSinglePWM() and FTM_ConfigCombinePWM().

[2.7.0]

- Improvements
 - Support period dithering and edge dithering feature with new APIs:
 - * FTM_SetPeriodDithering()
 - * FTM_SetEdgeDithering()
 - Support get channel n output and input state feature with new APIs:
 - * FTM_GetChannelOutputState()
 - * FTM_GetChannelInputState()
 - Support configure deadtime for specific combined channel pair with new API:
 - * FTM_SetPairDeadTime()
 - Support filter clock prescale, fault output state.
 - Support new APIs to configure PWM and Modified Combine PWM:
 - * FTM_ConfigSinglePWM()
 - * FTM_ConfigCombinePWM()
 - Support new API to configure channel software output control:
 - * FTM_SetSoftwareOutputCtrl()
 - * FTM_GetSoftwareOutputValue()
 - * FTM_GetSoftwareOutputEnable()
 - Support new API to update FTM counter initial value, modulo value and chanle value:
 - * FTM_SetInitialModuloValue()
 - * FTM_SetChannelValue()

[2.6.1]

- Improvements
 - Release peripheral from reset if necessary in init function.

[2.6.0]

- Improvements
 - Added support to half and full cycle reload feature with new APIs:
 - * FTM_SetLdok()
 - * FTM_SetHalfCycPeriod()
 - * FTM_LoadFreq()
- Bug Fixes

- Set the HWRSTCNT and SWRSTCNT bits to optional at initialization.

[2.5.0]

- Improvements
 - Added FTM_CalculateCounterClkDiv to help calculates the counter clock prescaler.
 - Modify FTM_UpdatePwmDutycycle API to make it return pwm duty cycles status.
- Bug Fixes
 - Fixed TPM_SetupPwm can't configure 100% center align combined PWM issues.

[2.4.1]

- Bug Fixes
 - Added function macro to determine if FTM instance has only basic features, to prevent access to protected register bits.

[2.4.0]

- Improvements
 - Added CNTIN register initialization in FTM_SetTimerPeriod API.
 - Added a new API to read the captured value of a FTM channel configured in capture mode:
 - * FTM_GetInputCaptureValue()

[2.3.0]

- Improvements
 - Added support of EdgeAligned/CenterAligned/Asymmetrical combine PWM mode in FTM_SetupPWM() and FTM_SetupPwmMode() APIs.
 - Remove kFTM_ComplementaryPwm from support PWM mode, and add new parameter "enableComplementary" in structure ftm_chnl_pwm_signal_param_t.
 - Rename FTM_SetupFault() API to FTM_SetupFaultInput() to avoid ambiguity.

[2.2.3]

- Bug Fixes
 - MISRA C-2012 issue fixed: rule 14.4 and 17.7.

[2.2.2]

- Bug Fixes
 - Fixed the issue that when FTM instance has only TPM features cannot be initialized by FTM_Init() function. By added function macro to assert FTM is TPM only instance.

[2.2.1]

- Bug Fixes
 - MISRA C-2012 issue fixed: rule 10.1, 10.3, 10.4, 10.6, 10.7 and 11.9.

[2.2.0]

- Bug Fixes
 - Fixed the issue of comparison between signed and unsigned integer expressions.
- Improvements
 - Added support of complementary mode in FTM_SetupPWM() and FTM_SetupPwmMode() APIs.
 - Added new parameter “enableDeadtime” in structure `ftm_chnl_pwm_signal_param_t`.

[2.1.1]

- Bug Fixes
 - Fixed COVERITY integer handing issue where the right operand of a left bit shift statement should not be a negative value. This appears in FTM_SetReloadPoints().

[2.1.0]

- Improvements
 - Added a new API FTM_SetupPwmMode() to allow the user to set the channel match value in units of timer ticks. New configure structure called `ftm_chnl_pwm_config_param_t` was added to configure the channel’s PWM parameters. This API is similar with FTM_SetupPwm() API, but the new API will not set the timer period(MOD value), it will be useful for users to set the PWM parameters without changing the timer period.
- Bug Fixes
 - Added feature macro to enable/disable the external trigger source configuration.

[2.0.4]

- Improvements
 - Added a new API to enable DMA transfer:
 - * FTM_EnableDmaTransfer()

[2.0.3]

- Bug Fixes
 - Updated the FTM driver to enable fault input after configuring polarity.

[2.0.2]

- Improvements
 - Added support to Quad Decoder feature with new APIs:
 - * FTM_GetQuadDecoderFlags()
 - * FTM_SetQuadDecoderModuloValue()
 - * FTM_GetQuadDecoderCounterValue()
 - * FTM_ClearQuadDecoderCounterValue()

[2.0.1]

- Bug Fixes
 - Updated the FTM driver to fix write to ELSA and ELSB bits.
 - FTM combine mode: set the COMBINE bit before writing to CnV register.

[2.0.0]

- Initial version.
-

GPIO**[2.8.2]**

- Bug Fixes
 - Fixed COVERITY issue that GPIO_GetInstance could return clock array overflow values due to GPIO base and clock being out of sync.

[2.8.1]

- Bug Fixes
 - Fixed CERT INT31-C issues.

[2.8.0]

- Improvements
 - Add API GPIO_PortInit/GPIO_PortDeinit to set GPIO clock enable and releasing GPIO reset.

[2.8.0]

- Improvements
 - Add API GPIO_PortInit/GPIO_PortDeinit to set GPIO clock enable and releasing GPIO reset.
 - Remove support for API GPIO_GetPinsDMARequestFlags with GPIO_ISFR_COUNT <= 1.

[2.7.3]

- Improvements
 - Release peripheral from reset if necessary in init function.

[2.7.2]

- New Features
 - Support devices without PORT module.

[2.7.1]

- Bug Fixes
 - Fixed MISRA C-2012 rule 10.4 issues in GPIO_GpioGetInterruptChannelFlags() function and GPIO_GpioClearInterruptChannelFlags() function.

[2.7.0]

- New Features
 - Added API to support Interrupt select (IRQS) bitfield.

[2.6.0]

- New Features
 - Added API to get GPIO version information.
 - Added API to control a pin for general purpose input.
 - Added some APIs to control pin in secure and privilege status.

[2.5.3]

- Bug Fixes
 - Correct the feature macro typo: FSL_FEATURE_GPIO_HAS_NO_INDEP_OUTPUT_CONTORL.

[2.5.2]

- Improvements
 - Improved GPIO_PortSet/GPIO_PortClear/GPIO_PortToggle functions to support devices without Set/Clear/Toggle registers.

[2.5.1]

- Bug Fixes
 - Fixed wrong macro definition.
 - Fixed MISRA C-2012 rule issues in the FGPIO_CheckAttributeBytes() function.
 - Defined the new macro to separate the scene when the width of registers is different.
 - Removed some redundant macros.
- New Features
 - Added some APIs to get/clear the interrupt status flag when the port doesn't control pins' interrupt.

[2.4.1]

- Improvements
 - Improved GPIO_CheckAttributeBytes() function to support 8 bits width GACR register.

[2.4.0]

- Improvements
 - API interface added:
 - * New APIs were added to configure the GPIO interrupt clear settings.

[2.3.2]

- Bug Fixes
 - Fixed the issue for MISRA-2012 check.
 - * Fixed rule 3.1, 10.1, 8.6, 10.6, and 10.3.

[2.3.1]

- Improvements
 - Removed deprecated APIs.

[2.3.0]

- New Features
 - Updated the driver code to adapt the case of interrupt configurations in GPIO module. New APIs were added to configure the GPIO interrupt settings if the module has this feature on it.

[2.2.1]

- Improvements
 - API interface changes:
 - * Refined naming of APIs while keeping all original APIs by marking them as deprecated. The original APIs will be removed in next release. The main change is updating APIs with prefix of `_PinXXX()` and `_PortXXX`.

[2.1.1]

- Improvements
 - API interface changes:
 - * Added an API for the check attribute bytes.

[2.1.0]

- Improvements
 - API interface changes:
 - * Added “pins” or “pin” to some APIs’ names.
 - * Renamed “`_PinConfigure`” to “`GPIO_PinInit`”.
-

LPI2C

[2.6.1]

- Bug Fixes
 - Fixed coverity issues.

[2.6.0]

- New Feature
 - Added common IRQ handler entry LPI2C_DriverIRQHandler.

[2.5.7]

- Improvements
 - Added support for separated IRQ handlers.

[2.5.6]

- Improvements
 - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.5.5]

- Bug Fixes
 - Fixed LPI2C_SlaveInit() - allow to disable SDA/SCL glitch filter.

[2.5.4]

- Bug Fixes
 - Fixed LPI2C_MasterTransferBlocking() - the return value was sometime affected by call of LPI2C_MasterStop().

[2.5.3]

- Improvements
 - Added handler for LPI2C7 and LPI2C8.

[2.5.2]

- Bug Fixes
 - Fixed ERR051119 to ignore the nak flag when IGNACK=1 in LPI2C_MasterCheckAndClearError.

[2.5.1]

- Bug Fixes
 - Added bus stop incase of bus stall in LPI2C_MasterTransferBlocking.
- Improvements
 - Release peripheral from reset if necessary in init function.

[2.5.0]

- New Features
 - Added new function LPI2C_SlaveEnableAckStall to enable or disable ACKSTALL.

[2.4.1]

- Improvements
 - Before master transfer with transactional APIs, enable master function while disable slave function and vise versa for slave transfer to avoid the one affecting the other.

[2.4.0]

- Improvements
 - Split some functions, fixed CCM problem in file fsl_lpi2c.c.
- Bug Fixes
 - Fixed bug in LPI2C_MasterInit that the MCFGR2's value set in LPI2C_MasterSetBaudRate may be overwritten by mistake.

[2.3.2]

- Improvements
 - Initialized the EDMA configuration structure in the LPI2C EDMA driver.

[2.3.1]

- Improvements
 - Updated LPI2C_GetCyclesForWidth to add the parameter of minimum cycle, because for master SDA/SCL filter, master bus idle/pin low timeout and slave SDA/SCL filter configuration, 0 means disabling the feature and cannot be used.
- Bug Fixes
 - Fixed bug in LPI2C_SlaveTransferHandleIRQ that when restart detect event happens the transfer structure should not be cleared.
 - Fixed bug in LPI2C_RunTransferStateMachine, that when only slave address is transferred or there is still data remaining in tx FIFO the last byte's nack cannot be ignored.
 - Fixed bug in slave filter doze enable, that when FILTDZ is set it means disable rather than enable.
 - Fixed bug in the usage of LPI2C_GetCyclesForWidth. First its return value cannot be used directly to configure the slave FILTSDA, FILTSCL, DATAVD or CLKHOLD, because the real cycle width for them should be FILTSDA+3, FILTSCL+3, FILTSCL+DATAVD+3 and CLKHOLD+3. Second when cycle period is not affected by the prescaler value, prescaler value should be passed as 0 rather than 1.

- Fixed wrong default setting for LPI2C slave. If enabling the slave tx SCL stall, then the default clock hold time should be set to 250ns according to I2C spec for 100kHz standard mode baudrate.
- Fixed bug that before pushing command to the tx FIFO the FIFO occupation should be checked first in case FIFO overflow.

[2.3.0]

- New Features

- Supported reading more than 256 bytes of data in one transfer as master.
- Added API LPI2C_GetInstance.

- Bug Fixes

- Fixed bug in LPI2C_MasterTransferAbortEDMA, LPI2C_MasterTransferAbort and LPI2C_MasterTransferHandleIRQ that before sending stop signal whether master is active and whether stop signal has been sent should be checked, to make sure no FIFO error or bus error will be caused.
- Fixed bug in LPI2C master EDMA transactional layer that the bus error cannot be caught and returned by user callback, by monitoring bus error events in interrupt handler.
- Fixed bug in LPI2C_GetCyclesForWidth that the parameter used to calculate clock cycle should be $2^{\text{prescaler}}$ rather than prescaler.
- Fixed bug in LPI2C_MasterInit that timeout value should be configured after baudrate, since the timeout calculation needs prescaler as parameter which is changed during baudrate configuration.
- Fixed bug in LPI2C_MasterTransferHandleIRQ and LPI2C_RunTransferStateMachine that when master writes with no stop signal, need to first make sure no data remains in the tx FIFO before finishes the transfer.

[2.2.0]

- Bug Fixes

- Fixed issue that the SCL high time, start hold time and stop setup time do not meet I2C specification, by changing the configuration of data valid delay, setup hold delay, clock high and low parameters.
- MISRA C-2012 issue fixed.
 - * Fixed rule 8.4, 13.5, 17.7, 20.8.

[2.1.12]

- Bug Fixes

- Fixed MISRA advisory 15.5 issues.

[2.1.11]

- Bug Fixes

- Fixed the bug that, during master non-blocking transfer, after the last byte is sent/received, the kLPI2C_MasterNackDetectFlag is expected, so master should not check and clear kLPI2C_MasterNackDetectFlag when remainingBytes is zero, in case FIFO is emptied when stop command has not been sent yet.

- Fixed the bug that, during non-blocking transfer slave may nack master while master is busy filling tx FIFO, and NDF may not be handled properly.

[2.1.10]

- Bug Fixes
 - MISRA C-2012 issue fixed.
 - * Fixed rule 10.3, 14.4, 15.5.
 - Fixed unaligned access issue in LPI2C_RunTransferStateMachine.
 - Fixed uninitialized variable issue in LPI2C_MasterTransferHandleIRQ.
 - Used linked TCD to disable tx and enable rx in read operation to fix the issue that for platform sharing the same DMA request with tx and rx, during LPI2C read operation if interrupt with higher priority happened exactly after command was sent and before tx disabled, potentially both tx and rx could trigger dma and cause trouble.
 - Fixed MISRA issues.
 - * Fixed rules 10.1, 10.3, 10.4, 11.6, 11.9, 14.4, 17.7.
 - Fixed the waitTimes variable not re-assignment issue for each byte read.
- New Features
 - Added the IRQHandler for LPI2C5 and LPI2C6 instances.
- Improvements
 - Updated the LPI2C_WAIT_TIMEOUT macro to unified name I2C_RETRY_TIMES.

[2.1.9]

- Bug Fixes
 - Fixed Coverity issue of unchecked return value in I2C_RTOS_Transfer.
 - Fixed Coverity issue of operands did not affect the result in LPI2C_SlaveReceive and LPI2C_SlaveSend.
 - Removed STOP signal wait when NAK detected.
 - Cleared slave repeat start flag before transmission started in LPI2C_SlaveSend/LPI2C_SlaveReceive. The issue was that LPI2C_SlaveSend/LPI2C_SlaveReceive did not handle with the reserved repeat start flag. This caused the next slave to send a break, and the master was always in the receive data status, but could not receive data.

[2.1.8]

- Bug Fixes
 - Fixed the transfer issue with LPI2C_MasterTransferNonBlocking, kLPI2C_TransferNoStopFlag, with the wait transfer done through callback in a way of not doing a blocking transfer.
 - Fixed the issue that STOP signal did not appear in the bus when NAK event occurred.

[2.1.7]

- Bug Fixes
 - Cleared the stopflag before transmission started in LPI2C_SlaveSend/LPI2C_SlaveReceive. The issue was that LPI2C_SlaveSend/LPI2C_SlaveReceive did not handle with the reserved stop flag and caused the next slave to send a break, and the master always stayed in the receive data status but could not receive data.

[2.1.6]

- Bug Fixes
 - Fixed driver MISRA build error and C++ build error in LPI2C_MasterSend and LPI2C_SlaveSend.
 - Reset FIFO in LPI2C Master Transfer functions to avoid any byte still remaining in FIFO during last transfer.
 - Fixed the issue that LPI2C_MasterStop did not return the correct NAK status in the bus for second transfer to the non-existing slave address.

[2.1.5]

- Bug Fixes
 - Extended the Driver IRQ handler to support LPI2C4.
 - Changed to use ARRAY_SIZE(kLpi2cBases) instead of FEATURE COUNT to decide the array size for handle pointer array.

[2.1.4]

- Bug Fixes
 - Fixed the LPI2C_MasterTransferEDMA receive issue when LPI2C shared same request source with TX/RX DMA request. Previously, the API used scatter-gather method, which handled the command transfer first, then the linked TCD which was pre-set with the receive data transfer. The issue was that the TX DMA request and the RX DMA request were both enabled, so when the DMA finished the first command TCD transfer and handled the receive data TCD, the TX DMA request still happened due to empty TX FIFO. The result was that the RX DMA transfer would start without waiting on the expected RX DMA request.
 - Fixed the issue by enabling IntMajor interrupt for the command TCD and checking if there was a linked TCD to disable the TX DMA request in LPI2C_MasterEDMACallback API.

[2.1.3]

- Improvements
 - Added LPI2C_WATI_TIMEOUT macro to allow the user to specify the timeout times for waiting flags in functional API and blocking transfer API.
 - Added LPI2C_MasterTransferBlocking API.

[2.1.2]

- Bug Fixes
 - In LPI2C_SlaveTransferHandleIRQ, reset the slave status to idle when stop flag was detected.

[2.1.1]

- Bug Fixes
 - Disabled the auto-stop feature in eDMA driver. Previously, the auto-stop feature was enabled at transfer when transferring with stop flag. Since transfer was without stop flag and the auto-stop feature was enabled, when starting a new transfer with stop flag, the stop flag would be sent before the new transfer started, causing unsuccessful sending of the start flag, so the transfer could not start.
 - Changed default slave configuration with address stall false.

[2.1.0]

- Improvements
 - API name changed:
 - * LPI2C_MasterTransferCreateHandle -> LPI2C_MasterCreateHandle.
 - * LPI2C_MasterTransferGetCount -> LPI2C_MasterGetTransferCount.
 - * LPI2C_MasterTransferAbort -> LPI2C_MasterAbortTransfer.
 - * LPI2C_MasterTransferHandleIRQ -> LPI2C_MasterHandleInterrupt.
 - * LPI2C_SlaveTransferCreateHandle -> LPI2C_SlaveCreateHandle.
 - * LPI2C_SlaveTransferGetCount -> LPI2C_SlaveGetTransferCount.
 - * LPI2C_SlaveTransferAbort -> LPI2C_SlaveAbortTransfer.
 - * LPI2C_SlaveTransferHandleIRQ -> LPI2C_SlaveHandleInterrupt.

[2.0.0]

- Initial version.
-

LPI2C_EDMA

[2.4.4]

- Improvements
 - Added support for 2KB data transfer

[2.4.3]

- Improvements
 - Added support for separated IRQ handlers.

[2.4.2]

- Improvements
 - Add EDMA ext API to accommodate more types of EDMA.

[2.4.1]

- Refer LPI2C driver change log 2.0.0 to 2.4.1
-

LPIT

[2.1.2]

- Bug Fixes
 - Fix CERT INT31-C issues.

[2.1.1]

- Improvements
 - Release peripheral from reset if necessary in init function.

[2.1.0]

- Improvements
 - Add new function LPIT_SetTimerValue to set timeout period.

[2.0.2]

- Improvements
 - Improved LPIT_SetTimerPeriod implementation, configure timeout value with LPIT ticks minus 1 generate more correct interval.
 - Added timeout value configuration check for LPIT_SetTimerPeriod, at least input 3 ticks for calling LPIT_SetTimerPeriod.
- Bug Fixes
 - Fixed MISRA C-2012 rule 17.7 violations.

[2.0.1]

- Bug Fixes
 - MISRA C-2012 issue fixed.
 - * Fixed rules, containing: rule-10.3, rule-14.4, rule-15.5.

[2.0.0]

- Initial version.
-

LPSPi

[2.7.2]

- Bug Fixes
 - Fixed coverity issues.

[2.7.1]

- Bug Fixes
 - Workaround for errata ERR050607
 - Workaround for errata ERR010655

[2.7.0]

- New Feature
 - Added common IRQ handler entry LPSPi_DriverIRQHandler.

[2.6.10]

- Improvements
 - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.6.9]

- Bug Fixes
 - Fixed reading of TCR register
 - Workaround for errata ERR050606

[2.6.8]

- Bug Fixes
 - Fixed build error when SPI_RETRY_TIMES is defined to non-zero value.

[2.6.7]

- Bug Fixes
 - Fixed the txData from void * to const void * in transmit API _lpspi_master_handle and _lpspi_slave_handle.

[2.6.6]

- Bug Fixes
 - Added LPSPi register init in LPSPi_MasterInit incase of LPSPi register exist.

[2.6.5]

- Improvements
 - Introduced FSL_FEATURE_LPSP_I_HAS_NO_PCSCFG and FSL_FEATURE_LPSP_I_HAS_NO_MULTI_WIDTH for conditional compile.
 - Release peripheral from reset if necessary in init function.

[2.6.4]

- Bug Fixes
 - Added LPSPI6_DriverIRQHandler for LPSPI6 instance.

[2.6.3]

- Hot Fixes
 - Added macro switch in function LPSPI_Enable about ERRATA051472.

[2.6.2]

- Bug Fixes
 - Disabled lpspi before LPSPI_MasterSetBaudRate incase of LPSPI opened.

[2.6.1]

- Bug Fixes
 - Fixed return value while calling LPSPI_WaitTxFifoEmpty in function LPSPI_MasterTransferNonBlocking.

[2.6.0]

- Feature
 - Added the new feature of multi-IO SPI .

[2.5.3]

- Bug Fixes
 - Fixed 3-wire txmask of handle vaule reentrant issue.

[2.5.2]

- Bug Fixes
 - Workaround for errata ERR051588 by clearing FIFO after transmit underrun occurs.

[2.5.1]

- Bug Fixes
 - Workaround for errata ERR050456 by resetting the entire module using LPSPIIn_CR[RST] bit.

[2.5.0]

- Bug Fixes
 - Workaround for errata ERR011097 to wait the TX FIFO to go empty when writing TCR register and TCR[TXMSK] value is 1.
 - Added API LPSPI_WaitTxFifoEmpty for wait the txfifo to go empty.

[2.4.7]

- Bug Fixes
 - Fixed bug that the SR[REF] would assert if software disabled or enabled the LPSPI module in LPSPI_Enable.

[2.4.6]

- Improvements
 - Moved the configuration of registers for the 3-wire lpspi mode to the LPSPI_MasterInit and LPSPI_SlaveInit function.

[2.4.5]

- Improvements
 - Improved LPSPI_MasterTransferBlocking send performance when frame size is 1-byte.

[2.4.4]

- Bug Fixes
 - Fixed LPSPI_MasterGetDefaultConfig incorrect default inter-transfer delay calculation.

[2.4.3]

- Bug Fixes
 - Fixed bug that the ISR response speed is too slow on some platforms, resulting in the first transmission of overflow, Set proper RX watermarks to reduce the ISR response times.

[2.4.2]

- Bug Fixes
 - Fixed bug that LPSPI_MasterTransferBlocking will modify the parameter txbuff and rxbuff pointer.

[2.4.1]

- Bug Fixes
 - Fixed bug that LPSPI_SlaveTransferNonBlocking can't detect RX error.

[2.4.0]

- Improvements
 - Split some functions, fixed CCM problem in file fsl_lpspi.c.

[2.3.1]

- Improvements
 - Initialized the EDMA configuration structure in the LPSPI EDMA driver.
- Bug Fixes
 - Fixed bug that function LPSPI_MasterTransferBlocking should return after the transfer complete flag is set to make sure the PCS is re-asserted.

[2.3.0]

- New Features
 - Supported the master configuration of sampling the input data using a delayed clock to improve slave setup time.

[2.2.1]

- Bug Fixes
 - Fixed bug in LPSPI_SetPCSContinuous when disabling PCS continuous mode.

[2.2.0]

- Bug Fixes
 - Fixed bug in 3-wire polling and interrupt transfer that the received data is not correct and the PCS continuous mode is not working.

[2.1.0]

- Improvements
 - Improved LPSPI_SlaveTransferHandleIRQ to fill up TX FIFO instead of write one data to TX register which improves the slave transmit performance.
 - Added new functional APIs LPSPI_SelectTransferPCS and LPSPI_SetPCSContinuous to support changing PCS selection and PCS continuous mode.
- Bug Fixes
 - Fixed bug in non-blocking and EDMA transfer APIs that kStatus_InvalidArgument is returned if user configures 3-wire mode and full-duplex transfer at the same time, but transfer state is already set to kLPSPI_Busy by mistake causing following transfer can not start.
 - Fixed bug when LPSPI slave using EDMA way to transfer, tx should be masked when tx data is null, otherwise in 3-wire mode which tx/rx use the same pin, the received data will be interfered.

[2.0.5]

- Improvements
 - Added timeout mechanism when waiting certain states in transfer driver.
- Bug Fixes
 - Fixed the bug that LPSPI can not transfer large data using EDMA.
 - Fixed MISRA 17.7 issues.
 - Fixed variable overflow issue introduced by MISRA fix.
 - Fixed issue that rxFifoMaxBytes should be calculated according to transfer width rather than FIFO width.
 - Fixed issue that completion flag was not cleared after transfer completed.

[2.0.4]

- Bug Fixes
 - Fixed in LPSPI_MasterTransferBlocking that master rxfifo may overflow in stall condition.
 - Eliminated IAR Pa082 warnings.
 - Fixed MISRA issues.
 - * Fixed rules 10.1, 10.3, 10.4, 10.6, 11.9, 14.2, 14.4, 15.7, 17.7.

[2.0.3]

- Bug Fixes
 - Removed LPSPI_Reset from LPSPI_MasterInit and LPSPI_SlaveInit, because this API may glitch the slave select line. If needed, call this function manually.

[2.0.2]

- New Features
 - Added dummy data set up API to allow users to configure the dummy data to be transferred.
 - Enabled the 3-wire mode, SIN and SOUT pins can be configured as input/output pin.

[2.0.1]

- Bug Fixes
 - Fixed the bug that the clock source should be divided by the PRESCALE setting in LPSPI_MasterSetDelayTimes function.
 - Fixed the bug that LPSPI_MasterTransferBlocking function would hang in some corner cases.
- Optimization
 - Added #ifndef/#endif to allow user to change the default TX value at compile time.

[2.0.0]

- Initial version.
-

LPSPi_EDMA

[2.4.7]

- Bug Fixes
 - Add macro LPSPi_ALIGN_TCD_SIZE_MASK to align an address to edma_tcd_t size.

[2.4.6]

- Improvements
 - Increased transmit FIFO watermark to ensure whole transmit FIFO will be used during data transfer.

[2.4.5]

- Bug Fixes
 - Fixed reading of TCR register
 - Workaround for errata ERR050606

[2.4.4]

- Improvements
 - Add EDMA ext API to accommodate more types of EDMA.

[2.4.3]

- Improvements
 - Supported 32K bytes transmit in DMA, improve the max datasize in LPSPi_MasterTransferEDMALite.

[2.4.2]

- Improvements
 - Added callback status in EDMA_LpspiMasterCallback and EDMA_LpspiSlaveCallback to check transferDone.

[2.4.1]

- Improvements
 - Add the TXMSK wait after TCR setting.

[2.4.0]

- Improvements
 - Separated LPSPI_MasterTransferEDMA functions to LPSPI_MasterTransferPrepareEDMA and LPSPI_MasterTransferEDMALite to optimize the process of transfer.
-

LPTMR**[2.2.1]**

- Bug Fixes
 - Fix CERT INT31-C issues.

[2.2.0]

- Improvements
 - Updated lptmr_prescaler_clock_select_t, only define the valid options.

[2.1.1]

- Improvements
 - Updated the characters from “PTMR” to “LPTMR” in “FSL_FEATURE_PTMR_HAS_NO_PRESCALER_CLOCK_SOURCE_1_SUPPORT” feature definition.

[2.1.0]

- Improvements
 - Implement for some special devices’ not supporting for all clock sources.
- Bug Fixes
 - Fixed issue when accessing CMR register.

[2.0.2]

- Bug Fixes
 - Fixed MISRA-2012 issues.
 - * Rule 10.1.

[2.0.1]

- Improvements
 - Updated the LPTMR driver to support 32-bit CNR and CMR registers in some devices.

[2.0.0]

- Initial version.
-

LPUART

[2.9.2]

- Bug Fixes
 - Fixed coverity issues.

[2.9.1]

- Bug Fixes
 - Fixed coverity issues.

[2.9.0]

- New Feature
 - Added support for swap TXD and RXD pins.
 - Added common IRQ handler entry LPUART_DriverIRQHandler.

[2.8.3]

- Improvements
 - Conditionally compile interrupt handling code to solve the problem of using this driver on CPU cores that do not support interrupts.

[2.8.2]

- Bug Fix
 - Fixed the bug that LPUART_TransferEnable16Bit controled by wrong feature macro.

[2.8.1]

- Bug Fixes
 - Fixed issue for MISRA-2012 check.
 - * Fixed rule-5.3, rule-5.8, rule-10.4, rule-11.3, rule-11.8.

[2.8.0]

- Improvements
 - Added support of DATA register for 9bit or 10bit data transmit in write and read API. Such as: LPUART_WriteBlocking16bit, LPUART_ReadBlocking16bit, LPUART_TransferEnable16Bit, LPUART_WriteNonBlocking16bit, LPUART_ReadNonBlocking16bit.

[2.7.7]

- Bug Fixes
 - Fixed the bug that baud rate calculation overflow when srcClock_Hz is 528MHz.

[2.7.6]

- Bug Fixes
 - Fixed LPUART_EnableInterrupts and LPUART_DisableInterrupts bug that blocks if the LPUART address doesn't support exclusive access.

[2.7.5]

- Improvements
 - Release peripheral from reset if necessary in init function.

[2.7.4]

- Improvements
 - Added support for atomic register accessing in LPUART_EnableInterrupts and LPUART_DisableInterrupts.

[2.7.3]

- Bug Fixes
 - Fixed violations of the MISRA C-2012 rules 15.7.

[2.7.2]

- Bug Fix
 - Fixed the bug that the OSR calculation error when lpuart init and lpuart set baud rate.

[2.7.1]

- Improvements
 - Added support for LPUART_BASE_PTRS_NS in security mode in file fsl_lpuart.c.

[2.7.0]

- Improvements
 - Split some functions, fixed CCM problem in file fsl_lpuart.c.

[2.6.0]

- Bug Fixes
 - Fixed bug that when there are multiple lpuart instance, unable to support different ISR.

[2.5.3]

- Bug Fixes
 - Fixed comments by replacing unused status flags kLPUART_NoiseErrorInRxDataRegFlag and kLPUART_ParityErrorInRxDataRegFlag with kLPUART_NoiseErrorFlag and kLPUART_ParityErrorFlag.

[2.5.2]

- Bug Fixes
 - Fixed bug that when setting watermark for TX or RX FIFO, the value may exceed the maximum limit.
- Improvements
 - Added check in LPUART_TransferDMAHandleIRQ and LPUART_TransferEdmaHandleIRQ to ensure if user enables any interrupts other than transfer complete interrupt, the dma transfer is not terminated by mistake.

[2.5.1]

- Improvements
 - Use separate data for TX and RX in lpuart_transfer_t.
- Bug Fixes
 - Fixed bug that when ring buffer is used, if some data is received in ring buffer first before calling LPUART_TransferReceiveNonBlocking, the received data count returned by LPUART_TransferGetReceiveCount is wrong.

[2.5.0]

- Bug Fixes
 - Added missing interrupt enable masks kLPUART_Match1InterruptEnable and kLPUART_Match2InterruptEnable.
 - Fixed bug in LPUART_EnableInterrupts, LPUART_DisableInterrupts and LPUART_GetEnabledInterrupts that the BAUD[LBKDIE] bit field should be soc specific.
 - Fixed bug in LPUART_TransferHandleIRQ that idle line interrupt should be disabled when rx data size is zero.
 - Deleted unused status flags kLPUART_NoiseErrorInRxDataRegFlag and kLPUART_ParityErrorInRxDataRegFlag, since firstly their function are the same as kLPUART_NoiseErrorFlag and kLPUART_ParityErrorFlag, secondly to obtain them one data word must be read out thus interfering with the receiving process.
 - Fixed bug in LPUART_GetStatusFlags that the STAT[LBKDIF], STAT[MA1F] and STAT[MA2F] should be soc specific.
 - Fixed bug in LPUART_ClearStatusFlags that tx/rx FIFO is reset by mistake when clearing flags.
 - Fixed bug in LPUART_TransferHandleIRQ that while clearing idle line flag the other bits should be masked in case other status bits be cleared by accident.
 - Fixed bug of race condition during LPUART transfer using transactional APIs, by disabling and re-enabling the global interrupt before and after critical operations on interrupt enable register.
 - Fixed DMA/eDMA transfer blocking issue by enabling tx idle interrupt after DMA/eDMA transmission finishes.
- New Features
 - Added APIs LPUART_GetRxFifoCount/LPUART_GetTxFifoCount to get rx/tx FIFO data count.
 - Added APIs LPUART_SetRxFifoWatermark/LPUART_SetTxFifoWatermark to set rx/tx FIFO water mark.

[2.4.1]

- Bug Fixes
 - Fixed MISRA advisory 17.7 issues.

[2.4.0]

- New Features
 - Added APIs to configure 9-bit data mode, set slave address and send address.

[2.3.1]

- Bug Fixes
 - Fixed MISRA advisory 15.5 issues.

[2.3.0]

- Improvements
 - Modified LPUART_TransferHandleIRQ so that txState will be set to idle only when all data has been sent out to bus.
 - Modified LPUART_TransferGetSendCount so that this API returns the real byte count that LPUART has sent out rather than the software buffer status.
 - Added timeout mechanism when waiting for certain states in transfer driver.

[2.2.8]

- Bug Fixes
 - Fixed issue for MISRA-2012 check.
 - * Fixed rule-10.3, rule-14.4, rule-15.5.
 - Eliminated Pa082 warnings by assigning volatile variables to local variables and using local variables instead.
 - Fixed MISRA issues.
 - * Fixed rules 10.1, 10.3, 10.4, 10.8, 14.4, 11.6, 17.7.
- Improvements
 - Added check for kLPUART_TransmissionCompleteFlag in LPUART_WriteBlocking, LPUART_TransferHandleIRQ, LPUART_TransferSendDMACallback and LPUART_SendEDMACallback to ensure all the data would be sent out to bus.
 - Rounded up the calculated sbr value in LPUART_SetBaudRate and LPUART_Init to achieve more accurate baudrate setting. Changed osr from uint32_t to uint8_t since osr's biggest value is 31.
 - Modified LPUART_ReadBlocking so that if more than one receiver errors occur, all status flags will be cleared and the most severe error status will be returned.

[2.2.7]

- Bug Fixes
 - Fixed issue for MISRA-2012 check.
 - * Fixed rule-12.1, rule-17.7, rule-14.4, rule-13.3, rule-14.4, rule-10.4, rule-10.8, rule-10.3, rule-10.7, rule-10.1, rule-11.6, rule-13.5, rule-11.3, rule-13.2, rule-8.3.

[2.2.6]

- Bug Fixes
 - Fixed the issue of register's being in repeated reading status while dealing with the IRQ routine.

[2.2.5]

- Bug Fixes
 - Do not set or clear the TIE/RIE bits when using LPUART_EnableTxDMA and LPUART_EnableRxDMA.

[2.2.4]

- Improvements
 - Added hardware flow control function support.
 - Added idle-line-detecting feature in LPUART_TransferNonBlocking function. If an idle line is detected, a callback is triggered with status kStatus_LPUART_IdleLineDetected returned. This feature may be useful when the received Bytes is less than the expected received data size. Before triggering the callback, data in the FIFO (if has FIFO) is read out, and no interrupt will be disabled, except for that the receive data size reaches 0.
 - Enabled the RX FIFO watermark function. With the idle-line-detecting feature enabled, users can set the watermark value to whatever you want (should be less than the RX FIFO size). Data is received and a callback will be triggered when data receive ends.

[2.2.3]

- Improvements
 - Changed parameter type in LPUART_RTOS_Init struct from rtos_lpuart_config to lpuart_rtos_config_t.
- Bug Fixes
 - Disabled LPUART receive interrupt instead of all NVICs when reading data from ring buffer. Otherwise when the ring buffer is used, receive nonblocking method will disable all NVICs to protect the ring buffer. This may has a negative effect on other IPs that are using the interrupt.

[2.2.2]

- Improvements
 - Added software reset feature support.
 - Added software reset API in LPUART_Init.

[2.2.1]

- Improvements
 - Added separate RX/TX IRQ number support.

[2.2.0]

- Improvements
 - Added support of 7 data bits and MSB.

[2.1.1]

- Improvements
 - Removed unnecessary check of event flags and assert in LPUART_RTOS_Receive.
 - Added code to always wait for RX event flag in LPUART_RTOS_Receive.

[2.1.0]

- Improvements
 - Update transactional APIs.
-

LPUART_EDMA

[2.4.0]

- Refer LPUART driver change log 2.1.0 to 2.4.0
-

MCM

[2.2.0]

- Improvements
 - Support platforms with less features.

[2.1.0]

- Others
 - Remove byteID from mcm_lmem_fault_attribute_t for document update.

[2.0.0]

- Initial version.
-

MMDVSQ

[2.0.4]

- Improvements
 - Fixed CERT-C issues.

[2.0.3]

- Bug Fixes
 - MISRA C-2012 issue fixed: rule 10.3, 10.4, and 14.4.

[2.0.2]

- Bug fix:
 - Fixed MMDVSQ_GetExecutionStatus function get execution status wrong.

[2.0.1]

- Other changes:
 - Changed name of MMDVSQ_GetDivideRemainder and MMDVSQ_GetDivideQuotient functions.

[2.0.0]

- Initial version.
-

PDB

[2.0.4]

- Bug Fixes
 - Fixed violations of MISRA C-2012 rule 10.1 and 10.4.

[2.0.3]

- Bug Fixes
 - Fixed violations of MISRA C-2012 rule 17.7.

[2.0.2]

- Improvement:
 - Used macros in feature file instead of that in IO map.

[2.0.1]

- Changed PDB register base array to const.

[2.0.0]

- Initial version.
-

PMC**[2.0.3]**

- Bug Fixes
 - Fixed the violation of MISRA C-2012 rule 11.3.

[2.0.2]

- Bug Fixes
 - Fixed the violations of MISRA 2012 rules:
 - * Rule 10.3.

[2.0.1]

- Bug Fixes
 - Fixed MISRA issues.
 - * Rule 10.8, Rule 10.3.

[2.0.0]

- Initial version.
-

PORT**[2.5.1]**

- Bug Fixes
 - Fix CERT INT31-C issues.

[2.5.0]

- Bug Fixes
 - Correct the kPORT_MuxAsGpio for some platforms.

[2.4.1]

- Bug Fixes
 - Fixed the violations of MISRA C-2012 rules: 10.1, 10.8 and 14.4.

[2.4.0]

- New Features
 - Updated port_pin_config_t to support input buffer and input invert.

[2.3.0]

- New Features
 - Added new APIs for Electrical Fast Transient(EFT) detect.
 - Added new API to configure port voltage range.

[2.2.0]

- New Features
 - Added new api PORT_EnablePinDoubleDriveStrength.

[2.1.1]

- Bug Fixes
 - Fixed the violations of MISRA C-2012 rules: 10.1, 10.4□11.3□11.8, 14.4.

[2.1.0]

- New Features
 - Updated the driver code to adapt the case of the interrupt configurations in GPIO module. Will move the pin configuration APIs to GPIO module.

[2.0.2]

- Other Changes
 - Added feature guard macros in the driver.

[2.0.1]

- Other Changes
 - Added “const” in function parameter.
 - Updated some enumeration variables’ names.
-

PWT

[2.0.2]

- Bug Fixes
 - Fixed CERT INT31-C violations.

[2.0.1]

- Bug Fixes
 - Fixed violations of MISRA C-2012 rules: 10.8, 10.3, 10.6.

[2.0.0]

- Initial version.
-

RCM**[2.0.4]**

- Bug Fixes
 - Fixed violation of MISRA C-2012 rule 10.3

[2.0.3]

- Bug Fixes
 - Fixed violation of MISRA C-2012 rules.

[2.0.2]

- Bug Fixes
 - Fixed MISRA issue.
 - * Rule 10.8, rule 10.1, rule 13.2, rule 3.1.

[2.0.1]

- Bug Fixes
 - Fixed kRCM_SourceSw bit shift issue.

[2.0.0]

- Initial version.
-

RTC**[2.3.3]**

- Bug Fixes
 - Fix RTC_GetDatetime function validating datetime issue.

[2.3.2]

- Improvements
 - Handle errata 010716: Disable the counter before setting alarm register and then reen-able the counter.

[2.3.1]

- Bug Fixes
 - Fixed CERT INT31-C violations.

[2.3.0]

- Improvements
 - Added API `RTC_EnableLPOClock` to set 1kHz LPO clock.
 - Added API `RTC_EnableCrystalClock` to replace API `RTC_SetClockSource`.

[2.2.2]

- Improvements
 - Refine `_rtc_interrupt_enable` order.

[2.2.1]

- Bug Fixes
 - Fixed the issue of Pa082 warning.
 - Fixed the issue of bit field mask checking.
 - Fixed the issue of hard code in `RTC_Init`.

[2.2.0]

- Bug Fixes
 - Fixed MISRA C-2012 issue.
 - * Fixed rule contain: rule-17.7, rule-14.4, rule-10.4, rule-10.7, rule-10.1, rule-10.3.
 - Fixed central repository code formatting issue.
- Improvements
 - Added an API for enabling wakeup pin.

[2.1.0]

- Improvements
 - Added feature macro check for many features.

[2.0.0]

- Initial version.
-

SIM

[2.2.0]

- Improvements
 - Added API to trigger TRGMUX.

[2.1.3]

- Improvements
 - Updated function `SIM_GetUniqueId` to support different register names.

[2.1.2]

- Bug Fixes
 - Fixed SIM_GetUniqueId bug that could not get UIDH.

[2.1.1]

- Bug Fixes
 - Fixed violations of the MISRA C-2012 rules 10.1, 10.4

[2.1.0]

- Improvements
 - Added new APIs: SIM_GetRfAddr() and SIM_EnableSystickClock().

[2.0.0]

- Initial version.
-

SMC**[2.0.7]**

- Bug Fixes
 - Fixed MISRA-2012 issue 10.3.

[2.0.6]

- Bug Fixes
 - Fixed issue for MISRA-2012 check.
 - * Fixed rule 10.3, rule 11.3.

[2.0.5]

- Bug Fixes
 - Fixed issue for MISRA-2012 check.
 - * Fixed rule 15.7, rule 14.4, rule 10.3, rule 10.1, rule 10.4.

[2.0.4]

- Bug Fixes
 - When entering stop modes, used RAM function for the flash synchronization issue. Application should make sure that, the RW data of fsl_smc.c is located in memory region which is not powered off in stop modes.

[2.0.3]

- Improvements
 - Added APIs SMC_PreEnterStopModes, SMC_PreEnterWaitModes, SMC_PostExitWaitModes, and SMC_PostExitStopModes.

[2.0.2]

- Bug Fixes
 - Added DSB before WFI while ISB after WFI.
- Other Changes
 - Updated SMC_SetPowerModeVlpw implementation.

[2.0.1]

- Other Changes
 - Updated for KL8x.

[2.0.0]

- Initial version.
-

TRGMUX

[2.0.1]

- Bug Fixes
 - Fixed violations of the MISRA C-2012 rules 10.1, 10.3, 10.8.

[2.0.0]

- Initial version.
-

TSI_V5

[2.6.1]

- Improvements
 - The SHIELD register write was fixed to be rewritten.

[2.6.0]

- Improvements
 - Add API TSI_ShieldChannelConfig to config all TSI shield channels.

[2.5.0]

- Improvements
 - Add API TSI_EnableShieldChannels to enable/disable TSI shield channels.

[2.4.0]

- Bug Fixes
 - Fixed some elements in the array tsi_sensitivity_xdn_option_t does not match the S_XDN bits.

[2.3.0]

- Other Changes
 - Changed the TSI SINC cutoff divider number.

[2.2.0]

- Improvements
 - Extended enableShield items from tsi_selfCap_config_t structure to cover three shields in the ke17z series.
 - Added interface for getting instance from TSI base address and apply it for clock and IRQ enable/disable.

[2.1.2]

- Bug Fixes
 - Fixed the violations of MISRA C-2012 rules: 10.1, 10.8.

[2.1.1]

- Improvements
 - Improved the module's noise immunity in mutual cap mode by setting M_TRIM2[0] to 1 in TSI_MUL1 register.
- Bug Fixes
 - Fixed the violations of MISRA C-2012 rules:
 - * Rule 10.1, 10.3, 10.4, 10.8, 12.2, 14.4, 17.7.

[2.1.0]

- Bug Fixes
 - Fixed incorrect TSI SSC clock calculation.

[2.0.1]

- Improvements
 - Added functions for M_TX_USED bitfield for ke16z only (Unused TX mutual pins can work as GPIO).

[2.0.0]

- Initial version.
-

WDOG32

[2.2.1]

- Bug Fixes
 - Fix CERT INT31-C that the bool value shall be converted to unsigned int 0 or 1 then passed to registers.

[2.2.0]

- Improvements
 - Added while loop timeout config value for WDOG32 reconfiguration and unlock sequence.
 - Change the return type of WDOG32_Init, WDOG32_Deinit and WDOG32_Unlock from void to status_t.

[2.1.0]

- Improvements
 - Release peripheral from reset if necessary in init function.

[2.0.4]

- Improvements
 - To ensure that the reconfiguration is inside 128 bus clocks unlock window, put all reconfiguration APIs in quick access code section.

[2.0.3]

- Bug Fixes
 - Fixed the noncompliance issue of the reference document.
 - * Waited until for new configuration to take effect by checking the RCS bit field.
 - * Waited until for registers to be unlocked by checking the ULK bit field.
- Improvements
 - Added 128 bus clocks delay ensures a smooth transition before restarting the counter with the new configuration when there is no RCS status bit.

[2.0.2]

- Bug Fixes
 - MISRA C-2012 issue fixed.
 - * Fixed rules, containing: rule-10.3, rule-14.4, rule-15.5.
 - Fixed the issue of the inseparable process interrupted by other interrupt source.
 - * WDOG32_Refresh

[2.0.1]

- Bug Fixes
 - WDOG must be configured within its configuration time period.
 - * Added WDOG32_Init API to quick access section.
 - * Defined register variable in WDOG32_Init API.

[2.0.0]

- Initial version.
-

1.6 Driver API Reference Manual

This section provides a link to the Driver API RM, detailing available drivers and their usage to help you integrate hardware efficiently.

[MKE15Z7](#)

1.7 Middleware Documentation

Find links to detailed middleware documentation for key components. While not all onboard middleware is covered, this serves as a useful reference for configuration and development.

1.7.1 FreeMASTER

[freemaster](#)

1.7.2 FreeRTOS

[FreeRTOS](#)

1.7.3 File systemFatfs

[FatFs](#)

Chapter 2

MKE15Z7

2.1 ACMP: Analog Comparator Driver

`void ACMP_Init(CMP_Type *base, const acmp_config_t *config)`

Initializes the ACMP.

The default configuration can be got by calling `ACMP_GetDefaultConfig()`.

Parameters

- `base` – ACMP peripheral base address.
- `config` – Pointer to ACMP configuration structure.

`void ACMP_Deinit(CMP_Type *base)`

Deinitializes the ACMP.

Parameters

- `base` – ACMP peripheral base address.

`void ACMP_GetDefaultConfig(acmp_config_t *config)`

Gets the default configuration for ACMP.

This function initializes the user configuration structure to default value. The default value are:

Example:

```
config->enableHighSpeed = false;
config->enableInvertOutput = false;
config->useUnfilteredOutput = false;
config->enablePinOut = false;
config->enableHysteresisBothDirections = false;
config->hysteresisMode = kACMP_hysteresisMode0;
```

Parameters

- `config` – Pointer to ACMP configuration structure.

`void ACMP_Enable(CMP_Type *base, bool enable)`

Enables or disables the ACMP.

Parameters

- `base` – ACMP peripheral base address.
- `enable` – True to enable the ACMP.

void ACMP_EnableLinkToDAC(CMP_Type *base, bool enable)

Enables the link from CMP to DAC enable.

When this bit is set, the DAC enable/disable is controlled by the bit CMP_C0[EN] instead of CMP_C1[DACEN].

Parameters

- base – ACMP peripheral base address.
- enable – Enable the feature or not.

void ACMP_SetChannelConfig(CMP_Type *base, const *acmp_channel_config_t* *config)

Sets the channel configuration.

Note that the plus/minus mux's setting is only valid when the positive/negative port's input isn't from DAC but from channel mux.

Example:

```
acmp_channel_config_t configStruct = {0};
configStruct.positivePortInput = kACMP_PortInputFromDAC;
configStruct.negativePortInput = kACMP_PortInputFromMux;
configStruct.minusMuxInput = 1U;
ACMP_SetChannelConfig(CMP0, &configStruct);
```

Parameters

- base – ACMP peripheral base address.
- config – Pointer to channel configuration structure.

void ACMP_EnableDMA(CMP_Type *base, bool enable)

Enables or disables DMA.

Parameters

- base – ACMP peripheral base address.
- enable – True to enable DMA.

void ACMP_EnableWindowMode(CMP_Type *base, bool enable)

Enables or disables window mode.

Parameters

- base – ACMP peripheral base address.
- enable – True to enable window mode.

void ACMP_SetFilterConfig(CMP_Type *base, const *acmp_filter_config_t* *config)

Configures the filter.

The filter can be enabled when the filter count is bigger than 1, the filter period is greater than 0 and the sample clock is from divided bus clock or the filter is bigger than 1 and the sample clock is from external clock. Detailed usage can be got from the reference manual.

Example:

```
acmp_filter_config_t configStruct = {0};
configStruct.filterCount = 5U;
configStruct.filterPeriod = 200U;
configStruct.enableSample = false;
ACMP_SetFilterConfig(CMP0, &configStruct);
```

Parameters

- base – ACMP peripheral base address.

- config – Pointer to filter configuration structure.

void ACMP_SetDACConfig(CMP_Type *base, const *acmp_dac_config_t* *config)

Configures the internal DAC.

Example:

```
acmp_dac_config_t configStruct = {0};
configStruct.referenceVoltageSource = kACMP_VrefSourceVin1;
configStruct.DACValue = 20U;
configStruct.enableOutput = false;
configStruct.workMode = kACMP_DACWorkLowSpeedMode;
ACMP_SetDACConfig(CMP0, &configStruct);
```

Parameters

- base – ACMP peripheral base address.
- config – Pointer to DAC configuration structure. “NULL” is for disabling the feature.

void ACMP_SetRoundRobinConfig(CMP_Type *base, const *acmp_round_robin_config_t* *config)

Configures the round robin mode.

Example:

```
acmp_round_robin_config_t configStruct = {0};
configStruct.fixedPort = kACMP_FixedPlusPort;
configStruct.fixedChannelNumber = 3U;
configStruct.checkerChannelMask = 0xF7U;
configStruct.sampleClockCount = 0U;
configStruct.delayModulus = 0U;
ACMP_SetRoundRobinConfig(CMP0, &configStruct);
```

Parameters

- base – ACMP peripheral base address.
- config – Pointer to round robin mode configuration structure. “NULL” is for disabling the feature.

void ACMP_SetRoundRobinPreState(CMP_Type *base, uint32_t mask)

Defines the pre-set state of channels in round robin mode.

Note: The pre-state has different circuit with get-round-robin-result in the SOC even though they are same bits. So get-round-robin-result can't return the same value as the value are set by pre-state.

Parameters

- base – ACMP peripheral base address.
- mask – Mask of round robin channel index. Available range is channel0:0x01 to channel7:0x80.

static inline uint32_t ACMP_GetRoundRobinStatusFlags(CMP_Type *base)

Gets the channel input changed flags in round robin mode.

Parameters

- base – ACMP peripheral base address.

Returns

Mask of channel input changed asserted flags. Available range is channel0:0x01 to channel7:0x80.

`void ACMP_ClearRoundRobinStatusFlags(CMP_Type *base, uint32_t mask)`

Clears the channel input changed flags in round robin mode.

Parameters

- `base` – ACMP peripheral base address.
- `mask` – Mask of channel index. Available range is channel0:0x01 to channel7:0x80.

`static inline uint32_t ACMP_GetRoundRobinResult(CMP_Type *base)`

Gets the round robin result.

Note that the set-pre-state has different circuit with get-round-robin-result in the SOC even though they are same bits. So `ACMP_GetRoundRobinResult()` can't return the same value as the value are set by `ACMP_SetRoundRobinPreState`.

Parameters

- `base` – ACMP peripheral base address.

Returns

Mask of round robin channel result. Available range is channel0:0x01 to channel7:0x80.

`void ACMP_EnableInterrupts(CMP_Type *base, uint32_t mask)`

Enables interrupts.

Parameters

- `base` – ACMP peripheral base address.
- `mask` – Interrupts mask. See “`_acmp_interrupt_enable`”.

`void ACMP_DisableInterrupts(CMP_Type *base, uint32_t mask)`

Disables interrupts.

Parameters

- `base` – ACMP peripheral base address.
- `mask` – Interrupts mask. See “`_acmp_interrupt_enable`”.

`uint32_t ACMP_GetStatusFlags(CMP_Type *base)`

Gets status flags.

Parameters

- `base` – ACMP peripheral base address.

Returns

Status flags asserted mask. See “`_acmp_status_flags`”.

`void ACMP_ClearStatusFlags(CMP_Type *base, uint32_t mask)`

Clears status flags.

Parameters

- `base` – ACMP peripheral base address.
- `mask` – Status flags mask. See “`_acmp_status_flags`”.

`void ACMP_SetDiscreteModeConfig(CMP_Type *base, const acmp_discrete_mode_config_t *config)`

Configure the discrete mode.

Configure the discrete mode when supporting 3V domain with 1.8V core.

Parameters

- base – ACMP peripheral base address.
- config – Pointer to configuration structure. See “acmp_discrete_mode_config_t”.

void ACMP_GetDefaultDiscreteModeConfig(*acmp_discrete_mode_config_t* *config)

Get the default configuration for discrete mode setting.

Parameters

- config – Pointer to configuration structure to be restored with the setting values.

FSL_ACMP_DRIVER_VERSION

ACMP driver version 2.3.0.

enum _acmp_interrupt_enable

Interrupt enable/disable mask.

Values:

enumerator kACMP_OutputRisingInterruptEnable

Enable the interrupt when comparator outputs rising.

enumerator kACMP_OutputFallingInterruptEnable

Enable the interrupt when comparator outputs falling.

enumerator kACMP_RoundRobinInterruptEnable

Enable the Round-Robin interrupt.

enum _acmp_status_flags

Status flag mask.

Values:

enumerator kACMP_OutputRisingEventFlag

Rising-edge on compare output has occurred.

enumerator kACMP_OutputFallingEventFlag

Falling-edge on compare output has occurred.

enumerator kACMP_OutputAssertEventFlag

Return the current value of the analog comparator output.

enum _acmp_offset_mode

Comparator hard block offset control.

If OFFSET level is 1, then there is no hysteresis in the case of positive port input crossing negative port input in the positive direction (or negative port input crossing positive port input in the negative direction). Hysteresis still exists for positive port input crossing negative port input in the falling direction. If OFFSET level is 0, then the hysteresis selected by *acmp_hysteresis_mode_t* is valid for both directions.

Values:

enumerator kACMP_OffsetLevel0

The comparator hard block output has level 0 offset internally.

enumerator kACMP_OffsetLevel1

The comparator hard block output has level 1 offset internally.

enum _acmp_hysteresis_mode

Comparator hard block hysteresis control.

See chip data sheet to get the actual hysteresis value with each level.

Values:

enumerator kACMP_HysteresisLevel0

Offset is level 0 and Hysteresis is level 0.

enumerator kACMP_HysteresisLevel1

Offset is level 0 and Hysteresis is level 1.

enumerator kACMP_HysteresisLevel2

Offset is level 0 and Hysteresis is level 2.

enumerator kACMP_HysteresisLevel3

Offset is level 0 and Hysteresis is level 3.

enum _acmp_reference_voltage_source

CMP Voltage Reference source.

Values:

enumerator kACMP_VrefSourceVin1

Vin1 is selected as resistor ladder network supply reference Vin.

enumerator kACMP_VrefSourceVin2

Vin2 is selected as resistor ladder network supply reference Vin.

enum _acmp_port_input

Port input source.

Values:

enumerator kACMP_PortInputFromDAC

Port input from the 8-bit DAC output.

enumerator kACMP_PortInputFromMux

Port input from the analog 8-1 mux.

enum _acmp_fixed_port

Fixed mux port.

Values:

enumerator kACMP_FixedPlusPort

Only the inputs to the Minus port are swept in each round.

enumerator kACMP_FixedMinusPort

Only the inputs to the Plus port are swept in each round.

enum _acmp_dac_work_mode

Internal DAC's work mode.

Values:

enumerator kACMP_DACWorkLowSpeedMode

DAC is selected to work in low speed and low power mode.

enumerator kACMP_DACWorkHighSpeedMode

DAC is selected to work in high speed high power mode.

enum _acmp_discrete_clock_source

Discrete mode clock selection.

Values:

enumerator kACMP_DiscreteClockSlow

Slow clock (32kHz) is used as the discrete mode clock.

enumerator kACMP_DiscreteClockFast

Fast clock (16-20MHz) is used as the discrete mode clock.

enum _acmp_discrete_sample_time

ACMP discrete sample selection. These values configures the analog comparator sampling timing (specified by the discrete mode clock period T which is selected by acmp_discrete_clock_source_t) in discrete mode.

Values:

enumerator kACMP_DiscreteSampleTimeAs1T

The sampling time equals to 1xT.

enumerator kACMP_DiscreteSampleTimeAs2T

The sampling time equals to 2xT.

enumerator kACMP_DiscreteSampleTimeAs4T

The sampling time equals to 4xT.

enumerator kACMP_DiscreteSampleTimeAs8T

The sampling time equals to 8xT.

enumerator kACMP_DiscreteSampleTimeAs16T

The sampling time equals to 16xT.

enumerator kACMP_DiscreteSampleTimeAs32T

The sampling time equals to 32xT.

enumerator kACMP_DiscreteSampleTimeAs64T

The sampling time equals to 64xT.

enumerator kACMP_DiscreteSampleTimeAs256T

The sampling time equals to 256xT.

enum _acmp_discrete_phase_time

ACMP discrete phase time selection. There are two phases for sampling input signals, phase 1 and phase 2.

Values:

enumerator kACMP_DiscretePhaseTimeAlt0

The phase x active in one sampling selection 0.

enumerator kACMP_DiscretePhaseTimeAlt1

The phase x active in one sampling selection 1.

enumerator kACMP_DiscretePhaseTimeAlt2

The phase x active in one sampling selection 2.

enumerator kACMP_DiscretePhaseTimeAlt3

The phase x active in one sampling selection 3.

enumerator kACMP_DiscretePhaseTimeAlt4

The phase x active in one sampling selection 4.

enumerator kACMP_DiscretePhaseTimeAlt5

The phase x active in one sampling selection 5.

enumerator kACMP_DiscretePhaseTimeAlt6

The phase x active in one sampling selection 6.

enumerator kACMP_DiscretePhaseTimeAlt7

The phase x active in one sampling selection 7.

typedef enum *_acmp_offset_mode* acmp_offset_mode_t

Comparator hard block offset control.

If OFFSET level is 1, then there is no hysteresis in the case of positive port input crossing negative port input in the positive direction (or negative port input crossing positive port input in the negative direction). Hysteresis still exists for positive port input crossing negative port input in the falling direction. If OFFSET level is 0, then the hysteresis selected by *acmp_hysteresis_mode_t* is valid for both directions.

typedef enum *_acmp_hysteresis_mode* acmp_hysteresis_mode_t

Comparator hard block hysteresis control.

See chip data sheet to get the actual hysteresis value with each level.

typedef enum *_acmp_reference_voltage_source* acmp_reference_voltage_source_t

CMP Voltage Reference source.

typedef enum *_acmp_port_input* acmp_port_input_t

Port input source.

typedef enum *_acmp_fixed_port* acmp_fixed_port_t

Fixed mux port.

typedef enum *_acmp_dac_work_mode* acmp_dac_work_mode_t

Internal DAC's work mode.

typedef struct *_acmp_config* acmp_config_t

Configuration for ACMP.

typedef struct *_acmp_channel_config* acmp_channel_config_t

Configuration for channel.

The comparator's port can be input from channel mux or DAC. If port input is from channel mux, detailed channel number for the mux should be configured.

typedef struct *_acmp_filter_config* acmp_filter_config_t

Configuration for filter.

typedef struct *_acmp_dac_config* acmp_dac_config_t

Configuration for DAC.

typedef struct *_acmp_round_robin_config* acmp_round_robin_config_t

Configuration for round robin mode.

typedef enum *_acmp_discrete_clock_source* acmp_discrete_clock_source_t

Discrete mode clock selection.

typedef enum *_acmp_discrete_sample_time* acmp_discrete_sample_time_t

ACMP discrete sample selection. These values configures the analog comparator sampling timing (specified by the discrete mode clock period T which is selected by *acmp_discrete_clock_source_t*) in discrete mode.

typedef enum *_acmp_discrete_phase_time* acmp_discrete_phase_time_t

ACMP discrete phase time selection. There are two phases for sampling input signals, phase 1 and phase 2.

typedef struct *_acmp_discrete_mode_config* acmp_discrete_mode_config_t

Configuration for discrete mode.

CMP_C0_CFx_MASK

The mask of status flags cleared by writing 1.

CMP_C1_CHNn_MASK

CMP_C2_CHnF_MASK

struct *_acmp_config*

#include <fsl_acmp.h> Configuration for ACMP.

Public Members

acmp_offset_mode_t offsetMode

Offset mode.

acmp_hysteresis_mode_t hysteresisMode

Hysteresis mode.

bool enableHighSpeed

Enable High Speed (HS) comparison mode.

bool enableInvertOutput

Enable inverted comparator output.

bool useUnfilteredOutput

Set compare output(COUT) to equal COUTA(true) or COUT(false).

bool enablePinOut

The comparator output is available on the associated pin.

struct *_acmp_channel_config*

#include <fsl_acmp.h> Configuration for channel.

The comparator's port can be input from channel mux or DAC. If port input is from channel mux, detailed channel number for the mux should be configured.

Public Members

acmp_port_input_t positivePortInput

Input source of the comparator's positive port.

uint32_t plusMuxInput

Plus mux input channel(0~7).

acmp_port_input_t negativePortInput

Input source of the comparator's negative port.

uint32_t minusMuxInput

Minus mux input channel(0~7).

struct *_acmp_filter_config*

#include <fsl_acmp.h> Configuration for filter.

Public Members

bool enableSample

Using external SAMPLE as sampling clock input, or using divided bus clock.

uint32_t filterCount

Filter Sample Count. Available range is 1-7, 0 would cause the filter disabled.

uint32_t filterPeriod

Filter Sample Period. The divider to bus clock. Available range is 0-255.

struct *_acmp_dac_config*

#include <fsl_acmp.h> Configuration for DAC.

Public Members

acmp_reference_voltage_source_t referenceVoltageSource

Supply voltage reference source.

uint32_t DACValue

Value for DAC Output Voltage. Available range is 0-255.

bool enableOutput

Enable the DAC output.

struct *_acmp_round_robin_config*

#include <fsl_acmp.h> Configuration for round robin mode.

Public Members

acmp_fixed_port_t fixedPort

Fixed mux port.

uint32_t fixedChannelNumber

Indicates which channel is fixed in the fixed mux port.

uint32_t checkerChannelMask

Mask of checker channel index. Available range is channel0:0x01 to channel7:0x80 for round-robin checker.

uint32_t sampleClockCount

Specifies how many round-robin clock cycles(0~3) later the sample takes place.

uint32_t delayModulus

Comparator and DAC initialization delay modulus.

struct *_acmp_discrete_mode_config*

#include <fsl_acmp.h> Configuration for discrete mode.

Public Members

bool enablePositiveChannelDiscreteMode

Positive Channel Continuous Mode Enable. By default, the continuous mode is used.

bool enableNegativeChannelDiscreteMode

Negative Channel Continuous Mode Enable. By default, the continuous mode is used.

bool enableResistorDivider

Resistor Divider Enable is used to enable the resistor divider for the inputs when they come from 3v domain and their values are above 1.8v.

acmp_discrete_clock_source_t clockSource

Select the clock source in order to generate the required timing for comparator to work in discrete mode.

acmp_discrete_sample_time_t sampleTime

Select the ACMP total sampling time period.

acmp_discrete_phase_time_t phase1Time

Select the ACMP phase 1 sampling time.

acmp_discrete_phase_time_t phase2Time

Select the ACMP phase 2 sampling time.

2.2 ADC12: Analog-to-Digital Converter

`void ADC12_Init(ADC_Type *base, const adc12_config_t *config)`

Initialize the ADC12 module.

Parameters

- `base` – ADC12 peripheral base address.
- `config` – Pointer to “`adc12_config_t`” structure.

`void ADC12_Deinit(ADC_Type *base)`

De-initialize the ADC12 module.

Parameters

- `base` – ADC12 peripheral base address.

`void ADC12_GetDefaultConfig(adc12_config_t *config)`

Gets an available pre-defined settings for converter’s configuration.

This function initializes the converter configuration structure with an available settings. The default values are:

Example:

```
config->referenceVoltageSource = kADC12_ReferenceVoltageSourceVref;
config->clockSource = kADC12_ClockSourceAlt0;
config->clockDivider = kADC12_ClockDivider1;
config->resolution = kADC12_Resolution8Bit;
config->sampleClockCount = 12U;
config->enableContinuousConversion = false;
```

Parameters

- `config` – Pointer to “`adc12_config_t`” structure.

`void ADC12_SetChannelConfig(ADC_Type *base, uint32_t channelGroup, const adc12_channel_config_t *config)`

Configure the conversion channel.

This operation triggers the conversion in software trigger mode. In hardware trigger mode, this API configures the channel while the external trigger source helps to trigger the conversion.

Note that the “Channel Group” has a detailed description. To allow sequential conversions of the ADC to be triggered by internal peripherals, the ADC can have more than one group of status and control register, one for each conversion. The channel group parameter indicates which group of registers are used, channel group 0 is for Group A registers and channel group 1 is for Group B registers. The channel groups are used in a “ping-pong” approach to control the ADC operation. At any time, only one of the channel groups is actively controlling ADC conversions. Channel group 0 is used for both software and hardware trigger modes of operation. Channel groups 1 and greater indicate potentially multiple channel group registers for use only in hardware trigger mode. See the chip configuration information in the MCU reference manual about the number of SC1n registers (channel groups) specific to this device. None of the channel groups 1 or greater are used for software trigger operation and therefore writes to these channel groups do not initiate a new conversion. Updating channel group 0 while a different channel group is actively controlling a conversion is allowed and vice versa. Writing any of the channel group registers while that specific channel group is actively controlling a conversion aborts the current conversion.

Parameters

- `base` – ADC12 peripheral base address.

- channelGroup – Channel group index.
- config – Pointer to “adc12_channel_config_t” structure.

static inline uint32_t ADC12_GetChannelConversionValue(ADC_Type *base, uint32_t channelGroup)

Get the conversion value.

Parameters

- base – ADC12 peripheral base address.
- channelGroup – Channel group index.

Returns

Conversion value.

uint32_t ADC12_GetChannelStatusFlags(ADC_Type *base, uint32_t channelGroup)

Get the status flags of channel.

Parameters

- base – ADC12 peripheral base address.
- channelGroup – Channel group index.

Returns

Flags' mask if indicated flags are asserted. See to “_adc12_channel_status_flags”.

status_t ADC12_DoAutoCalibration(ADC_Type *base)

Automate the hardware calibration.

This auto calibration helps to adjust the gain automatically according to the converter's working environment. Execute the calibration before conversion. Note that the software trigger should be used during calibration.

Parameters

- base – ADC12 peripheral base address.

Return values

- kStatus_Success – Calibration is done successfully.
- kStatus_Fail – Calibration is failed.

static inline void ADC12_SetOffsetValue(ADC_Type *base, uint32_t value)

Set the offset value for the conversion result.

This offset value takes effect on the conversion result. If the offset value is not zero, the conversion result is subtracted by it.

Parameters

- base – ADC12 peripheral base address.
- value – Offset value.

static inline void ADC12_SetGainValue(ADC_Type *base, uint32_t value)

Set the gain value for the conversion result.

This gain value takes effect on the conversion result. If the gain value is not zero, the conversion result is amplified as it.

Parameters

- base – ADC12 peripheral base address.
- value – Gain value.

static inline void ADC12_EnableDMA(ADC_Type *base, bool enable)

Enable generating the DMA trigger when conversion is completed.

Parameters

- base – ADC12 peripheral base address.
- enable – Switcher of DMA feature. “true” means to enable, “false” means to disable.

static inline void ADC12_EnableHardwareTrigger(ADC_Type *base, bool enable)

Enable of disable the hardware trigger mode.

Parameters

- base – ADC12 peripheral base address.
- enable – Switcher of hardware trigger feature. “true” means to enable, “false” means not.

void ADC12_SetHardwareCompareConfig(ADC_Type *base, const
adc12_hardware_compare_config_t *config)

Configure the hardware compare mode.

The hardware compare mode provides a way to process the conversion result automatically by hardware. Only the result in compare range is available. To compare the range, see “adc12_hardware_compare_mode_t”, or the reference manual document for more detailed information.

Parameters

- base – ADC12 peripheral base address.
- config – Pointer to “adc12_hardware_compare_config_t” structure. Pass “NULL” to disable the feature.

void ADC12_SetHardwareAverage(ADC_Type *base, adc12_hardware_average_mode_t mode)

Set the hardware average mode.

Hardware average mode provides a way to process the conversion result automatically by hardware. The multiple conversion results are accumulated and averaged internally. This aids to get more accurate conversion result.

Parameters

- base – ADC12 peripheral base address.
- mode – Setting hardware average mode. See to “adc12_hardware_average_mode_t”.

uint32_t ADC12_GetStatusFlags(ADC_Type *base)

Get the status flags of the converter.

Parameters

- base – ADC12 peripheral base address.

Returns

Flags’ mask if indicated flags are asserted. See to “_adc12_status_flags”.

enum _adc12_channel_status_flags

Channel status flags’ mask.

Values:

enumerator kADC12_ChannelConversionCompletedFlag
Conversion done.

enum _adc12_status_flags

Converter status flags' mask.

Values:

enumerator kADC12_ActiveFlag

Converter is active.

enumerator kADC12_CalibrationFailedFlag

Calibration is failed.

enum _adc12_clock_divider

Clock divider for the converter.

Values:

enumerator kADC12_ClockDivider1

For divider 1 from the input clock to the module.

enumerator kADC12_ClockDivider2

For divider 2 from the input clock to the module.

enumerator kADC12_ClockDivider4

For divider 4 from the input clock to the module.

enumerator kADC12_ClockDivider8

For divider 8 from the input clock to the module.

enum _adc12_resolution

Converter's resolution.

Values:

enumerator kADC12_Resolution8Bit

8 bit resolution.

enumerator kADC12_Resolution12Bit

12 bit resolution.

enumerator kADC12_Resolution10Bit

10 bit resolution.

enum _adc12_clock_source

Conversion clock source.

Values:

enumerator kADC12_ClockSourceAlt0

Alternate clock 1 (ADC_ALTCLK1).

enumerator kADC12_ClockSourceAlt1

Alternate clock 2 (ADC_ALTCLK2).

enumerator kADC12_ClockSourceAlt2

Alternate clock 3 (ADC_ALTCLK3).

enumerator kADC12_ClockSourceAlt3

Alternate clock 4 (ADC_ALTCLK4).

enum _adc12_reference_voltage_source

Reference voltage source.

Values:

enumerator `kADC12_ReferenceVoltageSourceVref`
For external pins pair of `VrefH` and `VrefL`.

enumerator `kADC12_ReferenceVoltageSourceValt`
For alternate reference pair of `ValtH` and `ValtL`.

enum `_adc12_hardware_average_mode`
Hardware average mode.

Values:

enumerator `kADC12_HardwareAverageCount4`
For hardware average with 4 samples.

enumerator `kADC12_HardwareAverageCount8`
For hardware average with 8 samples.

enumerator `kADC12_HardwareAverageCount16`
For hardware average with 16 samples.

enumerator `kADC12_HardwareAverageCount32`
For hardware average with 32 samples.

enumerator `kADC12_HardwareAverageDisabled`
Disable the hardware average feature.

enum `_adc12_hardware_compare_mode`
Hardware compare mode.

Values:

enumerator `kADC12_HardwareCompareMode0`
`x < value1`.

enumerator `kADC12_HardwareCompareMode1`
`x > value1`.

enumerator `kADC12_HardwareCompareMode2`
if `value1 <= value2`, then `x < value1 || x > value2`; else, `value1 > x > value2`.

enumerator `kADC12_HardwareCompareMode3`
if `value1 <= value2`, then `value1 <= x <= value2`; else `x >= value1 || x <= value2`.

typedef enum `_adc12_clock_divider` `adc12_clock_divider_t`
Clock divider for the converter.

typedef enum `_adc12_resolution` `adc12_resolution_t`
Converter's resolution.

typedef enum `_adc12_clock_source` `adc12_clock_source_t`
Conversion clock source.

typedef enum `_adc12_reference_voltage_source` `adc12_reference_voltage_source_t`
Reference voltage source.

typedef enum `_adc12_hardware_average_mode` `adc12_hardware_average_mode_t`
Hardware average mode.

typedef enum `_adc12_hardware_compare_mode` `adc12_hardware_compare_mode_t`
Hardware compare mode.

typedef struct `_adc12_config` `adc12_config_t`
Converter configuration.

```
typedef struct _adc12_hardware_compare_config adc12_hardware_compare_config_t
```

Hardware compare configuration.

```
typedef struct _adc12_channel_config adc12_channel_config_t
```

Channel conversion configuration.

```
FSL_ADC12_DRIVER_VERSION
```

ADC12 driver version.

```
struct _adc12_config
```

#include <fsl_adc12.h> Converter configuration.

Public Members

adc12_reference_voltage_source_t referenceVoltageSource

Select the reference voltage source.

adc12_clock_source_t clockSource

Select the input clock source to converter.

adc12_clock_divider_t clockDivider

Select the divider of input clock source.

adc12_resolution_t resolution

Select the sample resolution mode.

uint32_t sampleClockCount

Select the sample clock count. Add its value may improve the stability of the conversion result.

bool enableContinuousConversion

Enable continuous conversion mode.

```
struct _adc12_hardware_compare_config
```

#include <fsl_adc12.h> Hardware compare configuration.

Public Members

adc12_hardware_compare_mode_t hardwareCompareMode

Select the hardware compare mode.

int16_t value1

Setting value1 for hardware compare mode.

int16_t value2

Setting value2 for hardware compare mode.

```
struct _adc12_channel_config
```

#include <fsl_adc12.h> Channel conversion configuration.

Public Members

uint32_t channelNumber

Setting the conversion channel number. The available range is 0-31. See channel connection information for each chip in Reference Manual document.

bool enableInterruptOnConversionCompleted

Generate a interrupt request once the conversion is completed.

2.3 Clock Driver

enum `_clock_name`

Clock name used to get clock frequency.

Values:

enumerator `kCLOCK_CoreSysClk`

Core/system clock

enumerator `kCLOCK_BusClk`

Bus clock

enumerator `kCLOCK_FlexBusClk`

FlexBus clock

enumerator `kCLOCK_FlashClk`

Flash clock

enumerator `kCLOCK_ScgSysOscClk`

SCG system OSC clock. (SYSOSC)

enumerator `kCLOCK_ScgSircClk`

SCG SIRC clock.

enumerator `kCLOCK_ScgFircClk`

SCG FIRC clock.

enumerator `kCLOCK_ScgLpFllClk`

SCG low power FLL clock. (LPFLL)

enumerator `kCLOCK_ScgSysOscAsyncDiv2Clk`

SOSCDIV2_CLK.

enumerator `kCLOCK_ScgSircAsyncDiv2Clk`

SIRCDIV2_CLK.

enumerator `kCLOCK_ScgFircAsyncDiv2Clk`

FIRCDIV2_CLK.

enumerator `kCLOCK_ScgLpFllAsyncDiv2Clk`

LPFLLDIV2_CLK.

enumerator `kCLOCK_LpoClk`

LPO clock

enumerator `kCLOCK_Osc32kClk`

External OSC 32K clock (OSC32KCLK)

enumerator `kCLOCK_ErClk`

ERCLK. The external reference clock from SCG.

enum `_clock_ip_src`

Clock source for peripherals that support various clock selections.

Values:

enumerator `kCLOCK_IpSrcNoneOrExt`

Clock is off or external clock is used.

enumerator `kCLOCK_IpSrcSysOscAsync`

System Oscillator async clock.

enumerator kCLOCK_IpSrcSircAsync

Slow IRC async clock.

enumerator kCLOCK_IpSrcFireAsync

Fast IRC async clock.

enumerator kCLOCK_IpSrcLpFllAsync

LPFLL async clock.

enum _clock_ip_name

Peripheral clock name definition used for clock gate, clock source and clock divider setting. It is defined as the corresponding register address.

Values:

enumerator kCLOCK_IpInvalid

enumerator kCLOCK_Dma0

enumerator kCLOCK_Flash0

enumerator kCLOCK_Dmamux0

enumerator kCLOCK_Adc1

enumerator kCLOCK_Lpspi0

enumerator kCLOCK_Lpspi1

enumerator kCLOCK_Crc0

enumerator kCLOCK_Pdb0

enumerator kCLOCK_Lpit0

enumerator kCLOCK_Ftm0

enumerator kCLOCK_Ftm1

enumerator kCLOCK_Ftm2

enumerator kCLOCK_Adc0

enumerator kCLOCK_Rtc0

enumerator kCLOCK_Lptmr0

enumerator kCLOCK_Tsi0

enumerator kCLOCK_PortA

enumerator kCLOCK_PortB

enumerator kCLOCK_PortC

enumerator kCLOCK_PortD

enumerator kCLOCK_PortE

enumerator kCLOCK_Pwt0

enumerator kCLOCK_Flexio0

enumerator kCLOCK_RtcOsc0

enumerator kCLOCK_Ewm0
enumerator kCLOCK_Lpi2c0
enumerator kCLOCK_Lpi2c1
enumerator kCLOCK_Lpuart0
enumerator kCLOCK_Lpuart1
enumerator kCLOCK_Lpuart2
enumerator kCLOCK_Cmp0
enumerator kCLOCK_Cmp1

enum __osc32_mode

OSC32 work mode.

Values:

enumerator kOSC32_Bypass
Bypass mode, use external input clock directly.
enumerator kOSC32_Crystal
Crystal mode, does not work in stop mode.
enumerator kOSC32_CrystalEnableInStop
Crystal mode, still work in stop mode.

SCG status return codes.

Values:

enumerator kStatus_SCG_Busy
Clock is busy.
enumerator kStatus_SCG_InvalidSrc
Invalid source.

enum __scg_sys_clk

SCG system clock type.

Values:

enumerator kSCG_SysClkSlow
System slow clock.
enumerator kSCG_SysClkCore
Core clock.

enum __scg_sys_clk_src

SCG system clock source.

Values:

enumerator kSCG_SysClkSrcSysOsc
System OSC.
enumerator kSCG_SysClkSrcSirc
Slow IRC.
enumerator kSCG_SysClkSrcFirc
Fast IRC.

enumerator kSCG_SysClkSrcLpFll
Low power FLL.

enum _scg_sys_clk_div
SCG system clock divider value.

Values:

enumerator kSCG_SysClkDivBy1
Divided by 1.

enumerator kSCG_SysClkDivBy2
Divided by 2.

enumerator kSCG_SysClkDivBy3
Divided by 3.

enumerator kSCG_SysClkDivBy4
Divided by 4.

enumerator kSCG_SysClkDivBy5
Divided by 5.

enumerator kSCG_SysClkDivBy6
Divided by 6.

enumerator kSCG_SysClkDivBy7
Divided by 7.

enumerator kSCG_SysClkDivBy8
Divided by 8.

enumerator kSCG_SysClkDivBy9
Divided by 9.

enumerator kSCG_SysClkDivBy10
Divided by 10.

enumerator kSCG_SysClkDivBy11
Divided by 11.

enumerator kSCG_SysClkDivBy12
Divided by 12.

enumerator kSCG_SysClkDivBy13
Divided by 13.

enumerator kSCG_SysClkDivBy14
Divided by 14.

enumerator kSCG_SysClkDivBy15
Divided by 15.

enumerator kSCG_SysClkDivBy16
Divided by 16.

enum _clock_clkout_src
SCG clock out configuration (CLKOUTSEL).

Values:

enumerator kClockClkoutSelScgSlow
SCG slow clock.

enumerator kClockClkoutSelSysOsc
System OSC.

enumerator kClockClkoutSelSirc
Slow IRC.

enumerator kClockClkoutSelFirc
Fast IRC.

enumerator kClockClkoutSelLpFll
Low power FLL.

enum _scg_async_clk
SCG asynchronous clock type.

Values:

enumerator kSCG_AsyncDiv2Clk
The async clock by DIV2, e.g. SOSCDIV2_CLK, SIRCDIV2_CLK.

enum scg_async_clk_div
SCG asynchronous clock divider value.

Values:

enumerator kSCG_AsyncClkDisable
Clock output is disabled.

enumerator kSCG_AsyncClkDivBy1
Divided by 1.

enumerator kSCG_AsyncClkDivBy2
Divided by 2.

enumerator kSCG_AsyncClkDivBy4
Divided by 4.

enumerator kSCG_AsyncClkDivBy8
Divided by 8.

enumerator kSCG_AsyncClkDivBy16
Divided by 16.

enumerator kSCG_AsyncClkDivBy32
Divided by 32.

enumerator kSCG_AsyncClkDivBy64
Divided by 64.

enum _scg_sosc_monitor_mode
SCG system OSC monitor mode.

Values:

enumerator kSCG_SysOscMonitorDisable
Monitor disabled.

enumerator kSCG_SysOscMonitorInt
Interrupt when the system OSC error is detected.

enumerator kSCG_SysOscMonitorReset
Reset when the system OSC error is detected.

enum _scg_sosc_mode

OSC work mode.

Values:

enumerator kSCG_SysOscModeExt

Use external clock.

enumerator kSCG_SysOscModeOscLowPower

Oscillator low power.

enumerator kSCG_SysOscModeOscHighGain

Oscillator high gain.

OSC enable mode.

Values:

enumerator kSCG_SysOscEnable

Enable OSC clock.

enumerator kSCG_SysOscEnableInStop

Enable OSC in stop mode.

enumerator kSCG_SysOscEnableInLowPower

Enable OSC in low power mode.

enumerator kSCG_SysOscEnableErClk

Enable OSCERCLK.

enum _scg_sirc_range

SCG slow IRC clock frequency range.

Values:

enumerator kSCG_SircRangeLow

Slow IRC low range clock (2 MHz, 4 MHz for i.MX 7 ULP).

enumerator kSCG_SircRangeHigh

Slow IRC high range clock (8 MHz, 16 MHz for i.MX 7 ULP).

SIRC enable mode.

Values:

enumerator kSCG_SircEnable

Enable SIRC clock.

enumerator kSCG_SircEnableInStop

Enable SIRC in stop mode.

enumerator kSCG_SircEnableInLowPower

Enable SIRC in low power mode.

enum _scg_firc_trim_mode

SCG fast IRC trim mode.

Values:

enumerator kSCG_FircTrimNonUpdate

FIRC trim enable but not enable trim value update. In this mode, the trim value is fixed to the initialized value which is defined by trimCoar and trimFine in configure structure scg_firc_trim_config_t.

enumerator kSCG_FircTrimUpdate

FIRC trim enable and trim value update enable. In this mode, the trim value is auto update.

enum _scg_firc_trim_div

SCG fast IRC trim predivided value for system OSC.

Values:

enumerator kSCG_FircTrimDivBy1

Divided by 1.

enumerator kSCG_FircTrimDivBy128

Divided by 128.

enumerator kSCG_FircTrimDivBy256

Divided by 256.

enumerator kSCG_FircTrimDivBy512

Divided by 512.

enumerator kSCG_FircTrimDivBy1024

Divided by 1024.

enumerator kSCG_FircTrimDivBy2048

Divided by 2048.

enum _scg_firc_trim_src

SCG fast IRC trim source.

Values:

enumerator kSCG_FircTrimSrcSysOsc

System OSC.

enum _scg_firc_range

SCG fast IRC clock frequency range.

Values:

enumerator kSCG_FircRange48M

Fast IRC is trimmed to 48 MHz.

enumerator kSCG_FircRange52M

Fast IRC is trimmed to 52 MHz.

enumerator kSCG_FircRange56M

Fast IRC is trimmed to 56 MHz.

enumerator kSCG_FircRange60M

Fast IRC is trimmed to 60 MHz.

FIRC enable mode.

Values:

enumerator kSCG_FircEnable

Enable FIRC clock.

enumerator kSCG_FircEnableInStop

Enable FIRC in stop mode.

enumerator kSCG_FircEnableInLowPower

Enable FIRC in low power mode.

enumerator kSCG_FircDisableRegulator

Disable regulator.

LPFLL enable mode.

Values:

enumerator kSCG_LpFllEnable

Enable LPFLL clock.

enum _scg_lpfl_range

SCG LPFLL clock frequency range.

Values:

enumerator kSCG_LpFllRange48M

LPFLL is trimmed to 48MHz.

enumerator kSCG_LpFllRange72M

LPFLL is trimmed to 72MHz.

enumerator kSCG_LpFllRange96M

LPFLL is trimmed to 96MHz.

enumerator kSCG_LpFllRange120M

LPFLL is trimmed to 120MHz.

enum _scg_lpfl_trim_mode

SCG LPFLL trim mode.

Values:

enumerator kSCG_LpFllTrimNonUpdate

LPFLL trim is enabled but the trim value update is not enabled. In this mode, the trim value is fixed to the initialized value, which is defined by the Member variable trimValue in the structure scg_lpfl_trim_config_t.

enumerator kSCG_LpFllTrimUpdate

FIRC trim is enabled and trim value update is enabled. In this mode, the trim value is automatically updated.

enum _scg_lpfl_trim_src

SCG LPFLL trim source.

Values:

enumerator kSCG_LpFllTrimSrcSirc

SIRC.

enumerator kSCG_LpFllTrimSrcFirc

FIRC.

enumerator kSCG_LpFllTrimSrcSysOsc

System OSC.

enumerator kSCG_LpFllTrimSrcRtcOsc

RTC OSC (32.768 kHz).

enum `_scg_lpfll_lock_mode`

SCG LPFLL lock mode.

Values:

enumerator `kSCG_LpFllLock1Lsb`

Lock with 1 LSB.

enumerator `kSCG_LpFllLock2Lsb`

Lock with 2 LSB.

typedef enum `_clock_name` `clock_name_t`

Clock name used to get clock frequency.

typedef enum `_clock_ip_src` `clock_ip_src_t`

Clock source for peripherals that support various clock selections.

typedef enum `_clock_ip_name` `clock_ip_name_t`

Peripheral clock name definition used for clock gate, clock source and clock divider setting.
It is defined as the corresponding register address.

typedef enum `_osc32_mode` `osc32_mode_t`

OSC32 work mode.

typedef enum `_scg_sys_clk` `scg_sys_clk_t`

SCG system clock type.

typedef enum `_scg_sys_clk_src` `scg_sys_clk_src_t`

SCG system clock source.

typedef enum `_scg_sys_clk_div` `scg_sys_clk_div_t`

SCG system clock divider value.

typedef struct `_scg_sys_clk_config` `scg_sys_clk_config_t`

SCG system clock configuration.

typedef enum `_clock_clkout_src` `clock_clkout_src_t`

SCG clock out configuration (CLKOUTSEL).

typedef enum `_scg_async_clk` `scg_async_clk_t`

SCG asynchronous clock type.

typedef enum `scg_async_clk_div` `scg_async_clk_div_t`

SCG asynchronous clock divider value.

typedef enum `_scg_sosc_monitor_mode` `scg_sosc_monitor_mode_t`

SCG system OSC monitor mode.

typedef enum `_scg_sosc_mode` `scg_sosc_mode_t`

OSC work mode.

typedef struct `_scg_sosc_config` `scg_sosc_config_t`

SCG system OSC configuration.

typedef enum `_scg_sirc_range` `scg_sirc_range_t`

SCG slow IRC clock frequency range.

typedef struct `_scg_sirc_config` `scg_sirc_config_t`

SCG slow IRC clock configuration.

typedef enum `_scg_firc_trim_mode` `scg_firc_trim_mode_t`

SCG fast IRC trim mode.

typedef enum *_scg_firc_trim_div* scg_firc_trim_div_t

SCG fast IRC trim predivided value for system OSC.

typedef enum *_scg_firc_trim_src* scg_firc_trim_src_t

SCG fast IRC trim source.

typedef struct *_scg_firc_trim_config* scg_firc_trim_config_t

SCG fast IRC clock trim configuration.

typedef enum *_scg_firc_range* scg_firc_range_t

SCG fast IRC clock frequency range.

typedef struct *_scg_firc_config_t* scg_firc_config_t

SCG fast IRC clock configuration.

typedef enum *_scg_lpfl_range* scg_lpfl_range_t

SCG LPFLL clock frequency range.

typedef enum *_scg_lpfl_trim_mode* scg_lpfl_trim_mode_t

SCG LPFLL trim mode.

typedef enum *_scg_lpfl_trim_src* scg_lpfl_trim_src_t

SCG LPFLL trim source.

typedef enum *_scg_lpfl_lock_mode* scg_lpfl_lock_mode_t

SCG LPFLL lock mode.

typedef struct *_scg_lpfl_trim_config* scg_lpfl_trim_config_t

SCG LPFLL clock trim configuration.

typedef struct *_scg_lpfl_config* scg_lpfl_config_t

SCG low power FLL configuration.

volatile uint32_t g_xtal0Freq

External XTAL0 (OSC0/SYSOSC) clock frequency.

The XTAL0/EXTAL0 (OSC0/SYSOSC) clock frequency in Hz. When the clock is set up, use the function `CLOCK_SetXtal0Freq` to set the value in the clock driver. For example, if XTAL0 is 8 MHz:

```
CLOCK_InitSysOsc(...);  
CLOCK_SetXtal0Freq(8000000);
```

This is important for the multicore platforms where only one core needs to set up the OSC0/SYSOSC using `CLOCK_InitSysOsc`. All other cores need to call the `CLOCK_SetXtal0Freq` to get a valid clock frequency.

volatile uint32_t g_xtal32Freq

External XTAL32/EXTAL32 clock frequency.

The XTAL32/EXTAL32 clock frequency in Hz. When the clock is set up, use the function `CLOCK_SetXtal32Freq` to set the value in the clock driver.

This is important for the multicore platforms where only one core needs to set up the clock. All other cores need to call the `CLOCK_SetXtal32Freq` to get a valid clock frequency.

static inline void `CLOCK_EnableClock(clock_ip_name_t name)`

Enable the clock for specific IP.

Parameters

- name – Which clock to enable, see `clock_ip_name_t`.

static inline void CLOCK_DisableClock(*clock_ip_name_t* name)

Disable the clock for specific IP.

Parameters

- name – Which clock to disable, see *clock_ip_name_t*.

static inline bool CLOCK_IsEnabledByOtherCore(*clock_ip_name_t* name)

Check whether the clock is already enabled and configured by any other core.

Parameters

- name – Which peripheral to check, see *clock_ip_name_t*.

Returns

True if clock is already enabled, otherwise false.

static inline void CLOCK_SetIpSrc(*clock_ip_name_t* name, *clock_ip_src_t* src)

Set the clock source for specific IP module.

Set the clock source for specific IP, not all modules need to set the clock source, should only use this function for the modules need source setting.

Parameters

- name – Which peripheral to check, see *clock_ip_name_t*.
- src – Clock source to set.

uint32_t CLOCK_GetFreq(*clock_name_t* clockName)

Gets the clock frequency for a specific clock name.

This function checks the current clock configurations and then calculates the clock frequency for a specific clock name defined in *clock_name_t*.

Parameters

- clockName – Clock names defined in *clock_name_t*

Returns

Clock frequency value in hertz

uint32_t CLOCK_GetCoreSysClkFreq(void)

Get the core clock or system clock frequency.

Returns

Clock frequency in Hz.

uint32_t CLOCK_GetBusClkFreq(void)

Get the bus clock frequency.

Returns

Clock frequency in Hz.

uint32_t CLOCK_GetFlashClkFreq(void)

Get the flash clock frequency.

Returns

Clock frequency in Hz.

uint32_t CLOCK_GetOsc32kClkFreq(void)

Get the OSC 32K clock frequency (OSC32KCLK).

Returns

Clock frequency in Hz.

uint32_t CLOCK_GetErClkFreq(void)

Get the external reference clock frequency (ERCLK).

Returns

Clock frequency in Hz.

uint32_t CLOCK_GetIpFreq(*clock_ip_name_t* name)

Gets the clock frequency for a specific IP module.

This function gets the IP module clock frequency based on PCC registers. It is only used for the IP modules which could select clock source by PCC[PCS].

Parameters

- name – Which peripheral to get, see clock_ip_name_t.

Returns

Clock frequency value in hertz

FSL_CLOCK_DRIVER_VERSION

CLOCK driver version 2.4.0.

SDK_DEVICE_MAXIMUM_CPU_CLOCK_FREQUENCY

DMAMUX_CLOCKS

Clock ip name array for DMAMUX.

RTC_CLOCKS

Clock ip name array for RTC.

RTCOSC_CLOCKS

Clock ip name array for RTCOSC.

PORT_CLOCKS

Clock ip name array for PORT.

LPI2C_CLOCKS

Clock ip name array for LPI2C.

FLEXIO_CLOCKS

Clock ip name array for FLEXIO.

TSI_CLOCKS

Clock ip name array for TSI.

EDMA_CLOCKS

Clock ip name array for EDMA.

LPUART_CLOCKS

Clock ip name array for LPUART.

LPTMR_CLOCKS

Clock ip name array for LPTMR.

ADC12_CLOCKS

Clock ip name array for ADC12.

LPSPI_CLOCKS

Clock ip name array for LPSPI.

LPIT_CLOCKS

Clock ip name array for LPIT.

CRC_CLOCKS

Clock ip name array for CRC.

CMP_CLOCKS

Clock ip name array for CMP.

FLASH_CLOCKS

Clock ip name array for FLASH.

EWM_CLOCKS

Clock ip name array for EWM.

FTM_CLOCKS

Clock ip name array for FLEXTMR.

PDB_CLOCKS

Clock ip name array for PDB.

PWT_CLOCKS

Clock ip name array for PWT.

LPO_CLK_FREQ

LPO clock frequency.

kCLOCK_Osc0ErClk

kCLOCK_Er32kClk

CLOCK_GetOsc0ErClkFreq

For compatible with other MCG platforms.

CLOCK_GetEr32kClkFreq

For compatible with other MCG platforms.

uint32_t CLOCK_GetSysClkFreq(*scg_sys_clk_t* type)

Gets the SCG system clock frequency.

This function gets the SCG system clock frequency. These clocks are used for core, platform, external, and bus clock domains.

Parameters

- type – Which type of clock to get, core clock or slow clock.

Returns

Clock frequency.

static inline void CLOCK_SetVlprModeSysClkConfig(const *scg_sys_clk_config_t* *config)

Sets the system clock configuration for VLPR mode.

This function sets the system clock configuration for VLPR mode.

Parameters

- config – Pointer to the configuration.

static inline void CLOCK_SetRunModeSysClkConfig(const *scg_sys_clk_config_t* *config)

Sets the system clock configuration for RUN mode.

This function sets the system clock configuration for RUN mode.

Parameters

- config – Pointer to the configuration.

static inline void CLOCK_GetCurSysClkConfig(*scg_sys_clk_config_t* *config)

Gets the system clock configuration in the current power mode.

This function gets the system configuration in the current power mode.

Parameters

- config – Pointer to the configuration.

static inline void CLOCK_SetClkOutSel(*clock_clkout_src_t* setting)

Sets the clock out selection.

This function sets the clock out selection (CLKOUTSEL).

Parameters

- setting – The selection to set.

Returns

The current clock out selection.

status_t CLOCK_InitSysOsc(const *scg_sosc_config_t* *config)

Initializes the SCG system OSC.

This function enables the SCG system OSC clock according to the configuration.

Note: This function can't detect whether the system OSC has been enabled and used by an IP.

Parameters

- config – Pointer to the configuration structure.

Return values

- kStatus_Success – System OSC is initialized.
- kStatus_SCG_Busy – System OSC has been enabled and is used by the system clock.
- kStatus_ReadOnly – System OSC control register is locked.

status_t CLOCK_DeinitSysOsc(void)

De-initializes the SCG system OSC.

This function disables the SCG system OSC clock.

Note: This function can't detect whether the system OSC is used by an IP.

Return values

- kStatus_Success – System OSC is deinitialized.
- kStatus_SCG_Busy – System OSC is used by the system clock.
- kStatus_ReadOnly – System OSC control register is locked.

static inline void CLOCK_SetSysOscAsyncClkDiv(*scg_async_clk_t* asyncClk, *scg_async_clk_div_t* divider)

Set the asynchronous clock divider.

Note: There might be glitch when changing the asynchronous divider, so make sure the asynchronous clock is not used while changing divider.

Parameters

- `asyncClk` – Which asynchronous clock to configure.
- `divider` – The divider value to set.

`uint32_t CLOCK_GetSysOscFreq(void)`

Gets the SCG system OSC clock frequency (SYSOSC).

Returns

Clock frequency; If the clock is invalid, returns 0.

`uint32_t CLOCK_GetSysOscAsyncFreq(scg_async_clk_t type)`

Gets the SCG asynchronous clock frequency from the system OSC.

Parameters

- `type` – The asynchronous clock type.

Returns

Clock frequency; If the clock is invalid, returns 0.

`static inline bool CLOCK_IsSysOscErr(void)`

Checks whether the system OSC clock error occurs.

Returns

True if the error occurs, false if not.

`static inline void CLOCK_ClearSysOscErr(void)`

Clears the system OSC clock error.

`static inline void CLOCK_SetSysOscMonitorMode(scg_sosc_monitor_mode_t mode)`

Sets the system OSC monitor mode.

This function sets the system OSC monitor mode. The mode can be disabled, it can generate an interrupt when the error is disabled, or reset when the error is detected.

Parameters

- `mode` – Monitor mode to set.

`static inline bool CLOCK_IsSysOscValid(void)`

Checks whether the system OSC clock is valid.

Returns

True if clock is valid, false if not.

`status_t CLOCK_InitSirc(const scg_sirc_config_t *config)`

Initializes the SCG slow IRC clock.

This function enables the SCG slow IRC clock according to the configuration.

Note: This function can't detect whether the system OSC has been enabled and used by an IP.

Parameters

- `config` – Pointer to the configuration structure.

Return values

- `kStatus_Success` – SIRC is initialized.
- `kStatus_SCG_Busy` – SIRC has been enabled and is used by system clock.
- `kStatus_ReadOnly` – SIRC control register is locked.

status_t CLOCK_DeinitSirc(void)

De-initializes the SCG slow IRC.

This function disables the SCG slow IRC.

Note: This function can't detect whether the SIRC is used by an IP.

Return values

- kStatus_Success – SIRC is deinitialized.
- kStatus_SCG_Busy – SIRC is used by system clock.
- kStatus_ReadOnly – SIRC control register is locked.

static inline void CLOCK_SetSircAsyncClkDiv(*scg_async_clk_t* asyncClk, *scg_async_clk_div_t* divider)

Set the asynchronous clock divider.

Note: There might be glitch when changing the asynchronous divider, so make sure the asynchronous clock is not used while changing divider.

Parameters

- asyncClk – Which asynchronous clock to configure.
- divider – The divider value to set.

uint32_t CLOCK_GetSircFreq(void)

Gets the SCG SIRC clock frequency.

Returns

Clock frequency; If the clock is invalid, returns 0.

uint32_t CLOCK_GetSircAsyncFreq(*scg_async_clk_t* type)

Gets the SCG asynchronous clock frequency from the SIRC.

Parameters

- type – The asynchronous clock type.

Returns

Clock frequency; If the clock is invalid, returns 0.

static inline bool CLOCK_IsSircValid(void)

Checks whether the SIRC clock is valid.

Returns

True if clock is valid, false if not.

status_t CLOCK_InitFirc(const *scg_firc_config_t* *config)

Initializes the SCG fast IRC clock.

This function enables the SCG fast IRC clock according to the configuration.

Note: This function can't detect whether the FIRC has been enabled and used by an IP.

Parameters

- config – Pointer to the configuration structure.

Return values

- `kStatus_Success` – FIRC is initialized.
- `kStatus_SCG_Busy` – FIRC has been enabled and is used by the system clock.
- `kStatus_ReadOnly` – FIRC control register is locked.

`status_t` `CLOCK_DeinitFirc(void)`

De-initializes the SCG fast IRC.

This function disables the SCG fast IRC.

Note: This function can't detect whether the FIRC is used by an IP.

Return values

- `kStatus_Success` – FIRC is deinitialized.
- `kStatus_SCG_Busy` – FIRC is used by the system clock.
- `kStatus_ReadOnly` – FIRC control register is locked.

`static inline void` `CLOCK_SetFircAsyncClkDiv(scg_async_clk_t asyncClk, scg_async_clk_div_t divider)`

Set the asynchronous clock divider.

Note: There might be glitch when changing the asynchronous divider, so make sure the asynchronous clock is not used while changing divider.

Parameters

- `asyncClk` – Which asynchronous clock to configure.
- `divider` – The divider value to set.

`uint32_t` `CLOCK_GetFircFreq(void)`

Gets the SCG FIRC clock frequency.

Returns

Clock frequency; If the clock is invalid, returns 0.

`uint32_t` `CLOCK_GetFircAsyncFreq(scg_async_clk_t type)`

Gets the SCG asynchronous clock frequency from the FIRC.

Parameters

- `type` – The asynchronous clock type.

Returns

Clock frequency; If the clock is invalid, returns 0.

`static inline bool` `CLOCK_IsFircErr(void)`

Checks whether the FIRC clock error occurs.

Returns

True if the error occurs, false if not.

`static inline void` `CLOCK_ClearFircErr(void)`

Clears the FIRC clock error.

`static inline bool` `CLOCK_IsFircValid(void)`

Checks whether the FIRC clock is valid.

Returns

True if clock is valid, false if not.

status_t CLOCK_InitLpFll(const *scg_lpfl_config_t* *config)

Initializes the SCG LPFLL clock.

This function enables the SCG LPFLL clock according to the configuration.

Note: This function can't detect whether the LPFLL has been enabled and used by an IP.

Parameters

- config – Pointer to the configuration structure.

Return values

- kStatus_Success – LPFLL is initialized.
- kStatus_SCG_Busy – LPFLL has been enabled and is used by the system clock.
- kStatus_ReadOnly – LPFLL control register is locked.

status_t CLOCK_DeinitLpFll(void)

De-initializes the SCG LPFLL.

This function disables the SCG LPFLL.

Note: This function can't detect whether the LPFLL is used by an IP.

Return values

- kStatus_Success – LPFLL is deinitialized.
- kStatus_SCG_Busy – LPFLL is used by the system clock.
- kStatus_ReadOnly – LPFLL control register is locked.

static inline void CLOCK_SetLpFllAsyncClkDiv(*scg_async_clk_t* asyncClk, *scg_async_clk_div_t* divider)

Set the asynchronous clock divider.

Note: There might be glitch when changing the asynchronous divider, so make sure the asynchronous clock is not used while changing divider.

Parameters

- asyncClk – Which asynchronous clock to configure.
- divider – The divider value to set.

uint32_t CLOCK_GetLpFllFreq(void)

Gets the SCG LPFLL clock frequency.

Returns

Clock frequency in Hz; If the clock is invalid, returns 0.

uint32_t CLOCK_GetLpFllAsyncFreq(*scg_async_clk_t* type)

Gets the SCG asynchronous clock frequency from the LPFLL.

Parameters

- `type` – The asynchronous clock type.

Returns

Clock frequency in Hz; If the clock is invalid, returns 0.

`static inline bool CLOCK_IsLpFllValid(void)`

Checks whether the LPFLL clock is valid.

Returns

True if the clock is valid, false if not.

`void OSC32_Init(OSC32_Type *base, osc32_mode_t mode)`

Initializes OSC32.

Parameters

- `base` – OSC32 peripheral base address.
- `mode` – OSC32 work mode, see `osc32_mode_t`

`void OSC32_Deinit(OSC32_Type *base)`

Deinitializes OSC32.

Parameters

- `base` – OSC32 peripheral base address.

`static inline void CLOCK_SetXtal0Freq(uint32_t freq)`

Sets the XTAL0 frequency based on board settings.

Parameters

- `freq` – The XTAL0/EXTAL0 input clock frequency in Hz.

`static inline void CLOCK_SetXtal32Freq(uint32_t freq)`

Sets the XTAL32 frequency based on board settings.

Parameters

- `freq` – The XTAL32/EXTAL32 input clock frequency in Hz.

`uint32_t divSlow`

Slow clock divider, see `scg_sys_clk_div_t`.

`uint32_t __pad0__`

Reserved.

`uint32_t __pad1__`

Reserved.

`uint32_t __pad2__`

Reserved.

`uint32_t divCore`

Core clock divider, see `scg_sys_clk_div_t`.

`uint32_t __pad3__`

Reserved.

`uint32_t src`

System clock source, see `scg_sys_clk_src_t`.

`uint32_t __pad4__`

reserved.

`uint32_t freq`

System OSC frequency.

scg_sosc_monitor_mode_t monitorMode

Clock monitor mode selected.

uint8_t enableMode

Enable mode, OR'ed value of *_scg_sosc_enable_mode*.

scg_async_clk_div_t div2

SOSCDIV2 value.

scg_sosc_mode_t workMode

OSC work mode.

uint32_t enableMode

Enable mode, OR'ed value of *_scg_sirc_enable_mode*.

scg_async_clk_div_t div2

SIRCDIV2 value.

scg_sirc_range_t range

Slow IRC frequency range.

scg_firc_trim_mode_t trimMode

FIRC trim mode.

scg_firc_trim_src_t trimSrc

Trim source.

scg_firc_trim_div_t trimDiv

Trim predivided value for the system OSC.

uint8_t trimCoar

Trim coarse value; Irrelevant if trimMode is kSCG_FircTrimUpdate.

uint8_t trimFine

Trim fine value; Irrelevant if trimMode is kSCG_FircTrimUpdate.

uint32_t enableMode

Enable mode, OR'ed value of *_scg_firc_enable_mode*.

scg_async_clk_div_t div2

FIRCDIV2 value.

scg_firc_range_t range

Fast IRC frequency range.

const *scg_firc_trim_config_t* *trimConfig

Pointer to the FIRC trim configuration; set NULL to disable trim.

scg_lpfl_trim_mode_t trimMode

Trim mode.

scg_lpfl_lock_mode_t lockMode

Lock mode; Irrelevant if the trimMode is kSCG_LpFlTrimNonUpdate.

scg_lpfl_trim_src_t trimSrc

Trim source.

uint8_t trimDiv

Trim predivideds value, which can be 0 ~ 31. [Trim source frequency / (trimDiv + 1)] must be 2 MHz or 32768 Hz.

uint8_t trimValue

Trim value; Irrelevant if trimMode is the kSCG_LpFlTrimUpdate.

uint8_t enableMode

Enable mode, OR'ed value of _scg_lpfl_enable_mode

scg_async_clk_div_t div2

LPFLLDIV2 value.

scg_lpfl_range_t range

LPFLL frequency range.

const scg_lpfl_trim_config_t *trimConfig

Trim configuration; set NULL to disable trim.

FSL_SDK_DISABLE_DRIVER_CLOCK_CONTROL

Configure whether driver controls clock.

When set to 0, peripheral drivers will enable clock in initialize function and disable clock in de-initialize function. When set to 1, peripheral driver will not control the clock, application could control the clock out of the driver.

Note: All drivers share this feature switcher. If it is set to 1, application should handle clock enable and disable for all drivers.

struct _scg_sys_clk_config

#include <fsl_clock.h> SCG system clock configuration.

struct _scg_sosc_config

#include <fsl_clock.h> SCG system OSC configuration.

struct _scg_sirc_config

#include <fsl_clock.h> SCG slow IRC clock configuration.

struct _scg_firc_trim_config

#include <fsl_clock.h> SCG fast IRC clock trim configuration.

struct _scg_firc_config_t

#include <fsl_clock.h> SCG fast IRC clock configuration.

struct _scg_lpfl_trim_config

#include <fsl_clock.h> SCG LPFLL clock trim configuration.

struct _scg_lpfl_config

#include <fsl_clock.h> SCG low power FLL configuration.

2.4 CRC: Cyclic Redundancy Check Driver

FSL_CRC_DRIVER_VERSION

CRC driver version. Version 2.0.4.

Current version: 2.0.4

Change log:

- Version 2.0.4
 - Release peripheral from reset if necessary in init function.
- Version 2.0.3
 - Fix MISRA issues

- Version 2.0.2
 - Fix MISRA issues
- Version 2.0.1
 - move DATA and DATALL macro definition from header file to source file

enum `_crc_bits`

CRC bit width.

Values:

enumerator `kCrcBits16`

Generate 16-bit CRC code

enumerator `kCrcBits32`

Generate 32-bit CRC code

enum `_crc_result`

CRC result type.

Values:

enumerator `kCrcFinalChecksum`

CRC data register read value is the final checksum. Reflect out and final xor protocol features are applied.

enumerator `kCrcIntermediateChecksum`

CRC data register read value is intermediate checksum (raw value). Reflect out and final xor protocol feature are not applied. Intermediate checksum can be used as a seed for `CRC_Init()` to continue adding data to this checksum.

typedef enum `_crc_bits` `crc_bits_t`

CRC bit width.

typedef enum `_crc_result` `crc_result_t`

CRC result type.

typedef struct `_crc_config` `crc_config_t`

CRC protocol configuration.

This structure holds the configuration for the CRC protocol.

void `CRC_Init(CRC_Type *base, const crc_config_t *config)`

Enables and configures the CRC peripheral module.

This function enables the clock gate in the SIM module for the CRC peripheral. It also configures the CRC module and starts a checksum computation by writing the seed.

Parameters

- `base` – CRC peripheral address.
- `config` – CRC module configuration structure.

static inline void `CRC_Deinit(CRC_Type *base)`

Disables the CRC peripheral module.

This function disables the clock gate in the SIM module for the CRC peripheral.

Parameters

- `base` – CRC peripheral address.

`void CRC_GetDefaultConfig(crc_config_t *config)`

Loads default values to the CRC protocol configuration structure.

Loads default values to the CRC protocol configuration structure. The default values are as follows.

```
config->polynomial = 0x1021;
config->seed = 0xFFFF;
config->reflectIn = false;
config->reflectOut = false;
config->complementChecksum = false;
config->crcBits = kCrcBits16;
config->crcResult = kCrcFinalChecksum;
```

Parameters

- `config` – CRC protocol configuration structure.

`void CRC_WriteData(CRC_Type *base, const uint8_t *data, size_t dataSize)`

Writes data to the CRC module.

Writes input data buffer bytes to the CRC data register. The configured type of transpose is applied.

Parameters

- `base` – CRC peripheral address.
- `data` – Input data stream, MSByte in `data[0]`.
- `dataSize` – Size in bytes of the input data buffer.

`uint32_t CRC_Get32bitResult(CRC_Type *base)`

Reads the 32-bit checksum from the CRC module.

Reads the CRC data register (either an intermediate or the final checksum). The configured type of transpose and complement is applied.

Parameters

- `base` – CRC peripheral address.

Returns

An intermediate or the final 32-bit checksum, after configured transpose and complement operations.

`uint16_t CRC_Get16bitResult(CRC_Type *base)`

Reads a 16-bit checksum from the CRC module.

Reads the CRC data register (either an intermediate or the final checksum). The configured type of transpose and complement is applied.

Parameters

- `base` – CRC peripheral address.

Returns

An intermediate or the final 16-bit checksum, after configured transpose and complement operations.

`CRC_DRIVER_USE_CRC16_CCIT_FALSE_AS_DEFAULT`

Default configuration structure filled by `CRC_GetDefaultConfig()`. Use CRC16-CCIT-FALSE as default.

`struct _crc_config`

`#include <fsl_crc.h>` CRC protocol configuration.

This structure holds the configuration for the CRC protocol.

Public Members

uint32_t polynomial

CRC Polynomial, MSBit first. Example polynomial: 0x1021 = 1_0000_0010_0001 = $x^{12}+x^5+1$

uint32_t seed

Starting checksum value

bool reflectIn

Reflect bits on input.

bool reflectOut

Reflect bits on output.

bool complementChecksum

True if the result shall be complement of the actual checksum.

crc_bits_t crcBits

Selects 16- or 32- bit CRC protocol.

crc_result_t crcResult

Selects final or intermediate checksum return from CRC_Get16bitResult() or CRC_Get32bitResult()

2.5 DMAMUX: Direct Memory Access Multiplexer Driver

void DMAMUX_Init(DMAMUX_Type *base)

Initializes the DMAMUX peripheral.

This function ungates the DMAMUX clock.

Parameters

- base – DMAMUX peripheral base address.

void DMAMUX_Deinit(DMAMUX_Type *base)

Deinitializes the DMAMUX peripheral.

This function gates the DMAMUX clock.

Parameters

- base – DMAMUX peripheral base address.

static inline void DMAMUX_EnableChannel(DMAMUX_Type *base, uint32_t channel)

Enables the DMAMUX channel.

This function enables the DMAMUX channel.

Parameters

- base – DMAMUX peripheral base address.
- channel – DMAMUX channel number.

static inline void DMAMUX_DisableChannel(DMAMUX_Type *base, uint32_t channel)

Disables the DMAMUX channel.

This function disables the DMAMUX channel.

Note: The user must disable the DMAMUX channel before configuring it.

Parameters

- base – DMAMUX peripheral base address.
- channel – DMAMUX channel number.

```
static inline void DMAMUX_SetSource(DMAMUX_Type *base, uint32_t channel, int32_t source)
```

Configures the DMAMUX channel source.

Parameters

- base – DMAMUX peripheral base address.
- channel – DMAMUX channel number.
- source – Channel source, which is used to trigger the DMA transfer. User need to use the `dma_request_source_t` type as the input parameter.

```
static inline void DMAMUX_EnablePeriodTrigger(DMAMUX_Type *base, uint32_t channel)
```

Enables the DMAMUX period trigger.

This function enables the DMAMUX period trigger feature.

Parameters

- base – DMAMUX peripheral base address.
- channel – DMAMUX channel number.

```
static inline void DMAMUX_DisablePeriodTrigger(DMAMUX_Type *base, uint32_t channel)
```

Disables the DMAMUX period trigger.

This function disables the DMAMUX period trigger.

Parameters

- base – DMAMUX peripheral base address.
- channel – DMAMUX channel number.

```
FSL_DMAMUX_DRIVER_VERSION
```

DMAMUX driver version 2.1.1.

2.6 eDMA: Enhanced Direct Memory Access (eDMA) Controller Driver

```
void EDMA_Init(DMA_Type *base, const edma_config_t *config)
```

Initializes the eDMA peripheral.

This function ungates the eDMA clock and configures the eDMA peripheral according to the configuration structure. All emda enabled request will be cleared in this function.

Note: This function enables the minor loop map feature.

Parameters

- base – eDMA peripheral base address.
- config – A pointer to the configuration structure, see “`edma_config_t`”.

void EDMA_Deinit(DMA_Type *base)

Deinitializes the eDMA peripheral.

This function gates the eDMA clock.

Parameters

- base – eDMA peripheral base address.

void EDMA_InstallTCD(DMA_Type *base, uint32_t channel, *edma_tcd_t* *tcd)

Push content of TCD structure into hardware TCD register.

Parameters

- base – EDMA peripheral base address.
- channel – EDMA channel number.
- tcd – Point to TCD structure.

void EDMA_GetDefaultConfig(*edma_config_t* *config)

Gets the eDMA default configuration structure.

This function sets the configuration structure to default values. The default configuration is set to the following values.

```
config.enableContinuousLinkMode = false;
config.enableHaltOnError = true;
config.enableRoundRobinArbitration = false;
config.enableDebugMode = false;
```

Parameters

- config – A pointer to the eDMA configuration structure.

static inline void EDMA_EnableContinuousChannelLinkMode(DMA_Type *base, bool enable)

Enable/Disable continuous channel link mode.

Note: Do not use continuous link mode with a channel linking to itself if there is only one minor loop iteration per service request, for example, if the channel's NBYTES value is the same as either the source or destination size. The same data transfer profile can be achieved by simply increasing the NBYTES value, which provides more efficient, faster processing.

Parameters

- base – EDMA peripheral base address.
- enable – true is enable, false is disable.

static inline void EDMA_EnableMinorLoopMapping(DMA_Type *base, bool enable)

Enable/Disable minor loop mapping.

The TCDn.word2 is redefined to include individual enable fields, an offset field, and the NBYTES field.

Parameters

- base – EDMA peripheral base address.
- enable – true is enable, false is disable.

void EDMA_ResetChannel(DMA_Type *base, uint32_t channel)

Sets all TCD registers to default values.

This function sets TCD registers for this channel to default values.

Note: This function must not be called while the channel transfer is ongoing or it causes unpredictable results.

Note: This function enables the auto stop request feature.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.

void EDMA_SetTransferConfig(DMA_Type *base, uint32_t channel, const *edma_transfer_config_t* *config, *edma_tcd_t* *nextTcd)

Configures the eDMA transfer attribute.

This function configures the transfer attribute, including source address, destination address, transfer size, address offset, and so on. It also configures the scatter gather feature if the user supplies the TCD address. Example:

```
edma_transfer_t config;
edma_tcd_t tcd;
config.srcAddr = ..;
config.destAddr = ..;
...
EDMA_SetTransferConfig(DMA0, channel, &config, &stcd);
```

Note: If nextTcd is not NULL, it means scatter gather feature is enabled and DREQ bit is cleared in the previous transfer configuration, which is set in the EDMA_ResetChannel.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- config – Pointer to eDMA transfer configuration structure.
- nextTcd – Point to TCD structure. It can be NULL if users do not want to enable scatter/gather feature.

void EDMA_SetMinorOffsetConfig(DMA_Type *base, uint32_t channel, const *edma_minor_offset_config_t* *config)

Configures the eDMA minor offset feature.

The minor offset means that the signed-extended value is added to the source address or destination address after each minor loop.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- config – A pointer to the minor offset configuration structure.

```
void EDMA__SetChannelPreemptionConfig(DMA_Type *base, uint32_t channel, const
                                     edma_channel_preemption_config_t *config)
```

Configures the eDMA channel preemption feature.

This function configures the channel preemption attribute and the priority of the channel.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number
- config – A pointer to the channel preemption configuration structure.

```
void EDMA__SetChannelLink(DMA_Type *base, uint32_t channel, edma_channel_link_type_t
                          linkType, uint32_t linkedChannel)
```

Sets the channel link for the eDMA transfer.

This function configures either the minor link or the major link mode. The minor link means that the channel link is triggered every time CITER decreases by 1. The major link means that the channel link is triggered when the CITER is exhausted.

Note: Users should ensure that DONE flag is cleared before calling this interface, or the configuration is invalid.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- linkType – A channel link type, which can be one of the following:
 - kEDMA_LinkNone
 - kEDMA_MinorLink
 - kEDMA_MajorLink
- linkedChannel – The linked channel number.

```
void EDMA__SetBandWidth(DMA_Type *base, uint32_t channel, edma_bandwidth_t bandWidth)
```

Sets the bandwidth for the eDMA transfer.

Because the eDMA processes the minor loop, it continuously generates read/write sequences until the minor count is exhausted. The bandwidth forces the eDMA to stall after the completion of each read/write access to control the bus request bandwidth seen by the crossbar switch.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- bandWidth – A bandwidth setting, which can be one of the following:
 - kEDMABandwidthStallNone
 - kEDMABandwidthStall4Cycle
 - kEDMABandwidthStall8Cycle

```
void EDMA__SetModulo(DMA_Type *base, uint32_t channel, edma_modulo_t srcModulo,
                    edma_modulo_t destModulo)
```

Sets the source modulo and the destination modulo for the eDMA transfer.

This function defines a specific address range specified to be the value after (SADDR + SOFF)/(DADDR + DOFF) calculation is performed or the original register value. It provides the ability to implement a circular data queue easily.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- srcModulo – A source modulo value.
- destModulo – A destination modulo value.

```
static inline void EDMA_EnableAsyncRequest(DMA_Type *base, uint32_t channel, bool enable)
```

Enables an async request for the eDMA transfer.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- enable – The command to enable (true) or disable (false).

```
static inline void EDMA_EnableAutoStopRequest(DMA_Type *base, uint32_t channel, bool enable)
```

Enables an auto stop request for the eDMA transfer.

If enabling the auto stop request, the eDMA hardware automatically disables the hardware channel request.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- enable – The command to enable (true) or disable (false).

```
void EDMA_EnableChannelInterrupts(DMA_Type *base, uint32_t channel, uint32_t mask)
```

Enables the interrupt source for the eDMA transfer.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- mask – The mask of interrupt source to be set. Users need to use the defined `edma_interrupt_enable_t` type.

```
void EDMA_DisableChannelInterrupts(DMA_Type *base, uint32_t channel, uint32_t mask)
```

Disables the interrupt source for the eDMA transfer.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.
- mask – The mask of the interrupt source to be set. Use the defined `edma_interrupt_enable_t` type.

```
void EDMA_SetMajorOffsetConfig(DMA_Type *base, uint32_t channel, int32_t sourceOffset,  
                               int32_t destOffset)
```

Configures the eDMA channel TCD major offset feature.

Adjustment value added to the source address at the completion of the major iteration count

Parameters

- `base` – eDMA peripheral base address.
- `channel` – edma channel number.
- `sourceOffset` – source address offset will be applied to source address after major loop done.
- `destOffset` – destination address offset will be applied to source address after major loop done.

```
void EDMA_TcdReset(edma_tcd_t *tcd)
```

Sets all fields to default values for the TCD structure.

This function sets all fields for this TCD structure to default value.

Note: This function enables the auto stop request feature.

Parameters

- `tcd` – Pointer to the TCD structure.

```
void EDMA_TcdSetTransferConfig(edma_tcd_t *tcd, const edma_transfer_config_t *config,  
                               edma_tcd_t *nextTcd)
```

Configures the eDMA TCD transfer attribute.

The TCD is a transfer control descriptor. The content of the TCD is the same as the hardware TCD registers. The TCD is used in the scatter-gather mode. This function configures the TCD transfer attribute, including source address, destination address, transfer size, address offset, and so on. It also configures the scatter gather feature if the user supplies the next TCD address. Example:

```
edma_transfer_t config = {  
    ...  
}  
edma_tcd_t tcd __aligned(32);  
edma_tcd_t nextTcd __aligned(32);  
EDMA_TcdSetTransferConfig(&tcd, &config, &nextTcd);
```

Note: TCD address should be 32 bytes aligned or it causes an eDMA error.

Note: If the `nextTcd` is not NULL, the scatter gather feature is enabled and DREQ bit is cleared in the previous transfer configuration, which is set in the `EDMA_TcdReset`.

Parameters

- `tcd` – Pointer to the TCD structure.
- `config` – Pointer to eDMA transfer configuration structure.
- `nextTcd` – Pointer to the next TCD structure. It can be NULL if users do not want to enable scatter/gather feature.

```
void EDMA__TcdSetMinorOffsetConfig(edma_tcd_t *tcd, const edma_minor_offset_config_t
                                   *config)
```

Configures the eDMA TCD minor offset feature.

A minor offset is a signed-extended value added to the source address or a destination address after each minor loop.

Parameters

- tcd – A point to the TCD structure.
- config – A pointer to the minor offset configuration structure.

```
void EDMA__TcdSetChannelLink(edma_tcd_t *tcd, edma_channel_link_type_t linkType, uint32_t
                             linkedChannel)
```

Sets the channel link for the eDMA TCD.

This function configures either a minor link or a major link. The minor link means the channel link is triggered every time CITER decreases by 1. The major link means that the channel link is triggered when the CITER is exhausted.

Note: Users should ensure that DONE flag is cleared before calling this interface, or the configuration is invalid.

Parameters

- tcd – Point to the TCD structure.
- linkType – Channel link type, it can be one of:
 - kEDMA_LinkNone
 - kEDMA_MinorLink
 - kEDMA_MajorLink
- linkedChannel – The linked channel number.

```
static inline void EDMA__TcdSetBandWidth(edma_tcd_t *tcd, edma_bandwidth_t bandWidth)
```

Sets the bandwidth for the eDMA TCD.

Because the eDMA processes the minor loop, it continuously generates read/write sequences until the minor count is exhausted. The bandwidth forces the eDMA to stall after the completion of each read/write access to control the bus request bandwidth seen by the crossbar switch.

Parameters

- tcd – A pointer to the TCD structure.
- bandWidth – A bandwidth setting, which can be one of the following:
 - kEDMABandwidthStallNone
 - kEDMABandwidthStall4Cycle
 - kEDMABandwidthStall8Cycle

```
void EDMA__TcdSetModulo(edma_tcd_t *tcd, edma_modulo_t srcModulo, edma_modulo_t
                       destModulo)
```

Sets the source modulo and the destination modulo for the eDMA TCD.

This function defines a specific address range specified to be the value after (SADDR + SOFF)/(DADDR + DOFF) calculation is performed or the original register value. It provides the ability to implement a circular data queue easily.

Parameters

- `tcd` – A pointer to the TCD structure.
- `srcModulo` – A source modulo value.
- `destModulo` – A destination modulo value.

static inline void EDMA__TcdEnableAutoStopRequest(*edma_tcd_t* *tcd, bool enable)

Sets the auto stop request for the eDMA TCD.

If enabling the auto stop request, the eDMA hardware automatically disables the hardware channel request.

Parameters

- `tcd` – A pointer to the TCD structure.
- `enable` – The command to enable (true) or disable (false).

void EDMA__TcdEnableInterrupts(*edma_tcd_t* *tcd, uint32_t mask)

Enables the interrupt source for the eDMA TCD.

Parameters

- `tcd` – Point to the TCD structure.
- `mask` – The mask of interrupt source to be set. Users need to use the defined `edma_interrupt_enable_t` type.

void EDMA__TcdDisableInterrupts(*edma_tcd_t* *tcd, uint32_t mask)

Disables the interrupt source for the eDMA TCD.

Parameters

- `tcd` – Point to the TCD structure.
- `mask` – The mask of interrupt source to be set. Users need to use the defined `edma_interrupt_enable_t` type.

void EDMA__TcdSetMajorOffsetConfig(*edma_tcd_t* *tcd, int32_t sourceOffset, int32_t destOffset)

Configures the eDMA TCD major offset feature.

Adjustment value added to the source address at the completion of the major iteration count

Parameters

- `tcd` – A point to the TCD structure.
- `sourceOffset` – source address offset will be applied to source address after major loop done.
- `destOffset` – destination address offset will be applied to source address after major loop done.

static inline void EDMA__EnableChannelRequest(DMA_Type *base, uint32_t channel)

Enables the eDMA hardware channel request.

This function enables the hardware channel request.

Parameters

- `base` – eDMA peripheral base address.
- `channel` – eDMA channel number.

static inline void EDMA__DisableChannelRequest(DMA_Type *base, uint32_t channel)

Disables the eDMA hardware channel request.

This function disables the hardware channel request.

Parameters

- `base` – eDMA peripheral base address.

- channel – eDMA channel number.

static inline void EDMA_TriggerChannelStart(DMA_Type *base, uint32_t channel)

Starts the eDMA transfer by using the software trigger.

This function starts a minor loop transfer.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.

uint32_t EDMA_GetRemainingMajorLoopCount(DMA_Type *base, uint32_t channel)

Gets the remaining major loop count from the eDMA current channel TCD.

This function checks the TCD (Task Control Descriptor) status for a specified eDMA channel and returns the number of major loop count that has not finished.

Note: 1. This function can only be used to get unfinished major loop count of transfer without the next TCD, or it might be inaccurate.

- a. The unfinished/remaining transfer bytes cannot be obtained directly from registers while the channel is running. Because to calculate the remaining bytes, the initial NBYTES configured in DMA_TCDn_NBYTES_MLNO register is needed while the eDMA IP does not support getting it while a channel is active. In another word, the NBYTES value reading is always the actual (decrementing) NBYTES value the dma_engine is working with while a channel is running. Consequently, to get the remaining transfer bytes, a software-saved initial value of NBYTES (for example copied before enabling the channel) is needed. The formula to calculate it is shown below: $\text{RemainingBytes} = \text{RemainingMajorLoopCount} * \text{NBYTES}(\text{initially configured})$
-

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.

Returns

Major loop count which has not been transferred yet for the current TCD.

static inline uint32_t EDMA_GetErrorStatusFlags(DMA_Type *base)

Gets the eDMA channel error status flags.

Parameters

- base – eDMA peripheral base address.

Returns

The mask of error status flags. Users need to use the `_edma_error_status_flags` type to decode the return variables.

uint32_t EDMA_GetChannelStatusFlags(DMA_Type *base, uint32_t channel)

Gets the eDMA channel status flags.

Parameters

- base – eDMA peripheral base address.
- channel – eDMA channel number.

Returns

The mask of channel status flags. Users need to use the `_edma_channel_status_flags` type to decode the return variables.

`void EDMA__ClearChannelStatusFlags(DMA_Type *base, uint32_t channel, uint32_t mask)`

Clears the eDMA channel status flags.

Parameters

- `base` – eDMA peripheral base address.
- `channel` – eDMA channel number.
- `mask` – The mask of channel status to be cleared. Users need to use the defined `_edma_channel_status_flags` type.

`void EDMA__CreateHandle(edma_handle_t *handle, DMA_Type *base, uint32_t channel)`

Creates the eDMA handle.

This function is called if using the transactional API for eDMA. This function initializes the internal state of the eDMA handle.

Parameters

- `handle` – eDMA handle pointer. The eDMA handle stores callback function and parameters.
- `base` – eDMA peripheral base address.
- `channel` – eDMA channel number.

`void EDMA__InstallTCDMemory(edma_handle_t *handle, edma_tcd_t *tcdPool, uint32_t tcdSize)`

Installs the TCDs memory pool into the eDMA handle.

This function is called after the `EDMA_CreateHandle` to use scatter/gather feature. This function shall only be used while users need to use scatter gather mode. Scatter gather mode enables EDMA to load a new transfer control block (tcd) in hardware, and automatically reconfigure that DMA channel for a new transfer. Users need to prepare tcd memory and also configure tcds using interface `EDMA_SubmitTransfer`.

Parameters

- `handle` – eDMA handle pointer.
- `tcdPool` – A memory pool to store TCDs. It must be 32 bytes aligned.
- `tcdSize` – The number of TCD slots.

`void EDMA__SetCallback(edma_handle_t *handle, edma_callback callback, void *userData)`

Installs a callback function for the eDMA transfer.

This callback is called in the eDMA IRQ handler. Use the callback to do something after the current major loop transfer completes. This function will be called every time one tcd finished transfer.

Parameters

- `handle` – eDMA handle pointer.
- `callback` – eDMA callback function pointer.
- `userData` – A parameter for the callback function.

`void EDMA__PrepareTransferConfig(edma_transfer_config_t *config, void *srcAddr, uint32_t srcWidth, int16_t srcOffset, void *destAddr, uint32_t destWidth, int16_t destOffset, uint32_t bytesEachRequest, uint32_t transferBytes)`

Prepares the eDMA transfer structure configurations.

This function prepares the transfer configuration structure according to the user input.

Note: The data address and the data width must be consistent. For example, if the SRC is 4 bytes, the source address must be 4 bytes aligned, or it results in source address error (SAE).

Parameters

- `config` – The user configuration structure of type `edma_transfer_t`.
- `srcAddr` – eDMA transfer source address.
- `srcWidth` – eDMA transfer source address width(bytes).
- `srcOffset` – source address offset.
- `destAddr` – eDMA transfer destination address.
- `destWidth` – eDMA transfer destination address width(bytes).
- `destOffset` – destination address offset.
- `bytesEachRequest` – eDMA transfer bytes per channel request.
- `transferBytes` – eDMA transfer bytes to be transferred.

```
void EDMA__PrepareTransfer(edma_transfer_config_t *config, void *srcAddr, uint32_t srcWidth,
                          void *destAddr, uint32_t destWidth, uint32_t bytesEachRequest,
                          uint32_t transferBytes, edma_transfer_type_t transferType)
```

Prepares the eDMA transfer structure.

This function prepares the transfer configuration structure according to the user input.

Note: The data address and the data width must be consistent. For example, if the SRC is 4 bytes, the source address must be 4 bytes aligned, or it results in source address error (SAE).

Parameters

- `config` – The user configuration structure of type `edma_transfer_t`.
- `srcAddr` – eDMA transfer source address.
- `srcWidth` – eDMA transfer source address width(bytes).
- `destAddr` – eDMA transfer destination address.
- `destWidth` – eDMA transfer destination address width(bytes).
- `bytesEachRequest` – eDMA transfer bytes per channel request.
- `transferBytes` – eDMA transfer bytes to be transferred.
- `transferType` – eDMA transfer type.

```
status_t EDMA__SubmitTransfer(edma_handle_t *handle, const edma_transfer_config_t *config)
```

Submits the eDMA transfer request.

This function submits the eDMA transfer request according to the transfer configuration structure. In scatter gather mode, call this function will add a configured tcd to the circular list of tcd pool. The tcd pools is setup by call function `EDMA_InstallTCDMemory` before.

Parameters

- `handle` – eDMA handle pointer.
- `config` – Pointer to eDMA transfer configuration structure.

Return values

- `kStatus_EDMA_Success` – It means submit transfer request succeed.
- `kStatus_EDMA_QueueFull` – It means TCD queue is full. Submit transfer request is not allowed.
- `kStatus_EDMA_Busy` – It means the given channel is busy, need to submit request later.

`void EDMA_StartTransfer(edma_handle_t *handle)`

eDMA starts transfer.

This function enables the channel request. Users can call this function after submitting the transfer request or before submitting the transfer request.

Parameters

- `handle` – eDMA handle pointer.

`void EDMA_StopTransfer(edma_handle_t *handle)`

eDMA stops transfer.

This function disables the channel request to pause the transfer. Users can call `EDMA_StartTransfer()` again to resume the transfer.

Parameters

- `handle` – eDMA handle pointer.

`void EDMA_AbortTransfer(edma_handle_t *handle)`

eDMA aborts transfer.

This function disables the channel request and clear transfer status bits. Users can submit another transfer after calling this API.

Parameters

- `handle` – DMA handle pointer.

`static inline uint32_t EDMA_GetUnusedTCDNumber(edma_handle_t *handle)`

Get unused TCD slot number.

This function gets current tcd index which is run. If the TCD pool pointer is NULL, it will return 0.

Parameters

- `handle` – DMA handle pointer.

Returns

The unused tcd slot number.

`static inline uint32_t EDMA_GetNextTCDAddress(edma_handle_t *handle)`

Get the next tcd address.

This function gets the next tcd address. If this is last TCD, return 0.

Parameters

- `handle` – DMA handle pointer.

Returns

The next TCD address.

`void EDMA_HandleIRQ(edma_handle_t *handle)`

eDMA IRQ handler for the current major loop transfer completion.

This function clears the channel major interrupt flag and calls the callback function if it is not NULL.

Note: For the case using TCD queue, when the major iteration count is exhausted, additional operations are performed. These include the final address adjustments and reloading of the BITER field into the CITER. Assertion of an optional interrupt request also occurs at this time, as does a possible fetch of a new TCD from memory using the scatter/gather address pointer included in the descriptor (if scatter/gather is enabled).

For instance, when the time interrupt of TCD[0] happens, the TCD[1] has already been loaded into the eDMA engine. As sga and sga_index are calculated based on the DLAST_SGA bitfield lies in the TCD_CSR register, the sga_index in this case should be 2 (DLAST_SGA of TCD[1] stores the address of TCD[2]). Thus, the “tcdUsed” updated should be (tcdUsed - 2U) which indicates the number of TCDs can be loaded in the memory pool (because TCD[0] and TCD[1] have been loaded into the eDMA engine at this point already.).

For the last two continuous ISRs in a scatter/gather process, they both load the last TCD (The last ISR does not load a new TCD) from the memory pool to the eDMA engine when major loop completes. Therefore, ensure that the header and tcdUsed updated are identical for them. tcdUsed are both 0 in this case as no TCD to be loaded.

See the “eDMA basic data flow” in the eDMA Functional description section of the Reference Manual for further details.

Parameters

- handle – eDMA handle pointer.

FSL_EDMA_DRIVER_VERSION

eDMA driver version

Version 2.4.5.

enum _edma_transfer_size

eDMA transfer configuration

Values:

enumerator kEDMA_TransferSize1Bytes

Source/Destination data transfer size is 1 byte every time

enumerator kEDMA_TransferSize2Bytes

Source/Destination data transfer size is 2 bytes every time

enumerator kEDMA_TransferSize4Bytes

Source/Destination data transfer size is 4 bytes every time

enumerator kEDMA_TransferSize8Bytes

Source/Destination data transfer size is 8 bytes every time

enumerator kEDMA_TransferSize16Bytes

Source/Destination data transfer size is 16 bytes every time

enumerator kEDMA_TransferSize32Bytes

Source/Destination data transfer size is 32 bytes every time

enum _edma_modulo

eDMA modulo configuration

Values:

enumerator kEDMA_ModuloDisable

Disable modulo

enumerator kEDMA_Modulo2bytes

Circular buffer size is 2 bytes.

enumerator kEDMA_Modulo4bytes
Circular buffer size is 4 bytes.

enumerator kEDMA_Modulo8bytes
Circular buffer size is 8 bytes.

enumerator kEDMA_Modulo16bytes
Circular buffer size is 16 bytes.

enumerator kEDMA_Modulo32bytes
Circular buffer size is 32 bytes.

enumerator kEDMA_Modulo64bytes
Circular buffer size is 64 bytes.

enumerator kEDMA_Modulo128bytes
Circular buffer size is 128 bytes.

enumerator kEDMA_Modulo256bytes
Circular buffer size is 256 bytes.

enumerator kEDMA_Modulo512bytes
Circular buffer size is 512 bytes.

enumerator kEDMA_Modulo1Kbytes
Circular buffer size is 1 K bytes.

enumerator kEDMA_Modulo2Kbytes
Circular buffer size is 2 K bytes.

enumerator kEDMA_Modulo4Kbytes
Circular buffer size is 4 K bytes.

enumerator kEDMA_Modulo8Kbytes
Circular buffer size is 8 K bytes.

enumerator kEDMA_Modulo16Kbytes
Circular buffer size is 16 K bytes.

enumerator kEDMA_Modulo32Kbytes
Circular buffer size is 32 K bytes.

enumerator kEDMA_Modulo64Kbytes
Circular buffer size is 64 K bytes.

enumerator kEDMA_Modulo128Kbytes
Circular buffer size is 128 K bytes.

enumerator kEDMA_Modulo256Kbytes
Circular buffer size is 256 K bytes.

enumerator kEDMA_Modulo512Kbytes
Circular buffer size is 512 K bytes.

enumerator kEDMA_Modulo1Mbytes
Circular buffer size is 1 M bytes.

enumerator kEDMA_Modulo2Mbytes
Circular buffer size is 2 M bytes.

enumerator kEDMA_Modulo4Mbytes
Circular buffer size is 4 M bytes.

enumerator kEDMA_Modulo8Mbytes

Circular buffer size is 8 M bytes.

enumerator kEDMA_Modulo16Mbytes

Circular buffer size is 16 M bytes.

enumerator kEDMA_Modulo32Mbytes

Circular buffer size is 32 M bytes.

enumerator kEDMA_Modulo64Mbytes

Circular buffer size is 64 M bytes.

enumerator kEDMA_Modulo128Mbytes

Circular buffer size is 128 M bytes.

enumerator kEDMA_Modulo256Mbytes

Circular buffer size is 256 M bytes.

enumerator kEDMA_Modulo512Mbytes

Circular buffer size is 512 M bytes.

enumerator kEDMA_Modulo1Gbytes

Circular buffer size is 1 G bytes.

enumerator kEDMA_Modulo2Gbytes

Circular buffer size is 2 G bytes.

enum _edma_bandwidth

Bandwidth control.

Values:

enumerator kEDMA_BandwidthStallNone

No eDMA engine stalls.

enumerator kEDMA_BandwidthStall4Cycle

eDMA engine stalls for 4 cycles after each read/write.

enumerator kEDMA_BandwidthStall8Cycle

eDMA engine stalls for 8 cycles after each read/write.

enum _edma_channel_link_type

Channel link type.

Values:

enumerator kEDMA_LinkNone

No channel link

enumerator kEDMA_MinorLink

Channel link after each minor loop

enumerator kEDMA_MajorLink

Channel link while major loop count exhausted

_edma_channel_status_flags eDMA channel status flags.

Values:

enumerator kEDMA_DoneFlag

DONE flag, set while transfer finished, CITER value exhausted

enumerator kEDMA_ErrorFlag

eDMA error flag, an error occurred in a transfer

enumerator kEDMA_InterruptFlag

eDMA interrupt flag, set while an interrupt occurred of this channel

_edma_error_status_flags eDMA channel error status flags.

Values:

enumerator kEDMA_DestinationBusErrorFlag

Bus error on destination address

enumerator kEDMA_SourceBusErrorFlag

Bus error on the source address

enumerator kEDMA_ScatterGatherErrorFlag

Error on the Scatter/Gather address, not 32byte aligned.

enumerator kEDMA_NbytesErrorFlag

NBYTES/CITER configuration error

enumerator kEDMA_DestinationOffsetErrorFlag

Destination offset not aligned with destination size

enumerator kEDMA_DestinationAddressErrorFlag

Destination address not aligned with destination size

enumerator kEDMA_SourceOffsetErrorFlag

Source offset not aligned with source size

enumerator kEDMA_SourceAddressErrorFlag

Source address not aligned with source size

enumerator kEDMA_ErrorChannelFlag

Error channel number of the cancelled channel number

enumerator kEDMA_ChannelPriorityErrorFlag

Channel priority is not unique.

enumerator kEDMA_TransferCanceledFlag

Transfer cancelled

enumerator kEDMA_ValidFlag

No error occurred, this bit is 0. Otherwise, it is 1.

enum _edma_interrupt_enable

eDMA interrupt source

Values:

enumerator kEDMA_ErrorInterruptEnable

Enable interrupt while channel error occurs.

enumerator kEDMA_MajorInterruptEnable

Enable interrupt while major count exhausted.

enumerator kEDMA_HalfInterruptEnable

Enable interrupt while major count to half value.

enum _edma_transfer_type

eDMA transfer type

Values:

enumerator kEDMA_MemoryToMemory

Transfer from memory to memory

enumerator kEDMA_PeripheralToMemory

Transfer from peripheral to memory

enumerator kEDMA_MemoryToPeripheral

Transfer from memory to peripheral

enumerator kEDMA_PeripheralToPeripheral

Transfer from Peripheral to peripheral

_edma_transfer_status eDMA transfer status

Values:

enumerator kStatus_EDMA_QueueFull

TCD queue is full.

enumerator kStatus_EDMA_Busy

Channel is busy and can't handle the transfer request.

typedef enum _edma_transfer_size edma_transfer_size_t

eDMA transfer configuration

typedef enum _edma_modulo edma_modulo_t

eDMA modulo configuration

typedef enum _edma_bandwidth edma_bandwidth_t

Bandwidth control.

typedef enum _edma_channel_link_type edma_channel_link_type_t

Channel link type.

typedef enum _edma_interrupt_enable edma_interrupt_enable_t

eDMA interrupt source

typedef enum _edma_transfer_type edma_transfer_type_t

eDMA transfer type

typedef struct _edma_config edma_config_t

eDMA global configuration structure.

typedef struct _edma_transfer_config edma_transfer_config_t

eDMA transfer configuration

This structure configures the source/destination transfer attribute.

typedef struct _edma_channel_Preemption_config edma_channel_Preemption_config_t

eDMA channel priority configuration

typedef struct _edma_minor_offset_config edma_minor_offset_config_t

eDMA minor offset configuration

typedef struct _edma_tcd edma_tcd_t

eDMA TCD.

This structure is same as TCD register which is described in reference manual, and is used to configure the scatter/gather feature as a next hardware TCD.


```
typedef void (*edma_callback)(struct _edma_handle *handle, void *userData, bool transferDone,
uint32_t tcds)
```

Define callback function for eDMA.

This callback function is called in the EDMA interrupt handle. In normal mode, run into callback function means the transfer users need is done. In scatter gather mode, run into callback function means a transfer control block (tcd) is finished. Not all transfer finished, users can get the finished tcd numbers using interface EDMA_GetUnusedTCDNumber.

Param handle

EDMA handle pointer, users shall not touch the values inside.

Param userData

The callback user parameter pointer. Users can use this parameter to involve things users need to change in EDMA callback function.

Param transferDone

If the current loaded transfer done. In normal mode it means if all transfer done. In scatter gather mode, this parameter shows is the current transfer block in EDMA register is done. As the load of core is different, it will be different if the new tcd loaded into EDMA registers while this callback called. If true, it always means new tcd still not loaded into registers, while false means new tcd already loaded into registers.

Param tcds

How many tcds are done from the last callback. This parameter only used in scatter gather mode. It tells user how many tcds are finished between the last callback and this.

```
typedef struct _edma_handle edma_handle_t
```

eDMA transfer handle structure

```
DMA_DCHPRI_INDEX(channel)
```

Compute the offset unit from DCHPRI3.

```
struct _edma_config
```

#include <fsl_edma.h> eDMA global configuration structure.

Public Members

bool enableContinuousLinkMode

Enable (true) continuous link mode. Upon minor loop completion, the channel activates again if that channel has a minor loop channel link enabled and the link channel is itself.

bool enableHaltOnError

Enable (true) transfer halt on error. Any error causes the HALT bit to set. Subsequently, all service requests are ignored until the HALT bit is cleared.

bool enableRoundRobinArbitration

Enable (true) round robin channel arbitration method or fixed priority arbitration is used for channel selection

bool enableDebugMode

Enable(true) eDMA debug mode. When in debug mode, the eDMA stalls the start of a new channel. Executing channels are allowed to complete.

```
struct _edma_transfer_config
```

#include <fsl_edma.h> eDMA transfer configuration

This structure configures the source/destination transfer attribute.

Public Members

uint32_t srcAddr

Source data address.

uint32_t destAddr

Destination data address.

edma_transfer_size_t srcTransferSize

Source data transfer size.

edma_transfer_size_t destTransferSize

Destination data transfer size.

int16_t srcOffset

Sign-extended offset applied to the current source address to form the next-state value as each source read is completed.

int16_t destOffset

Sign-extended offset applied to the current destination address to form the next-state value as each destination write is completed.

uint32_t minorLoopBytes

Bytes to transfer in a minor loop

uint32_t majorLoopCounts

Major loop iteration count.

struct _edma_channel_Preemption_config

#include <fsl_edma.h> eDMA channel priority configuration

Public Members

bool enableChannelPreemption

If true: a channel can be suspended by other channel with higher priority

bool enablePreemptAbility

If true: a channel can suspend other channel with low priority

uint8_t channelPriority

Channel priority

struct _edma_minor_offset_config

#include <fsl_edma.h> eDMA minor offset configuration

Public Members

bool enableSrcMinorOffset

Enable(true) or Disable(false) source minor loop offset.

bool enableDestMinorOffset

Enable(true) or Disable(false) destination minor loop offset.

uint32_t minorOffset

Offset for a minor loop mapping.

struct _edma_tcd

#include <fsl_edma.h> eDMA TCD.

This structure is same as TCD register which is described in reference manual, and is used to configure the scatter/gather feature as a next hardware TCD.

Public Members

__IO uint32_t SADDR
SADDR register, used to save source address

__IO uint16_t SOFF
SOFF register, save offset bytes every transfer

__IO uint16_t ATTR
ATTR register, source/destination transfer size and modulo

__IO uint32_t NBYTES
Nbytes register, minor loop length in bytes

__IO uint32_t SLAST
SLAST register

__IO uint32_t DADDR
DADDR register, used for destination address

__IO uint16_t DOFF
DOFF register, used for destination offset

__IO uint16_t CITER
CITER register, current minor loop numbers, for unfinished minor loop.

__IO uint32_t DLAST_SGA
DLASTSGA register, next tcd address used in scatter-gather mode

__IO uint16_t CSR
CSR register, for TCD control status

__IO uint16_t BITER
BITER register, begin minor loop count.

struct __edma_handle
#include <fsl_edma.h> eDMA transfer handle structure

Public Members

edma_callback callback
Callback function for major count exhausted.

void *userData
Callback function parameter.

DMA_Type *base
eDMA peripheral base address.

edma_tcd_t *tcdPool
Pointer to memory stored TCDs.

uint8_t channel
eDMA channel number.

volatile int8_t header
The first TCD index. Should point to the next TCD to be loaded into the eDMA engine.

volatile int8_t tail
The last TCD index. Should point to the next TCD to be stored into the memory pool.

volatile int8_t tcdUsed

The number of used TCD slots. Should reflect the number of TCDs can be used/loaded in the memory.

volatile int8_t tcdSize

The total number of TCD slots in the queue.

uint8_t flags

The status of the current channel.

2.7 EWM: External Watchdog Monitor Driver

void EWM_Init(EWM_Type *base, const ewm_config_t *config)

Initializes the EWM peripheral.

This function is used to initialize the EWM. After calling, the EWM runs immediately according to the configuration. Note that, except for the interrupt enable control bit, other control bits and registers are write once after a CPU reset. Modifying them more than once generates a bus transfer error.

This is an example.

```
ewm_config_t config;
EWM_GetDefaultConfig(&config);
config.compareHighValue = 0xAAU;
EWM_Init(ewm_base,&config);
```

Parameters

- base – EWM peripheral base address
- config – The configuration of the EWM

void EWM_Deinit(EWM_Type *base)

Deinitializes the EWM peripheral.

This function is used to shut down the EWM.

Parameters

- base – EWM peripheral base address

void EWM_GetDefaultConfig(ewm_config_t *config)

Initializes the EWM configuration structure.

This function initializes the EWM configuration structure to default values. The default values are as follows.

```
ewmConfig->enableEwm = true;
ewmConfig->enableEwmInput = false;
ewmConfig->setInputAssertLogic = false;
ewmConfig->enableInterrupt = false;
ewmConfig->ewm_lpo_clock_source_t = kEWM_LpoClockSource0;
ewmConfig->prescaler = 0;
ewmConfig->compareLowValue = 0;
ewmConfig->compareHighValue = 0xFEU;
```

See also:

ewm_config_t

Parameters

- `config` – Pointer to the EWM configuration structure.

`static inline void EWM_EnableInterrupts(EWM_Type *base, uint32_t mask)`

Enables the EWM interrupt.

This function enables the EWM interrupt.

Parameters

- `base` – EWM peripheral base address
- `mask` – The interrupts to enable The parameter can be combination of the following source if defined
 - `kEWM_InterruptEnable`

`static inline void EWM_DisableInterrupts(EWM_Type *base, uint32_t mask)`

Disables the EWM interrupt.

This function enables the EWM interrupt.

Parameters

- `base` – EWM peripheral base address
- `mask` – The interrupts to disable The parameter can be combination of the following source if defined
 - `kEWM_InterruptEnable`

`static inline uint32_t EWM_GetStatusFlags(EWM_Type *base)`

Gets all status flags.

This function gets all status flags.

This is an example for getting the running flag.

```
uint32_t status;  
status = EWM_GetStatusFlags(ewm_base) & kEWM_RunningFlag;
```

See also:

`_ewm_status_flags_t`

- True: a related status flag has been set.
- False: a related status flag is not set.

Parameters

- `base` – EWM peripheral base address

Returns

State of the status flag: asserted (true) or not-asserted (false).

`void EWM_Refresh(EWM_Type *base)`

Services the EWM.

This function resets the EWM counter to zero.

Parameters

- `base` – EWM peripheral base address

`FSL_EWM_DRIVER_VERSION`

EWM driver version 2.0.4.

enum `_ewm_lpo_clock_source`

Describes EWM clock source.

Values:

enumerator `kEWM_LpoClockSource0`

EWM clock sourced from `lpo_clk[0]`

enumerator `kEWM_LpoClockSource1`

EWM clock sourced from `lpo_clk[1]`

enumerator `kEWM_LpoClockSource2`

EWM clock sourced from `lpo_clk[2]`

enumerator `kEWM_LpoClockSource3`

EWM clock sourced from `lpo_clk[3]`

enum `_ewm_interrupt_enable_t`

EWM interrupt configuration structure with default settings all disabled.

This structure contains the settings for all of EWM interrupt configurations.

Values:

enumerator `kEWM_InterruptEnable`

Enable the EWM to generate an interrupt

enum `_ewm_status_flags_t`

EWM status flags.

This structure contains the constants for the EWM status flags for use in the EWM functions.

Values:

enumerator `kEWM_RunningFlag`

Running flag, set when EWM is enabled

typedef enum `_ewm_lpo_clock_source` `ewm_lpo_clock_source_t`

Describes EWM clock source.

typedef struct `_ewm_config` `ewm_config_t`

Data structure for EWM configuration.

This structure is used to configure the EWM.

struct `_ewm_config`

#include <fsl_ewm.h> Data structure for EWM configuration.

This structure is used to configure the EWM.

Public Members

bool `enableEwm`

Enable EWM module

bool `enableEwmInput`

Enable EWM_in input

bool `setInputAssertLogic`

EWM_in signal assertion state

bool `enableInterrupt`

Enable EWM interrupt

ewm_lpo_clock_source_t clockSource
Clock source select
uint8_t prescaler
Clock prescaler value
uint8_t compareLowValue
Compare low-register value
uint8_t compareHighValue
Compare high-register value

2.8 FGPIO Driver

`void FGPIO_PinInit(FGPIO_Type *base, uint32_t pin, const gpio_pin_config_t *config)`

Initializes a FGPIO pin used by the board.

To initialize the FGPIO driver, define a pin configuration, as either input or output, in the user file. Then, call the `FGPIO_PinInit()` function.

This is an example to define an input pin or an output pin configuration:

```
Define a digital input pin configuration,
gpio_pin_config_t config =
{
    kGPIO_DigitalInput,
    0,
}
Define a digital output pin configuration,
gpio_pin_config_t config =
{
    kGPIO_DigitalOutput,
    0,
}
```

Parameters

- *base* – FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
- *pin* – FGPIO port pin number
- *config* – FGPIO pin configuration pointer

`static inline void FGPIO_PinWrite(FGPIO_Type *base, uint32_t pin, uint8_t output)`

Sets the output level of the multiple FGPIO pins to the logic 1 or 0.

Parameters

- *base* – FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
- *pin* – FGPIO pin number
- *output* – FGPIOpin output logic level.
 - 0: corresponding pin output low-logic level.
 - 1: corresponding pin output high-logic level.

static inline void FGPIO_PortSet(FGPIO_Type *base, uint32_t mask)

Sets the output level of the multiple FGPIO pins to the logic 1.

Parameters

- base – FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
- mask – FGPIO pin number macro

static inline void FGPIO_PortClear(FGPIO_Type *base, uint32_t mask)

Sets the output level of the multiple FGPIO pins to the logic 0.

Parameters

- base – FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
- mask – FGPIO pin number macro

static inline void FGPIO_PortToggle(FGPIO_Type *base, uint32_t mask)

Reverses the current output logic of the multiple FGPIO pins.

Parameters

- base – FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
- mask – FGPIO pin number macro

static inline uint32_t FGPIO_PinRead(FGPIO_Type *base, uint32_t pin)

Reads the current input value of the FGPIO port.

Parameters

- base – FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
- pin – FGPIO pin number

Return values

FGPIO – port input value

- 0: corresponding pin input low-logic level.
- 1: corresponding pin input high-logic level.

uint32_t FGPIO_PortGetInterruptFlags(FGPIO_Type *base)

Reads the FGPIO port interrupt status flag.

If a pin is configured to generate the DMA request, the corresponding flag is cleared automatically at the completion of the requested DMA transfer. Otherwise, the flag remains set until a logic one is written to that flag. If configured for a level-sensitive interrupt that remains asserted, the flag is set again immediately.

Parameters

- base – FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)

Return values

The – current FGPIO port interrupt status flags, for example, 0x00010001 means the pin 0 and 17 have the interrupt.

void FGPIO_PortClearInterruptFlags(FGPIO_Type *base, uint32_t mask)

Clears the multiple FGPIO pin interrupt status flag.

Parameters

- base – FGPIO peripheral base pointer (FGPIOA, FGPIOB, FGPIOC, and so on.)
- mask – FGPIO pin number macro

2.9 C90TFS Flash Driver

2.10 FlexIO: FlexIO Driver

2.11 FlexIO Driver

void FLEXIO_GetDefaultConfig(*flexio_config_t* *userConfig)

Gets the default configuration to configure the FlexIO module. The configuration can be used directly to call the FLEXIO_Configure().

Example:

```
flexio_config_t config;
FLEXIO_GetDefaultConfig(&config);
```

Parameters

- userConfig – pointer to flexio_config_t structure

void FLEXIO_Init(FLEXIO_Type *base, const *flexio_config_t* *userConfig)

Configures the FlexIO with a FlexIO configuration. The configuration structure can be filled by the user or be set with default values by FLEXIO_GetDefaultConfig().

Example

```
flexio_config_t config = {
    .enableFlexio = true,
    .enableInDoze = false,
    .enableInDebug = true,
    .enableFastAccess = false
};
FLEXIO_Configure(base, &config);
```

Parameters

- base – FlexIO peripheral base address
- userConfig – pointer to flexio_config_t structure

void FLEXIO_Deinit(FLEXIO_Type *base)

Gates the FlexIO clock. Call this API to stop the FlexIO clock.

Note: After calling this API, call the FLEXIO_Init to use the FlexIO module.

Parameters

- base – FlexIO peripheral base address

uint32_t FLEXIO_GetInstance(FLEXIO_Type *base)

Get instance number for FLEXIO module.

Parameters

- base – FLEXIO peripheral base address.

void FLEXIO_Reset(FLEXIO_Type *base)

Resets the FlexIO module.

Parameters

- base – FlexIO peripheral base address

static inline void FLEXIO_Enable(FLEXIO_Type *base, bool enable)

Enables the FlexIO module operation.

Parameters

- base – FlexIO peripheral base address
- enable – true to enable, false to disable.

static inline uint32_t FLEXIO_ReadPinInput(FLEXIO_Type *base)

Reads the input data on each of the FlexIO pins.

Parameters

- base – FlexIO peripheral base address

Returns

FlexIO pin input data

static inline uint8_t FLEXIO_GetShifterState(FLEXIO_Type *base)

Gets the current state pointer for state mode use.

Parameters

- base – FlexIO peripheral base address

Returns

current State pointer

void FLEXIO_SetShifterConfig(FLEXIO_Type *base, uint8_t index, const *flexio_shifter_config_t* *shifterConfig)

Configures the shifter with the shifter configuration. The configuration structure covers both the SHIFTCTL and SHIFTCFG registers. To configure the shifter to the proper mode, select which timer controls the shifter to shift, whether to generate start bit/stop bit, and the polarity of start bit and stop bit.

Example

```
flexio_shifter_config_t config = {
    .timerSelect = 0,
    .timerPolarity = kFLEXIO_ShifterTimerPolarityOnPositive,
    .pinConfig = kFLEXIO_PinConfigOpenDrainOrBidirection,
    .pinPolarity = kFLEXIO_PinActiveLow,
    .shifterMode = kFLEXIO_ShifterModeTransmit,
    .inputSource = kFLEXIO_ShifterInputFromPin,
    .shifterStop = kFLEXIO_ShifterStopBitHigh,
    .shifterStart = kFLEXIO_ShifterStartBitLow
};
FLEXIO_SetShifterConfig(base, &config);
```

Parameters

- base – FlexIO peripheral base address
- index – Shifter index
- shifterConfig – Pointer to flexio_shifter_config_t structure

```
void FLEXIO_SetTimerConfig(FLEXIO_Type *base, uint8_t index, const flexio_timer_config_t *timerConfig)
```

Configures the timer with the timer configuration. The configuration structure covers both the TIMCTL and TIMCFG registers. To configure the timer to the proper mode, select trigger source for timer and the timer pin output and the timing for timer.

Example

```
flexio_timer_config_t config = {  
    .triggerSelect = FLEXIO_TIMER_TRIGGER_SEL_SHIFTnSTAT(0),  
    .triggerPolarity = kFLEXIO_TimerTriggerPolarityActiveLow,  
    .triggerSource = kFLEXIO_TimerTriggerSourceInternal,  
    .pinConfig = kFLEXIO_PinConfigOpenDrainOrBidirection,  
    .pinSelect = 0,  
    .pinPolarity = kFLEXIO_PinActiveHigh,  
    .timerMode = kFLEXIO_TimerModeDual8BitBaudBit,  
    .timerOutput = kFLEXIO_TimerOutputZeroNotAffectedByReset,  
    .timerDecrement = kFLEXIO_TimerDecSrcOnFlexIOClockShiftTimerOutput,  
    .timerReset = kFLEXIO_TimerResetOnTimerPinEqualToTimerOutput,  
    .timerDisable = kFLEXIO_TimerDisableOnTimerCompare,  
    .timerEnable = kFLEXIO_TimerEnableOnTriggerHigh,  
    .timerStop = kFLEXIO_TimerStopBitEnableOnTimerDisable,  
    .timerStart = kFLEXIO_TimerStartBitEnabled  
};  
FLEXIO_SetTimerConfig(base, &config);
```

Parameters

- base – FlexIO peripheral base address
- index – Timer index
- timerConfig – Pointer to the flexio_timer_config_t structure

```
static inline void FLEXIO_SetClockMode(FLEXIO_Type *base, uint8_t index,  
                                       flexio_timer_decrement_source_t clocksource)
```

This function set the value of the prescaler on flexio channels.

Parameters

- base – Pointer to the FlexIO simulated peripheral type.
- index – Timer index
- clocksource – Set clock value

```
static inline void FLEXIO_EnableShifterStatusInterrupts(FLEXIO_Type *base, uint32_t mask)
```

Enables the shifter status interrupt. The interrupt generates when the corresponding SSF is set.

Note: For multiple shifter status interrupt enable, for example, two shifter status enable, can calculate the mask by using ((1 « shifter index0) | (1 « shifter index1))

Parameters

- base – FlexIO peripheral base address
- mask – The shifter status mask which can be calculated by (1 « shifter index)

```
static inline void FLEXIO_DisableShifterStatusInterrupts(FLEXIO_Type *base, uint32_t mask)
```

Disables the shifter status interrupt. The interrupt won't generate when the corresponding SSF is set.

Note: For multiple shifter status interrupt enable, for example, two shifter status enable, can calculate the mask by using $((1 \ll \text{shifter index0}) | (1 \ll \text{shifter index1}))$

Parameters

- base – FlexIO peripheral base address
- mask – The shifter status mask which can be calculated by $(1 \ll \text{shifter index})$

static inline void FLEXIO_EnableShifterErrorInterrupts(FLEXIO_Type *base, uint32_t mask)
Enables the shifter error interrupt. The interrupt generates when the corresponding SEF is set.

Note: For multiple shifter error interrupt enable, for example, two shifter error enable, can calculate the mask by using $((1 \ll \text{shifter index0}) | (1 \ll \text{shifter index1}))$

Parameters

- base – FlexIO peripheral base address
- mask – The shifter error mask which can be calculated by $(1 \ll \text{shifter index})$

static inline void FLEXIO_DisableShifterErrorInterrupts(FLEXIO_Type *base, uint32_t mask)
Disables the shifter error interrupt. The interrupt won't generate when the corresponding SEF is set.

Note: For multiple shifter error interrupt enable, for example, two shifter error enable, can calculate the mask by using $((1 \ll \text{shifter index0}) | (1 \ll \text{shifter index1}))$

Parameters

- base – FlexIO peripheral base address
- mask – The shifter error mask which can be calculated by $(1 \ll \text{shifter index})$

static inline void FLEXIO_EnableTimerStatusInterrupts(FLEXIO_Type *base, uint32_t mask)
Enables the timer status interrupt. The interrupt generates when the corresponding SSF is set.

Note: For multiple timer status interrupt enable, for example, two timer status enable, can calculate the mask by using $((1 \ll \text{timer index0}) | (1 \ll \text{timer index1}))$

Parameters

- base – FlexIO peripheral base address
- mask – The timer status mask which can be calculated by $(1 \ll \text{timer index})$

static inline void FLEXIO_DisableTimerStatusInterrupts(FLEXIO_Type *base, uint32_t mask)
Disables the timer status interrupt. The interrupt won't generate when the corresponding SSF is set.

Note: For multiple timer status interrupt enable, for example, two timer status enable, can calculate the mask by using $((1 \ll \text{timer index0}) | (1 \ll \text{timer index1}))$

Parameters

- base – FlexIO peripheral base address
- mask – The timer status mask which can be calculated by $(1 \ll \text{timer index})$

static inline uint32_t FLEXIO_GetShifterStatusFlags(FLEXIO_Type *base)

Gets the shifter status flags.

Parameters

- base – FlexIO peripheral base address

Returns

Shifter status flags

static inline void FLEXIO_ClearShifterStatusFlags(FLEXIO_Type *base, uint32_t mask)

Clears the shifter status flags.

Note: For clearing multiple shifter status flags, for example, two shifter status flags, can calculate the mask by using $((1 \ll \text{shifter index0}) | (1 \ll \text{shifter index1}))$

Parameters

- base – FlexIO peripheral base address
- mask – The shifter status mask which can be calculated by $(1 \ll \text{shifter index})$

static inline uint32_t FLEXIO_GetShifterErrorFlags(FLEXIO_Type *base)

Gets the shifter error flags.

Parameters

- base – FlexIO peripheral base address

Returns

Shifter error flags

static inline void FLEXIO_ClearShifterErrorFlags(FLEXIO_Type *base, uint32_t mask)

Clears the shifter error flags.

Note: For clearing multiple shifter error flags, for example, two shifter error flags, can calculate the mask by using $((1 \ll \text{shifter index0}) | (1 \ll \text{shifter index1}))$

Parameters

- base – FlexIO peripheral base address
- mask – The shifter error mask which can be calculated by $(1 \ll \text{shifter index})$

static inline uint32_t FLEXIO_GetTimerStatusFlags(FLEXIO_Type *base)

Gets the timer status flags.

Parameters

- base – FlexIO peripheral base address

Returns

Timer status flags

static inline void FLEXIO_ClearTimerStatusFlags(FLEXIO_Type *base, uint32_t mask)

Clears the timer status flags.

Note: For clearing multiple timer status flags, for example, two timer status flags, can calculate the mask by using $((1 \ll \text{timer index0}) | (1 \ll \text{timer index1}))$

Parameters

- base – FlexIO peripheral base address
- mask – The timer status mask which can be calculated by $(1 \ll \text{timer index})$

static inline void FLEXIO_EnableShifterStatusDMA(FLEXIO_Type *base, uint32_t mask, bool enable)

Enables/disables the shifter status DMA. The DMA request generates when the corresponding SSF is set.

Note: For multiple shifter status DMA enables, for example, calculate the mask by using $((1 \ll \text{shifter index0}) | (1 \ll \text{shifter index1}))$

Parameters

- base – FlexIO peripheral base address
- mask – The shifter status mask which can be calculated by $(1 \ll \text{shifter index})$
- enable – True to enable, false to disable.

uint32_t FLEXIO_GetShifterBufferAddress(FLEXIO_Type *base, flexio_shifter_buffer_type_t type, uint8_t index)

Gets the shifter buffer address for the DMA transfer usage.

Parameters

- base – FlexIO peripheral base address
- type – Shifter type of flexio_shifter_buffer_type_t
- index – Shifter index

Returns

Corresponding shifter buffer index

status_t FLEXIO_RegisterHandleIRQ(void *base, void *handle, flexio_isr_t isr)

Registers the handle and the interrupt handler for the FlexIO-simulated peripheral.

Parameters

- base – Pointer to the FlexIO simulated peripheral type.
- handle – Pointer to the handler for FlexIO simulated peripheral.
- isr – FlexIO simulated peripheral interrupt handler.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/ISR table out of range.

status_t FLEXIO_UnregisterHandleIRQ(void *base)

Unregisters the handle and the interrupt handler for the FlexIO-simulated peripheral.

Parameters

- base – Pointer to the FlexIO simulated peripheral type.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/ISR table out of range.

FSL_FLEXIO_DRIVER_VERSION

FlexIO driver version.

enum _flexio_timer_trigger_polarity

Define time of timer trigger polarity.

Values:

enumerator kFLEXIO_TimerTriggerPolarityActiveHigh
Active high.

enumerator kFLEXIO_TimerTriggerPolarityActiveLow
Active low.

enum _flexio_timer_trigger_source

Define type of timer trigger source.

Values:

enumerator kFLEXIO_TimerTriggerSourceExternal
External trigger selected.

enumerator kFLEXIO_TimerTriggerSourceInternal
Internal trigger selected.

enum _flexio_pin_config

Define type of timer/shifter pin configuration.

Values:

enumerator kFLEXIO_PinConfigOutputDisabled
Pin output disabled.

enumerator kFLEXIO_PinConfigOpenDrainOrBidirection
Pin open drain or bidirectional output enable.

enumerator kFLEXIO_PinConfigBidirectionOutputData
Pin bidirectional output data.

enumerator kFLEXIO_PinConfigOutput
Pin output.

enum _flexio_pin_polarity

Definition of pin polarity.

Values:

enumerator kFLEXIO_PinActiveHigh
Active high.

enumerator kFLEXIO_PinActiveLow
Active low.

enum _flexio_timer_mode

Define type of timer work mode.

Values:

enumerator kFLEXIO__TimerModeDisabled

Timer Disabled.

enumerator kFLEXIO__TimerModeDual8BitBaudBit

Dual 8-bit counters baud/bit mode.

enumerator kFLEXIO__TimerModeDual8BitPWM

Dual 8-bit counters PWM mode.

enumerator kFLEXIO__TimerModeSingle16Bit

Single 16-bit counter mode.

enumerator kFLEXIO__TimerModeDual8BitPWMLow

Dual 8-bit counters PWM Low mode.

enum _flexio_timer_output

Define type of timer initial output or timer reset condition.

Values:

enumerator kFLEXIO__TimerOutputOneNotAffectedByReset

Logic one when enabled and is not affected by timer reset.

enumerator kFLEXIO__TimerOutputZeroNotAffectedByReset

Logic zero when enabled and is not affected by timer reset.

enumerator kFLEXIO__TimerOutputOneAffectedByReset

Logic one when enabled and on timer reset.

enumerator kFLEXIO__TimerOutputZeroAffectedByReset

Logic zero when enabled and on timer reset.

enum _flexio_timer_decrement_source

Define type of timer decrement.

Values:

enumerator kFLEXIO__TimerDecSrcOnFlexIOClockShiftTimerOutput

Decrement counter on FlexIO clock, Shift clock equals Timer output.

enumerator kFLEXIO__TimerDecSrcOnTriggerInputShiftTimerOutput

Decrement counter on Trigger input (both edges), Shift clock equals Timer output.

enumerator kFLEXIO__TimerDecSrcOnPinInputShiftPinInput

Decrement counter on Pin input (both edges), Shift clock equals Pin input.

enumerator kFLEXIO__TimerDecSrcOnTriggerInputShiftTriggerInput

Decrement counter on Trigger input (both edges), Shift clock equals Trigger input.

enum _flexio_timer_reset_condition

Define type of timer reset condition.

Values:

enumerator kFLEXIO__TimerResetNever

Timer never reset.

enumerator kFLEXIO__TimerResetOnTimerPinEqualToTimerOutput

Timer reset on Timer Pin equal to Timer Output.

enumerator kFLEXIO__TimerResetOnTimerTriggerEqualToTimerOutput
Timer reset on Timer Trigger equal to Timer Output.

enumerator kFLEXIO__TimerResetOnTimerPinRisingEdge
Timer reset on Timer Pin rising edge.

enumerator kFLEXIO__TimerResetOnTimerTriggerRisingEdge
Timer reset on Trigger rising edge.

enumerator kFLEXIO__TimerResetOnTimerTriggerBothEdge
Timer reset on Trigger rising or falling edge.

enum _flexio_timer_disable_condition
Define type of timer disable condition.

Values:

enumerator kFLEXIO__TimerDisableNever
Timer never disabled.

enumerator kFLEXIO__TimerDisableOnPreTimerDisable
Timer disabled on Timer N-1 disable.

enumerator kFLEXIO__TimerDisableOnTimerCompare
Timer disabled on Timer compare.

enumerator kFLEXIO__TimerDisableOnTimerCompareTriggerLow
Timer disabled on Timer compare and Trigger Low.

enumerator kFLEXIO__TimerDisableOnPinBothEdge
Timer disabled on Pin rising or falling edge.

enumerator kFLEXIO__TimerDisableOnPinBothEdgeTriggerHigh
Timer disabled on Pin rising or falling edge provided Trigger is high.

enumerator kFLEXIO__TimerDisableOnTriggerFallingEdge
Timer disabled on Trigger falling edge.

enum _flexio_timer_enable_condition
Define type of timer enable condition.

Values:

enumerator kFLEXIO__TimerEnabledAlways
Timer always enabled.

enumerator kFLEXIO__TimerEnableOnPrevTimerEnable
Timer enabled on Timer N-1 enable.

enumerator kFLEXIO__TimerEnableOnTriggerHigh
Timer enabled on Trigger high.

enumerator kFLEXIO__TimerEnableOnTriggerHighPinHigh
Timer enabled on Trigger high and Pin high.

enumerator kFLEXIO__TimerEnableOnPinRisingEdge
Timer enabled on Pin rising edge.

enumerator kFLEXIO__TimerEnableOnPinRisingEdgeTriggerHigh
Timer enabled on Pin rising edge and Trigger high.

enumerator kFLEXIO__TimerEnableOnTriggerRisingEdge
Timer enabled on Trigger rising edge.

enumerator kFLEXIO_TimerEnableOnTriggerBothEdge

Timer enabled on Trigger rising or falling edge.

enum _flexio_timer_stop_bit_condition

Define type of timer stop bit generate condition.

Values:

enumerator kFLEXIO_TimerStopBitDisabled

Stop bit disabled.

enumerator kFLEXIO_TimerStopBitEnableOnTimerCompare

Stop bit is enabled on timer compare.

enumerator kFLEXIO_TimerStopBitEnableOnTimerDisable

Stop bit is enabled on timer disable.

enumerator kFLEXIO_TimerStopBitEnableOnTimerCompareDisable

Stop bit is enabled on timer compare and timer disable.

enum _flexio_timer_start_bit_condition

Define type of timer start bit generate condition.

Values:

enumerator kFLEXIO_TimerStartBitDisabled

Start bit disabled.

enumerator kFLEXIO_TimerStartBitEnabled

Start bit enabled.

enum _flexio_timer_output_state

FlexIO as PWM channel output state.

Values:

enumerator kFLEXIO_PwmLow

The output state of PWM channel is low

enumerator kFLEXIO_PwmHigh

The output state of PWM channel is high

enum _flexio_shifter_timer_polarity

Define type of timer polarity for shifter control.

Values:

enumerator kFLEXIO_ShifterTimerPolarityOnPositive

Shift on positive edge of shift clock.

enumerator kFLEXIO_ShifterTimerPolarityOnNegative

Shift on negative edge of shift clock.

enum _flexio_shifter_mode

Define type of shifter working mode.

Values:

enumerator kFLEXIO_ShifterDisabled

Shifter is disabled.

enumerator kFLEXIO_ShifterModeReceive

Receive mode.

enumerator kFLEXIO__ShifterModeTransmit
Transmit mode.

enumerator kFLEXIO__ShifterModeMatchStore
Match store mode.

enumerator kFLEXIO__ShifterModeMatchContinuous
Match continuous mode.

enumerator kFLEXIO__ShifterModeState
SHIFTBUF contents are used for storing programmable state attributes.

enumerator kFLEXIO__ShifterModeLogic
SHIFTBUF contents are used for implementing programmable logic look up table.

enum _flexio_shifter_input_source
Define type of shifter input source.

Values:

enumerator kFLEXIO__ShifterInputFromPin
Shifter input from pin.

enumerator kFLEXIO__ShifterInputFromNextShifterOutput
Shifter input from Shifter N+1.

enum _flexio_shifter_stop_bit
Define of STOP bit configuration.

Values:

enumerator kFLEXIO__ShifterStopBitDisable
Disable shifter stop bit.

enumerator kFLEXIO__ShifterStopBitLow
Set shifter stop bit to logic low level.

enumerator kFLEXIO__ShifterStopBitHigh
Set shifter stop bit to logic high level.

enum _flexio_shifter_start_bit
Define type of START bit configuration.

Values:

enumerator kFLEXIO__ShifterStartBitDisabledLoadDataOnEnable
Disable shifter start bit, transmitter loads data on enable.

enumerator kFLEXIO__ShifterStartBitDisabledLoadDataOnShift
Disable shifter start bit, transmitter loads data on first shift.

enumerator kFLEXIO__ShifterStartBitLow
Set shifter start bit to logic low level.

enumerator kFLEXIO__ShifterStartBitHigh
Set shifter start bit to logic high level.

enum _flexio_shifter_buffer_type
Define FlexIO shifter buffer type.

Values:

enumerator kFLEXIO__ShifterBuffer
Shifter Buffer N Register.

enumerator kFLEXIO_ShifterBufferBitSwapped
Shifter Buffer N Bit Byte Swapped Register.

enumerator kFLEXIO_ShifterBufferByteSwapped
Shifter Buffer N Byte Swapped Register.

enumerator kFLEXIO_ShifterBufferBitByteSwapped
Shifter Buffer N Bit Swapped Register.

enumerator kFLEXIO_ShifterBufferNibbleByteSwapped
Shifter Buffer N Nibble Byte Swapped Register.

enumerator kFLEXIO_ShifterBufferHalfWordSwapped
Shifter Buffer N Half Word Swapped Register.

enumerator kFLEXIO_ShifterBufferNibbleSwapped
Shifter Buffer N Nibble Swapped Register.

typedef enum *_flexio_timer_trigger_polarity* flexio_timer_trigger_polarity_t
Define time of timer trigger polarity.

typedef enum *_flexio_timer_trigger_source* flexio_timer_trigger_source_t
Define type of timer trigger source.

typedef enum *_flexio_pin_config* flexio_pin_config_t
Define type of timer/shifter pin configuration.

typedef enum *_flexio_pin_polarity* flexio_pin_polarity_t
Definition of pin polarity.

typedef enum *_flexio_timer_mode* flexio_timer_mode_t
Define type of timer work mode.

typedef enum *_flexio_timer_output* flexio_timer_output_t
Define type of timer initial output or timer reset condition.

typedef enum *_flexio_timer_decrement_source* flexio_timer_decrement_source_t
Define type of timer decrement.

typedef enum *_flexio_timer_reset_condition* flexio_timer_reset_condition_t
Define type of timer reset condition.

typedef enum *_flexio_timer_disable_condition* flexio_timer_disable_condition_t
Define type of timer disable condition.

typedef enum *_flexio_timer_enable_condition* flexio_timer_enable_condition_t
Define type of timer enable condition.

typedef enum *_flexio_timer_stop_bit_condition* flexio_timer_stop_bit_condition_t
Define type of timer stop bit generate condition.

typedef enum *_flexio_timer_start_bit_condition* flexio_timer_start_bit_condition_t
Define type of timer start bit generate condition.

typedef enum *_flexio_timer_output_state* flexio_timer_output_state_t
FlexIO as PWM channel output state.

typedef enum *_flexio_shifter_timer_polarity* flexio_shifter_timer_polarity_t
Define type of timer polarity for shifter control.

typedef enum *_flexio_shifter_mode* flexio_shifter_mode_t
Define type of shifter working mode.

typedef enum *_flexio_shifter_input_source* flexio_shifter_input_source_t

Define type of shifter input source.

typedef enum *_flexio_shifter_stop_bit* flexio_shifter_stop_bit_t

Define of STOP bit configuration.

typedef enum *_flexio_shifter_start_bit* flexio_shifter_start_bit_t

Define type of START bit configuration.

typedef enum *_flexio_shifter_buffer_type* flexio_shifter_buffer_type_t

Define FlexIO shifter buffer type.

typedef struct *_flexio_config* flexio_config_t

Define FlexIO user configuration structure.

typedef struct *_flexio_timer_config* flexio_timer_config_t

Define FlexIO timer configuration structure.

typedef struct *_flexio_shifter_config* flexio_shifter_config_t

Define FlexIO shifter configuration structure.

typedef void (*flexio_isr_t)(void *base, void *handle)

typedef for FlexIO simulated driver interrupt handler.

FLEXIO_Type *const s_flexioBases[]

Pointers to flexio bases for each instance.

const clock_ip_name_t s_flexioClocks[]

Pointers to flexio clocks for each instance.

FLEXIO_TIMER_TRIGGER_SEL_PININPUT(x)

Calculate FlexIO timer trigger.

FLEXIO_TIMER_TRIGGER_SEL_SHIFThSTAT(x)

FLEXIO_TIMER_TRIGGER_SEL_TIMn(x)

struct _flexio_config

#include <fsl_flexio.h> Define FlexIO user configuration structure.

Public Members

bool enableFlexio

Enable/disable FlexIO module

bool enableInDoze

Enable/disable FlexIO operation in doze mode

bool enableInDebug

Enable/disable FlexIO operation in debug mode

bool enableFastAccess

Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

struct _flexio_timer_config

#include <fsl_flexio.h> Define FlexIO timer configuration structure.

Public Members

`uint32_t triggerSelect`

The internal trigger selection number using MACROs.

`flexio_timer_trigger_polarity_t triggerPolarity`

Trigger Polarity.

`flexio_timer_trigger_source_t triggerSource`

Trigger Source, internal (see 'trgsel') or external.

`flexio_pin_config_t pinConfig`

Timer Pin Configuration.

`uint32_t pinSelect`

Timer Pin number Select.

`flexio_pin_polarity_t pinPolarity`

Timer Pin Polarity.

`flexio_timer_mode_t timerMode`

Timer work Mode.

`flexio_timer_output_t timerOutput`

Configures the initial state of the Timer Output and whether it is affected by the Timer reset.

`flexio_timer_decrement_source_t timerDecrement`

Configures the source of the Timer decrement and the source of the Shift clock.

`flexio_timer_reset_condition_t timerReset`

Configures the condition that causes the timer counter (and optionally the timer output) to be reset.

`flexio_timer_disable_condition_t timerDisable`

Configures the condition that causes the Timer to be disabled and stop decrementing.

`flexio_timer_enable_condition_t timerEnable`

Configures the condition that causes the Timer to be enabled and start decrementing.

`flexio_timer_stop_bit_condition_t timerStop`

Timer STOP Bit generation.

`flexio_timer_start_bit_condition_t timerStart`

Timer STRAT Bit generation.

`uint32_t timerCompare`

Value for Timer Compare N Register.

`struct _flexio_shifter_config`

`#include <fsl_flexio.h>` Define FlexIO shifter configuration structure.

Public Members

`uint32_t timerSelect`

Selects which Timer is used for controlling the logic/shift register and generating the Shift clock.

`flexio_shifter_timer_polarity_t timerPolarity`

Timer Polarity.

flexio_pin_config_t pinConfig
Shifter Pin Configuration.

uint32_t pinSelect
Shifter Pin number Select.

flexio_pin_polarity_t pinPolarity
Shifter Pin Polarity.

flexio_shifter_mode_t shifterMode
Configures the mode of the Shifter.

uint32_t parallelWidth
Configures the parallel width when using parallel mode.

flexio_shifter_input_source_t inputSource
Selects the input source for the shifter.

flexio_shifter_stop_bit_t shifterStop
Shifter STOP bit.

flexio_shifter_start_bit_t shifterStart
Shifter START bit.

2.12 FlexIO eDMA I2S Driver

```
void FLEXIO_I2S_TransferTxCreateHandleEDMA(FLEXIO_I2S_Type *base,  
                                           flexio_i2s_edma_handle_t *handle,  
                                           flexio_i2s_edma_callback_t callback, void  
                                           *userData, edma_handle_t *dmaHandle)
```

Initializes the FlexIO I2S eDMA handle.

This function initializes the FlexIO I2S master DMA handle which can be used for other FlexIO I2S master transactional APIs. Usually, for a specified FlexIO I2S instance, call this API once to get the initialized handle.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S eDMA handle pointer.
- callback – FlexIO I2S eDMA callback function called while finished a block.
- userData – User parameter for callback.
- dmaHandle – eDMA handle for FlexIO I2S. This handle is a static value allocated by users.

```
void FLEXIO_I2S_TransferRxCreateHandleEDMA(FLEXIO_I2S_Type *base,  
                                           flexio_i2s_edma_handle_t *handle,  
                                           flexio_i2s_edma_callback_t callback, void  
                                           *userData, edma_handle_t *dmaHandle)
```

Initializes the FlexIO I2S Rx eDMA handle.

This function initializes the FlexIO I2S slave DMA handle which can be used for other FlexIO I2S master transactional APIs. Usually, for a specified FlexIO I2S instance, call this API once to get the initialized handle.

Parameters

- base – FlexIO I2S peripheral base address.

- handle – FlexIO I2S eDMA handle pointer.
- callback – FlexIO I2S eDMA callback function called while finished a block.
- userData – User parameter for callback.
- dmaHandle – eDMA handle for FlexIO I2S. This handle is a static value allocated by users.

```
void FLEXIO_I2S_TransferSetFormatEDMA(FLEXIO_I2S_Type *base, flexio_i2s_edma_handle_t
                                     *handle, flexio_i2s_format_t *format, uint32_t
                                     srcClock_Hz)
```

Configures the FlexIO I2S Tx audio format.

Audio format can be changed in run-time of FlexIO I2S. This function configures the sample rate and audio data format to be transferred. This function also sets the eDMA parameter according to format.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S eDMA handle pointer
- format – Pointer to FlexIO I2S audio data format structure.
- srcClock_Hz – FlexIO I2S clock source frequency in Hz, it should be 0 while in slave mode.

```
status_t FLEXIO_I2S_TransferSendEDMA(FLEXIO_I2S_Type *base, flexio_i2s_edma_handle_t
                                     *handle, flexio_i2s_transfer_t *xfer)
```

Performs a non-blocking FlexIO I2S transfer using DMA.

Note: This interface returned immediately after transfer initiates. Users should call FLEXIO_I2S_GetTransferStatus to poll the transfer status and check whether the FlexIO I2S transfer is finished.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S DMA handle pointer.
- xfer – Pointer to DMA transfer structure.

Return values

- kStatus_Success – Start a FlexIO I2S eDMA send successfully.
- kStatus_InvalidArgument – The input arguments is invalid.
- kStatus_TxBusy – FlexIO I2S is busy sending data.

```
status_t FLEXIO_I2S_TransferReceiveEDMA(FLEXIO_I2S_Type *base, flexio_i2s_edma_handle_t
                                         *handle, flexio_i2s_transfer_t *xfer)
```

Performs a non-blocking FlexIO I2S receive using eDMA.

Note: This interface returned immediately after transfer initiates. Users should call FLEXIO_I2S_GetReceiveRemainingBytes to poll the transfer status and check whether the FlexIO I2S transfer is finished.

Parameters

- base – FlexIO I2S peripheral base address.

- handle – FlexIO I2S DMA handle pointer.
- xfer – Pointer to DMA transfer structure.

Return values

- kStatus__Success – Start a FlexIO I2S eDMA receive successfully.
- kStatus__InvalidArgument – The input arguments is invalid.
- kStatus__RxBusy – FlexIO I2S is busy receiving data.

```
void FLEXIO_I2S__TransferAbortSendEDMA(FLEXIO_I2S_Type *base, flexio_i2s_edma_handle_t *handle)
```

Aborts a FlexIO I2S transfer using eDMA.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S DMA handle pointer.

```
void FLEXIO_I2S__TransferAbortReceiveEDMA(FLEXIO_I2S_Type *base, flexio_i2s_edma_handle_t *handle)
```

Aborts a FlexIO I2S receive using eDMA.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S DMA handle pointer.

```
status_t FLEXIO_I2S__TransferGetSendCountEDMA(FLEXIO_I2S_Type *base, flexio_i2s_edma_handle_t *handle, size_t *count)
```

Gets the remaining bytes to be sent.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S DMA handle pointer.
- count – Bytes sent.

Return values

- kStatus__Success – Succeed get the transfer count.
- kStatus__NoTransferInProgress – There is not a non-blocking transaction currently in progress.

```
status_t FLEXIO_I2S__TransferGetReceiveCountEDMA(FLEXIO_I2S_Type *base, flexio_i2s_edma_handle_t *handle, size_t *count)
```

Get the remaining bytes to be received.

Parameters

- base – FlexIO I2S peripheral base address.
- handle – FlexIO I2S DMA handle pointer.
- count – Bytes received.

Return values

- kStatus__Success – Succeed get the transfer count.
- kStatus__NoTransferInProgress – There is not a non-blocking transaction currently in progress.

FSL_FLEXIO_I2S_EDMA_DRIVER_VERSION

FlexIO I2S EDMA driver version 2.1.9.

typedef struct *flexio_i2s_edma_handle* flexio_i2s_edma_handle_t

typedef void (*flexio_i2s_edma_callback_t)(FLEXIO_I2S_Type *base, *flexio_i2s_edma_handle_t* *handle, *status_t* status, void *userData)

FlexIO I2S eDMA transfer callback function for finish and error.

struct *flexio_i2s_edma_handle*

#include <fsl_flexio_i2s_edma.h> FlexIO I2S DMA transfer handle, users should not touch the content of the handle.

Public Members

edma_handle_t *dmaHandle

DMA handler for FlexIO I2S send

uint8_t bytesPerFrame

Bytes in a frame

uint8_t nbytes

eDMA minor byte transfer count initially configured.

uint32_t state

Internal state for FlexIO I2S eDMA transfer

flexio_i2s_edma_callback_t callback

Callback for users while transfer finish or error occurred

void *userData

User callback parameter

edma_tcd_t tcd[(4U) + 1U]

TCD pool for eDMA transfer.

flexio_i2s_transfer_t queue[(4U)]

Transfer queue storing queued transfer.

size_t transferSize[(4U)]

Data bytes need to transfer

volatile uint8_t queueUser

Index for user to queue transfer.

volatile uint8_t queueDriver

Index for driver to get the transfer data and size

2.13 FlexIO eDMA SPI Driver

status_t FLEXIO_SPI_MasterTransferCreateHandleEDMA(*FLEXIO_SPI_Type* *base,
flexio_spi_master_edma_handle_t *handle,
flexio_spi_master_edma_transfer_callback_t callback, void *userData,
edma_handle_t *txHandle,
edma_handle_t *rxHandle)

Initializes the FlexIO SPI master eDMA handle.

This function initializes the FlexIO SPI master eDMA handle which can be used for other FlexIO SPI master transactional APIs. For a specified FlexIO SPI instance, call this API once to get the initialized handle.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – Pointer to flexio_spi_master_edma_handle_t structure to store the transfer state.
- callback – SPI callback, NULL means no callback.
- userData – callback function parameter.
- txHandle – User requested eDMA handle for FlexIO SPI RX eDMA transfer.
- rxHandle – User requested eDMA handle for FlexIO SPI TX eDMA transfer.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO SPI eDMA type/handle table out of range.

```
status_t FLEXIO_SPI_MasterTransferEDMA(FLEXIO_SPI_Type *base,  
                                         flexio_spi_master_edma_handle_t *handle,  
                                         flexio_spi_transfer_t *xfer)
```

Performs a non-blocking FlexIO SPI transfer using eDMA.

Note: This interface returns immediately after transfer initiates. Call FLEXIO_SPI_MasterGetTransferCountEDMA to poll the transfer status and check whether the FlexIO SPI transfer is finished.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – Pointer to flexio_spi_master_edma_handle_t structure to store the transfer state.
- xfer – Pointer to FlexIO SPI transfer structure.

Return values

- kStatus_Success – Successfully start a transfer.
- kStatus_InvalidArgument – Input argument is invalid.
- kStatus_FLEXIO_SPI_Busy – FlexIO SPI is not idle, is running another transfer.

```
void FLEXIO_SPI_MasterTransferAbortEDMA(FLEXIO_SPI_Type *base,  
                                         flexio_spi_master_edma_handle_t *handle)
```

Aborts a FlexIO SPI transfer using eDMA.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – FlexIO SPI eDMA handle pointer.

```
status_t FLEXIO_SPI_MasterTransferGetCountEDMA(FLEXIO_SPI_Type *base,  
                                              flexio_spi_master_edma_handle_t *handle,  
                                              size_t *count)
```

Gets the number of bytes transferred so far using FlexIO SPI master eDMA.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – FlexIO SPI eDMA handle pointer.
- count – Number of bytes transferred so far by the non-blocking transaction.

```
static inline void FLEXIO_SPI_SlaveTransferCreateHandleEDMA(FLEXIO_SPI_Type *base,  
                                                         flexio_spi_slave_edma_handle_t  
                                                         *handle,  
                                                         flexio_spi_slave_edma_transfer_callback_t  
                                                         callback, void *userData,  
                                                         edma_handle_t *txHandle,  
                                                         edma_handle_t *rxHandle)
```

Initializes the FlexIO SPI slave eDMA handle.

This function initializes the FlexIO SPI slave eDMA handle.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – Pointer to flexio_spi_slave_edma_handle_t structure to store the transfer state.
- callback – SPI callback, NULL means no callback.
- userData – callback function parameter.
- txHandle – User requested eDMA handle for FlexIO SPI TX eDMA transfer.
- rxHandle – User requested eDMA handle for FlexIO SPI RX eDMA transfer.

```
status_t FLEXIO_SPI_SlaveTransferEDMA(FLEXIO_SPI_Type *base,  
                                     flexio_spi_slave_edma_handle_t *handle,  
                                     flexio_spi_transfer_t *xfer)
```

Performs a non-blocking FlexIO SPI transfer using eDMA.

Note: This interface returns immediately after transfer initiates. Call FLEXIO_SPI_SlaveGetTransferCountEDMA to poll the transfer status and check whether the FlexIO SPI transfer is finished.

Parameters

- base – Pointer to FLEXIO_SPI_Type structure.
- handle – Pointer to flexio_spi_slave_edma_handle_t structure to store the transfer state.
- xfer – Pointer to FlexIO SPI transfer structure.

Return values

- kStatus_Success – Successfully start a transfer.
- kStatus_InvalidArgument – Input argument is invalid.
- kStatus_FLEXIO_SPI_Busy – FlexIO SPI is not idle, is running another transfer.

```
static inline void FLEXIO_SPI_SlaveTransferAbortEDMA(FLEXIO_SPI_Type *base,  
                                                    flexio_spi_slave_edma_handle_t  
                                                    *handle)
```

Aborts a FlexIO SPI transfer using eDMA.

Parameters

- base – Pointer to *FLEXIO_SPI_Type* structure.
- handle – Pointer to *flexio_spi_slave_edma_handle_t* structure to store the transfer state.

```
static inline status_t FLEXIO_SPI_SlaveTransferGetCountEDMA(FLEXIO_SPI_Type *base,  
                                                           flexio_spi_slave_edma_handle_t  
                                                           *handle, size_t *count)
```

Gets the number of bytes transferred so far using FlexIO SPI slave eDMA.

Parameters

- base – Pointer to *FLEXIO_SPI_Type* structure.
- handle – FlexIO SPI eDMA handle pointer.
- count – Number of bytes transferred so far by the non-blocking transaction.

```
FSL_FLEXIO_SPI_EDMA_DRIVER_VERSION
```

FlexIO SPI EDMA driver version.

```
typedef struct flexio_spi_master_edma_handle flexio_spi_master_edma_handle_t  
typedef for flexio_spi_master_edma_handle_t in advance.
```

```
typedef flexio_spi_master_edma_handle_t flexio_spi_slave_edma_handle_t  
Slave handle is the same with master handle.
```

```
typedef void (*flexio_spi_master_edma_transfer_callback_t)(FLEXIO_SPI_Type *base,  
flexio_spi_master_edma_handle_t *handle, status_t status, void *userData)
```

FlexIO SPI master callback for finished transmit.

```
typedef void (*flexio_spi_slave_edma_transfer_callback_t)(FLEXIO_SPI_Type *base,  
flexio_spi_slave_edma_handle_t *handle, status_t status, void *userData)
```

FlexIO SPI slave callback for finished transmit.

```
struct flexio_spi_master_edma_handle
```

```
#include <fsl_flexio_spi_edma.h> FlexIO SPI eDMA transfer handle, users should not touch  
the content of the handle.
```

Public Members

```
size_t transferSize
```

Total bytes to be transferred.

```
uint8_t nbytes
```

eDMA minor byte transfer count initially configured.

```
bool txInProgress
```

Send transfer in progress

```
bool rxInProgress
```

Receive transfer in progress

```
edma_handle_t *txHandle
```

DMA handler for SPI send

edma_handle_t *rxHandle

DMA handler for SPI receive

flexio_spi_master_edma_transfer_callback_t callback

Callback for SPI DMA transfer

void *userData

User Data for SPI DMA callback

2.14 FlexIO eDMA UART Driver

status_t FLEXIO_UART_TransferCreateHandleEDMA(*FLEXIO_UART_Type* *base,
 flexio_uart_edma_handle_t *handle,
 flexio_uart_edma_transfer_callback_t
 callback, void *userData, *edma_handle_t*
 *txEdmaHandle, *edma_handle_t*
 *rxEdmaHandle)

Initializes the UART handle which is used in transactional functions.

Parameters

- base – Pointer to FLEXIO_UART_Type.
- handle – Pointer to flexio_uart_edma_handle_t structure.
- callback – The callback function.
- userData – The parameter of the callback function.
- rxEdmaHandle – User requested DMA handle for RX DMA transfer.
- txEdmaHandle – User requested DMA handle for TX DMA transfer.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO SPI eDMA type/handle table out of range.

status_t FLEXIO_UART_TransferSendEDMA(*FLEXIO_UART_Type* *base,
 flexio_uart_edma_handle_t *handle,
 flexio_uart_transfer_t *xfer)

Sends data using eDMA.

This function sends data using eDMA. This is a non-blocking function, which returns right away. When all data is sent out, the send callback function is called.

Parameters

- base – Pointer to FLEXIO_UART_Type
- handle – UART handle pointer.
- xfer – UART eDMA transfer structure, see flexio_uart_transfer_t.

Return values

- kStatus_Success – if succeed, others failed.
- kStatus_FLEXIO_UART_TxBusy – Previous transfer on going.

status_t FLEXIO_UART_TransferReceiveEDMA(*FLEXIO_UART_Type* *base,
 flexio_uart_edma_handle_t *handle,
 flexio_uart_transfer_t *xfer)

Receives data using eDMA.

This function receives data using eDMA. This is a non-blocking function, which returns right away. When all data is received, the receive callback function is called.

Parameters

- base – Pointer to FLEXIO_UART_Type
- handle – Pointer to flexio_uart_edma_handle_t structure
- xfer – UART eDMA transfer structure, see flexio_uart_transfer_t.

Return values

- kStatus_Success – if succeed, others failed.
- kStatus_UART_RxBusy – Previous transfer on going.

```
void FLEXIO_UART_TransferAbortSendEDMA(FLEXIO_UART_Type *base,  
                                         flexio_uart_edma_handle_t *handle)
```

Aborts the sent data which using eDMA.

This function aborts sent data which using eDMA.

Parameters

- base – Pointer to FLEXIO_UART_Type
- handle – Pointer to flexio_uart_edma_handle_t structure

```
void FLEXIO_UART_TransferAbortReceiveEDMA(FLEXIO_UART_Type *base,  
                                           flexio_uart_edma_handle_t *handle)
```

Aborts the receive data which using eDMA.

This function aborts the receive data which using eDMA.

Parameters

- base – Pointer to FLEXIO_UART_Type
- handle – Pointer to flexio_uart_edma_handle_t structure

```
status_t FLEXIO_UART_TransferGetSendCountEDMA(FLEXIO_UART_Type *base,  
                                                flexio_uart_edma_handle_t *handle,  
                                                size_t *count)
```

Gets the number of bytes sent out.

This function gets the number of bytes sent out.

Parameters

- base – Pointer to FLEXIO_UART_Type
- handle – Pointer to flexio_uart_edma_handle_t structure
- count – Number of bytes sent so far by the non-blocking transaction.

Return values

- kStatus_NoTransferInProgress – transfer has finished or no transfer in progress.
- kStatus_Success – Successfully return the count.

```
status_t FLEXIO_UART_TransferGetReceiveCountEDMA(FLEXIO_UART_Type *base,  
                                                  flexio_uart_edma_handle_t *handle,  
                                                  size_t *count)
```

Gets the number of bytes received.

This function gets the number of bytes received.

Parameters

- `base` – Pointer to `FLEXIO_UART_Type`
- `handle` – Pointer to `flexio_uart_edma_handle_t` structure
- `count` – Number of bytes received so far by the non-blocking transaction.

Return values

- `kStatus_NoTransferInProgress` – transfer has finished or no transfer in progress.
- `kStatus_Success` – Successfully return the count.

`FSL_FLEXIO_UART_EDMA_DRIVER_VERSION`

FlexIO UART EDMA driver version.

```
typedef struct flexio_uart_edma_handle flexio_uart_edma_handle_t
```

```
typedef void (*flexio_uart_edma_transfer_callback_t)(FLEXIO_UART_Type *base,  
flexio_uart_edma_handle_t *handle, status_t status, void *userData)
```

UART transfer callback function.

```
struct flexio_uart_edma_handle
```

`#include <fsl_flexio_uart_edma.h>` UART eDMA handle.

Public Members

flexio_uart_edma_transfer_callback_t callback

Callback function.

`void *userData`

UART callback function parameter.

`size_t txDataSizeAll`

Total bytes to be sent.

`size_t rxDataSizeAll`

Total bytes to be received.

edma_handle_t *txEdmaHandle

The eDMA TX channel used.

edma_handle_t *rxEdmaHandle

The eDMA RX channel used.

`uint8_t nbytes`

eDMA minor byte transfer count initially configured.

`volatile uint8_t txState`

TX transfer state.

`volatile uint8_t rxState`

RX transfer state

2.15 FlexIO I2C Master Driver

status_t FLEXIO_I2C_CheckForBusyBus(*FLEXIO_I2C_Type* *base)

Make sure the bus isn't already pulled down.

Check the FLEXIO pin status to see whether either of SDA and SCL pin is pulled down.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure..

Return values

- kStatus_Success –
- kStatus_FLEXIO_I2C_Busy –

status_t FLEXIO_I2C_MasterInit(*FLEXIO_I2C_Type* *base, *flexio_i2c_master_config_t* *masterConfig, *uint32_t* srcClock_Hz)

Ungates the FlexIO clock, resets the FlexIO module, and configures the FlexIO I2C hardware configuration.

Example

```
FLEXIO_I2C_Type base = {
    .flexioBase = FLEXIO,
    .SDAPinIndex = 0,
    .SCLPinIndex = 1,
    .shifterIndex = {0,1},
    .timerIndex = {0,1}
};
flexio_i2c_master_config_t config = {
    .enableInDoze = false,
    .enableInDebug = true,
    .enableFastAccess = false,
    .baudRate_Bps = 100000
};
FLEXIO_I2C_MasterInit(base, &config, srcClock_Hz);
```

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- masterConfig – Pointer to flexio_i2c_master_config_t structure.
- srcClock_Hz – FlexIO source clock in Hz.

Return values

- kStatus_Success – Initialization successful
- kStatus_InvalidArgument – The source clock exceed upper range limitation

void FLEXIO_I2C_MasterDeinit(*FLEXIO_I2C_Type* *base)

De-initializes the FlexIO I2C master peripheral. Calling this API Resets the FlexIO I2C master shifer and timer config, module can't work unless the FLEXIO_I2C_MasterInit is called.

Parameters

- base – pointer to FLEXIO_I2C_Type structure.

void FLEXIO_I2C_MasterGetDefaultConfig(*flexio_i2c_master_config_t* *masterConfig)

Gets the default configuration to configure the FlexIO module. The configuration can be used directly for calling the FLEXIO_I2C_MasterInit().

Example:

```
flexio_i2c_master_config_t config;
FLEXIO_I2C_MasterGetDefaultConfig(&config);
```

Parameters

- masterConfig – Pointer to flexio_i2c_master_config_t structure.

static inline void FLEXIO_I2C_MasterEnable(*FLEXIO_I2C_Type* *base, bool enable)

Enables/disables the FlexIO module operation.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- enable – Pass true to enable module, false does not have any effect.

uint32_t FLEXIO_I2C_MasterGetStatusFlags(*FLEXIO_I2C_Type* *base)

Gets the FlexIO I2C master status flags.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure

Returns

Status flag, use status flag to AND _flexio_i2c_master_status_flags can get the related status.

void FLEXIO_I2C_MasterClearStatusFlags(*FLEXIO_I2C_Type* *base, uint32_t mask)

Clears the FlexIO I2C master status flags.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- mask – Status flag. The parameter can be any combination of the following values:
 - kFLEXIO_I2C_RxFullFlag
 - kFLEXIO_I2C_ReceiveNakFlag

void FLEXIO_I2C_MasterEnableInterrupts(*FLEXIO_I2C_Type* *base, uint32_t mask)

Enables the FlexIO i2c master interrupt requests.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- mask – Interrupt source. Currently only one interrupt request source:
 - kFLEXIO_I2C_TransferCompleteInterruptEnable

void FLEXIO_I2C_MasterDisableInterrupts(*FLEXIO_I2C_Type* *base, uint32_t mask)

Disables the FlexIO I2C master interrupt requests.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- mask – Interrupt source.

void FLEXIO_I2C_MasterSetBaudRate(*FLEXIO_I2C_Type* *base, uint32_t baudRate_Bps,
uint32_t srcClock_Hz)

Sets the FlexIO I2C master transfer baudrate.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure
- baudRate_Bps – the baud rate value in HZ

- srcClock_Hz – source clock in HZ

void FLEXIO_I2C_MasterStart(*FLEXIO_I2C_Type* *base, uint8_t address, *flexio_i2c_direction_t* direction)

Sends START + 7-bit address to the bus.

Note: This API should be called when the transfer configuration is ready to send a START signal and 7-bit address to the bus. This is a non-blocking API, which returns directly after the address is put into the data register but the address transfer is not finished on the bus. Ensure that the kFLEXIO_I2C_RxFullFlag status is asserted before calling this API.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- address – 7-bit address.
- direction – transfer direction. This parameter is one of the values in flexio_i2c_direction_t:
 - kFLEXIO_I2C_Write: Transmit
 - kFLEXIO_I2C_Read: Receive

void FLEXIO_I2C_MasterStop(*FLEXIO_I2C_Type* *base)

Sends the stop signal on the bus.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.

void FLEXIO_I2C_MasterRepeatedStart(*FLEXIO_I2C_Type* *base)

Sends the repeated start signal on the bus.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.

void FLEXIO_I2C_MasterAbortStop(*FLEXIO_I2C_Type* *base)

Sends the stop signal when transfer is still on-going.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.

void FLEXIO_I2C_MasterEnableAck(*FLEXIO_I2C_Type* *base, bool enable)

Configures the sent ACK/NAK for the following byte.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- enable – True to configure send ACK, false configure to send NAK.

status_t FLEXIO_I2C_MasterSetTransferCount(*FLEXIO_I2C_Type* *base, uint16_t count)

Sets the number of bytes to be transferred from a start signal to a stop signal.

Note: Call this API before a transfer begins because the timer generates a number of clocks according to the number of bytes that need to be transferred.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.

- `count` – Number of bytes need to be transferred from a start signal to a re-start/stop signal

Return values

- `kStatus_Success` – Successfully configured the count.
- `kStatus_InvalidArgument` – Input argument is invalid.

`static inline void FLEXIO_I2C_MasterWriteByte(FLEXIO_I2C_Type *base, uint32_t data)`

Writes one byte of data to the I2C bus.

Note: This is a non-blocking API, which returns directly after the data is put into the data register but the data transfer is not finished on the bus. Ensure that the `TxEmptyFlag` is asserted before calling this API.

Parameters

- `base` – Pointer to `FLEXIO_I2C_Type` structure.
- `data` – a byte of data.

`static inline uint8_t FLEXIO_I2C_MasterReadByte(FLEXIO_I2C_Type *base)`

Reads one byte of data from the I2C bus.

Note: This is a non-blocking API, which returns directly after the data is read from the data register. Ensure that the data is ready in the register.

Parameters

- `base` – Pointer to `FLEXIO_I2C_Type` structure.

Returns

data byte read.

`status_t FLEXIO_I2C_MasterWriteBlocking(FLEXIO_I2C_Type *base, const uint8_t *txBuff, uint8_t txSize)`

Sends a buffer of data in bytes.

Note: This function blocks via polling until all bytes have been sent.

Parameters

- `base` – Pointer to `FLEXIO_I2C_Type` structure.
- `txBuff` – The data bytes to send.
- `txSize` – The number of data bytes to send.

Return values

- `kStatus_Success` – Successfully write data.
- `kStatus_FLEXIO_I2C_Nak` – Receive NAK during writing data.
- `kStatus_FLEXIO_I2C_Timeout` – Timeout polling status flags.

`status_t FLEXIO_I2C_MasterReadBlocking(FLEXIO_I2C_Type *base, uint8_t *rxBuff, uint8_t rxSize)`

Receives a buffer of bytes.

Note: This function blocks via polling until all bytes have been received.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- rxBuff – The buffer to store the received bytes.
- rxSize – The number of data bytes to be received.

Return values

- kStatus_Success – Successfully read data.
- kStatus_FLEXIO_I2C_Timeout – Timeout polling status flags.

status_t FLEXIO_I2C_MasterTransferBlocking(*FLEXIO_I2C_Type* *base,
flexio_i2c_master_transfer_t *xfer)

Performs a master polling transfer on the I2C bus.

Note: The API does not return until the transfer succeeds or fails due to receiving NAK.

Parameters

- base – pointer to FLEXIO_I2C_Type structure.
- xfer – pointer to flexio_i2c_master_transfer_t structure.

Returns

status of status_t.

status_t FLEXIO_I2C_MasterTransferCreateHandle(*FLEXIO_I2C_Type* *base,
flexio_i2c_master_handle_t *handle,
flexio_i2c_master_transfer_callback_t
callback, void *userData)

Initializes the I2C handle which is used in transactional functions.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- handle – Pointer to flexio_i2c_master_handle_t structure to store the transfer state.
- callback – Pointer to user callback function.
- userData – User param passed to the callback function.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/isr table out of range.

status_t FLEXIO_I2C_MasterTransferNonBlocking(*FLEXIO_I2C_Type* *base,
flexio_i2c_master_handle_t *handle,
flexio_i2c_master_transfer_t *xfer)

Performs a master interrupt non-blocking transfer on the I2C bus.

Note: The API returns immediately after the transfer initiates. Call FLEXIO_I2C_MasterTransferGetCount to poll the transfer status to check whether the

transfer is finished. If the return status is not kStatus_FLEXIO_I2C_Busy, the transfer is finished.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure
- handle – Pointer to flexio_i2c_master_handle_t structure which stores the transfer state
- xfer – pointer to flexio_i2c_master_transfer_t structure

Return values

- kStatus_Success – Successfully start a transfer.
- kStatus_FLEXIO_I2C_Busy – FlexIO I2C is not idle, is running another transfer.

status_t FLEXIO_I2C_MasterTransferGetCount(*FLEXIO_I2C_Type* *base,
flexio_i2c_master_handle_t *handle, size_t
*count)

Gets the master transfer status during a interrupt non-blocking transfer.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure.
- handle – Pointer to flexio_i2c_master_handle_t structure which stores the transfer state.
- count – Number of bytes transferred so far by the non-blocking transaction.

Return values

- kStatus_InvalidArgument – count is Invalid.
- kStatus_NoTransferInProgress – There is not a non-blocking transaction currently in progress.
- kStatus_Success – Successfully return the count.

void FLEXIO_I2C_MasterTransferAbort(*FLEXIO_I2C_Type* *base, flexio_i2c_master_handle_t
*handle)

Aborts an interrupt non-blocking transfer early.

Note: This API can be called at any time when an interrupt non-blocking transfer initiates to abort the transfer early.

Parameters

- base – Pointer to FLEXIO_I2C_Type structure
- handle – Pointer to flexio_i2c_master_handle_t structure which stores the transfer state

void FLEXIO_I2C_MasterTransferHandleIRQ(void *i2cType, void *i2cHandle)

Master interrupt handler.

Parameters

- i2cType – Pointer to FLEXIO_I2C_Type structure
- i2cHandle – Pointer to flexio_i2c_master_transfer_t structure

FSL_FLEXIO_I2C_MASTER_DRIVER_VERSION

FlexIO I2C transfer status.

Values:

enumerator kStatus_FLEXIO_I2C_Busy

I2C is busy doing transfer.

enumerator kStatus_FLEXIO_I2C_Idle

I2C is busy doing transfer.

enumerator kStatus_FLEXIO_I2C_Nak

NAK received during transfer.

enumerator kStatus_FLEXIO_I2C_Timeout

Timeout polling status flags.

enum _flexio_i2c_master_interrupt

Define FlexIO I2C master interrupt mask.

Values:

enumerator kFLEXIO_I2C_TxEmptyInterruptEnable

Tx buffer empty interrupt enable.

enumerator kFLEXIO_I2C_RxFullInterruptEnable

Rx buffer full interrupt enable.

enum _flexio_i2c_master_status_flags

Define FlexIO I2C master status mask.

Values:

enumerator kFLEXIO_I2C_TxEmptyFlag

Tx shifter empty flag.

enumerator kFLEXIO_I2C_RxFullFlag

Rx shifter full/Transfer complete flag.

enumerator kFLEXIO_I2C_ReceiveNakFlag

Receive NAK flag.

enum _flexio_i2c_direction

Direction of master transfer.

Values:

enumerator kFLEXIO_I2C_Write

Master send to slave.

enumerator kFLEXIO_I2C_Read

Master receive from slave.

typedef enum _flexio_i2c_direction flexio_i2c_direction_t

Direction of master transfer.

typedef struct _flexio_i2c_type FLEXIO_I2C_Type

Define FlexIO I2C master access structure typedef.

typedef struct _flexio_i2c_master_config flexio_i2c_master_config_t

Define FlexIO I2C master user configuration structure.

```
typedef struct _flexio_i2c_master_transfer flexio_i2c_master_transfer_t
```

Define FlexIO I2C master transfer structure.

```
typedef struct _flexio_i2c_master_handle flexio_i2c_master_handle_t
```

FlexIO I2C master handle typedef.

```
typedef void (*flexio_i2c_master_transfer_callback_t)(FLEXIO_I2C_Type *base,  
flexio_i2c_master_handle_t *handle, status_t status, void *userData)
```

FlexIO I2C master transfer callback typedef.

```
I2C_RETRY_TIMES
```

Retry times for waiting flag.

```
struct _flexio_i2c_type
```

#include <fsl_flexio_i2c_master.h> Define FlexIO I2C master access structure typedef.

Public Members

FLEXIO_Type *flexioBase

FlexIO base pointer.

uint8_t SDAPinIndex

Pin select for I2C SDA.

uint8_t SCLPinIndex

Pin select for I2C SCL.

uint8_t shifterIndex[2]

Shifter index used in FlexIO I2C.

uint8_t timerIndex[3]

Timer index used in FlexIO I2C.

uint32_t baudrate

Master transfer baudrate, used to calculate delay time.

```
struct _flexio_i2c_master_config
```

#include <fsl_flexio_i2c_master.h> Define FlexIO I2C master user configuration structure.

Public Members

bool enableMaster

Enables the FlexIO I2C peripheral at initialization time.

bool enableInDoze

Enable/disable FlexIO operation in doze mode.

bool enableInDebug

Enable/disable FlexIO operation in debug mode.

bool enableFastAccess

Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

uint32_t baudRate_Bps

Baud rate in Bps.

```
struct _flexio_i2c_master_transfer
```

#include <fsl_flexio_i2c_master.h> Define FlexIO I2C master transfer structure.

Public Members

uint32_t flags

Transfer flag which controls the transfer, reserved for FlexIO I2C.

uint8_t slaveAddress

7-bit slave address.

flexio_i2c_direction_t direction

Transfer direction, read or write.

uint32_t subaddress

Sub address. Transferred MSB first.

uint8_t subaddressSize

Size of sub address.

uint8_t volatile *data

Transfer buffer.

volatile size_t dataSize

Transfer size.

struct *_flexio_i2c_master_handle*

#include <fsl_flexio_i2c_master.h> Define FlexIO I2C master handle structure.

Public Members

flexio_i2c_master_transfer_t transfer

FlexIO I2C master transfer copy.

size_t transferSize

Total bytes to be transferred.

uint8_t state

Transfer state maintained during transfer.

flexio_i2c_master_transfer_callback_t completionCallback

Callback function called at transfer event. Callback function called at transfer event.

void *userData

Callback parameter passed to callback function.

bool needRestart

Whether master needs to send re-start signal.

2.16 FlexIO I2S Driver

void FLEXIO_I2S_Init(*FLEXIO_I2S_Type* *base, const *flexio_i2s_config_t* *config)

Initializes the FlexIO I2S.

This API configures FlexIO pins and shifter to I2S and configures the FlexIO I2S with a configuration structure. The configuration structure can be filled by the user, or be set with default values by FLEXIO_I2S_GetDefaultConfig().

Note: This API should be called at the beginning of the application to use the FlexIO I2S driver. Otherwise, any access to the FlexIO I2S module can cause hard fault because the clock is not enabled.

Parameters

- base – FlexIO I2S base pointer
- config – FlexIO I2S configure structure.

void FLEXIO_I2S_GetDefaultConfig(*flexio_i2s_config_t* *config)

Sets the FlexIO I2S configuration structure to default values.

The purpose of this API is to get the configuration structure initialized for use in FLEXIO_I2S_Init(). Users may use the initialized structure unchanged in FLEXIO_I2S_Init() or modify some fields of the structure before calling FLEXIO_I2S_Init().

Parameters

- config – pointer to master configuration structure

void FLEXIO_I2S_Deinit(*FLEXIO_I2S_Type* *base)

De-initializes the FlexIO I2S.

Calling this API resets the FlexIO I2S shifter and timer config. After calling this API, call the FLEXIO_I2S_Init to use the FlexIO I2S module.

Parameters

- base – FlexIO I2S base pointer

static inline void FLEXIO_I2S_Enable(*FLEXIO_I2S_Type* *base, bool enable)

Enables/disables the FlexIO I2S module operation.

Parameters

- base – Pointer to FLEXIO_I2S_Type
- enable – True to enable, false dose not have any effect.

uint32_t FLEXIO_I2S_GetStatusFlags(*FLEXIO_I2S_Type* *base)

Gets the FlexIO I2S status flags.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure

Returns

Status flag, which are ORed by the enumerators in the `_flexio_i2s_status_flags`.

void FLEXIO_I2S_EnableInterrupts(*FLEXIO_I2S_Type* *base, uint32_t mask)

Enables the FlexIO I2S interrupt.

This function enables the FlexIO UART interrupt.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure
- mask – interrupt source

void FLEXIO_I2S_DisableInterrupts(*FLEXIO_I2S_Type* *base, uint32_t mask)

Disables the FlexIO I2S interrupt.

This function enables the FlexIO UART interrupt.

Parameters

- base – pointer to FLEXIO_I2S_Type structure
- mask – interrupt source

```
static inline void FLEXIO_I2S_TxEnableDMA(FLEXIO_I2S_Type *base, bool enable)
```

Enables/disables the FlexIO I2S Tx DMA requests.

Parameters

- base – FlexIO I2S base pointer
- enable – True means enable DMA, false means disable DMA.

```
static inline void FLEXIO_I2S_RxEnableDMA(FLEXIO_I2S_Type *base, bool enable)
```

Enables/disables the FlexIO I2S Rx DMA requests.

Parameters

- base – FlexIO I2S base pointer
- enable – True means enable DMA, false means disable DMA.

```
static inline uint32_t FLEXIO_I2S_TxGetDataRegisterAddress(FLEXIO_I2S_Type *base)
```

Gets the FlexIO I2S send data register address.

This function returns the I2S data register address, mainly used by DMA/eDMA.

Parameters

- base – Pointer to *FLEXIO_I2S_Type* structure

Returns

FlexIO i2s send data register address.

```
static inline uint32_t FLEXIO_I2S_RxGetDataRegisterAddress(FLEXIO_I2S_Type *base)
```

Gets the FlexIO I2S receive data register address.

This function returns the I2S data register address, mainly used by DMA/eDMA.

Parameters

- base – Pointer to *FLEXIO_I2S_Type* structure

Returns

FlexIO i2s receive data register address.

```
void FLEXIO_I2S_MasterSetFormat(FLEXIO_I2S_Type *base, flexio_i2s_format_t *format,  
                                uint32_t srcClock_Hz)
```

Configures the FlexIO I2S audio format in master mode.

Audio format can be changed in run-time of FlexIO I2S. This function configures the sample rate and audio data format to be transferred.

Parameters

- base – Pointer to *FLEXIO_I2S_Type* structure
- format – Pointer to FlexIO I2S audio data format structure.
- srcClock_Hz – I2S master clock source frequency in Hz.

```
void FLEXIO_I2S_SlaveSetFormat(FLEXIO_I2S_Type *base, flexio_i2s_format_t *format)
```

Configures the FlexIO I2S audio format in slave mode.

Audio format can be changed in run-time of FlexIO I2S. This function configures the sample rate and audio data format to be transferred.

Parameters

- base – Pointer to *FLEXIO_I2S_Type* structure
- format – Pointer to FlexIO I2S audio data format structure.

```
status_t FLEXIO_I2S_WriteBlocking(FLEXIO_I2S_Type *base, uint8_t bitWidth, uint8_t *txData,  
                                size_t size)
```

Sends data using a blocking method.

Note: This function blocks via polling until data is ready to be sent.

Parameters

- base – FlexIO I2S base pointer.
- bitWidth – How many bits in a audio word, usually 8/16/24/32 bits.
- txData – Pointer to the data to be written.
- size – Bytes to be written.

Return values

- kStatus_Success – Successfully write data.
- kStatus_FLEXIO_I2C_Timeout – Timeout polling status flags.

```
static inline void FLEXIO_I2S_WriteData(FLEXIO_I2S_Type *base, uint8_t bitWidth, uint32_t  
                                       data)
```

Writes data into a data register.

Parameters

- base – FlexIO I2S base pointer.
- bitWidth – How many bits in a audio word, usually 8/16/24/32 bits.
- data – Data to be written.

```
status_t FLEXIO_I2S_ReadBlocking(FLEXIO_I2S_Type *base, uint8_t bitWidth, uint8_t *rxData,  
                                size_t size)
```

Receives a piece of data using a blocking method.

Note: This function blocks via polling until data is ready to be sent.

Parameters

- base – FlexIO I2S base pointer
- bitWidth – How many bits in a audio word, usually 8/16/24/32 bits.
- rxData – Pointer to the data to be read.
- size – Bytes to be read.

Return values

- kStatus_Success – Successfully read data.
- kStatus_FLEXIO_I2C_Timeout – Timeout polling status flags.

```
static inline uint32_t FLEXIO_I2S_ReadData(FLEXIO_I2S_Type *base)
```

Reads a data from the data register.

Parameters

- base – FlexIO I2S base pointer

Returns

Data read from data register.

```
void FLEXIO_I2S_TransferTxCreateHandle(FLEXIO_I2S_Type *base, flexio_i2s_handle_t *handle,  
                                       flexio_i2s_callback_t callback, void *userData)
```

Initializes the FlexIO I2S handle.

This function initializes the FlexIO I2S handle which can be used for other FlexIO I2S transactional APIs. Call this API once to get the initialized handle.

Parameters

- base – Pointer to *FLEXIO_I2S_Type* structure
- handle – Pointer to *flexio_i2s_handle_t* structure to store the transfer state.
- callback – FlexIO I2S callback function, which is called while finished a block.
- userData – User parameter for the FlexIO I2S callback.

```
void FLEXIO_I2S_TransferSetFormat(FLEXIO_I2S_Type *base, flexio_i2s_handle_t *handle,  
                                  flexio_i2s_format_t *format, uint32_t srcClock_Hz)
```

Configures the FlexIO I2S audio format.

Audio format can be changed at run-time of FlexIO I2S. This function configures the sample rate and audio data format to be transferred.

Parameters

- base – Pointer to *FLEXIO_I2S_Type* structure.
- handle – FlexIO I2S handle pointer.
- format – Pointer to audio data format structure.
- srcClock_Hz – FlexIO I2S bit clock source frequency in Hz. This parameter should be 0 while in slave mode.

```
void FLEXIO_I2S_TransferRxCreateHandle(FLEXIO_I2S_Type *base, flexio_i2s_handle_t *handle,  
                                       flexio_i2s_callback_t callback, void *userData)
```

Initializes the FlexIO I2S receive handle.

This function initializes the FlexIO I2S handle which can be used for other FlexIO I2S transactional APIs. Call this API once to get the initialized handle.

Parameters

- base – Pointer to *FLEXIO_I2S_Type* structure.
- handle – Pointer to *flexio_i2s_handle_t* structure to store the transfer state.
- callback – FlexIO I2S callback function, which is called while finished a block.
- userData – User parameter for the FlexIO I2S callback.

```
status_t FLEXIO_I2S_TransferSendNonBlocking(FLEXIO_I2S_Type *base, flexio_i2s_handle_t  
                                             *handle, flexio_i2s_transfer_t *xfer)
```

Performs an interrupt non-blocking send transfer on FlexIO I2S.

Note: The API returns immediately after transfer initiates. Call *FLEXIO_I2S_GetRemainingBytes* to poll the transfer status and check whether the transfer is finished. If the return status is 0, the transfer is finished.

Parameters

- base – Pointer to *FLEXIO_I2S_Type* structure.

- handle – Pointer to flexio_i2s_handle_t structure which stores the transfer state
- xfer – Pointer to flexio_i2s_transfer_t structure

Return values

- kStatus_Success – Successfully start the data transmission.
- kStatus_FLEXIO_I2S_TxBusy – Previous transmission still not finished, data not all written to TX register yet.
- kStatus_InvalidArgument – The input parameter is invalid.

status_t FLEXIO_I2S_TransferReceiveNonBlocking(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle, *flexio_i2s_transfer_t* *xfer)

Performs an interrupt non-blocking receive transfer on FlexIO I2S.

Note: The API returns immediately after transfer initiates. Call FLEXIO_I2S_GetRemainingBytes to poll the transfer status to check whether the transfer is finished. If the return status is 0, the transfer is finished.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure.
- handle – Pointer to flexio_i2s_handle_t structure which stores the transfer state
- xfer – Pointer to flexio_i2s_transfer_t structure

Return values

- kStatus_Success – Successfully start the data receive.
- kStatus_FLEXIO_I2S_RxBusy – Previous receive still not finished.
- kStatus_InvalidArgument – The input parameter is invalid.

void FLEXIO_I2S_TransferAbortSend(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle)

Aborts the current send.

Note: This API can be called at any time when interrupt non-blocking transfer initiates to abort the transfer in a early time.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure.
- handle – Pointer to flexio_i2s_handle_t structure which stores the transfer state

void FLEXIO_I2S_TransferAbortReceive(*FLEXIO_I2S_Type* *base, *flexio_i2s_handle_t* *handle)

Aborts the current receive.

Note: This API can be called at any time when interrupt non-blocking transfer initiates to abort the transfer in a early time.

Parameters

- base – Pointer to FLEXIO_I2S_Type structure.

- `handle` – Pointer to `flexio_i2s_handle_t` structure which stores the transfer state

`status_t FLEXIO_I2S_TransferGetSendCount(FLEXIO_I2S_Type *base, flexio_i2s_handle_t *handle, size_t *count)`

Gets the remaining bytes to be sent.

Parameters

- `base` – Pointer to `FLEXIO_I2S_Type` structure.
- `handle` – Pointer to `flexio_i2s_handle_t` structure which stores the transfer state
- `count` – Bytes sent.

Return values

- `kStatus_Success` – Succeed get the transfer count.
- `kStatus_NoTransferInProgress` – There is not a non-blocking transaction currently in progress.

`status_t FLEXIO_I2S_TransferGetReceiveCount(FLEXIO_I2S_Type *base, flexio_i2s_handle_t *handle, size_t *count)`

Gets the remaining bytes to be received.

Parameters

- `base` – Pointer to `FLEXIO_I2S_Type` structure.
- `handle` – Pointer to `flexio_i2s_handle_t` structure which stores the transfer state
- `count` – Bytes recieved.

Return values

- `kStatus_Success` – Succeed get the transfer count.
- `kStatus_NoTransferInProgress` – There is not a non-blocking transaction currently in progress.

Returns

`count` Bytes received.

`void FLEXIO_I2S_TransferTxHandleIRQ(void *i2sBase, void *i2sHandle)`

Tx interrupt handler.

Parameters

- `i2sBase` – Pointer to `FLEXIO_I2S_Type` structure.
- `i2sHandle` – Pointer to `flexio_i2s_handle_t` structure

`void FLEXIO_I2S_TransferRxHandleIRQ(void *i2sBase, void *i2sHandle)`

Rx interrupt handler.

Parameters

- `i2sBase` – Pointer to `FLEXIO_I2S_Type` structure.
- `i2sHandle` – Pointer to `flexio_i2s_handle_t` structure.

`FSL_FLEXIO_I2S_DRIVER_VERSION`

FlexIO I2S driver version 2.2.2.

FlexIO I2S transfer status.

Values:

enumerator kStatus_FLEXIO_I2S_Idle

FlexIO I2S is in idle state

enumerator kStatus_FLEXIO_I2S_TxBusy

FlexIO I2S Tx is busy

enumerator kStatus_FLEXIO_I2S_RxBusy

FlexIO I2S Rx is busy

enumerator kStatus_FLEXIO_I2S_Error

FlexIO I2S error occurred

enumerator kStatus_FLEXIO_I2S_QueueFull

FlexIO I2S transfer queue is full.

enumerator kStatus_FLEXIO_I2S_Timeout

FlexIO I2S timeout polling status flags.

enum _flexio_i2s_master_slave

Master or slave mode.

Values:

enumerator kFLEXIO_I2S_Master

Master mode

enumerator kFLEXIO_I2S_Slave

Slave mode

_flexio_i2s_interrupt_enable Define FlexIO FlexIO I2S interrupt mask.

Values:

enumerator kFLEXIO_I2S_TxDataRegEmptyInterruptEnable

Transmit buffer empty interrupt enable.

enumerator kFLEXIO_I2S_RxDataRegFullInterruptEnable

Receive buffer full interrupt enable.

_flexio_i2s_status_flags Define FlexIO FlexIO I2S status mask.

Values:

enumerator kFLEXIO_I2S_TxDataRegEmptyFlag

Transmit buffer empty flag.

enumerator kFLEXIO_I2S_RxDataRegFullFlag

Receive buffer full flag.

enum _flexio_i2s_sample_rate

Audio sample rate.

Values:

enumerator kFLEXIO_I2S_SampleRate8KHz

Sample rate 8000Hz


```
enumerator kFLEXIO_I2S_SampleRate11025Hz
    Sample rate 11025Hz
enumerator kFLEXIO_I2S_SampleRate12KHz
    Sample rate 12000Hz
enumerator kFLEXIO_I2S_SampleRate16KHz
    Sample rate 16000Hz
enumerator kFLEXIO_I2S_SampleRate22050Hz
    Sample rate 22050Hz
enumerator kFLEXIO_I2S_SampleRate24KHz
    Sample rate 24000Hz
enumerator kFLEXIO_I2S_SampleRate32KHz
    Sample rate 32000Hz
enumerator kFLEXIO_I2S_SampleRate44100Hz
    Sample rate 44100Hz
enumerator kFLEXIO_I2S_SampleRate48KHz
    Sample rate 48000Hz
enumerator kFLEXIO_I2S_SampleRate96KHz
    Sample rate 96000Hz
enum _flexio_i2s_word_width
    Audio word width.
    Values:
enumerator kFLEXIO_I2S_WordWidth8bits
    Audio data width 8 bits
enumerator kFLEXIO_I2S_WordWidth16bits
    Audio data width 16 bits
enumerator kFLEXIO_I2S_WordWidth24bits
    Audio data width 24 bits
enumerator kFLEXIO_I2S_WordWidth32bits
    Audio data width 32 bits
typedef struct _flexio_i2s_type FLEXIO_I2S_Type
    Define FlexIO I2S access structure typedef.
typedef enum _flexio_i2s_master_slave flexio_i2s_master_slave_t
    Master or slave mode.
typedef struct _flexio_i2s_config flexio_i2s_config_t
    FlexIO I2S configure structure.
typedef struct _flexio_i2s_format flexio_i2s_format_t
    FlexIO I2S audio format, FlexIO I2S only support the same format in Tx and Rx.
typedef enum _flexio_i2s_sample_rate flexio_i2s_sample_rate_t
    Audio sample rate.
typedef enum _flexio_i2s_word_width flexio_i2s_word_width_t
    Audio word width.
```

```
typedef struct _flexio_i2s_transfer flexio_i2s_transfer_t
```

Define FlexIO I2S transfer structure.

```
typedef struct _flexio_i2s_handle flexio_i2s_handle_t
```

```
typedef void (*flexio_i2s_callback_t)(FLEXIO_I2S_Type *base, flexio_i2s_handle_t *handle,  
status_t status, void *userData)
```

FlexIO I2S xfer callback prototype.

```
I2S_RETRY_TIMES
```

Retry times for waiting flag.

```
FLEXIO_I2S_XFER_QUEUE_SIZE
```

FlexIO I2S transfer queue size, user can refine it according to use case.

```
struct _flexio_i2s_type
```

#include <fsl_flexio_i2s.h> Define FlexIO I2S access structure typedef.

Public Members

FLEXIO_Type *flexioBase

FlexIO base pointer

uint8_t txPinIndex

Tx data pin index in FlexIO pins

uint8_t rxPinIndex

Rx data pin index

uint8_t bclkPinIndex

Bit clock pin index

uint8_t fsPinIndex

Frame sync pin index

uint8_t txShifterIndex

Tx data shifter index

uint8_t rxShifterIndex

Rx data shifter index

uint8_t bclkTimerIndex

Bit clock timer index

uint8_t fsTimerIndex

Frame sync timer index

```
struct _flexio_i2s_config
```

#include <fsl_flexio_i2s.h> FlexIO I2S configure structure.

Public Members

bool enableI2S

Enable FlexIO I2S

flexio_i2s_master_slave_t masterSlave

Master or slave

flexio_pin_polarity_t txPinPolarity

Tx data pin polarity, active high or low

flexio_pin_polarity_t rxPinPolarity
Rx data pin polarity

flexio_pin_polarity_t bclkPinPolarity
Bit clock pin polarity

flexio_pin_polarity_t fsPinPolarity
Frame sync pin polarity

flexio_shifter_timer_polarity_t txTimerPolarity
Tx data valid on bclk rising or falling edge

flexio_shifter_timer_polarity_t rxTimerPolarity
Rx data valid on bclk rising or falling edge

struct *_flexio_i2s_format*

#include <fsl_flexio_i2s.h> FlexIO I2S audio format, FlexIO I2S only support the same format in Tx and Rx.

Public Members

uint8_t bitWidth
Bit width of audio data, always 8/16/24/32 bits

uint32_t sampleRate_Hz
Sample rate of the audio data

struct *_flexio_i2s_transfer*

#include <fsl_flexio_i2s.h> Define FlexIO I2S transfer structure.

Public Members

uint8_t *data
Data buffer start pointer

size_t dataSize
Bytes to be transferred.

struct *_flexio_i2s_handle*

#include <fsl_flexio_i2s.h> Define FlexIO I2S handle structure.

Public Members

uint32_t state
Internal state

flexio_i2s_callback_t callback
Callback function called at transfer event

void *userData
Callback parameter passed to callback function

uint8_t bitWidth
Bit width for transfer, 8/16/24/32bits

flexio_i2s_transfer_t queue[(4U)]
Transfer queue storing queued transfer

```
size_t transferSize[(4U)]
```

Data bytes need to transfer

```
volatile uint8_t queueUser
```

Index for user to queue transfer

```
volatile uint8_t queueDriver
```

Index for driver to get the transfer data and size

2.17 FlexIO SPI Driver

```
void FLEXIO_SPI_MasterInit(FLEXIO_SPI_Type *base, flexio_spi_master_config_t
                           *masterConfig, uint32_t srcClock_Hz)
```

Ungates the FlexIO clock, resets the FlexIO module, configures the FlexIO SPI master hardware, and configures the FlexIO SPI with FlexIO SPI master configuration. The configuration structure can be filled by the user, or be set with default values by the FLEXIO_SPI_MasterGetDefaultConfig().

Example

```
FLEXIO_SPI_Type spiDev = {
    .flexioBase = FLEXIO,
    .SDOPinIndex = 0,
    .SDIPinIndex = 1,
    .SCKPinIndex = 2,
    .CSnPinIndex = 3,
    .shifterIndex = {0,1},
    .timerIndex = {0,1}
};
flexio_spi_master_config_t config = {
    .enableMaster = true,
    .enableInDoze = false,
    .enableInDebug = true,
    .enableFastAccess = false,
    .baudRate_Bps = 500000,
    .phase = kFLEXIO_SPI_ClockPhaseFirstEdge,
    .direction = kFLEXIO_SPI_MsbFirst,
    .dataMode = kFLEXIO_SPI_8BitMode
};
FLEXIO_SPI_MasterInit(&spiDev, &config, srcClock_Hz);
```

Note: 1.FlexIO SPI master only support CPOL = 0, which means clock inactive low. 2.For FlexIO SPI master, the input valid time is 1.5 clock cycles, for slave the output valid time is 2.5 clock cycles. So if FlexIO SPI master communicates with other spi IPs, the maximum baud rate is FlexIO clock frequency divided by $2*2=4$. If FlexIO SPI master communicates with FlexIO SPI slave, the maximum baud rate is FlexIO clock frequency divided by $(1.5+2.5)*2=8$.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- masterConfig – Pointer to the flexio_spi_master_config_t structure.
- srcClock_Hz – FlexIO source clock in Hz.

```
void FLEXIO_SPI_MasterDeinit(FLEXIO_SPI_Type *base)
```

Resets the FlexIO SPI timer and shifter config.

Parameters

- base – Pointer to the *FLEXIO_SPI_Type*.

```
void FLEXIO_SPI_MasterGetDefaultConfig(flexio_spi_master_config_t *masterConfig)
```

Gets the default configuration to configure the FlexIO SPI master. The configuration can be used directly by calling the *FLEXIO_SPI_MasterConfigure()*. Example:

```
flexio_spi_master_config_t masterConfig;  
FLEXIO_SPI_MasterGetDefaultConfig(&masterConfig);
```

Parameters

- masterConfig – Pointer to the *flexio_spi_master_config_t* structure.

```
void FLEXIO_SPI_SlaveInit(FLEXIO_SPI_Type *base, flexio_spi_slave_config_t *slaveConfig)
```

Ungates the FlexIO clock, resets the FlexIO module, configures the FlexIO SPI slave hardware configuration, and configures the FlexIO SPI with FlexIO SPI slave configuration. The configuration structure can be filled by the user, or be set with default values by the *FLEXIO_SPI_SlaveGetDefaultConfig()*.

Note: 1. Only one timer is needed in the FlexIO SPI slave. As a result, the second timer index is ignored. 2. FlexIO SPI slave only support CPOL = 0, which means clock inactive low. 3. For FlexIO SPI master, the input valid time is 1.5 clock cycles, for slave the output valid time is 2.5 clock cycles. So if FlexIO SPI slave communicates with other spi IPs, the maximum baud rate is FlexIO clock frequency divided by $3*2=6$. If FlexIO SPI slave communicates with FlexIO SPI master, the maximum baud rate is FlexIO clock frequency divided by $(1.5+2.5)*2=8$. Example

```
FLEXIO_SPI_Type spiDev = {  
    .flexioBase = FLEXIO,  
    .SDOPinIndex = 0,  
    .SDIPinIndex = 1,  
    .SCKPinIndex = 2,  
    .CSnPinIndex = 3,  
    .shifterIndex = {0,1},  
    .timerIndex = {0}  
};  
flexio_spi_slave_config_t config = {  
    .enableSlave = true,  
    .enableInDoze = false,  
    .enableInDebug = true,  
    .enableFastAccess = false,  
    .phase = kFLEXIO_SPI_ClockPhaseFirstEdge,  
    .direction = kFLEXIO_SPI_MsbFirst,  
    .dataMode = kFLEXIO_SPI_8BitMode  
};  
FLEXIO_SPI_SlaveInit(&spiDev, &config);
```

Parameters

- base – Pointer to the *FLEXIO_SPI_Type* structure.
- slaveConfig – Pointer to the *flexio_spi_slave_config_t* structure.

void FLEXIO_SPI_SlaveDeinit(*FLEXIO_SPI_Type* *base)

Gates the FlexIO clock.

Parameters

- base – Pointer to the FLEXIO_SPI_Type.

void FLEXIO_SPI_SlaveGetDefaultConfig(*flexio_spi_slave_config_t* *slaveConfig)

Gets the default configuration to configure the FlexIO SPI slave. The configuration can be used directly for calling the FLEXIO_SPI_SlaveConfigure(). Example:

```
flexio_spi_slave_config_t slaveConfig;
FLEXIO_SPI_SlaveGetDefaultConfig(&slaveConfig);
```

Parameters

- slaveConfig – Pointer to the flexio_spi_slave_config_t structure.

uint32_t FLEXIO_SPI_GetStatusFlags(*FLEXIO_SPI_Type* *base)

Gets FlexIO SPI status flags.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.

Returns

status flag; Use the status flag to AND the following flag mask and get the status.

- kFLEXIO_SPI_TxEmptyFlag
- kFLEXIO_SPI_RxEmptyFlag

void FLEXIO_SPI_ClearStatusFlags(*FLEXIO_SPI_Type* *base, uint32_t mask)

Clears FlexIO SPI status flags.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- mask – status flag The parameter can be any combination of the following values:
 - kFLEXIO_SPI_TxEmptyFlag
 - kFLEXIO_SPI_RxEmptyFlag

void FLEXIO_SPI_EnableInterrupts(*FLEXIO_SPI_Type* *base, uint32_t mask)

Enables the FlexIO SPI interrupt.

This function enables the FlexIO SPI interrupt.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- mask – interrupt source. The parameter can be any combination of the following values:
 - kFLEXIO_SPI_RxFullInterruptEnable
 - kFLEXIO_SPI_TxEmptyInterruptEnable

void FLEXIO_SPI_DisableInterrupts(*FLEXIO_SPI_Type* *base, uint32_t mask)

Disables the FlexIO SPI interrupt.

This function disables the FlexIO SPI interrupt.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- mask – interrupt source The parameter can be any combination of the following values:
 - kFLEXIO_SPI_RxFullInterruptEnable
 - kFLEXIO_SPI_TxEmptyInterruptEnable

void FLEXIO_SPI_EnableDMA(*FLEXIO_SPI_Type* *base, uint32_t mask, bool enable)

Enables/disables the FlexIO SPI transmit DMA. This function enables/disables the FlexIO SPI Tx DMA, which means that asserting the kFLEXIO_SPI_TxEmptyFlag does/doesn't trigger the DMA request.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- mask – SPI DMA source.
- enable – True means enable DMA, false means disable DMA.

static inline uint32_t FLEXIO_SPI_GetTxDataRegisterAddress(*FLEXIO_SPI_Type* *base,
flexio_spi_shift_direction_t
direction)

Gets the FlexIO SPI transmit data register address for MSB first transfer.

This function returns the SPI data register address, which is mainly used by DMA/eDMA.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- direction – Shift direction of MSB first or LSB first.

Returns

FlexIO SPI transmit data register address.

static inline uint32_t FLEXIO_SPI_GetRxDataRegisterAddress(*FLEXIO_SPI_Type* *base,
flexio_spi_shift_direction_t
direction)

Gets the FlexIO SPI receive data register address for the MSB first transfer.

This function returns the SPI data register address, which is mainly used by DMA/eDMA.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- direction – Shift direction of MSB first or LSB first.

Returns

FlexIO SPI receive data register address.

static inline void FLEXIO_SPI_Enable(*FLEXIO_SPI_Type* *base, bool enable)

Enables/disables the FlexIO SPI module operation.

Parameters

- base – Pointer to the FLEXIO_SPI_Type.
- enable – True to enable, false does not have any effect.

void FLEXIO_SPI_MasterSetBaudRate(*FLEXIO_SPI_Type* *base, uint32_t baudRate_Bps,
uint32_t srcClockHz)

Sets baud rate for the FlexIO SPI transfer, which is only used for the master.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- baudRate_Bps – Baud Rate needed in Hz.
- srcClockHz – SPI source clock frequency in Hz.

```
static inline void FLEXIO_SPI_WriteData(FLEXIO_SPI_Type *base, flexio_spi_shift_direction_t  
                                         direction, uint32_t data)
```

Writes one byte of data, which is sent using the MSB method.

Note: This is a non-blocking API, which returns directly after the data is put into the data register but the data transfer is not finished on the bus. Ensure that the TxEmptyFlag is asserted before calling this API.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- direction – Shift direction of MSB first or LSB first.
- data – 8/16/32 bit data.

```
static inline uint32_t FLEXIO_SPI_ReadData(FLEXIO_SPI_Type *base,  
                                           flexio_spi_shift_direction_t direction)
```

Reads 8 bit/16 bit data.

Note: This is a non-blocking API, which returns directly after the data is read from the data register. Ensure that the RxFullFlag is asserted before calling this API.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- direction – Shift direction of MSB first or LSB first.

Returns

8 bit/16 bit data received.

```
status_t FLEXIO_SPI_WriteBlocking(FLEXIO_SPI_Type *base, flexio_spi_shift_direction_t  
                                   direction, const uint8_t *buffer, size_t size)
```

Sends a buffer of data bytes.

Note: This function blocks using the polling method until all bytes have been sent.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- direction – Shift direction of MSB first or LSB first.
- buffer – The data bytes to send.
- size – The number of data bytes to send.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_FLEXIO_SPI_Timeout – The transfer timed out and was aborted.

status_t FLEXIO_SPI_ReadBlocking(*FLEXIO_SPI_Type* *base, *flexio_spi_shift_direction_t* direction, *uint8_t* *buffer, *size_t* size)

Receives a buffer of bytes.

Note: This function blocks using the polling method until all bytes have been received.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- direction – Shift direction of MSB first or LSB first.
- buffer – The buffer to store the received bytes.
- size – The number of data bytes to be received.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_FLEXIO_SPI_Timeout – The transfer timed out and was aborted.

status_t FLEXIO_SPI_MasterTransferBlocking(*FLEXIO_SPI_Type* *base, *flexio_spi_transfer_t* *xfer)

Receives a buffer of bytes.

Note: This function blocks via polling until all bytes have been received.

Parameters

- base – pointer to FLEXIO_SPI_Type structure
- xfer – FlexIO SPI transfer structure, see flexio_spi_transfer_t.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_FLEXIO_SPI_Timeout – The transfer timed out and was aborted.

void FLEXIO_SPI_FlushShifters(*FLEXIO_SPI_Type* *base)

Flush tx/rx shifters.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.

status_t FLEXIO_SPI_MasterTransferCreateHandle(*FLEXIO_SPI_Type* *base, *flexio_spi_master_handle_t* *handle, *flexio_spi_master_transfer_callback_t* callback, *void* *userData)

Initializes the FlexIO SPI Master handle, which is used in transactional functions.

Parameters

- base – Pointer to the FLEXIO_SPI_Type structure.
- handle – Pointer to the flexio_spi_master_handle_t structure to store the transfer state.
- callback – The callback function.
- userData – The parameter of the callback function.

Return values

- `kStatus_Success` – Successfully create the handle.
- `kStatus_OutOfRange` – The FlexIO type/handle/ISR table out of range.

`status_t` FLEXIO_SPI_MasterTransferNonBlocking(*FLEXIO_SPI_Type* *base,
 flexio_spi_master_handle_t *handle,
 flexio_spi_transfer_t *xfer)

Master transfer data using IRQ.

This function sends data using IRQ. This is a non-blocking function, which returns right away. When all data is sent out/received, the callback function is called.

Parameters

- `base` – Pointer to the `FLEXIO_SPI_Type` structure.
- `handle` – Pointer to the `flexio_spi_master_handle_t` structure to store the transfer state.
- `xfer` – FlexIO SPI transfer structure. See `flexio_spi_transfer_t`.

Return values

- `kStatus_Success` – Successfully start a transfer.
- `kStatus_InvalidArgument` – Input argument is invalid.
- `kStatus_FLEXIO_SPI_Busy` – SPI is not idle, is running another transfer.

`void` FLEXIO_SPI_MasterTransferAbort(*FLEXIO_SPI_Type* *base, *flexio_spi_master_handle_t*
 *handle)

Aborts the master data transfer, which used IRQ.

Parameters

- `base` – Pointer to the `FLEXIO_SPI_Type` structure.
- `handle` – Pointer to the `flexio_spi_master_handle_t` structure to store the transfer state.

`status_t` FLEXIO_SPI_MasterTransferGetCount(*FLEXIO_SPI_Type* *base,
 flexio_spi_master_handle_t *handle, `size_t`
 *count)

Gets the data transfer status which used IRQ.

Parameters

- `base` – Pointer to the `FLEXIO_SPI_Type` structure.
- `handle` – Pointer to the `flexio_spi_master_handle_t` structure to store the transfer state.
- `count` – Number of bytes transferred so far by the non-blocking transaction.

Return values

- `kStatus_InvalidArgument` – `count` is Invalid.
- `kStatus_Success` – Successfully return the count.

`void` FLEXIO_SPI_MasterTransferHandleIRQ(`void` *spiType, `void` *spiHandle)

FlexIO SPI master IRQ handler function.

Parameters

- `spiType` – Pointer to the `FLEXIO_SPI_Type` structure.
- `spiHandle` – Pointer to the `flexio_spi_master_handle_t` structure to store the transfer state.

```
status_t FLEXIO_SPI_SlaveTransferCreateHandle(FLEXIO_SPI_Type *base,  
                                              flexio_spi_slave_handle_t *handle,  
                                              flexio_spi_slave_transfer_callback_t callback,  
                                              void *userData)
```

Initializes the FlexIO SPI Slave handle, which is used in transactional functions.

Parameters

- base – Pointer to the `FLEXIO_SPI_Type` structure.
- handle – Pointer to the `flexio_spi_slave_handle_t` structure to store the transfer state.
- callback – The callback function.
- userData – The parameter of the callback function.

Return values

- `kStatus_Success` – Successfully create the handle.
- `kStatus_OutOfRange` – The FlexIO type/handle/ISR table out of range.

```
status_t FLEXIO_SPI_SlaveTransferNonBlocking(FLEXIO_SPI_Type *base,  
                                              flexio_spi_slave_handle_t *handle,  
                                              flexio_spi_transfer_t *xfer)
```

Slave transfer data using IRQ.

This function sends data using IRQ. This is a non-blocking function, which returns right away. When all data is sent out/received, the callback function is called.

Parameters

- handle – Pointer to the `flexio_spi_slave_handle_t` structure to store the transfer state.
- base – Pointer to the `FLEXIO_SPI_Type` structure.
- xfer – FlexIO SPI transfer structure. See `flexio_spi_transfer_t`.

Return values

- `kStatus_Success` – Successfully start a transfer.
- `kStatus_InvalidArgument` – Input argument is invalid.
- `kStatus_FLEXIO_SPI_Busy` – SPI is not idle; it is running another transfer.

```
static inline void FLEXIO_SPI_SlaveTransferAbort(FLEXIO_SPI_Type *base,  
                                              flexio_spi_slave_handle_t *handle)
```

Aborts the slave data transfer which used IRQ, share same API with master.

Parameters

- base – Pointer to the `FLEXIO_SPI_Type` structure.
- handle – Pointer to the `flexio_spi_slave_handle_t` structure to store the transfer state.

```
static inline status_t FLEXIO_SPI_SlaveTransferGetCount(FLEXIO_SPI_Type *base,  
                                                       flexio_spi_slave_handle_t *handle,  
                                                       size_t *count)
```

Gets the data transfer status which used IRQ, share same API with master.

Parameters

- base – Pointer to the `FLEXIO_SPI_Type` structure.
- handle – Pointer to the `flexio_spi_slave_handle_t` structure to store the transfer state.

- `count` – Number of bytes transferred so far by the non-blocking transaction.

Return values

- `kStatus_InvalidArgument` – `count` is Invalid.
- `kStatus_Success` – Successfully return the count.

`void FLEXIO_SPI_SlaveTransferHandleIRQ(void *spiType, void *spiHandle)`

FlexIO SPI slave IRQ handler function.

Parameters

- `spiType` – Pointer to the `FLEXIO_SPI_Type` structure.
- `spiHandle` – Pointer to the `flexio_spi_slave_handle_t` structure to store the transfer state.

`FSL_FLEXIO_SPI_DRIVER_VERSION`

FlexIO SPI driver version.

Error codes for the FlexIO SPI driver.

Values:

enumerator `kStatus_FLEXIO_SPI_Busy`
FlexIO SPI is busy.

enumerator `kStatus_FLEXIO_SPI_Idle`
SPI is idle

enumerator `kStatus_FLEXIO_SPI_Error`
FlexIO SPI error.

enumerator `kStatus_FLEXIO_SPI_Timeout`
FlexIO SPI timeout polling status flags.

enum `_flexio_spi_clock_phase`

FlexIO SPI clock phase configuration.

Values:

enumerator `kFLEXIO_SPI_ClockPhaseFirstEdge`
First edge on SPSCCK occurs at the middle of the first cycle of a data transfer.

enumerator `kFLEXIO_SPI_ClockPhaseSecondEdge`
First edge on SPSCCK occurs at the start of the first cycle of a data transfer.

enum `_flexio_spi_shift_direction`

FlexIO SPI data shifter direction options.

Values:

enumerator `kFLEXIO_SPI_MsbFirst`
Data transfers start with most significant bit.

enumerator `kFLEXIO_SPI_LsbFirst`
Data transfers start with least significant bit.

enum `_flexio_spi_data_bitcount_mode`

FlexIO SPI data length mode options.

Values:

enumerator `kFLEXIO_SPI_8BitMode`
8-bit data transmission mode.

enumerator kFLEXIO_SPI_16BitMode
16-bit data transmission mode.

enumerator kFLEXIO_SPI_32BitMode
32-bit data transmission mode.

enum _flexio_spi_interrupt_enable
Define FlexIO SPI interrupt mask.

Values:

enumerator kFLEXIO_SPI_TxEmptyInterruptEnable
Transmit buffer empty interrupt enable.

enumerator kFLEXIO_SPI_RxFullInterruptEnable
Receive buffer full interrupt enable.

enum _flexio_spi_status_flags
Define FlexIO SPI status mask.

Values:

enumerator kFLEXIO_SPI_TxBufferEmptyFlag
Transmit buffer empty flag.

enumerator kFLEXIO_SPI_RxBufferFullFlag
Receive buffer full flag.

enum _flexio_spi_dma_enable
Define FlexIO SPI DMA mask.

Values:

enumerator kFLEXIO_SPI_TxDmaEnable
Tx DMA request source

enumerator kFLEXIO_SPI_RxDmaEnable
Rx DMA request source

enumerator kFLEXIO_SPI_DmaAllEnable
All DMA request source

enum _flexio_spi_transfer_flags
Define FlexIO SPI transfer flags.

Note: Use kFLEXIO_SPI_csContinuous and one of the other flags to OR together to form the transfer flag.

Values:

enumerator kFLEXIO_SPI_8bitMsb
FlexIO SPI 8-bit MSB first

enumerator kFLEXIO_SPI_8bitLsb
FlexIO SPI 8-bit LSB first

enumerator kFLEXIO_SPI_16bitMsb
FlexIO SPI 16-bit MSB first

enumerator kFLEXIO_SPI_16bitLsb
FlexIO SPI 16-bit LSB first

```

enumerator kFLEXIO__SPI__32bitMsb
    FlexIO SPI 32-bit MSB first
enumerator kFLEXIO__SPI__32bitLsb
    FlexIO SPI 32-bit LSB first
enumerator kFLEXIO__SPI__csContinuous
    Enable the CS signal continuous mode
typedef enum _flexio_spi_clock_phase flexio_spi_clock_phase_t
    FlexIO SPI clock phase configuration.
typedef enum _flexio_spi_shift_direction flexio_spi_shift_direction_t
    FlexIO SPI data shifter direction options.
typedef enum _flexio_spi_data_bitcount_mode flexio_spi_data_bitcount_mode_t
    FlexIO SPI data length mode options.
typedef struct _flexio_spi_type FLEXIO__SPI_Type
    Define FlexIO SPI access structure typedef.
typedef struct _flexio_spi_master_config flexio_spi_master_config_t
    Define FlexIO SPI master configuration structure.
typedef struct _flexio_spi_slave_config flexio_spi_slave_config_t
    Define FlexIO SPI slave configuration structure.
typedef struct _flexio_spi_transfer flexio_spi_transfer_t
    Define FlexIO SPI transfer structure.
typedef struct _flexio_spi_master_handle flexio_spi_master_handle_t
    typedef for flexio_spi_master_handle_t in advance.
typedef flexio_spi_master_handle_t flexio_spi_slave_handle_t
    Slave handle is the same with master handle.
typedef void (*flexio_spi_master_transfer_callback_t)(FLEXIO_SPI_Type *base,
flexio_spi_master_handle_t *handle, status_t status, void *userData)
    FlexIO SPI master callback for finished transmit.
typedef void (*flexio_spi_slave_transfer_callback_t)(FLEXIO_SPI_Type *base,
flexio_spi_slave_handle_t *handle, status_t status, void *userData)
    FlexIO SPI slave callback for finished transmit.
FLEXIO__SPI__DUMMYDATA
    FlexIO SPI dummy transfer data, the data is sent while txData is NULL.
SPI_RETRY_TIMES
    Retry times for waiting flag.
FLEXIO__SPI__XFER_DATA_FORMAT(flag)
    Get the transfer data format of width and bit order.
struct _flexio_spi_type
    #include <fsl_flexio_spi.h> Define FlexIO SPI access structure typedef.

```

Public Members

```

FLEXIO_Type *flexioBase
    FlexIO base pointer.

```

uint8_t SDOPinIndex

Pin select for data output. To set SDO pin in Hi-Z state, user needs to mux the pin as GPIO input and disable all pull up/down in application.

uint8_t SDIPinIndex

Pin select for data input.

uint8_t SCKPinIndex

Pin select for clock.

uint8_t CSnPinIndex

Pin select for enable.

uint8_t shifterIndex[2]

Shifter index used in FlexIO SPI.

uint8_t timerIndex[2]

Timer index used in FlexIO SPI.

struct __flexio_spi_master_config

#include <fsl_flexio_spi.h> Define FlexIO SPI master configuration structure.

Public Members

bool enableMaster

Enable/disable FlexIO SPI master after configuration.

bool enableInDoze

Enable/disable FlexIO operation in doze mode.

bool enableInDebug

Enable/disable FlexIO operation in debug mode.

bool enableFastAccess

Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

uint32_t baudRate_Bps

Baud rate in Bps.

flexio_spi_clock_phase_t phase

Clock phase.

flexio_spi_data_bitcount_mode_t dataMode

8bit or 16bit mode.

struct __flexio_spi_slave_config

#include <fsl_flexio_spi.h> Define FlexIO SPI slave configuration structure.

Public Members

bool enableSlave

Enable/disable FlexIO SPI slave after configuration.

bool enableInDoze

Enable/disable FlexIO operation in doze mode.

bool enableInDebug

Enable/disable FlexIO operation in debug mode.

bool enableFastAccess

Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

flexio_spi_clock_phase_t phase

Clock phase.

flexio_spi_data_bitcount_mode_t dataMode

8bit or 16bit mode.

struct *_flexio_spi_transfer*

#include <fsl_flexio_spi.h> Define FlexIO SPI transfer structure.

Public Members

const uint8_t *txData

Send buffer.

uint8_t *rxData

Receive buffer.

size_t dataSize

Transfer bytes.

uint8_t flags

FlexIO SPI control flag, MSB first or LSB first.

struct *_flexio_spi_master_handle*

#include <fsl_flexio_spi.h> Define FlexIO SPI handle structure.

Public Members

const uint8_t *txData

Transfer buffer.

uint8_t *rxData

Receive buffer.

size_t transferSize

Total bytes to be transferred.

volatile size_t txRemainingBytes

Send data remaining in bytes.

volatile size_t rxRemainingBytes

Receive data remaining in bytes.

volatile uint32_t state

FlexIO SPI internal state.

uint8_t bytePerFrame

SPI mode, 2bytes or 1byte in a frame

flexio_spi_shift_direction_t direction

Shift direction.

flexio_spi_master_transfer_callback_t callback

FlexIO SPI callback.

void *userData

Callback parameter.

bool isCsContinuous

Is current transfer using CS continuous mode.

uint32_t timer1Cfg

TIMER1 TIMCFG register value backup.

2.18 FlexIO UART Driver

status_t FLEXIO_UART_Init(*FLEXIO_UART_Type* *base, const *flexio_uart_config_t* *userConfig, uint32_t srcClock_Hz)

Ungates the FlexIO clock, resets the FlexIO module, configures FlexIO UART hardware, and configures the FlexIO UART with FlexIO UART configuration. The configuration structure can be filled by the user or be set with default values by FLEXIO_UART_GetDefaultConfig().

Example

```
FLEXIO_UART_Type base = {
    .flexioBase = FLEXIO,
    .TxPinIndex = 0,
    .RxPinIndex = 1,
    .shifterIndex = {0,1},
    .timerIndex = {0,1}
};
flexio_uart_config_t config = {
    .enableInDoze = false,
    .enableInDebug = true,
    .enableFastAccess = false,
    .baudRate_Bps = 115200U,
    .bitCountPerChar = 8
};
FLEXIO_UART_Init(base, &config, srcClock_Hz);
```

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- userConfig – Pointer to the flexio_uart_config_t structure.
- srcClock_Hz – FlexIO source clock in Hz.

Return values

- kStatus_Success – Configuration success.
- kStatus_FLEXIO_UART_BaudrateNotSupport – Baudrate is not supported for current clock source frequency.

void FLEXIO_UART_Deinit(*FLEXIO_UART_Type* *base)

Resets the FlexIO UART shifter and timer config.

Note: After calling this API, call the FLEXIO_UART_Init to use the FlexIO UART module.

Parameters

- base – Pointer to FLEXIO_UART_Type structure

void FLEXIO_UART_GetDefaultConfig(*flexio_uart_config_t* *userConfig)

Gets the default configuration to configure the FlexIO UART. The configuration can be used directly for calling the FLEXIO_UART_Init(). Example:

```
flexio_uart_config_t config;
FLEXIO_UART_GetDefaultConfig(&userConfig);
```

Parameters

- userConfig – Pointer to the flexio_uart_config_t structure.

uint32_t FLEXIO_UART_GetStatusFlags(*FLEXIO_UART_Type* *base)

Gets the FlexIO UART status flags.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.

Returns

FlexIO UART status flags.

void FLEXIO_UART_ClearStatusFlags(*FLEXIO_UART_Type* *base, uint32_t mask)

Gets the FlexIO UART status flags.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- mask – Status flag. The parameter can be any combination of the following values:
 - kFLEXIO_UART_TxDataRegEmptyFlag
 - kFLEXIO_UART_RxEmptyFlag
 - kFLEXIO_UART_RxOverRunFlag

void FLEXIO_UART_EnableInterrupts(*FLEXIO_UART_Type* *base, uint32_t mask)

Enables the FlexIO UART interrupt.

This function enables the FlexIO UART interrupt.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- mask – Interrupt source.

void FLEXIO_UART_DisableInterrupts(*FLEXIO_UART_Type* *base, uint32_t mask)

Disables the FlexIO UART interrupt.

This function disables the FlexIO UART interrupt.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- mask – Interrupt source.

static inline uint32_t FLEXIO_UART_GetTxDataRegisterAddress(*FLEXIO_UART_Type* *base)

Gets the FlexIO UART transmit data register address.

This function returns the UART data register address, which is mainly used by DMA/eDMA.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.

Returns

FlexIO UART transmit data register address.

```
static inline uint32_t FLEXIO_UART_GetRxDataRegisterAddress(FLEXIO_UART_Type *base)
```

Gets the FlexIO UART receive data register address.

This function returns the UART data register address, which is mainly used by DMA/eDMA.

Parameters

- base – Pointer to the *FLEXIO_UART_Type* structure.

Returns

FlexIO UART receive data register address.

```
static inline void FLEXIO_UART_EnableTxDMA(FLEXIO_UART_Type *base, bool enable)
```

Enables/disables the FlexIO UART transmit DMA. This function enables/disables the FlexIO UART Tx DMA, which means asserting the *kFLEXIO_UART_TxDataRegEmptyFlag* does/doesn't trigger the DMA request.

Parameters

- base – Pointer to the *FLEXIO_UART_Type* structure.
- enable – True to enable, false to disable.

```
static inline void FLEXIO_UART_EnableRxDMA(FLEXIO_UART_Type *base, bool enable)
```

Enables/disables the FlexIO UART receive DMA. This function enables/disables the FlexIO UART Rx DMA, which means asserting *kFLEXIO_UART_RxDataRegFullFlag* does/doesn't trigger the DMA request.

Parameters

- base – Pointer to the *FLEXIO_UART_Type* structure.
- enable – True to enable, false to disable.

```
static inline void FLEXIO_UART_Enable(FLEXIO_UART_Type *base, bool enable)
```

Enables/disables the FlexIO UART module operation.

Parameters

- base – Pointer to the *FLEXIO_UART_Type*.
- enable – True to enable, false does not have any effect.

```
static inline void FLEXIO_UART_WriteByte(FLEXIO_UART_Type *base, const uint8_t *buffer)
```

Writes one byte of data.

Note: This is a non-blocking API, which returns directly after the data is put into the data register. Ensure that the *TxEmptyFlag* is asserted before calling this API.

Parameters

- base – Pointer to the *FLEXIO_UART_Type* structure.
- buffer – The data bytes to send.

```
static inline void FLEXIO_UART_ReadByte(FLEXIO_UART_Type *base, uint8_t *buffer)
```

Reads one byte of data.

Note: This is a non-blocking API, which returns directly after the data is read from the data register. Ensure that the *RxFullFlag* is asserted before calling this API.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- buffer – The buffer to store the received bytes.

status_t FLEXIO_UART_WriteBlocking(*FLEXIO_UART_Type* *base, const uint8_t *txData, size_t txSize)

Sends a buffer of data bytes.

Note: This function blocks using the polling method until all bytes have been sent.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- txData – The data bytes to send.
- txSize – The number of data bytes to send.

Return values

- kStatus_FLEXIO_UART_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully wrote all data.

status_t FLEXIO_UART_ReadBlocking(*FLEXIO_UART_Type* *base, uint8_t *rxData, size_t rxSize)

Receives a buffer of bytes.

Note: This function blocks using the polling method until all bytes have been received.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- rxData – The buffer to store the received bytes.
- rxSize – The number of data bytes to be received.

Return values

- kStatus_FLEXIO_UART_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully received all data.

status_t FLEXIO_UART_TransferCreateHandle(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle, *flexio_uart_transfer_callback_t* callback, void *userData)

Initializes the UART handle.

This function initializes the FlexIO UART handle, which can be used for other FlexIO UART transactional APIs. Call this API once to get the initialized handle.

The UART driver supports the “background” receiving, which means that users can set up a RX ring buffer optionally. Data received is stored into the ring buffer even when the user doesn’t call the FLEXIO_UART_TransferReceiveNonBlocking() API. If there is already data received in the ring buffer, users can get the received data from the ring buffer directly. The ring buffer is disabled if passing NULL as ringBuffer.

Parameters

- base – to FLEXIO_UART_Type structure.

- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.
- callback – The callback function.
- userData – The parameter of the callback function.

Return values

- kStatus_Success – Successfully create the handle.
- kStatus_OutOfRange – The FlexIO type/handle/ISR table out of range.

```
void FLEXIO_UART_TransferStartRingBuffer(FLEXIO_UART_Type *base, flexio_uart_handle_t
                                         *handle, uint8_t *ringBuffer, size_t
                                         ringBufferSize)
```

Sets up the RX ring buffer.

This function sets up the RX ring buffer to a specific UART handle.

When the RX ring buffer is used, data received is stored into the ring buffer even when the user doesn't call the UART_ReceiveNonBlocking() API. If there is already data received in the ring buffer, users can get the received data from the ring buffer directly.

Note: When using the RX ring buffer, one byte is reserved for internal use. In other words, if ringBufferSize is 32, only 31 bytes are used for saving data.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.
- ringBuffer – Start address of ring buffer for background receiving. Pass NULL to disable the ring buffer.
- ringBufferSize – Size of the ring buffer.

```
void FLEXIO_UART_TransferStopRingBuffer(FLEXIO_UART_Type *base, flexio_uart_handle_t
                                         *handle)
```

Aborts the background transfer and uninstalls the ring buffer.

This function aborts the background transfer and uninstalls the ring buffer.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.

```
status_t FLEXIO_UART_TransferSendNonBlocking(FLEXIO_UART_Type *base,
                                              flexio_uart_handle_t *handle,
                                              flexio_uart_transfer_t *xfer)
```

Transmits a buffer of data using the interrupt method.

This function sends data using an interrupt method. This is a non-blocking function, which returns directly without waiting for all data to be written to the TX register. When all data is written to the TX register in ISR, the FlexIO UART driver calls the callback function and passes the kStatus_FLEXIO_UART_TxIdle as status parameter.

Note: The kStatus_FLEXIO_UART_TxIdle is passed to the upper layer when all data is written to the TX register. However, it does not ensure that all data is sent out.

Parameters

- `base` – Pointer to the `FLEXIO_UART_Type` structure.
- `handle` – Pointer to the `flexio_uart_handle_t` structure to store the transfer state.
- `xfer` – FlexIO UART transfer structure. See `flexio_uart_transfer_t`.

Return values

- `kStatus_Success` – Successfully starts the data transmission.
- `kStatus_UART_TxBusy` – Previous transmission still not finished, data not written to the TX register.

```
void FLEXIO_UART_TransferAbortSend(FLEXIO_UART_Type *base, flexio_uart_handle_t *handle)
```

Aborts the interrupt-driven data transmit.

This function aborts the interrupt-driven data sending. Get the `remainBytes` to find out how many bytes are still not sent out.

Parameters

- `base` – Pointer to the `FLEXIO_UART_Type` structure.
- `handle` – Pointer to the `flexio_uart_handle_t` structure to store the transfer state.

```
status_t FLEXIO_UART_TransferGetSendCount(FLEXIO_UART_Type *base, flexio_uart_handle_t *handle, size_t *count)
```

Gets the number of bytes sent.

This function gets the number of bytes sent driven by interrupt.

Parameters

- `base` – Pointer to the `FLEXIO_UART_Type` structure.
- `handle` – Pointer to the `flexio_uart_handle_t` structure to store the transfer state.
- `count` – Number of bytes sent so far by the non-blocking transaction.

Return values

- `kStatus_NoTransferInProgress` – transfer has finished or no transfer in progress.
- `kStatus_Success` – Successfully return the count.

```
status_t FLEXIO_UART_TransferReceiveNonBlocking(FLEXIO_UART_Type *base, flexio_uart_handle_t *handle, flexio_uart_transfer_t *xfer, size_t *receivedBytes)
```

Receives a buffer of data using the interrupt method.

This function receives data using the interrupt method. This is a non-blocking function, which returns without waiting for all data to be received. If the RX ring buffer is used and not empty, the data in ring buffer is copied and the parameter `receivedBytes` shows how many bytes are copied from the ring buffer. After copying, if the data in ring buffer is not enough to read, the receive request is saved by the UART driver. When new data arrives, the receive request is serviced first. When all data is received, the UART driver notifies the upper layer through a callback function and passes the status parameter `kStatus_UART_RxIdle`. For example, if the upper layer needs 10 bytes but there are only 5 bytes in the ring buffer, the 5 bytes are copied to `xfer->data`. This function returns with the parameter `receivedBytes` set to 5. For the last 5 bytes, newly arrived data is saved from the

xfer->data[5]. When 5 bytes are received, the UART driver notifies upper layer. If the RX ring buffer is not enabled, this function enables the RX and RX interrupt to receive data to xfer->data. When all data is received, the upper layer is notified.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.
- xfer – UART transfer structure. See flexio_uart_transfer_t.
- receivedBytes – Bytes received from the ring buffer directly.

Return values

- kStatus__Success – Successfully queue the transfer into the transmit queue.
- kStatus_FLEXIO_UART_RxBusy – Previous receive request is not finished.

void FLEXIO_UART_TransferAbortReceive(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle)

Aborts the receive data which was using IRQ.

This function aborts the receive data which was using IRQ.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.

status_t FLEXIO_UART_TransferGetReceiveCount(*FLEXIO_UART_Type* *base, *flexio_uart_handle_t* *handle, *size_t* *count)

Gets the number of bytes received.

This function gets the number of bytes received driven by interrupt.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.
- handle – Pointer to the flexio_uart_handle_t structure to store the transfer state.
- count – Number of bytes received so far by the non-blocking transaction.

Return values

- kStatus_NoTransferInProgress – transfer has finished or no transfer in progress.
- kStatus__Success – Successfully return the count.

void FLEXIO_UART_TransferHandleIRQ(void *uartType, void *uartHandle)

FlexIO UART IRQ handler function.

This function processes the FlexIO UART transmit and receives the IRQ request.

Parameters

- uartType – Pointer to the FLEXIO_UART_Type structure.
- uartHandle – Pointer to the flexio_uart_handle_t structure to store the transfer state.

void FLEXIO_UART_FlushShifters(*FLEXIO_UART_Type* *base)

Flush tx/rx shifters.

Parameters

- base – Pointer to the FLEXIO_UART_Type structure.

FSL_FLEXIO_UART_DRIVER_VERSION

FlexIO UART driver version.

Error codes for the UART driver.

Values:

enumerator kStatus_FLEXIO_UART_TxBusy

Transmitter is busy.

enumerator kStatus_FLEXIO_UART_RxBusy

Receiver is busy.

enumerator kStatus_FLEXIO_UART_TxIdle

UART transmitter is idle.

enumerator kStatus_FLEXIO_UART_RxIdle

UART receiver is idle.

enumerator kStatus_FLEXIO_UART_ERROR

ERROR happens on UART.

enumerator kStatus_FLEXIO_UART_RxRingBufferOverrun

UART RX software ring buffer overrun.

enumerator kStatus_FLEXIO_UART_RxHardwareOverrun

UART RX receiver overrun.

enumerator kStatus_FLEXIO_UART_Timeout

UART times out.

enumerator kStatus_FLEXIO_UART_BaudrateNotSupport

Baudrate is not supported in current clock source

enum _flexio_uart_bit_count_per_char

FlexIO UART bit count per char.

Values:

enumerator kFLEXIO_UART_7BitsPerChar

7-bit data characters

enumerator kFLEXIO_UART_8BitsPerChar

8-bit data characters

enumerator kFLEXIO_UART_9BitsPerChar

9-bit data characters

enum _flexio_uart_interrupt_enable

Define FlexIO UART interrupt mask.

Values:

enumerator kFLEXIO_UART_TxDataRegEmptyInterruptEnable

Transmit buffer empty interrupt enable.

enumerator kFLEXIO_UART_RxDataRegFullInterruptEnable
Receive buffer full interrupt enable.

enum _flexio_uart_status_flags
Define FlexIO UART status mask.

Values:

enumerator kFLEXIO_UART_TxDataRegEmptyFlag
Transmit buffer empty flag.

enumerator kFLEXIO_UART_RxDataRegFullFlag
Receive buffer full flag.

enumerator kFLEXIO_UART_RxOverRunFlag
Receive buffer over run flag.

typedef enum _flexio_uart_bit_count_per_char flexio_uart_bit_count_per_char_t
FlexIO UART bit count per char.

typedef struct _flexio_uart_type FLEXIO_UART_Type
Define FlexIO UART access structure typedef.

typedef struct _flexio_uart_config flexio_uart_config_t
Define FlexIO UART user configuration structure.

typedef struct _flexio_uart_transfer flexio_uart_transfer_t
Define FlexIO UART transfer structure.

typedef struct _flexio_uart_handle flexio_uart_handle_t

typedef void (*flexio_uart_transfer_callback_t)(FLEXIO_UART_Type *base, flexio_uart_handle_t *handle, status_t status, void *userData)
FlexIO UART transfer callback function.

UART_RETRY_TIMES
Retry times for waiting flag.

struct _flexio_uart_type
#include <fsl_flexio_uart.h> Define FlexIO UART access structure typedef.

Public Members

FLEXIO_Type *flexioBase
FlexIO base pointer.

uint8_t TxPinIndex
Pin select for UART_Tx.

uint8_t RxPinIndex
Pin select for UART_Rx.

uint8_t shifterIndex[2]
Shifter index used in FlexIO UART.

uint8_t timerIndex[2]
Timer index used in FlexIO UART.

struct _flexio_uart_config
#include <fsl_flexio_uart.h> Define FlexIO UART user configuration structure.

Public Members

`bool enableUart`
Enable/disable FlexIO UART TX & RX.

`bool enableInDoze`
Enable/disable FlexIO operation in doze mode

`bool enableInDebug`
Enable/disable FlexIO operation in debug mode

`bool enableFastAccess`
Enable/disable fast access to FlexIO registers, fast access requires the FlexIO clock to be at least twice the frequency of the bus clock.

`uint32_t baudRate_Bps`
Baud rate in Bps.

`flexio_uart_bit_count_per_char_t bitCountPerChar`
number of bits, 7/8/9 -bit

`struct _flexio_uart_transfer`
#include <fsl_flexio_uart.h> Define FlexIO UART transfer structure.

Public Members

`size_t dataSize`
Transfer size

`struct _flexio_uart_handle`
#include <fsl_flexio_uart.h> Define FLEXIO UART handle structure.

Public Members

`const uint8_t *volatile txData`
Address of remaining data to send.

`volatile size_t txDataSize`
Size of the remaining data to send.

`uint8_t *volatile rxData`
Address of remaining data to receive.

`volatile size_t rxDataSize`
Size of the remaining data to receive.

`size_t txDataSizeAll`
Total bytes to be sent.

`size_t rxDataSizeAll`
Total bytes to be received.

`uint8_t *rxRingBuffer`
Start address of the receiver ring buffer.

`size_t rxRingBufferSize`
Size of the ring buffer.

`volatile uint16_t rxRingBufferHead`
Index for the driver to store received data into ring buffer.

volatile uint16_t rxRingBufferTail
Index for the user to get data from the ring buffer.

flexio_uart_transfer_callback_t callback
Callback function.

void *userData
UART callback function parameter.

volatile uint8_t txState
TX transfer state.

volatile uint8_t rxState
RX transfer state

union __unnamed41__

Public Members

uint8_t *data
The buffer of data to be transfer.

uint8_t *rxData
The buffer to receive data.

const uint8_t *txData
The buffer of data to be sent.

2.19 ftfx adapter

2.20 Ftftx CACHE Driver

enum _ftfx_cache_ram_func_constants
Constants for execute-in-RAM flash function.

Values:

enumerator kFTFX_CACHE_RamFuncMaxSizeInWords
The maximum size of execute-in-RAM function.

typedef struct *_flash_prefetch_speculation_status* ftfx_prefetch_speculation_status_t
FTFX prefetch speculation status.

typedef struct *_ftfx_cache_config* ftfx_cache_config_t
FTFX cache driver state information.

An instance of this structure is allocated by the user of the flash driver and passed into each of the driver APIs.

status_t FTFX_CACHE_Init(*ftfx_cache_config_t* *config)
Initializes the global FTFX cache structure members.

This function checks and initializes the Flash module for the other FTFX cache APIs.

Parameters

- config – Pointer to the storage for the driver runtime state.

Return values

- kStatus_FTFx_Success – API was executed successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_ExecuteInRamFunctionNotReady – Execute-in-RAM function is not available.

status_t FTFx_CACHE_ClearCachePrefetchSpeculation(*ftfx_cache_config_t* *config, bool isPreProcess)

Process the cache/prefetch/speculation to the flash.

Parameters

- config – A pointer to the storage for the driver runtime state.
- isPreProcess – The possible option used to control flash cache/prefetch/speculation

Return values

- kStatus_FTFx_Success – API was executed successfully.
- kStatus_FTFx_InvalidArgument – Invalid argument is provided.
- kStatus_FTFx_ExecuteInRamFunctionNotReady – Execute-in-RAM function is not available.

status_t FTFx_CACHE_PflashSetPrefetchSpeculation(*ftfx_prefetch_speculation_status_t* *speculationStatus)

Sets the PFlash prefetch speculation to the intended speculation status.

Parameters

- speculationStatus – The expected protect status to set to the PFlash protection register. Each bit is

Return values

- kStatus_FTFx_Success – API was executed successfully.
- kStatus_FTFx_InvalidSpeculationOption – An invalid speculation option argument is provided.

status_t FTFx_CACHE_PflashGetPrefetchSpeculation(*ftfx_prefetch_speculation_status_t* *speculationStatus)

Gets the PFlash prefetch speculation status.

Parameters

- speculationStatus – Speculation status returned by the PFlash IP.

Return values

kStatus_FTFx_Success – API was executed successfully.

struct *_flash_prefetch_speculation_status*

#include <fsl_ftfx_cache.h> FTFx prefetch speculation status.

Public Members

bool instructionOff

Instruction speculation.

bool dataOff

Data speculation.

union *function_bit_operation_ptr_t*

#include <fsl_ftfx_cache.h>

Public Members

uint32_t commadAddr

void (*callFlashCommand)(volatile uint32_t *base, uint32_t bitMask, uint32_t bitShift, uint32_t bitValue)

struct _ftfx_cache_config

#include <fsl_ftfx_cache.h> FTFx cache driver state information.

An instance of this structure is allocated by the user of the flash driver and passed into each of the driver APIs.

Public Members

uint8_t flashMemoryIndex

0 - primary flash; 1 - secondary flash

function_bit_operation_ptr_t bitOperFuncAddr

An buffer point to the flash execute-in-RAM function.

2.21 ftfx controller

FTFx driver status codes.

Values:

enumerator kStatus_FTFx_Success

API is executed successfully

enumerator kStatus_FTFx_InvalidArgument

Invalid argument

enumerator kStatus_FTFx_SizeError

Error size

enumerator kStatus_FTFx_AlignmentError

Parameter is not aligned with the specified baseline

enumerator kStatus_FTFx_AddressError

Address is out of range

enumerator kStatus_FTFx_AccessError

Invalid instruction codes and out-of bound addresses

enumerator kStatus_FTFx_ProtectionViolation

The program/erase operation is requested to execute on protected areas

enumerator kStatus_FTFx_CommandFailure

Run-time error during command execution.

enumerator kStatus_FTFx_UnknownProperty

Unknown property.

enumerator kStatus_FTFx_EraseKeyError

API erase key is invalid.

enumerator kStatus_FTFx_RegionExecuteOnly

The current region is execute-only.

enumerator kStatus_FTFx_ExecuteInRamFunctionNotReady

Execute-in-RAM function is not available.

enumerator kStatus_FTFx_PartitionStatusUpdateFailure

Failed to update partition status.

enumerator kStatus_FTFx_SetFlexramAsEepromError

Failed to set FlexRAM as EEPROM.

enumerator kStatus_FTFx_RecoverFlexramAsRamError

Failed to recover FlexRAM as RAM.

enumerator kStatus_FTFx_SetFlexramAsRamError

Failed to set FlexRAM as RAM.

enumerator kStatus_FTFx_RecoverFlexramAsEepromError

Failed to recover FlexRAM as EEPROM.

enumerator kStatus_FTFx_CommandNotSupported

Flash API is not supported.

enumerator kStatus_FTFx_SwapSystemNotInUninitialized

Swap system is not in an uninitialized state.

enumerator kStatus_FTFx_SwapIndicatorAddressError

The swap indicator address is invalid.

enumerator kStatus_FTFx_ReadOnlyProperty

The flash property is read-only.

enumerator kStatus_FTFx_InvalidPropertyValue

The flash property value is out of range.

enumerator kStatus_FTFx_InvalidSpeculationOption

The option of flash prefetch speculation is invalid.

enumerator kStatus_FTFx_CommandOperationInProgress

The option of flash command is processing.

enum _ftfx_driver_api_keys

Enumeration for FTFx driver API keys.

Note: The resulting value is built with a byte order such that the string being readable in expected order when viewed in a hex editor, if the value is treated as a 32-bit little endian value.

Values:

enumerator kFTFx_ApiEraseKey

Key value used to validate all FTFx erase APIs.

void FTFx_API_Init(*ftfx_config_t* *config)

Initializes the global flash properties structure members.

This function checks and initializes the Flash module for the other Flash APIs.

Parameters

- config – Pointer to the storage for the driver runtime state.

status_t FTFx_API_UpdateFlexnvmPartitionStatus(*ftfx_config_t* *config)

Updates FlexNVM memory partition status according to data flash 0 IFR.

This function updates FlexNVM memory partition status.

Parameters

- config – Pointer to the storage for the driver runtime state.

Return values

- kStatus_FTFx_Success – API was executed successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_PartitionStatusUpdateFailure – Failed to update the partition status.

status_t FTFx_CMD_Erase(*ftfx_config_t* *config, uint32_t start, uint32_t lengthInBytes, uint32_t key)

Erases the flash sectors encompassed by parameters passed into function.

This function erases the appropriate number of flash sectors based on the desired start address and length.

Parameters

- config – The pointer to the storage for the driver runtime state.
- start – The start address of the desired flash memory to be erased. The start address does not need to be sector-aligned but must be word-aligned.
- lengthInBytes – The length, given in bytes (not words or long-words) to be erased. Must be word-aligned.
- key – The value used to validate all flash erase APIs.

Return values

- kStatus_FTFx_Success – API was executed successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_AlignmentError – The parameter is not aligned with the specified baseline.
- kStatus_FTFx_AddressError – The address is out of range.
- kStatus_FTFx_EraseKeyError – The API erase key is invalid.
- kStatus_FTFx_ExecuteInRamFunctionNotReady – Execute-in-RAM function is not available.
- kStatus_FTFx_AccessError – Invalid instruction codes and out-of bounds addresses.
- kStatus_FTFx_ProtectionViolation – The program/erase operation is requested to execute on protected areas.
- kStatus_FTFx_CommandFailure – Run-time error during the command execution.

status_t FTFx_CMD_EraseSectorNonBlocking(*ftfx_config_t* *config, uint32_t start, uint32_t key)

Erases the flash sectors encompassed by parameters passed into function.

This function erases one flash sector size based on the start address.

Parameters

- config – The pointer to the storage for the driver runtime state.

- `start` – The start address of the desired flash memory to be erased. The start address does not need to be sector-aligned but must be word-aligned.
- `key` – The value used to validate all flash erase APIs.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – The parameter is not aligned with the specified baseline.
- `kStatus_FTFx_AddressError` – The address is out of range.
- `kStatus_FTFx_EraseKeyError` – The API erase key is invalid.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.

`status_t FTFx_CMD_EraseAll(ftfx_config_t *config, uint32_t key)`

Erases entire flash.

Parameters

- `config` – Pointer to the storage for the driver runtime state.
- `key` – A value used to validate all flash erase APIs.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_EraseKeyError` – API erase key is invalid.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.
- `kStatus_FTFx_PartitionStatusUpdateFailure` – Failed to update the partition status.

`status_t FTFx_CMD_EraseAllUnsecure(ftfx_config_t *config, uint32_t key)`

Erases the entire flash, including protected sectors.

Parameters

- `config` – Pointer to the storage for the driver runtime state.
- `key` – A value used to validate all flash erase APIs.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_EraseKeyError` – API erase key is invalid.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.

- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.
- `kStatus_FTFx_PartitionStatusUpdateFailure` – Failed to update the partition status.

`status_t FTFx_CMD_EraseAllExecuteOnlySegments(ftfx_config_t *config, uint32_t key)`

Erases all program flash execute-only segments defined by the FXACC registers.

Parameters

- `config` – Pointer to the storage for the driver runtime state.
- `key` – A value used to validate all flash erase APIs.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_EraseKeyError` – API erase key is invalid.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_Program(ftfx_config_t *config, uint32_t start, const uint8_t *src, uint32_t lengthInBytes)`

Programs flash with data at locations passed in through parameters.

This function programs the flash memory with the desired data for a given flash area as determined by the start address and the length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be programmed. Must be word-aligned.
- `src` – A pointer to the source buffer of data that is to be programmed into the flash.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with the specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.

- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_ProgramOnce(ftfx_config_t *config, uint32_t index, const uint8_t *src, uint32_t lengthInBytes)`

Programs Program Once Field through parameters.

This function programs the Program Once Field with the desired data for a given flash area as determined by the index and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `index` – The index indicating which area of the Program Once Field to be programmed.
- `src` – A pointer to the source buffer of data that is to be programmed into the Program Once Field.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_ProgramSection(ftfx_config_t *config, uint32_t start, const uint8_t *src, uint32_t lengthInBytes)`

Programs flash with data at locations passed in through parameters via the Program Section command.

This function programs the flash memory with the desired data for a given flash area as determined by the start address and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be programmed. Must be word-aligned.
- `src` – A pointer to the source buffer of data that is to be programmed into the flash.

- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_SetFlexramAsRamError` – Failed to set flexram as RAM.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.
- `kStatus_FTFx_RecoverFlexramAsEepromError` – Failed to recover FlexRAM as EEPROM.

`status_t FTFx_CMD_ProgramPartition(ftfx_config_t *config, ftfx_partition_flexram_load_opt_t option, uint32_t eepromDataSizeCode, uint32_t flexnvmPartitionCode, uint8_t CSEcKeySize, uint8_t CFE)`

Prepares the FlexNVM block for use as data flash, EEPROM backup, or a combination of both and initializes the FlexRAM.

Parameters

- `config` – Pointer to storage for the driver runtime state.
- `option` – The option used to set FlexRAM load behavior during reset.
- `eepromDataSizeCode` – Determines the amount of FlexRAM used in each of the available EEPROM subsystems.
- `flexnvmPartitionCode` – Specifies how to split the FlexNVM block between data flash memory and EEPROM backup memory supporting EEPROM functions.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – Invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.

status_t FTFx_CMD_ReadOnce(*ftfx_config_t* *config, uint32_t index, uint8_t *dst, uint32_t lengthInBytes)

Reads the Program Once Field through parameters.

This function reads the read once feild with given index and length.

Parameters

- config – A pointer to the storage for the driver runtime state.
- index – The index indicating the area of program once field to be read.
- dst – A pointer to the destination buffer of data that is used to store data to be read.
- lengthInBytes – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- kStatus_FTFx_Success – API was executed successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_ExecuteInRamFunctionNotReady – Execute-in-RAM function is not available.
- kStatus_FTFx_AccessError – Invalid instruction codes and out-of bounds addresses.
- kStatus_FTFx_ProtectionViolation – The program/erase operation is requested to execute on protected areas.
- kStatus_FTFx_CommandFailure – Run-time error during the command execution.

status_t FTFx_CMD_ReadResource(*ftfx_config_t* *config, uint32_t start, uint8_t *dst, uint32_t lengthInBytes, *ftfx_read_resource_opt_t* option)

Reads the resource with data at locations passed in through parameters.

This function reads the flash memory with the desired location for a given flash area as determined by the start address and length.

Parameters

- config – A pointer to the storage for the driver runtime state.
- start – The start address of the desired flash memory to be programmed. Must be word-aligned.
- dst – A pointer to the destination buffer of data that is used to store data to be read.
- lengthInBytes – The length, given in bytes (not words or long-words), to be read. Must be word-aligned.
- option – The resource option which indicates which area should be read back.

Return values

- kStatus_FTFx_Success – API was executed successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_AlignmentError – Parameter is not aligned with the specified baseline.
- kStatus_FTFx_ExecuteInRamFunctionNotReady – Execute-in-RAM function is not available.

- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_VerifyErase(ftfx_config_t *config, uint32_t start, uint32_t lengthInBytes, ftfx_margin_value_t margin)`

Verifies an erasure of the desired flash area at a specified margin level.

This function checks the appropriate number of flash sectors based on the desired start address and length to check whether the flash is erased to the specified read margin level.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be verified. The start address does not need to be sector-aligned but must be word-aligned.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be verified. Must be word-aligned.
- `margin` – Read margin choice.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_VerifyEraseAll(ftfx_config_t *config, ftfx_margin_value_t margin)`

Verifies erasure of the entire flash at a specified margin level.

This function checks whether the flash is erased to the specified read margin level.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `margin` – Read margin choice.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.

- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_VerifyEraseAllExecuteOnlySegments(ftfx_config_t *config, ftfx_margin_value_t margin)`

Verifies whether the program flash execute-only segments have been erased to the specified read margin level.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `margin` – Read margin choice.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_VerifyProgram(ftfx_config_t *config, uint32_t start, uint32_t lengthInBytes, const uint8_t *expectedData, ftfx_margin_value_t margin, uint32_t *failedAddress, uint32_t *failedData)`

Verifies programming of the desired flash area at a specified margin level.

This function verifies the data programed in the flash memory using the Flash Program Check Command and compares it to the expected data for a given flash area as determined by the start address and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be verified. Must be word-aligned.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be verified. Must be word-aligned.
- `expectedData` – A pointer to the expected data that is to be verified against.
- `margin` – Read margin choice.
- `failedAddress` – A pointer to the returned failing address.
- `failedData` – A pointer to the returned failing data. Some derivatives do not include failed data as part of the FCCOBx registers. In this case, zeros are returned upon failure.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.

- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_REG_GetSecurityState(ftfx_config_t *config, ftfx_security_state_t *state)`

Returns the security state via the pointer passed into the function.

This function retrieves the current flash security status, including the security enabling state and the backdoor key enabling state.

Parameters

- `config` – A pointer to storage for the driver runtime state.
- `state` – A pointer to the value returned for the current security status code:

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.

`status_t FTFx_CMD_SecurityBypass(ftfx_config_t *config, const uint8_t *backdoorKey)`

Allows users to bypass security with a backdoor key.

If the MCU is in secured state, this function unsecures the MCU by comparing the provided backdoor key with ones in the flash configuration field.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `backdoorKey` – A pointer to the user buffer containing the backdoor key.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_SetFlexramFunction(ftfx_config_t *config, ftfx_flexram_func_opt_t option)`

Sets the FlexRAM function command.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `option` – The option used to set the work mode of FlexRAM.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

```
status_t FTFx_CMD_SwapControl(ftfx_config_t *config, uint32_t address,
                             ftfx_swap_control_opt_t option, ftfx_swap_state_config_t
                             *returnInfo)
```

Configures the Swap function or checks the swap state of the Flash module.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `address` – Address used to configure the flash Swap function.
- `option` – The possible option used to configure Flash Swap function or check the flash Swap status
- `returnInfo` – A pointer to the data which is used to return the information of flash Swap.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_SwapIndicatorAddressError` – Swap indicator address is invalid.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

```
enum _ftfx_partition_flexram_load_option
```

Enumeration for the FlexRAM load during reset option.

Values:

```
enumerator kFTFx_PartitionFlexramLoadOptLoadedWithValidEepromData
```

FlexRAM is loaded with valid EEPROM data during reset sequence.

enumerator kFTFx_PartitionFlexramLoadOptNotLoaded

FlexRAM is not loaded during reset sequence.

enum _ftfx_read_resource_opt

Enumeration for the two possible options of flash read resource command.

Values:

enumerator kFTFx_ResourceOptionFlashIfc

Select code for Program flash 0 IFR, Program flash swap 0 IFR, Data flash 0 IFR

enumerator kFTFx_ResourceOptionVersionId

Select code for the version ID

enum _ftfx_margin_value

Enumeration for supported FTFx margin levels.

Values:

enumerator kFTFx_MarginValueNormal

Use the 'normal' read level for 1s.

enumerator kFTFx_MarginValueUser

Apply the 'User' margin to the normal read-1 level.

enumerator kFTFx_MarginValueFactory

Apply the 'Factory' margin to the normal read-1 level.

enumerator kFTFx_MarginValueInvalid

Not real margin level, Used to determine the range of valid margin level.

enum _ftfx_security_state

Enumeration for the three possible FTFx security states.

Values:

enumerator kFTFx_SecurityStateNotSecure

Flash is not secure.

enumerator kFTFx_SecurityStateBackdoorEnabled

Flash backdoor is enabled.

enumerator kFTFx_SecurityStateBackdoorDisabled

Flash backdoor is disabled.

enum _ftfx_flexram_function_option

Enumeration for the two possible options of set FlexRAM function command.

Values:

enumerator kFTFx_FlexramFuncOptAvailableAsRam

An option used to make FlexRAM available as RAM

enumerator kFTFx_FlexramFuncOptAvailableForEeprom

An option used to make FlexRAM available for EEPROM

enum _flash_acceleration_ram_property

Enumeration for acceleration ram property.

Values:

enumerator kFLASH_AccelerationRamSize

enum _ftfx_swap_control_option

Enumeration for the possible options of Swap control commands.

Values:

enumerator kFTFx_SwapControlOptionIntializeSystem

An option used to initialize the Swap system

enumerator kFTFx_SwapControlOptionSetInUpdateState

An option used to set the Swap in an update state

enumerator kFTFx_SwapControlOptionSetInCompleteState

An option used to set the Swap in a complete state

enumerator kFTFx_SwapControlOptionReportStatus

An option used to report the Swap status

enumerator kFTFx_SwapControlOptionDisableSystem

An option used to disable the Swap status

enum _ftfx_swap_state

Enumeration for the possible flash Swap status.

Values:

enumerator kFTFx_SwapStateUninitialized

Flash Swap system is in an uninitialized state.

enumerator kFTFx_SwapStateReady

Flash Swap system is in a ready state.

enumerator kFTFx_SwapStateUpdate

Flash Swap system is in an update state.

enumerator kFTFx_SwapStateUpdateErased

Flash Swap system is in an updateErased state.

enumerator kFTFx_SwapStateComplete

Flash Swap system is in a complete state.

enumerator kFTFx_SwapStateDisabled

Flash Swap system is in a disabled state.

enum _ftfx_swap_block_status

Enumeration for the possible flash Swap block status.

Values:

enumerator kFTFx_SwapBlockStatusLowerHalfProgramBlocksAtZero

Swap block status is that lower half program block at zero.

enumerator kFTFx_SwapBlockStatusUpperHalfProgramBlocksAtZero

Swap block status is that upper half program block at zero.

enum _ftfx_memory_type

Enumeration for FTFx memory type.

Values:

enumerator kFTFx_MemTypePflash

enumerator kFTFx_MemTypeFlexnvm

typedef enum *_ftfx_partition_flexram_load_option* ftfx_partition_flexram_load_opt_t

Enumeration for the FlexRAM load during reset option.

typedef enum *_ftfx_read_resource_opt* ftfx_read_resource_opt_t

Enumeration for the two possible options of flash read resource command.

typedef enum *_ftfx_margin_value* ftfx_margin_value_t

Enumeration for supported FTFx margin levels.

typedef enum *_ftfx_security_state* ftfx_security_state_t

Enumeration for the three possible FTFx security states.

typedef enum *_ftfx_flexram_function_option* ftfx_flexram_func_opt_t

Enumeration for the two possible options of set FlexRAM function command.

typedef enum *_ftfx_swap_control_option* ftfx_swap_control_opt_t

Enumeration for the possible options of Swap control commands.

typedef enum *_ftfx_swap_state* ftfx_swap_state_t

Enumeration for the possible flash Swap status.

typedef enum *_ftfx_swap_block_status* ftfx_swap_block_status_t

Enumeration for the possible flash Swap block status.

typedef struct *_ftfx_swap_state_config* ftfx_swap_state_config_t

Flash Swap information.

typedef struct *_ftfx_special_mem* ftfx_spec_mem_t

ftfx special memory access information.

typedef struct *_ftfx_mem_descriptor* ftfx_mem_desc_t

Flash memory descriptor.

typedef struct *_ftfx_ops_config* ftfx_ops_config_t

Active FTFx information for the current operation.

typedef struct *_ftfx_ifr_descriptor* ftfx_ifr_desc_t

Flash IFR memory descriptor.

typedef struct *_ftfx_config* ftfx_config_t

Flash driver state information.

An instance of this structure is allocated by the user of the flash driver and passed into each of the driver APIs.

struct *_ftfx_swap_state_config*

#include <fsl_ftfx_controller.h> Flash Swap information.

Public Members

ftfx_swap_state_t flashSwapState

The current Swap system status.

ftfx_swap_block_status_t currentSwapBlockStatus

The current Swap block status.

ftfx_swap_block_status_t nextSwapBlockStatus

The next Swap block status.

struct *_ftfx_special_mem*

#include <fsl_ftfx_controller.h> ftfx special memory access information.

Public Members

uint32_t base

Base address of flash special memory.

uint32_t size

size of flash special memory.

uint32_t count

flash special memory count.

struct __ftfx_mem_descriptor

#include <fsl_ftfx_controller.h> Flash memory descriptor.

Public Members

uint32_t blockBase

A base address of the flash block

uint32_t aliasBlockBase

A base address of the alias flash block

uint32_t totalSize

The size of the flash block.

uint32_t sectorSize

The size in bytes of a sector of flash.

uint32_t blockCount

A number of flash blocks.

struct __ftfx_ops_config

#include <fsl_ftfx_controller.h> Active FTFx information for the current operation.

Public Members

uint32_t convertedAddress

A converted address for the current flash type.

struct __ftfx_ifr_descriptor

#include <fsl_ftfx_controller.h> Flash IFR memory descriptor.

union function_ptr_t

#include <fsl_ftfx_controller.h>

Public Members

uint32_t commadAddr

void (*callFlashCommand)(volatile uint8_t *FTMRx_fstat)

struct __ftfx_config

#include <fsl_ftfx_controller.h> Flash driver state information.

An instance of this structure is allocated by the user of the flash driver and passed into each of the driver APIs.

Public Members

uint32_t flexramBlockBase

The base address of the FlexRAM/acceleration RAM

uint32_t flexramTotalSize

The size of the FlexRAM/acceleration RAM

uint16_t eepromTotalSize

The size of EEPROM area which was partitioned from FlexRAM

function_ptr_t runCmdFuncAddr

An buffer point to the flash execute-in-RAM function.

struct ____unnamed11____

Public Members

uint8_t type

Type of flash block.

uint8_t index

Index of flash block.

struct feature

struct addrAligment

struct feature

struct resRange

Public Members

uint8_t versionIdStart

Version ID start address

uint32_t pflashIfrStart

Program Flash 0 IFR start address

uint32_t dflashIfrStart

Data Flash 0 IFR start address

uint32_t pflashSwapIfrStart

Program Flash Swap IFR start address

struct idxInfo

2.22 ftfx feature

FTFx_DRIVER_IS_FLASH_RESIDENT

Flash driver location.

Used for the flash resident application.

FTFx_DRIVER_IS_EXPORTED

Flash Driver Export option.

Used for the MCUXpresso SDK application.

FTFx_FLASH1_HAS_PROT_CONTROL

Indicates whether the secondary flash has its own protection register in flash module.

FTFx_FLASH1_HAS_XACC_CONTROL

Indicates whether the secondary flash has its own Execute-Only access register in flash module.

FTFx_DRIVER_HAS_FLASH1_SUPPORT

Indicates whether the secondary flash is supported in the Flash driver.

FTFx_FLASH_COUNT

FTFx_FLASH1_IS_INDEPENDENT_BLOCK

2.23 Ftftx FLASH Driver

status_t FLASH_Init(*flash_config_t* *config)

Initializes the global flash properties structure members.

This function checks and initializes the Flash module for the other Flash APIs.

Parameters

- config – Pointer to the storage for the driver runtime state.

Return values

- kStatus_FTFx_Success – API was executed successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_ExecuteInRamFunctionNotReady – Execute-in-RAM function is not available.
- kStatus_FTFx_PartitionStatusUpdateFailure – Failed to update the partition status.

status_t FLASH_Erase(*flash_config_t* *config, uint32_t start, uint32_t lengthInBytes, uint32_t key)

Erases the Dflash sectors encompassed by parameters passed into function.

This function erases the appropriate number of flash sectors based on the desired start address and length.

Parameters

- config – The pointer to the storage for the driver runtime state.
- start – The start address of the desired flash memory to be erased. The start address does not need to be sector-aligned but must be word-aligned.
- lengthInBytes – The length, given in bytes (not words or long-words) to be erased. Must be word-aligned.
- key – The value used to validate all flash erase APIs.

Return values

- kStatus_FTFx_Success – API was executed successfully; the appropriate number of flash sectors based on the desired start address and length were erased successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_AlignmentError – The parameter is not aligned with the specified baseline.

- `kStatus_FTFx_AddressError` – The address is out of range.
- `kStatus_FTFx_EraseKeyError` – The API erase key is invalid.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t` FLASH_EraseSectorNonBlocking(*flash_config_t* *config, uint32_t start, uint32_t key)

Erases the Dflash sectors encompassed by parameters passed into function.

This function erases one flash sector size based on the start address, and it is executed asynchronously.

NOTE: This function can only erase one flash sector at a time, and the other commands can be executed after the previous command has been completed.

Parameters

- `config` – The pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be erased. The start address does not need to be sector-aligned but must be word-aligned.
- `key` – The value used to validate all flash erase APIs.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – The parameter is not aligned with the specified baseline.
- `kStatus_FTFx_AddressError` – The address is out of range.
- `kStatus_FTFx_EraseKeyError` – The API erase key is invalid.

`status_t` FLASH_EraseAll(*flash_config_t* *config, uint32_t key)

Erases entire flexnvm.

Parameters

- `config` – Pointer to the storage for the driver runtime state.
- `key` – A value used to validate all flash erase APIs.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the all pflash and flexnvm were erased successfully, the swap and eeprom have been reset to unconfigured state.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_EraseKeyError` – API erase key is invalid.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.

- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.
- `kStatus_FTFx_PartitionStatusUpdateFailure` – Failed to update the partition status.

`status_t FLASH_EraseAllUnsecure(flash_config_t *config, uint32_t key)`

Erases the entire flexnvm, including protected sectors.

Parameters

- `config` – Pointer to the storage for the driver runtime state.
- `key` – A value used to validate all flash erase APIs.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the protected sectors of flash were reset to unprotected status.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_EraseKeyError` – API erase key is invalid.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.
- `kStatus_FTFx_PartitionStatusUpdateFailure` – Failed to update the partition status.

`status_t FLASH_Program(flash_config_t *config, uint32_t start, uint8_t *src, uint32_t lengthInBytes)`

Programs flash with data at locations passed in through parameters.

This function programs the flash memory with the desired data for a given flash area as determined by the start address and the length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be programmed. Must be word-aligned.
- `src` – A pointer to the source buffer of data that is to be programmed into the flash.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the desired data were programmed successfully into flash based on desired start address and length.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.

- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with the specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t` FLASH_ProgramOnce(*flash_config_t* *config, uint32_t index, uint8_t *src, uint32_t lengthInBytes)

Program the Program-Once-Field through parameters.

This function Program the Program-once-field with given index and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `index` – The index indicating the area of program once field to be read.
- `src` – A pointer to the source buffer of data that is used to store data to be write.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; The index indicating the area of program once field was programmed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t` FLASH_ProgramSection(*flash_config_t* *config, uint32_t start, uint8_t *src, uint32_t lengthInBytes)

Programs flash with data at locations passed in through parameters via the Program Section command.

This function programs the flash memory with the desired data for a given flash area as determined by the start address and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be programmed. Must be word-aligned.

- `src` – A pointer to the source buffer of data that is to be programmed into the flash.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the desired data have been programmed successfully into flash based on start address and length.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_SetFlexramAsRamError` – Failed to set flexram as RAM.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.
- `kStatus_FTFx_RecoverFlexramAsEepromError` – Failed to recover FlexRAM as EEPROM.

`status_t` FLASH_ReadResource(*flash_config_t* *config, uint32_t start, uint8_t *dst, uint32_t lengthInBytes, *ftfx_read_resource_opt_t* option)

Reads the resource with data at locations passed in through parameters.

This function reads the flash memory with the desired location for a given flash area as determined by the start address and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be programmed. Must be word-aligned.
- `dst` – A pointer to the destination buffer of data that is used to store data to be read.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be read. Must be word-aligned.
- `option` – The resource option which indicates which area should be read back.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the data have been read successfully from program flash IFR, data flash IFR space, and the Version ID field.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with the specified baseline.

- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FLASH_ReadOnce(flash_config_t *config, uint32_t index, uint8_t *dst, uint32_t lengthInBytes)`

Reads the Program Once Field through parameters.

This function reads the read once field with given index and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `index` – The index indicating the area of program once field to be read.
- `dst` – A pointer to the destination buffer of data that is used to store data to be read.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the data have been successfully read from Program flash0 IFR map and Program Once field based on index and length.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FLASH_VerifyErase(flash_config_t *config, uint32_t start, uint32_t lengthInBytes, ftfx_margin_value_t margin)`

Verifies an erasure of the desired flash area at a specified margin level.

This function checks the appropriate number of flash sectors based on the desired start address and length to check whether the flash is erased to the specified read margin level.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be verified. The start address does not need to be sector-aligned but must be word-aligned.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be verified. Must be word-aligned.
- `margin` – Read margin choice.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the specified FLASH region has been erased.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FLASH_VerifyEraseAll(flash_config_t *config, ftfx_margin_value_t margin)`

Verifies erasure of the entire flash at a specified margin level.

This function checks whether the flash is erased to the specified read margin level.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `margin` – Read margin choice.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; all program flash and flexnvm were in erased state.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FLASH_VerifyProgram(flash_config_t *config, uint32_t start, uint32_t lengthInBytes, const uint8_t *expectedData, ftfx_margin_value_t margin, uint32_t *failedAddress, uint32_t *failedData)`

Verifies programming of the desired flash area at a specified margin level.

This function verifies the data programmed in the flash memory using the Flash Program Check Command and compares it to the expected data for a given flash area as determined by the start address and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be verified. Must be word-aligned.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be verified. Must be word-aligned.

- `expectedData` – A pointer to the expected data that is to be verified against.
- `margin` – Read margin choice.
- `failedAddress` – A pointer to the returned failing address.
- `failedData` – A pointer to the returned failing data. Some derivatives do not include failed data as part of the FCCOBx registers. In this case, zeros are returned upon failure.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the desired data have been successfully programmed into specified FLASH region.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

status_t FLASH_GetSecurityState(*flash_config_t* *config, *ftfx_security_state_t* *state)

Returns the security state via the pointer passed into the function.

This function retrieves the current flash security status, including the security enabling state and the backdoor key enabling state.

Parameters

- `config` – A pointer to storage for the driver runtime state.
- `state` – A pointer to the value returned for the current security status code:

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the security state of flash was stored to state.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.

status_t FLASH_SecurityBypass(*flash_config_t* *config, const uint8_t *backdoorKey)

Allows users to bypass security with a backdoor key.

If the MCU is in secured state, this function unsecures the MCU by comparing the provided backdoor key with ones in the flash configuration field.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `backdoorKey` – A pointer to the user buffer containing the backdoor key.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.

- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t` FLASH_SetFlexramFunction(*flash_config_t* *config, *ftfx_flexram_func_opt_t* option)

Sets the FlexRAM function command.

Parameters

- config – A pointer to the storage for the driver runtime state.
- option – The option used to set the work mode of FlexRAM.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the FlexRAM has been successfully configured as RAM or EEPROM.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t` FLASH_Swap(*flash_config_t* *config, `uint32_t` address, `bool` isSetEnable)

Swaps the lower half flash with the higher half flash.

Parameters

- config – A pointer to the storage for the driver runtime state.
- address – Address used to configure the flash swap function
- isSetEnable – The possible option used to configure the Flash Swap function or check the flash Swap status.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the lower half flash and higher half flash have been swapped.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_SwapIndicatorAddressError` – Swap indicator address is invalid.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.

- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.
- `kStatus_FTFx_SwapSystemNotInUninitialized` – Swap system is not in an uninitialized state.

`status_t FLASH_IsProtected(flash_config_t *config, uint32_t start, uint32_t lengthInBytes, flash_prot_state_t *protection_state)`

Returns the protection state of the desired flash area via the pointer passed into the function.

This function retrieves the current flash protect status for a given flash area as determined by the start address and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be checked. Must be word-aligned.
- `lengthInBytes` – The length, given in bytes (not words or long-words) to be checked. Must be word-aligned.
- `protection_state` – A pointer to the value returned for the current protection status code for the desired flash area.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the protection state of specified FLASH region was stored to `protection_state`.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – The address is out of range.

`status_t FLASH_IsExecuteOnly(flash_config_t *config, uint32_t start, uint32_t lengthInBytes, flash_xacc_state_t *access_state)`

Returns the access state of the desired flash area via the pointer passed into the function.

This function retrieves the current flash access status for a given flash area as determined by the start address and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be checked. Must be word-aligned.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be checked. Must be word-aligned.
- `access_state` – A pointer to the value returned for the current access status code for the desired flash area.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the `executeOnly` state of specified FLASH region was stored to `access_state`.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.

- `kStatus_FTFx_AlignmentError` – The parameter is not aligned to the specified baseline.
- `kStatus_FTFx_AddressError` – The address is out of range.

`status_t FLASH_PflashSetProtection(flash_config_t *config, pflash_prot_status_t *protectStatus)`

Sets the PFlash Protection to the intended protection status.

Parameters

- `config` – A pointer to storage for the driver runtime state.
- `protectStatus` – The expected protect status to set to the PFlash protection register. Each bit is corresponding to protection of 1/32(64) of the total PFlash. The least significant bit is corresponding to the lowest address area of PFlash. The most significant bit is corresponding to the highest address area of PFlash. There are two possible cases as shown below: 0: this area is protected. 1: this area is unprotected.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the specified FLASH region is protected.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.

`status_t FLASH_PflashGetProtection(flash_config_t *config, pflash_prot_status_t *protectStatus)`

Gets the PFlash protection status.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `protectStatus` – Protect status returned by the PFlash IP. Each bit is corresponding to the protection of 1/32(64) of the total PFlash. The least significant bit corresponds to the lowest address area of the PFlash. The most significant bit corresponds to the highest address area of PFlash. There are two possible cases as shown below: 0: this area is protected. 1: this area is unprotected.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the Protection state was stored to `protectStatus`;
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.

`status_t FLASH_GetProperty(flash_config_t *config, flash_property_tag_t whichProperty, uint32_t *value)`

Returns the desired flash property.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `whichProperty` – The desired property from the list of properties in enum `flash_property_tag_t`
- `value` – A pointer to the value returned for the desired flash property.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the flash property was stored to `value`.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.

- `kStatus_FTFx_UnknownProperty` – An unknown property tag.

`status_t` FLASH_GetCommandState(void)

Get previous command status.

This function is used to obtain the execution status of the previous command.

Return values

- `kStatus_FTFx_Success` – The previous command is executed successfully.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

FSL_FLASH_DRIVER_VERSION

Flash driver version for SDK.

Version 3.1.3.

FSL_FLASH_DRIVER_VERSION_ROM

Flash driver version for ROM.

Version 3.0.0.

enum _flash_protection_state

Enumeration for the three possible flash protection levels.

Values:

enumerator `kFLASH_ProtectionStateUnprotected`

Flash region is not protected.

enumerator `kFLASH_ProtectionStateProtected`

Flash region is protected.

enumerator `kFLASH_ProtectionStateMixed`

Flash is mixed with protected and unprotected region.

enum _flash_execute_only_access_state

Enumeration for the three possible flash execute access levels.

Values:

enumerator `kFLASH_AccessStateUnLimited`

Flash region is unlimited.

enumerator `kFLASH_AccessStateExecuteOnly`

Flash region is execute only.

enumerator `kFLASH_AccessStateMixed`

Flash is mixed with unlimited and execute only region.

enum _flash_property_tag

Enumeration for various flash properties.

Values:

enumerator kFLASH_PropertyPflash0SectorSize
Pflash sector size property.

enumerator kFLASH_PropertyPflash0TotalSize
Pflash total size property.

enumerator kFLASH_PropertyPflash0BlockSize
Pflash block size property.

enumerator kFLASH_PropertyPflash0BlockCount
Pflash block count property.

enumerator kFLASH_PropertyPflash0BlockBaseAddr
Pflash block base address property.

enumerator kFLASH_PropertyPflash0FacSupport
Pflash fac support property.

enumerator kFLASH_PropertyPflash0AccessSegmentSize
Pflash access segment size property.

enumerator kFLASH_PropertyPflash0AccessSegmentCount
Pflash access segment count property.

enumerator kFLASH_PropertyPflash1SectorSize
Pflash sector size property.

enumerator kFLASH_PropertyPflash1TotalSize
Pflash total size property.

enumerator kFLASH_PropertyPflash1BlockSize
Pflash block size property.

enumerator kFLASH_PropertyPflash1BlockCount
Pflash block count property.

enumerator kFLASH_PropertyPflash1BlockBaseAddr
Pflash block base address property.

enumerator kFLASH_PropertyPflash1FacSupport
Pflash fac support property.

enumerator kFLASH_PropertyPflash1AccessSegmentSize
Pflash access segment size property.

enumerator kFLASH_PropertyPflash1AccessSegmentCount
Pflash access segment count property.

enumerator kFLASH_PropertyFlexRamBlockBaseAddr
FlexRam block base address property.

enumerator kFLASH_PropertyFlexRamTotalSize
FlexRam total size property.

typedef enum *_flash_protection_state* flash_prot_state_t
Enumeration for the three possible flash protection levels.

typedef union *_pflash_protection_status* pflash_prot_status_t
PFlash protection status.

typedef enum *_flash_execute_only_access_state* flash_xacc_state_t
Enumeration for the three possible flash execute access levels.

```
typedef enum _flash_property_tag flash_property_tag_t
```

Enumeration for various flash properties.

```
typedef struct _flash_config flash_config_t
```

Flash driver state information.

An instance of this structure is allocated by the user of the flash driver and passed into each of the driver APIs.

```
kStatus_FLASH_Success
```

```
kFLASH_ApiEraseKey
```

```
union _pflash_protection_status
```

#include <fsl_ftfx_flash.h> PFlash protection status.

Public Members

```
uint32_t protl
```

PROT[31:0] .

```
uint32_t proth
```

PROT[63:32].

```
uint8_t protsl
```

PROTS[7:0] .

```
uint8_t protsh
```

PROTS[15:8] .

```
uint8_t reserved[2]
```

```
struct _flash_config
```

#include <fsl_ftfx_flash.h> Flash driver state information.

An instance of this structure is allocated by the user of the flash driver and passed into each of the driver APIs.

2.24 Ftftx FLEXNVM Driver

```
status_t FLEXNVM_Init(flexnvm_config_t *config)
```

Initializes the global flash properties structure members.

This function checks and initializes the Flash module for the other Flash APIs.

Parameters

- *config* – Pointer to the storage for the driver runtime state.

Return values

- *kStatus_FTFx_Success* – API was executed successfully.
- *kStatus_FTFx_InvalidArgument* – An invalid argument is provided.
- *kStatus_FTFx_ExecuteInRamFunctionNotReady* – Execute-in-RAM function is not available.
- *kStatus_FTFx_PartitionStatusUpdateFailure* – Failed to update the partition status.

status_t FLEXNVM_DflashErase(*flexnvm_config_t* *config, uint32_t start, uint32_t lengthInBytes, uint32_t key)

Erases the Dflash sectors encompassed by parameters passed into function.

This function erases the appropriate number of flash sectors based on the desired start address and length.

Parameters

- config – The pointer to the storage for the driver runtime state.
- start – The start address of the desired flash memory to be erased. The start address does not need to be sector-aligned but must be word-aligned.
- lengthInBytes – The length, given in bytes (not words or long-words) to be erased. Must be word-aligned.
- key – The value used to validate all flash erase APIs.

Return values

- kStatus_FTFx_Success – API was executed successfully; the appropriate number of data flash sectors based on the desired start address and length were erased successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_AlignmentError – The parameter is not aligned with the specified baseline.
- kStatus_FTFx_AddressError – The address is out of range.
- kStatus_FTFx_EraseKeyError – The API erase key is invalid.
- kStatus_FTFx_ExecuteInRamFunctionNotReady – Execute-in-RAM function is not available.
- kStatus_FTFx_AccessError – Invalid instruction codes and out-of bounds addresses.
- kStatus_FTFx_ProtectionViolation – The program/erase operation is requested to execute on protected areas.
- kStatus_FTFx_CommandFailure – Run-time error during the command execution.

status_t FLEXNVM_EraseAll(*flexnvm_config_t* *config, uint32_t key)

Erases entire flexnvm.

Parameters

- config – Pointer to the storage for the driver runtime state.
- key – A value used to validate all flash erase APIs.

Return values

- kStatus_FTFx_Success – API was executed successfully; the entire flexnvm has been erased successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_EraseKeyError – API erase key is invalid.
- kStatus_FTFx_ExecuteInRamFunctionNotReady – Execute-in-RAM function is not available.
- kStatus_FTFx_AccessError – Invalid instruction codes and out-of bounds addresses.

- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.
- `kStatus_FTFx_PartitionStatusUpdateFailure` – Failed to update the partition status.

`status_t` FLEXNVM_EraseAllUnsecure(*flexnvm_config_t* *config, uint32_t key)

Erases the entire flexnvm, including protected sectors.

Parameters

- config – Pointer to the storage for the driver runtime state.
- key – A value used to validate all flash erase APIs.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the flexnvm is not in security state.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_EraseKeyError` – API erase key is invalid.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.
- `kStatus_FTFx_PartitionStatusUpdateFailure` – Failed to update the partition status.

`status_t` FLEXNVM_DflashProgram(*flexnvm_config_t* *config, uint32_t start, uint8_t *src, uint32_t lengthInBytes)

Programs flash with data at locations passed in through parameters.

This function programs the flash memory with the desired data for a given flash area as determined by the start address and the length.

Parameters

- config – A pointer to the storage for the driver runtime state.
- start – The start address of the desired flash memory to be programmed. Must be word-aligned.
- src – A pointer to the source buffer of data that is to be programmed into the flash.
- lengthInBytes – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the desired data have been successfully programed into specified date flash region.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with the specified baseline.

- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t` FLEXNVM_DflashProgramSection(*flexnvm_config_t* *config, uint32_t start, uint8_t *src, uint32_t lengthInBytes)

Programs flash with data at locations passed in through parameters via the Program Section command.

This function programs the flash memory with the desired data for a given flash area as determined by the start address and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be programmed. Must be word-aligned.
- `src` – A pointer to the source buffer of data that is to be programmed into the flash.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the desired data have been successfully programmed into specified data flash area.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_SetFlexramAsRamError` – Failed to set flexram as RAM.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.
- `kStatus_FTFx_RecoverFlexramAsEepromError` – Failed to recover FlexRAM as EEPROM.

`status_t` FLEXNVM_ProgramPartition(*flexnvm_config_t* *config, *ftfx_partition_flexram_load_opt_t* option, uint32_t eepromDataSizeCode, uint32_t flexnvmPartitionCode)

Prepares the FlexNVM block for use as data flash, EEPROM backup, or a combination of both and initializes the FlexRAM.

Parameters

- `config` – Pointer to storage for the driver runtime state.
- `option` – The option used to set FlexRAM load behavior during reset.
- `eeepromDataSizeCode` – Determines the amount of FlexRAM used in each of the available EEPROM subsystems.
- `flexnvmPartitionCode` – Specifies how to split the FlexNVM block between data flash memory and EEPROM backup memory supporting EEPROM functions.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the FlexNVM block for use as data flash, EEPROM backup, or a combination of both have been Prepared.
- `kStatus_FTFx_InvalidArgument` – Invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.

`status_t FLEXNVM_ProgramPartition_CSE(flexnvm_config_t *config,
ftfx_partition_flexram_load_opt_t option, uint32_t
eeepromDataSizeCode, uint32_t
flexnvmPartitionCode, uint8_t CSEcKeySize, uint8_t
SFE)`

Prepares the FlexNVM block for use as data flash, EEPROM backup, or a combination of both and initializes the FlexRAM. This is the CSE enabled version for IP's like FTFC.

Parameters

- `config` – Pointer to storage for the driver runtime state.
- `option` – The option used to set FlexRAM load behavior during reset.
- `eeepromDataSizeCode` – Determines the amount of FlexRAM used in each of the available EEPROM subsystems.
- `flexnvmPartitionCode` – Specifies how to split the FlexNVM block between data flash memory and EEPROM backup memory supporting EEPROM functions.
- `CSEcKeySize` – CSEc/SHE key size, see RM for details and possible values
- `SFE` – Security Flag Extension (SFE), see RM for details and possible values

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the FlexNVM block for use as data flash, EEPROM backup, or a combination of both have been Prepared.
- `kStatus_FTFx_InvalidArgument` – Invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.

- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.

`status_t FLEXNVM_ReadResource(flexnvm_config_t *config, uint32_t start, uint8_t *dst, uint32_t lengthInBytes, ftfx_read_resource_opt_t option)`

Reads the resource with data at locations passed in through parameters.

This function reads the flash memory with the desired location for a given flash area as determined by the start address and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be programmed. Must be word-aligned.
- `dst` – A pointer to the destination buffer of data that is used to store data to be read.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be read. Must be word-aligned.
- `option` – The resource option which indicates which area should be read back.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the data have been read successfully from program flash IFR, data flash IFR space, and the Version ID field
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with the specified baseline.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FLEXNVM_DflashVerifyErase(flexnvm_config_t *config, uint32_t start, uint32_t lengthInBytes, ftfx_margin_value_t margin)`

Verifies an erasure of the desired flash area at a specified margin level.

This function checks the appropriate number of flash sectors based on the desired start address and length to check whether the flash is erased to the specified read margin level.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be verified. The start address does not need to be sector-aligned but must be word-aligned.

- `lengthInBytes` – The length, given in bytes (not words or long-words), to be verified. Must be word-aligned.
- `margin` – Read margin choice.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the specified data flash region is in erased state.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FLEXNVM_VerifyEraseAll(flexnvm_config_t *config, ftfx_margin_value_t margin)`

Verifies erasure of the entire flash at a specified margin level.

This function checks whether the flash is erased to the specified read margin level.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `margin` – Read margin choice.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the entire flexnvm region is in erased state.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FLEXNVM_DflashVerifyProgram(flexnvm_config_t *config, uint32_t start, uint32_t lengthInBytes, const uint8_t *expectedData, ftfx_margin_value_t margin, uint32_t *failedAddress, uint32_t *failedData)`

Verifies programming of the desired flash area at a specified margin level.

This function verifies the data programmed in the flash memory using the Flash Program Check Command and compares it to the expected data for a given flash area as determined by the start address and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be verified. Must be word-aligned.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be verified. Must be word-aligned.
- `expectedData` – A pointer to the expected data that is to be verified against.
- `margin` – Read margin choice.
- `failedAddress` – A pointer to the returned failing address.
- `failedData` – A pointer to the returned failing data. Some derivatives do not include failed data as part of the FCCOBx registers. In this case, zeros are returned upon failure.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the desired data have been programmed successfully into specified data flash region.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t` FLEXNVM_GetSecurityState(*flexnvm_config_t* *config, *ftfx_security_state_t* *state)

Returns the security state via the pointer passed into the function.

This function retrieves the current flash security status, including the security enabling state and the backdoor key enabling state.

Parameters

- `config` – A pointer to storage for the driver runtime state.
- `state` – A pointer to the value returned for the current security status code:

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the security state of flexnvm was stored to state.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.

`status_t` FLEXNVM_SecurityBypass(*flexnvm_config_t* *config, const `uint8_t` *backdoorKey)

Allows users to bypass security with a backdoor key.

If the MCU is in secured state, this function unsecures the MCU by comparing the provided backdoor key with ones in the flash configuration field.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `backdoorKey` – A pointer to the user buffer containing the backdoor key.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FLEXNVM_SetFlexramFunction(flexnvm_config_t *config, ftfx_flexram_func_opt_t option)`

Sets the FlexRAM function command.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `option` – The option used to set the work mode of FlexRAM.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the FlexRAM has been successfully configured as RAM or EEPROM
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FLEXNVM_DflashSetProtection(flexnvm_config_t *config, uint8_t protectStatus)`

Sets the DFlash protection to the intended protection status.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `protectStatus` – The expected protect status to set to the DFlash protection register. Each bit corresponds to the protection of the 1/8 of the total DFlash. The least significant bit corresponds to the lowest address area of the DFlash. The most significant bit corresponds to the highest address area of the DFlash. There are two possible cases as shown below: 0: this area is protected. 1: this area is unprotected.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the specified DFlash region is protected.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_CommandNotSupported` – Flash API is not supported.

- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.

`status_t` FLEXNVM_DflashGetProtection(*flexnvm_config_t* *config, `uint8_t` *protectStatus)

Gets the DFlash protection status.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `protectStatus` – DFlash Protect status returned by the PFlash IP. Each bit corresponds to the protection of the 1/8 of the total DFlash. The least significant bit corresponds to the lowest address area of the DFlash. The most significant bit corresponds to the highest address area of the DFlash, and so on. There are two possible cases as below: 0: this area is protected. 1: this area is unprotected.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_CommandNotSupported` – Flash API is not supported.

`status_t` FLEXNVM_EepromSetProtection(*flexnvm_config_t* *config, `uint8_t` protectStatus)

Sets the EEPROM protection to the intended protection status.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `protectStatus` – The expected protect status to set to the EEPROM protection register. Each bit corresponds to the protection of the 1/8 of the total EEPROM. The least significant bit corresponds to the lowest address area of the EEPROM. The most significant bit corresponds to the highest address area of EEPROM, and so on. There are two possible cases as shown below: 0: this area is protected. 1: this area is unprotected.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_CommandNotSupported` – Flash API is not supported.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.

`status_t` FLEXNVM_EepromGetProtection(*flexnvm_config_t* *config, `uint8_t` *protectStatus)

Gets the EEPROM protection status.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `protectStatus` – DFlash Protect status returned by the PFlash IP. Each bit corresponds to the protection of the 1/8 of the total EEPROM. The least significant bit corresponds to the lowest address area of the EEPROM. The most significant bit corresponds to the highest address area of the EEPROM. There are two possible cases as below: 0: this area is protected. 1: this area is unprotected.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.

- kStatus_FTFx_CommandNotSupported – Flash API is not supported.

status_t FLEXNVM_GetProperty(*flexnvm_config_t* *config, *flexnvm_property_tag_t* whichProperty, *uint32_t* *value)

Returns the desired flexnvm property.

Parameters

- config – A pointer to the storage for the driver runtime state.
- whichProperty – The desired property from the list of properties in enum *flexnvm_property_tag_t*
- value – A pointer to the value returned for the desired flexnvm property.

Return values

- kStatus_FTFx_Success – API was executed successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_UnknownProperty – An unknown property tag.

enum *_flexnvm_property_tag*

Enumeration for various flexnvm properties.

Values:

enumerator kFLEXNVM_PropertyDflashSectorSize
Dflash sector size property.

enumerator kFLEXNVM_PropertyDflashTotalSize
Dflash total size property.

enumerator kFLEXNVM_PropertyDflashBlockSize
Dflash block size property.

enumerator kFLEXNVM_PropertyDflashBlockCount
Dflash block count property.

enumerator kFLEXNVM_PropertyDflashBlockBaseAddr
Dflash block base address property.

enumerator kFLEXNVM_PropertyAliasDflashBlockBaseAddr
Dflash block base address Alias property.

enumerator kFLEXNVM_PropertyFlexRamBlockBaseAddr
FlexRam block base address property.

enumerator kFLEXNVM_PropertyFlexRamTotalSize
FlexRam total size property.

enumerator kFLEXNVM_PropertyEepromTotalSize
EEPROM total size property.

typedef enum *_flexnvm_property_tag* *flexnvm_property_tag_t*

Enumeration for various flexnvm properties.

typedef struct *_flexnvm_config* *flexnvm_config_t*

Flexnvm driver state information.

An instance of this structure is allocated by the user of the Flexnvm driver and passed into each of the driver APIs.

status_t FLEXNVM_EepromWrite(*flexnvm_config_t* *config, uint32_t start, uint8_t *src, uint32_t lengthInBytes)

Programs the EEPROM with data at locations passed in through parameters.

This function programs the emulated EEPROM with the desired data for a given flash area as determined by the start address and length.

Parameters

- config – A pointer to the storage for the driver runtime state.
- start – The start address of the desired flash memory to be programmed. Must be word-aligned.
- src – A pointer to the source buffer of data that is to be programmed into the flash.
- lengthInBytes – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- kStatus_FTFx_Success – API was executed successfully; the desired data have been successfully programmed into specified eeprom region.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_AddressError – Address is out of range.
- kStatus_FTFx_SetFlexramAsEepromError – Failed to set flexram as eeprom.
- kStatus_FTFx_ProtectionViolation – The program/erase operation is requested to execute on protected areas.
- kStatus_FTFx_RecoverFlexramAsRamError – Failed to recover the FlexRAM as RAM.

struct _flexnvm_config

#include <fsl_ftfx_flexnvm.h> Flexnvm driver state information.

An instance of this structure is allocated by the user of the Flexnvm driver and passed into each of the driver APIs.

2.25 ftfx utilities

ALIGN_DOWN(x, a)

Alignment(down) utility.

ALIGN_UP(x, a)

Alignment(up) utility.

MAKE_VERSION(major, minor, bugfix)

Constructs the version number for drivers.

MAKE_STATUS(group, code)

Constructs a status code value from a group and a code number.

FOUR_CHAR_CODE(a, b, c, d)

Constructs the four character code for the Flash driver API key.

B1P4(b)

bytes2word utility.

B1P3(b)

B1P2(b)

B1P1(b)

B2P3(b)

B2P2(b)

B2P1(b)

B3P2(b)

B3P1(b)

BYTE2WORD_1_3(x, y)

BYTE2WORD_2_2(x, y)

BYTE2WORD_3_1(x, y)

BYTE2WORD_1_1_2(x, y, z)

BYTE2WORD_1_2_1(x, y, z)

BYTE2WORD_2_1_1(x, y, z)

BYTE2WORD_1_1_1_1(x, y, z, w)

2.26 FTM: FlexTimer Driver

status_t FTM_Init(FTM_Type *base, const *ftm_config_t* *config)

Un gates the FTM clock and config ures the peripheral for basic operation.

Note: This API should be called at the beginning of the application which is using the FTM driver. If the FTM instance has only TPM features, please use the TPM driver.

Parameters

- base – FTM peripheral base address
- config – Pointer to the user configuration structure.

Returns

kStatus_Success indicates success; Else indicates failure.

void FTM_Deinit(FTM_Type *base)

Gates the FTM clock.

Parameters

- base – FTM peripheral base address

void FTM_GetDefaultConfig(*ftm_config_t* *config)

Fills in the FTM configuration structure with the default settings.

The default values are:

```

config->prescale = kFTM_Prescale_Divide_1;
config->bdmMode = kFTM_BdmMode_0;
config->pwmSyncMode = kFTM_SoftwareTrigger;
config->reloadPoints = 0;
config->faultMode = kFTM_Fault_Disable;
config->faultFilterValue = 0;
config->deadTimePrescale = kFTM_Deadtime_Prescale_1;
config->deadTimeValue = 0;
config->extTriggers = 0;
config->chnlInitState = 0;
config->chnlPolarity = 0;
config->useGlobalTimeBase = false;
config->hwTriggerResetCount = false;
config->swTriggerResetCount = true;

```

Parameters

- config – Pointer to the user configuration structure.

```
static inline ftm_clock_prescale_t FTM__CalculateCounterClkDiv(FTM_Type *base, uint32_t
counterPeriod_Hz, uint32_t
srcClock_Hz)
```

brief Calculates the counter clock prescaler.

This function calculates the values for SC[PS] bit.

param base FTM peripheral base address param counterPeriod_Hz The desired frequency in Hz which corresponding to the time when the counter reaches the mod value param srcClock_Hz FTM counter clock in Hz

return Calculated clock prescaler value, see *ftm_clock_prescale_t*.

```
status_t FTM_SetupPwm(FTM_Type *base, const ftm_chnl_pwm_signal_param_t *chnlParams,
uint8_t numOfChnls, ftm_pwm_mode_t mode, uint32_t pwmFreq_Hz,
uint32_t srcClock_Hz)
```

Configures the PWM signal parameters.

Call this function to configure the PWM signal period, mode, duty cycle, and edge. Use this function to configure all FTM channels that are used to output a PWM signal.

Parameters

- base – FTM peripheral base address
- chnlParams – Array of PWM channel parameters to configure the channel(s)
- numOfChnls – Number of channels to configure; This should be the size of the array passed in
- mode – PWM operation mode, options available in enumeration *ftm_pwm_mode_t*
- pwmFreq_Hz – PWM signal frequency in Hz
- srcClock_Hz – FTM counter clock in Hz

Returns

kStatus_Success if the PWM setup was successful *kStatus_Error* on failure

```
status_t FTM_UpdatePwmDutycycle(FTM_Type *base, ftm_chnl_t chnlNumber, ftm_pwm_mode_t
currentPwmMode, uint8_t dutyCyclePercent)
```

Updates the duty cycle of an active PWM signal.

Parameters

- `base` – FTM peripheral base address
- `chnlNumber` – The channel/channel pair number. In combined mode, this represents the channel pair number
- `currentPwmMode` – The current PWM mode set during PWM setup
- `dutyCyclePercent` – New PWM pulse width; The value should be between 0 to 100 0=inactive signal(0% duty cycle)... 100=active signal (100% duty cycle)

Returns

`kStatus_Success` if the PWM update was successful `kStatus_Error` on failure

`void FTM_UpdateChnlEdgeLevelSelect(FTM_Type *base, ftm_chnl_t chnlNumber, uint8_t level)`

Updates the edge level selection for a channel.

Parameters

- `base` – FTM peripheral base address
- `chnlNumber` – The channel number
- `level` – The level to be set to the `ELSnB:ELSnA` field; Valid values are 00, 01, 10, 11. See the Kinetis SoC reference manual for details about this field.

`status_t FTM_SetupPwmMode(FTM_Type *base, const ftm_chnl_pwm_config_param_t *chnlParams, uint8_t numOfChnls, ftm_pwm_mode_t mode)`

Configures the PWM mode parameters.

Call this function to configure the PWM signal mode, duty cycle in ticks, and edge. Use this function to configure all FTM channels that are used to output a PWM signal. Please note that: This API is similar with `FTM_SetupPwm()` API, but will not set the timer period, and this API will set channel match value in timer ticks, not period percent.

Parameters

- `base` – FTM peripheral base address
- `chnlParams` – Array of PWM channel parameters to configure the channel(s)
- `numOfChnls` – Number of channels to configure; This should be the size of the array passed in
- `mode` – PWM operation mode, options available in enumeration `ftm_pwm_mode_t`

Returns

`kStatus_Success` if the PWM setup was successful `kStatus_Error` on failure

`void FTM_ConfigSinglePWM(FTM_Type *base, const ftm_chnl_param_t *chnlParams, ftm_chnl_t chnlNumber)`

Configure FTM edge aligned PWM or center aligned PWM by each channel.

This function configure PWM signal by setting channel `n` value register. Need to invoke `FTM_SetInitialModuloValue` to configure FTM period.

Parameters

- `base` – FTM peripheral base address
- `chnlParams` – PWM configuration structure pointer.
- `chnlPairNumber` – Channel number.

```
void FTM_ConfigCombinePWM(FTM_Type *base, const ftm_chnl_param_t *chnlParams,
                          ftm_chnl_t chnlPairNumber)
```

Configure FTM Combine PWM, Modified Combine PWM or Asymmetrical PWM by each channel pair.

This function configure PWM signal by setting channel n value register. Need to invoke FTM_SetInitialModuloValue to configure FTM period.

Parameters

- base – FTM peripheral base address
- chnlParams – PWM configuration structure pointer.
- chnlPairNumber – Channel pair number, options are 0, 1, 2, 3.

```
void FTM_SetupInputCapture(FTM_Type *base, ftm_chnl_t chnlNumber,
                           ftm_input_capture_edge_t captureMode, uint32_t filterValue)
```

Enables capturing an input signal on the channel using the function parameters.

When the edge specified in the captureMode argument occurs on the channel, the FTM counter is captured into the CnV register. The user has to read the CnV register separately to get this value. The filter function is disabled if the filterVal argument passed in is 0. The filter function is available only for channels 0, 1, 2, 3.

Parameters

- base – FTM peripheral base address
- chnlNumber – The channel number
- captureMode – Specifies which edge to capture
- filterValue – Filter value, specify 0 to disable filter. Available only for channels 0-3.

```
void FTM_SetupOutputCompare(FTM_Type *base, ftm_chnl_t chnlNumber,
                             ftm_output_compare_mode_t compareMode, uint32_t
                             compareValue)
```

Configures the FTM to generate timed pulses.

When the FTM counter matches the value of compareVal argument (this is written into CnV reg), the channel output is changed based on what is specified in the compareMode argument.

Parameters

- base – FTM peripheral base address
- chnlNumber – The channel number
- compareMode – Action to take on the channel output when the compare condition is met
- compareValue – Value to be programmed in the CnV register.

```
void FTM_SetupDualEdgeCapture(FTM_Type *base, ftm_chnl_t chnlPairNumber, const
                               ftm_dual_edge_capture_param_t *edgeParam, uint32_t
                               filterValue)
```

Configures the dual edge capture mode of the FTM.

This function sets up the dual edge capture mode on a channel pair. The capture edge for the channel pair and the capture mode (one-shot or continuous) is specified in the parameter argument. The filter function is disabled if the filterVal argument passed is zero. The filter function is available only on channels 0 and 2. The user has to read the channel CnV registers separately to get the capture values.

Parameters

- `base` – FTM peripheral base address
- `chnlPairNumber` – The FTM channel pair number; options are 0, 1, 2, 3
- `edgeParam` – Sets up the dual edge capture function
- `filterValue` – Filter value, specify 0 to disable filter. Available only for channel pair 0 and 1.

`void FTM_EnableInterrupts(FTM_Type *base, uint32_t mask)`

Enables the selected FTM interrupts.

Parameters

- `base` – FTM peripheral base address
- `mask` – The interrupts to enable. This is a logical OR of members of the enumeration `ftm_interrupt_enable_t`

`void FTM_DisableInterrupts(FTM_Type *base, uint32_t mask)`

Disables the selected FTM interrupts.

Parameters

- `base` – FTM peripheral base address
- `mask` – The interrupts to enable. This is a logical OR of members of the enumeration `ftm_interrupt_enable_t`

`uint32_t FTM_GetEnabledInterrupts(FTM_Type *base)`

Gets the enabled FTM interrupts.

Parameters

- `base` – FTM peripheral base address

Returns

The enabled interrupts. This is the logical OR of members of the enumeration `ftm_interrupt_enable_t`

`uint32_t FTM_GetInstance(FTM_Type *base)`

Gets the instance from the base address.

Parameters

- `base` – FTM peripheral base address

Returns

The FTM instance

`uint32_t FTM_GetStatusFlags(FTM_Type *base)`

Gets the FTM status flags.

Parameters

- `base` – FTM peripheral base address

Returns

The status flags. This is the logical OR of members of the enumeration `ftm_status_flags_t`

`void FTM_ClearStatusFlags(FTM_Type *base, uint32_t mask)`

Clears the FTM status flags.

Parameters

- `base` – FTM peripheral base address
- `mask` – The status flags to clear. This is a logical OR of members of the enumeration `ftm_status_flags_t`

```
static inline void FTM_SetTimerPeriod(FTM_Type *base, uint32_t ticks)
```

Sets the timer period in units of ticks.

Timers counts from 0 until it equals the count value set here. The count value is written to the MOD register.

Note:

- a. This API allows the user to use the FTM module as a timer. Do not mix usage of this API with FTM's PWM setup API's.
 - b. Call the utility macros provided in the `fsl_common.h` to convert usec or msec to ticks.
-

Parameters

- `base` – FTM peripheral base address
- `ticks` – A timer period in units of ticks, which should be equal or greater than 1.

```
static inline void FTM_SetInitialModuloValue(FTM_Type *base, uint16_t initialValue, uint16_t moduloValue)
```

Set initial value and modulo value for FTM.

Parameters

- `base` – FTM peripheral base address
- `initialValue` – FTM counter initial value.
- `moduloValue` – FTM counter modulo value.

```
static inline uint32_t FTM_GetCurrentTimerCount(FTM_Type *base)
```

Reads the current timer counting value.

This function returns the real-time timer counting value in a range from 0 to a timer period.

Note: Call the utility macros provided in the `fsl_common.h` to convert ticks to usec or msec.

Parameters

- `base` – FTM peripheral base address

Returns

The current counter value in ticks

```
static inline void FTM_SetChannelMatchValue(FTM_Type *base, ftm_chnl_t chnlNumber, uint16_t value)
```

Set channel match value for output.

Parameters

- `base` – FTM peripheral base address
- `chnlNumber` – Channel to set.
- `value` – Channel match value for output.

```
static inline uint32_t FTM_GetInputCaptureValue(FTM_Type *base, ftm_chnl_t chnlNumber)
```

Reads the captured value.

This function returns the captured value of a FTM channel configured in input capture or dual edge capture mode.

Note: Call the utility macros provided in the `fsl_common.h` to convert ticks to usec or msec.

Parameters

- `base` – FTM peripheral base address
- `chnlNumber` – Channel to be read

Returns

The captured FTM counter value of the input modes.

```
static inline void FTM_StartTimer(FTM_Type *base, ftm_clock_source_t clockSource)
```

Starts the FTM counter.

Parameters

- `base` – FTM peripheral base address
- `clockSource` – FTM clock source; After the clock source is set, the counter starts running.

```
static inline void FTM_StopTimer(FTM_Type *base)
```

Stops the FTM counter.

Parameters

- `base` – FTM peripheral base address

```
static inline uint32_t FTM_GetSoftwareOutputValue(FTM_Type *base)
```

Get channel software output status.

Parameters

- `base` – FTM peripheral base address

Returns

Status of channel software output, logical OR value of `ftm_channel_index_t`.

```
static inline uint32_t FTM_GetSoftwareOutputEnable(FTM_Type *base)
```

Get channel software enable status.

Parameters

- `base` – FTM peripheral base address

Returns

Status of channel software enable, logical OR value of `ftm_channel_index_t`.

```
static inline void FTM_SetSoftwareOutputCtrl(FTM_Type *base, uint32_t chnlEnable, uint32_t  
                                             chnlValue)
```

Enables or disables the channel software output control and set channel software output value.

Parameters

- `base` – FTM peripheral base address
- `chnlEnable` – Channels to enable or disable software output control, logical OR of enumeration `ftm_channel_index_t` members.
- `chnlValue` – Channels output value, logical OR of enumeration `ftm_channel_index_t` members

```
static inline void FTM_SetSoftwareCtrlEnable(FTM_Type *base, ftm_chnl_t chnlNumber, bool  
                                             value)
```

Enables or disables the channel software output control.

Parameters

- base – FTM peripheral base address
- chnlNumber – Channel to be enabled or disabled
- value – true: channel output is affected by software output control false: channel output is unaffected by software output control

static inline void FTM_SetSoftwareCtrlVal(FTM_Type *base, *ftm_chnl_t* chnlNumber, bool value)
Sets the channel software output control value.

Parameters

- base – FTM peripheral base address.
- chnlNumber – Channel to be configured
- value – true to set 1, false to set 0

static inline void FTM_SetFaultControlEnable(FTM_Type *base, *ftm_chnl_t* chnlPairNumber, bool value)

This function enables/disables the fault control in a channel pair.

Parameters

- base – FTM peripheral base address
- chnlPairNumber – The FTM channel pair number; options are 0, 1, 2, 3
- value – true: Enable fault control for this channel pair; false: No fault control

static inline void FTM_SetDeadTimeEnable(FTM_Type *base, *ftm_chnl_t* chnlPairNumber, bool value)

This function enables/disables the dead time insertion in a channel pair.

Parameters

- base – FTM peripheral base address
- chnlPairNumber – The FTM channel pair number; options are 0, 1, 2, 3
- value – true: Insert dead time in this channel pair; false: No dead time inserted

static inline void FTM_SetComplementaryEnable(FTM_Type *base, *ftm_chnl_t* chnlPairNumber, bool value)

This function enables/disables complementary mode in a channel pair.

Parameters

- base – FTM peripheral base address
- chnlPairNumber – The FTM channel pair number; options are 0, 1, 2, 3
- value – true: enable complementary mode; false: disable complementary mode

static inline void FTM_SetInvertEnable(FTM_Type *base, *ftm_chnl_t* chnlPairNumber, bool value)

This function enables/disables inverting control in a channel pair.

Parameters

- base – FTM peripheral base address
- chnlPairNumber – The FTM channel pair number; options are 0, 1, 2, 3
- value – true: enable inverting; false: disable inverting

```
void FTM_SetupQuadDecode(FTM_Type *base, const ftm_phase_params_t *phaseAParams,  
                        const ftm_phase_params_t *phaseBParams,  
                        ftm_quad_decode_mode_t quadMode)
```

Configures the parameters and activates the quadrature decoder mode.

Parameters

- base – FTM peripheral base address
- phaseAParams – Phase A configuration parameters
- phaseBParams – Phase B configuration parameters
- quadMode – Selects encoding mode used in quadrature decoder mode

```
static inline uint32_t FTM_GetQuadDecoderFlags(FTM_Type *base)
```

Gets the FTM Quad Decoder flags.

Parameters

- base – FTM peripheral base address.

Returns

Flag mask of FTM Quad Decoder, see `_ftm_quad_decoder_flags`.

```
static inline void FTM_SetQuadDecoderModuloValue(FTM_Type *base, uint32_t startValue,  
                                                uint32_t overValue)
```

Sets the modulo values for Quad Decoder.

The modulo values configure the minimum and maximum values that the Quad decoder counter can reach. After the counter goes over, the counter value goes to the other side and decrease/increase again.

Parameters

- base – FTM peripheral base address.
- startValue – The low limit value for Quad Decoder counter.
- overValue – The high limit value for Quad Decoder counter.

```
static inline uint32_t FTM_GetQuadDecoderCounterValue(FTM_Type *base)
```

Gets the current Quad Decoder counter value.

Parameters

- base – FTM peripheral base address.

Returns

Current quad Decoder counter value.

```
static inline void FTM_ClearQuadDecoderCounterValue(FTM_Type *base)
```

Clears the current Quad Decoder counter value.

The counter is set as the initial value.

Parameters

- base – FTM peripheral base address.

```
FSL_FTM_DRIVER_VERSION
```

FTM driver version 2.7.1.

```
enum _ftm_chnl
```

List of FTM channels.

Note: Actual number of available channels is SoC dependent

Values:

enumerator kFTM_Chnl_0
FTM channel number 0

enumerator kFTM_Chnl_1
FTM channel number 1

enumerator kFTM_Chnl_2
FTM channel number 2

enumerator kFTM_Chnl_3
FTM channel number 3

enumerator kFTM_Chnl_4
FTM channel number 4

enumerator kFTM_Chnl_5
FTM channel number 5

enumerator kFTM_Chnl_6
FTM channel number 6

enumerator kFTM_Chnl_7
FTM channel number 7

enum _ftm_fault_input

List of FTM faults.

Values:

enumerator kFTM_Fault_0
FTM fault 0 input pin

enumerator kFTM_Fault_1
FTM fault 1 input pin

enumerator kFTM_Fault_2
FTM fault 2 input pin

enumerator kFTM_Fault_3
FTM fault 3 input pin

enum _ftm_pwm_mode

FTM PWM operation modes.

Values:

enumerator kFTM_EdgeAlignedPwm
Edge-aligned PWM

enumerator kFTM_CenterAlignedPwm
Center-aligned PWM

enumerator kFTM_EdgeAlignedCombinedPwm
Edge-aligned combined PWM

enumerator kFTM_CenterAlignedCombinedPwm
Center-aligned combined PWM

enumerator kFTM_AsymmetricalCombinedPwm
Asymmetrical combined PWM

enum _ftm_pwm_level_select

FTM PWM output pulse mode: high-true, low-true or no output.

Note: kFTM_NoPwmSignal: ELSnB:ELSnA = 0:0 kFTM_LowTrue: ELSnB:ELSnA = 0:1
EPWM: Channel n output is forced low at counter overflow, forced high at channel n match.
CPWM: Channel n output is forced low at channel n match when counting down, and forced high at channel n match when counting up. Combined PWM: Channel n output is forced high at beginning of period and at channel n+1 match. It is forced low at the channel n match. kFTM_HighTrue: ELSnB:ELSnA = 1:0 EPWM: Channel n output is forced high at counter overflow, forced low at channel n match. CPWM: Channel n output is forced high at channel n match when counting down, and forced low at channel n match when counting up. Combined PWM: Channel n output is forced low at beginning of period and at channel n+1 match. It is forced high at the channel n match.

Values:

enumerator kFTM_NoPwmSignal

No PWM output on pin

enumerator kFTM_LowTrue

Low true pulses

enumerator kFTM_HighTrue

High true pulses

enum _ftm_output_compare_mode

FlexTimer output compare mode.

Values:

enumerator kFTM_NoOutputSignal

No channel output when counter reaches CnV

enumerator kFTM_ToggleOnMatch

Toggle output

enumerator kFTM_ClearOnMatch

Clear output

enumerator kFTM_SetOnMatch

Set output

enum _ftm_input_capture_edge

FlexTimer input capture edge.

Values:

enumerator kFTM_RisingEdge

Capture on rising edge only

enumerator kFTM_FallingEdge

Capture on falling edge only

enumerator kFTM_RiseAndFallEdge

Capture on rising or falling edge

enum _ftm_dual_edge_capture_mode

FlexTimer dual edge capture modes.

Values:

enumerator kFTM_OneShot
One-shot capture mode

enumerator kFTM_Continuous
Continuous capture mode

enum _ftm_quad_decode_mode
FlexTimer quadrature decode modes.
Values:

enumerator kFTM_QuadPhaseEncode
Phase A and Phase B encoding mode

enumerator kFTM_QuadCountAndDir
Count and direction encoding mode

enum _ftm_phase_polarity
FlexTimer quadrature phase polarities.
Values:

enumerator kFTM_QuadPhaseNormal
Phase input signal is not inverted

enumerator kFTM_QuadPhaseInvert
Phase input signal is inverted

enum _ftm_deadtime_prescale
FlexTimer pre-scaler factor for the dead time insertion.
Values:

enumerator kFTM_Deadtime_Prescale_1
Divide by 1

enumerator kFTM_Deadtime_Prescale_4
Divide by 4

enumerator kFTM_Deadtime_Prescale_16
Divide by 16

enum _ftm_clock_source
FlexTimer clock source selection.
Values:

enumerator kFTM_SystemClock
System clock selected

enumerator kFTM_FixedClock
Fixed frequency clock

enumerator kFTM_ExternalClock
External clock

enum _ftm_clock_prescale
FlexTimer pre-scaler factor selection for the clock source.
Values:

enumerator kFTM_Prescale_Divide_1
Divide by 1

enumerator kFTM_Prescale_Divide_2
Divide by 2

enumerator kFTM_Prescale_Divide_4
Divide by 4

enumerator kFTM_Prescale_Divide_8
Divide by 8

enumerator kFTM_Prescale_Divide_16
Divide by 16

enumerator kFTM_Prescale_Divide_32
Divide by 32

enumerator kFTM_Prescale_Divide_64
Divide by 64

enumerator kFTM_Prescale_Divide_128
Divide by 128

enum _ftm_bdm_mode

Options for the FlexTimer behaviour in BDM Mode.

Values:

enumerator kFTM_BdmMode_0
FTM counter stopped, CH(n)F bit can be set, FTM channels in functional mode, writes to MOD,CNTIN and C(n)V registers bypass the register buffers

enumerator kFTM_BdmMode_1
FTM counter stopped, CH(n)F bit is not set, FTM channels outputs are forced to their safe value , writes to MOD,CNTIN and C(n)V registers bypass the register buffers

enumerator kFTM_BdmMode_2
FTM counter stopped, CH(n)F bit is not set, FTM channels outputs are frozen when chip enters in BDM mode, writes to MOD,CNTIN and C(n)V registers bypass the register buffers

enumerator kFTM_BdmMode_3
FTM counter in functional mode, CH(n)F bit can be set, FTM channels in functional mode, writes to MOD,CNTIN and C(n)V registers is in fully functional mode

enum _ftm_fault_mode

Options for the FTM fault control mode.

Values:

enumerator kFTM_Fault_Disable
Fault control is disabled for all channels

enumerator kFTM_Fault_EvenChnls
Enabled for even channels only(0,2,4,6) with manual fault clearing

enumerator kFTM_Fault_AllChnlsMan
Enabled for all channels with manual fault clearing

enumerator kFTM_Fault_AllChnlsAuto
Enabled for all channels with automatic fault clearing

enum _ftm_external_trigger
FTM external trigger options.

Note: Actual available external trigger sources are SoC-specific

Values:

enumerator kFTM_Chnl0Trigger
Generate trigger when counter equals chnl 0 CnV reg

enumerator kFTM_Chnl1Trigger
Generate trigger when counter equals chnl 1 CnV reg

enumerator kFTM_Chnl2Trigger
Generate trigger when counter equals chnl 2 CnV reg

enumerator kFTM_Chnl3Trigger
Generate trigger when counter equals chnl 3 CnV reg

enumerator kFTM_Chnl4Trigger
Generate trigger when counter equals chnl 4 CnV reg

enumerator kFTM_Chnl5Trigger
Generate trigger when counter equals chnl 5 CnV reg

enumerator kFTM_Chnl6Trigger
Available on certain SoC's, generate trigger when counter equals chnl 6 CnV reg

enumerator kFTM_Chnl7Trigger
Available on certain SoC's, generate trigger when counter equals chnl 7 CnV reg

enumerator kFTM_InitTrigger
Generate Trigger when counter is updated with CNTIN

enumerator kFTM_ReloadInitTrigger
Available on certain SoC's, trigger on reload point

enum _ftm_pwm_sync_method
FlexTimer PWM sync options to update registers with buffer.

Values:

enumerator kFTM_SoftwareTrigger
Software triggers PWM sync

enumerator kFTM_HardwareTrigger_0
Hardware trigger 0 causes PWM sync

enumerator kFTM_HardwareTrigger_1
Hardware trigger 1 causes PWM sync

enumerator kFTM_HardwareTrigger_2
Hardware trigger 2 causes PWM sync

enum _ftm_reload_point
FTM options available as loading point for register reload.

Note: Actual available reload points are SoC-specific

Values:

enumerator kFTM_Chnl0Match

Channel 0 match included as a reload point

enumerator kFTM_Chnl1Match

Channel 1 match included as a reload point

enumerator kFTM_Chnl2Match

Channel 2 match included as a reload point

enumerator kFTM_Chnl3Match

Channel 3 match included as a reload point

enumerator kFTM_Chnl4Match

Channel 4 match included as a reload point

enumerator kFTM_Chnl5Match

Channel 5 match included as a reload point

enumerator kFTM_Chnl6Match

Channel 6 match included as a reload point

enumerator kFTM_Chnl7Match

Channel 7 match included as a reload point

enumerator kFTM_CntMax

Use in up-down count mode only, reload when counter reaches the maximum value

enumerator kFTM_CntMin

Use in up-down count mode only, reload when counter reaches the minimum value

enumerator kFTM_HalfCycMatch

Available on certain SoC's, half cycle match reload point

enum _ftm_interrupt_enable

List of FTM interrupts.

Note: Actual available interrupts are SoC-specific

Values:

enumerator kFTM_Chnl0InterruptEnable

Channel 0 interrupt

enumerator kFTM_Chnl1InterruptEnable

Channel 1 interrupt

enumerator kFTM_Chnl2InterruptEnable

Channel 2 interrupt

enumerator kFTM_Chnl3InterruptEnable

Channel 3 interrupt

enumerator kFTM_Chnl4InterruptEnable

Channel 4 interrupt

enumerator kFTM_Chnl5InterruptEnable

Channel 5 interrupt

enumerator kFTM_Chnl6InterruptEnable

Channel 6 interrupt

enumerator kFTM_Chnl7InterruptEnable

Channel 7 interrupt

enumerator kFTM_FaultInterruptEnable

Fault interrupt

enumerator kFTM_TimeOverflowInterruptEnable

Time overflow interrupt

enumerator kFTM_ReloadInterruptEnable

Reload interrupt; Available only on certain SoC's

enum _ftm_status_flags

List of FTM flags.

Note: Actual available flags are SoC-specific

Values:

enumerator kFTM_Chnl0Flag

Channel 0 Flag

enumerator kFTM_Chnl1Flag

Channel 1 Flag

enumerator kFTM_Chnl2Flag

Channel 2 Flag

enumerator kFTM_Chnl3Flag

Channel 3 Flag

enumerator kFTM_Chnl4Flag

Channel 4 Flag

enumerator kFTM_Chnl5Flag

Channel 5 Flag

enumerator kFTM_Chnl6Flag

Channel 6 Flag

enumerator kFTM_Chnl7Flag

Channel 7 Flag

enumerator kFTM_FaultFlag

Fault Flag

enumerator kFTM_TimeOverflowFlag

Time overflow Flag

enumerator kFTM_ChnlTriggerFlag

Channel trigger Flag

enumerator kFTM_ReloadFlag

Reload Flag; Available only on certain SoC's

enum _ftm_channel_index

List of FTM channel index used in logic OR.

Values:

enumerator kFTM_Chnl0_Mask

Channel 0 Mask

enumerator kFTM_Chnl1_Mask

Channel 1 Mask

enumerator kFTM_Chnl2_Mask

Channel 2 Mask

enumerator kFTM_Chnl3_Mask

Channel 3 Mask

enumerator kFTM_Chnl4_Mask

Channel 4 Mask

enumerator kFTM_Chnl5_Mask

Channel 5 Mask

enumerator kFTM_Chnl6_Mask

Channel 6 Mask

enumerator kFTM_Chnl7_Mask

Channel 7 Mask

List of FTM Quad Decoder flags.

Values:

enumerator kFTM_QuadDecoderCountingIncreaseFlag

Counting direction is increasing (FTM counter increment), or the direction is decreasing.

enumerator kFTM_QuadDecoderCountingOverflowOnTopFlag

Indicates if the TOF bit was set on the top or the bottom of counting.

typedef enum *_ftm_chnl* ftm_chnl_t

List of FTM channels.

Note: Actual number of available channels is SoC dependent

typedef enum *_ftm_fault_input* ftm_fault_input_t

List of FTM faults.

typedef enum *_ftm_pwm_mode* ftm_pwm_mode_t

FTM PWM operation modes.

typedef enum *_ftm_pwm_level_select* ftm_pwm_level_select_t

FTM PWM output pulse mode: high-true, low-true or no output.

Note: kFTM_NoPwmSignal: ELSnB:ELSnA = 0:0 kFTM_LowTrue: ELSnB:ELSnA = 0:1 EPWM: Channel n output is forced low at counter overflow, forced high at channel n match. CPWM: Channel n output is forced low at channel n match when counting down, and forced high at channel n match when counting up. Combined PWM: Channel n output is forced high at beginning of period and at channel n+1 match. It is forced low at the channel n match. kFTM_HighTrue: ELSnB:ELSnA = 1:0 EPWM: Channel n output is forced high at counter overflow, forced low at channel n match. CPWM: Channel n output is forced high at channel n match when counting down, and forced low at channel n match when counting up. Combined PWM: Channel n output is forced low at beginning of period and at channel n+1 match. It is forced high at the channel n match.

`typedef struct _ftm_chnl_pwm_signal_param` `ftm_chnl_pwm_signal_param_t`
Options to configure a FTM channel's PWM signal.

`typedef struct _ftm_chnl_pwm_config_param` `ftm_chnl_pwm_config_param_t`
Options to configure a FTM channel using precise setting.

`typedef struct _ftm_chnl_param` `ftm_chnl_param_t`
General options to configure a FTM channel using precise setting.

`typedef enum _ftm_output_compare_mode` `ftm_output_compare_mode_t`
FlexTimer output compare mode.

`typedef enum _ftm_input_capture_edge` `ftm_input_capture_edge_t`
FlexTimer input capture edge.

`typedef enum _ftm_dual_edge_capture_mode` `ftm_dual_edge_capture_mode_t`
FlexTimer dual edge capture modes.

`typedef struct _ftm_dual_edge_capture_param` `ftm_dual_edge_capture_param_t`
FlexTimer dual edge capture parameters.

`typedef enum _ftm_quad_decode_mode` `ftm_quad_decode_mode_t`
FlexTimer quadrature decode modes.

`typedef enum _ftm_phase_polarity` `ftm_phase_polarity_t`
FlexTimer quadrature phase polarities.

`typedef struct _ftm_phase_param` `ftm_phase_params_t`
FlexTimer quadrature decode phase parameters.

`typedef struct _ftm_fault_param` `ftm_fault_param_t`
Structure is used to hold the parameters to configure a FTM fault.

`typedef enum _ftm_deadtime_prescale` `ftm_deadtime_prescale_t`
FlexTimer pre-scaler factor for the dead time insertion.

`typedef enum _ftm_clock_source` `ftm_clock_source_t`
FlexTimer clock source selection.

`typedef enum _ftm_clock_prescale` `ftm_clock_prescale_t`
FlexTimer pre-scaler factor selection for the clock source.

`typedef enum _ftm_bdm_mode` `ftm_bdm_mode_t`
Options for the FlexTimer behaviour in BDM Mode.

`typedef enum _ftm_fault_mode` `ftm_fault_mode_t`
Options for the FTM fault control mode.

`typedef enum _ftm_external_trigger` `ftm_external_trigger_t`
FTM external trigger options.

Note: Actual available external trigger sources are SoC-specific

`typedef enum _ftm_pwm_sync_method` `ftm_pwm_sync_method_t`
FlexTimer PWM sync options to update registers with buffer.

`typedef enum _ftm_reload_point` `ftm_reload_point_t`
FTM options available as loading point for register reload.

Note: Actual available reload points are SoC-specific

```
typedef enum _ftm_interrupt_enable ftm_interrupt_enable_t
```

List of FTM interrupts.

Note: Actual available interrupts are SoC-specific

```
typedef enum _ftm_status_flags ftm_status_flags_t
```

List of FTM flags.

Note: Actual available flags are SoC-specific

```
typedef enum _ftm_channel_index ftm_channel_index_t
```

List of FTM channel index used in logic OR.

```
typedef struct _ftm_config ftm_config_t
```

FTM configuration structure.

This structure holds the configuration settings for the FTM peripheral. To initialize this structure to reasonable defaults, call the FTM_GetDefaultConfig() function and pass a pointer to the configuration structure instance.

The configuration structure can be made constant so as to reside in flash.

```
void FTM_SetupFaultInput(FTM_Type *base, ftm_fault_input_t faultNumber, const  
                        ftm_fault_param_t *faultParams)
```

Sets up the working of the FTM fault inputs protection.

FTM can have up to 4 fault inputs. This function sets up fault parameters, fault level, and input filter.

Parameters

- base – FTM peripheral base address
- faultNumber – FTM fault to configure.
- faultParams – Parameters passed in to set up the fault

```
static inline void FTM_SetGlobalTimeBaseOutputEnable(FTM_Type *base, bool enable)
```

Enables or disables the FTM global time base signal generation to other FTMs.

Parameters

- base – FTM peripheral base address
- enable – true to enable, false to disable

```
static inline void FTM_SetOutputMask(FTM_Type *base, ftm_chnl_t chnlNumber, bool mask)
```

Sets the FTM peripheral timer channel output mask.

Parameters

- base – FTM peripheral base address
- chnlNumber – Channel to be configured
- mask – true: masked, channel is forced to its inactive state; false: un-masked

```
static inline void FTM_SetPwmOutputEnable(FTM_Type *base, ftm_chnl_t chnlNumber, bool  
                                         value)
```

Allows users to enable an output on an FTM channel.

To enable the PWM channel output call this function with val=true. For input mode, call this function with val=false.

Parameters

- base – FTM peripheral base address
- chnlNumber – Channel to be configured
- value – true: enable output; false: output is disabled, used in input mode

static inline void FTM_SetSoftwareTrigger(FTM_Type *base, bool enable)

Enables or disables the FTM software trigger for PWM synchronization.

Parameters

- base – FTM peripheral base address
- enable – true: software trigger is selected, false: software trigger is not selected

static inline void FTM_SetWriteProtection(FTM_Type *base, bool enable)

Enables or disables the FTM write protection.

Parameters

- base – FTM peripheral base address
- enable – true: Write-protection is enabled, false: Write-protection is disabled

static inline void FTM_EnableDmaTransfer(FTM_Type *base, *ftm_chnl_t* chnlNumber, bool enable)

Enable DMA transfer or not.

Note: CHnIE bit needs to be set when calling this API. The channel DMA transfer request is generated and the channel interrupt is not generated if (CHnF = 1) when DMA and CHnIE bits are set.

Parameters

- base – FTM peripheral base address.
- chnlNumber – Channel to be configured
- enable – true to enable, false to disable

static inline void FTM_SetLdok(FTM_Type *base, bool value)

Enable the LDOK bit.

This function enables loading updated values.

Parameters

- base – FTM peripheral base address
- value – true: loading updated values is enabled; false: loading updated values is disabled.

static inline void FTM_SetHalfCycReloadMatchValue(FTM_Type *base, uint32_t ticks)

Sets the half cycle relade period in units of ticks.

This function can be called to set the half-cycle reload value when half-cycle matching is enabled as a reload point. Note: Need enable kFTM_HalfCycMatch as reload point, and when this API call after FTM_StartTimer(), the new HCR value will not be active until next reload point (need call FTM_SetLdok to set LDOK) or register synchronization.

Parameters

- base – FTM peripheral base address
- ticks – A timer period in units of ticks, which should be equal or greater than 1.

```
static inline void FTM_SetLoadFreq(FTM_Type *base, uint32_t loadfreq)
```

Set load frequency value.

Parameters

- base – FTM peripheral base address.
- loadfreq – PWM reload frequency, range: 0 ~ 31.

```
struct _ftm_chnl_pwm_signal_param
```

#include <fsl_ftm.h> Options to configure a FTM channel's PWM signal.

Public Members

ftm_chnl_t chnlNumber

The channel/channel pair number. In combined mode, this represents the channel pair number.

ftm_pwm_level_select_t level

PWM output active level select.

uint8_t dutyCyclePercent

PWM pulse width, value should be between 0 to 100 0 = inactive signal(0% duty cycle)... 100 = always active signal (100% duty cycle).

uint8_t firstEdgeDelayPercent

Used only in kFTM_AsymmetricalCombinedPwm mode to generate an asymmetrical PWM. Specifies the delay to the first edge in a PWM period. If unsure leave as 0; Should be specified as a percentage of the PWM period

bool enableComplementary

Used only in combined PWM mode. true: The combined channels output complementary signals; false: The combined channels output same signals;

bool enableDeadtime

Used only in combined PWM mode with enable complementary. true: The deadtime insertion in this pair of channels is enabled; false: The deadtime insertion in this pair of channels is disabled.

```
struct _ftm_chnl_pwm_config_param
```

#include <fsl_ftm.h> Options to configure a FTM channel using precise setting.

Public Members

ftm_chnl_t chnlNumber

The channel/channel pair number. In combined mode, this represents the channel pair number.

ftm_pwm_level_select_t level

PWM output active level select.

uint16_t dutyValue

PWM pulse width, the uint of this value is timer ticks.

uint16_t firstEdgeValue

Used only in kFTM_AsymmetricalCombinedPwm mode to generate an asymmetrical PWM. Specifies the delay to the first edge in a PWM period. If unsure leave as 0, uint of this value is timer ticks.

bool enableComplementary

Used only in combined PWM mode. true: The combined channels output complementary signals; false: The combined channels output same signals;

bool enableDeadtime

Used only in combined PWM mode with enable complementary. true: The deadtime insertion in this pair of channels is enabled; false: The deadtime insertion in this pair of channels is disabled.

struct _ftm_chnl_param

#include <fsl_ftm.h> General options to configure a FTM channel using precise setting.

Public Members

ftm_pwm_mode_t mode

PWM output mode.

ftm_pwm_level_select_t level

PWM output active level select.

uint16_t initialValue

FTM counter initial value.

uint16_t moduloValue

FTM counter modulo value.

uint16_t chnlValue

FTM channel n match value.

uint16_t combinedChnlValue

FTM combined channel n+1 match value, used only in (modified) combined PWM mode.

bool enableComplementary

Used only in combined PWM mode. true: The combined channels output complementary signals; false: The combined channels output same signals;

bool enableDeadtime

Used only in combined PWM mode with enable complementary. true: The deadtime insertion in this pair of channels is enabled; false: The deadtime insertion in this pair of channels is disabled.

struct _ftm_dual_edge_capture_param

#include <fsl_ftm.h> FlexTimer dual edge capture parameters.

Public Members

ftm_dual_edge_capture_mode_t mode

Dual Edge Capture mode

ftm_input_capture_edge_t currChanEdgeMode

Input capture edge select for channel n

ftm_input_capture_edge_t nextChanEdgeMode

Input capture edge select for channel n+1

struct _ftm_phase_param

#include <fsl_ftm.h> FlexTimer quadrature decode phase parameters.

Public Members

bool enablePhaseFilter

True: enable phase filter; false: disable filter

uint32_t phaseFilterVal

Filter value, used only if phase filter is enabled

ftm_phase_polarity_t phasePolarity

Phase polarity

struct *_ftm_fault_param*

#include <fsl_ftm.h> Structure is used to hold the parameters to configure a FTM fault.

Public Members

bool enableFaultInput

True: Fault input is enabled; false: Fault input is disabled

bool faultLevel

True: Fault polarity is active low; in other words, '0' indicates a fault; False: Fault polarity is active high

bool useFaultFilter

True: Use the filtered fault signal; False: Use the direct path from fault input

struct *_ftm_config*

#include <fsl_ftm.h> FTM configuration structure.

This structure holds the configuration settings for the FTM peripheral. To initialize this structure to reasonable defaults, call the *FTM_GetDefaultConfig()* function and pass a pointer to the configuration structure instance.

The configuration structure can be made constant so as to reside in flash.

Public Members

ftm_clock_prescale_t prescale

FTM clock prescale value

ftm_bdm_mode_t bdmMode

FTM behavior in BDM mode

uint32_t pwmSyncMode

Synchronization methods to use to update buffered registers; Multiple update modes can be used by providing an OR'ed list of options available in enumeration *ftm_pwm_sync_method_t*.

uint32_t reloadPoints

FTM reload points; When using this, the PWM synchronization is not required. Multiple reload points can be used by providing an OR'ed list of options available in enumeration *ftm_reload_point_t*.

ftm_fault_mode_t faultMode

FTM fault control mode

uint8_t faultFilterValue

Fault input filter value

ftm_deadtime_prescale_t deadTimePrescale

The dead time prescalar value

uint32_t deadTimeValue

The dead time value deadTimeValue's available range is 0-1023 when register has DT-VALEX, otherwise its available range is 0-63.

uint32_t extTriggers

External triggers to enable. Multiple trigger sources can be enabled by providing an OR'ed list of options available in enumeration *ftm_external_trigger_t*.

uint8_t chnlInitState

Defines the initialization value of the channels in OUTINT register

uint8_t chnlPolarity

Defines the output polarity of the channels in POL register

bool useGlobalTimeBase

True: Use of an external global time base is enabled; False: disabled

bool swTriggerResetCount

FTM counter synchronization activated by software trigger, active when (syncMethod & FTM_SYNC_SWSYNC_MASK) != 0U

bool hwTriggerResetCount

FTM counter synchronization activated by hardware trigger, active when (syncMethod & (FTM_SYNC_TRIG0_MASK | FTM_SYNC_TRIG1_MASK | FTM_SYNC_TRIG2_MASK)) != 0U

2.27 GPIO: General-Purpose Input/Output Driver

FSL_GPIO_DRIVER_VERSION

GPIO driver version.

enum _gpio_pin_direction

GPIO direction definition.

Values:

enumerator *kGPIO_DigitalInput*

Set current pin as digital input

enumerator *kGPIO_DigitalOutput*

Set current pin as digital output

enum _gpio_checker_attribute

GPIO checker attribute.

Values:

enumerator *kGPIO_UsernonsecureRWUsersecureRWPrivilegedsecureRW*

User nonsecure:Read+Write; User Secure:Read+Write; Privileged Secure:Read+Write

enumerator *kGPIO_UsernonsecureRUsersecureRWPrivilegedsecureRW*

User nonsecure:Read; User Secure:Read+Write; Privileged Secure:Read+Write

enumerator *kGPIO_UsernonsecureNUsersecureRWPrivilegedsecureRW*

User nonsecure:None; User Secure:Read+Write; Privileged Secure:Read+Write

enumerator kGPIO_UsernonsecureRUsersecureRPrivilegedsecureRW
User nonsecure:Read; User Secure:Read; Privileged Secure:Read+Write

enumerator kGPIO_UsernonsecureNUsersecureRPrivilegedsecureRW
User nonsecure:None; User Secure:Read; Privileged Secure:Read+Write

enumerator kGPIO_UsernonsecureNUsersecureNPrivilegedsecureRW
User nonsecure:None; User Secure:None; Privileged Secure:Read+Write

enumerator kGPIO_UsernonsecureNUsersecureNPrivilegedsecureR
User nonsecure:None; User Secure:None; Privileged Secure:Read

enumerator kGPIO_UsernonsecureNUsersecureNPrivilegedsecureN
User nonsecure:None; User Secure:None; Privileged Secure:None

enumerator kGPIO_IgnoreAttributeCheck
Ignores the attribute check

typedef enum *_gpio_pin_direction* gpio_pin_direction_t
GPIO direction definition.

typedef enum *_gpio_checker_attribute* gpio_checker_attribute_t
GPIO checker attribute.

typedef struct *_gpio_pin_config* gpio_pin_config_t
The GPIO pin configuration structure.

Each pin can only be configured as either an output pin or an input pin at a time. If configured as an input pin, leave the outputConfig unused. Note that in some use cases, the corresponding port property should be configured in advance with the PORT_SetPinConfig().

GPIO_FIT_REG(value)

struct *_gpio_pin_config*
#include <fsl_gpio.h> The GPIO pin configuration structure.

Each pin can only be configured as either an output pin or an input pin at a time. If configured as an input pin, leave the outputConfig unused. Note that in some use cases, the corresponding port property should be configured in advance with the PORT_SetPinConfig().

Public Members

gpio_pin_direction_t pinDirection
GPIO direction, input or output

uint8_t outputLogic
Set a default output logic, which has no use in input

2.28 GPIO Driver

void GPIO_PortInit(GPIO_Type *base)
Initializes the GPIO peripheral.
This function ungates the GPIO clock.

Parameters

- base – GPIO peripheral base pointer.

void GPIO_PortDenit(GPIO_Type *base)

Denitalizes the GPIO peripheral.

Parameters

- base – GPIO peripheral base pointer.

void GPIO_PinInit(GPIO_Type *base, uint32_t pin, const *gpio_pin_config_t* *config)

Initializes a GPIO pin used by the board.

To initialize the GPIO, define a pin configuration, as either input or output, in the user file. Then, call the GPIO_PinInit() function.

This is an example to define an input pin or an output pin configuration.

```
Define a digital input pin configuration,
gpio_pin_config_t config =
{
    kGPIO_DigitalInput,
    0,
}
Define a digital output pin configuration,
gpio_pin_config_t config =
{
    kGPIO_DigitalOutput,
    0,
}
```

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- pin – GPIO port pin number
- config – GPIO pin configuration pointer

static inline void GPIO_PinWrite(GPIO_Type *base, uint32_t pin, uint8_t output)

Sets the output level of the multiple GPIO pins to the logic 1 or 0.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- pin – GPIO pin number
- output – GPIO pin output logic level.
 - 0: corresponding pin output low-logic level.
 - 1: corresponding pin output high-logic level.

static inline void GPIO_PortSet(GPIO_Type *base, uint32_t mask)

Sets the output level of the multiple GPIO pins to the logic 1.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

static inline void GPIO_PortClear(GPIO_Type *base, uint32_t mask)

Sets the output level of the multiple GPIO pins to the logic 0.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro


```
static inline void GPIO_PortToggle(GPIO_Type *base, uint32_t mask)
```

Reverses the current output logic of the multiple GPIO pins.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

```
static inline uint32_t GPIO_PinRead(GPIO_Type *base, uint32_t pin)
```

Reads the current input value of the GPIO port.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- pin – GPIO pin number

Return values

GPIO – port input value

- 0: corresponding pin input low-logic level.
- 1: corresponding pin input high-logic level.

```
uint32_t GPIO_PortGetInterruptFlags(GPIO_Type *base)
```

Reads the GPIO port interrupt status flag.

If a pin is configured to generate the DMA request, the corresponding flag is cleared automatically at the completion of the requested DMA transfer. Otherwise, the flag remains set until a logic one is written to that flag. If configured for a level sensitive interrupt that remains asserted, the flag is set again immediately.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)

Return values

The – current GPIO port interrupt status flag, for example, 0x00010001 means the pin 0 and 17 have the interrupt.

```
void GPIO_PortClearInterruptFlags(GPIO_Type *base, uint32_t mask)
```

Clears multiple GPIO pin interrupt status flags.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- mask – GPIO pin number macro

```
void GPIO_CheckAttributeBytes(GPIO_Type *base, gpio_checker_attribute_t attribute)
```

brief The GPIO module supports a device-specific number of data ports, organized as 32-bit words/8-bit Bytes. Each 32-bit/8-bit data port includes a GACR register, which defines the byte-level attributes required for a successful access to the GPIO programming model. If the GPIO module's GACR register organized as 32-bit words, the attribute controls for the 4 data bytes in the GACR follow a standard little endian data convention.

Parameters

- base – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- attribute – GPIO checker attribute

2.29 Common Driver

FSL_COMMON_DRIVER_VERSION

common driver version.

DEBUG_CONSOLE_DEVICE_TYPE_NONE

No debug console.

DEBUG_CONSOLE_DEVICE_TYPE_UART

Debug console based on UART.

DEBUG_CONSOLE_DEVICE_TYPE_LPUART

Debug console based on LPUART.

DEBUG_CONSOLE_DEVICE_TYPE_LPSCI

Debug console based on LPSCI.

DEBUG_CONSOLE_DEVICE_TYPE_USBCDC

Debug console based on USB CDC.

DEBUG_CONSOLE_DEVICE_TYPE_FLEXCOMM

Debug console based on FLEXCOMM.

DEBUG_CONSOLE_DEVICE_TYPE_IUART

Debug console based on i.MX UART.

DEBUG_CONSOLE_DEVICE_TYPE_VUSART

Debug console based on LPC_VUSART.

DEBUG_CONSOLE_DEVICE_TYPE_MINI_USART

Debug console based on LPC_USART.

DEBUG_CONSOLE_DEVICE_TYPE_SWO

Debug console based on SWO.

DEBUG_CONSOLE_DEVICE_TYPE_QSCI

Debug console based on QSCI.

MIN(*a*, *b*)

Computes the minimum of *a* and *b*.

MAX(*a*, *b*)

Computes the maximum of *a* and *b*.

UINT16_MAX

Max value of uint16_t type.

UINT32_MAX

Max value of uint32_t type.

SDK_ATOMIC_LOCAL_ADD(*addr*, *val*)

Add value *val* from the variable at address *address*.

SDK_ATOMIC_LOCAL_SUB(*addr*, *val*)

Subtract value *val* to the variable at address *address*.

SDK_ATOMIC_LOCAL_SET(*addr*, *bits*)

Set the bits specified by *bits* to the variable at address *address*.

SDK_ATOMIC_LOCAL_CLEAR(*addr*, *bits*)

Clear the bits specified by *bits* to the variable at address *address*.

SDK_ATOMIC_LOCAL_TOGGLE(*addr*, *bits*)

Toggle the bits specified by *bits* to the variable at address *address*.

SDK_ATOMIC_LOCAL_CLEAR_AND_SET(addr, clearBits, setBits)

For the variable at address *address*, clear the bits specified by *clearBits* and set the bits specified by *setBits*.

SDK_ATOMIC_LOCAL_COMPARE_AND_SET(addr, expected, newValue)

For the variable at address *address*, check whether the value equal to *expected*. If value same as *expected* then update *newValue* to address and return **true** , else return **false** .

SDK_ATOMIC_LOCAL_TEST_AND_SET(addr, newValue)

For the variable at address *address*, set as *newValue* value and return old value.

USEC_TO_COUNT(us, clockFreqInHz)

Macro to convert a microsecond period to raw count value

COUNT_TO_USEC(count, clockFreqInHz)

Macro to convert a raw count value to microsecond

MSEC_TO_COUNT(ms, clockFreqInHz)

Macro to convert a millisecond period to raw count value

COUNT_TO_MSEC(count, clockFreqInHz)

Macro to convert a raw count value to millisecond

SDK_ISR_EXIT_BARRIER

SDK_SIZEALIGN(var, alignbytes)

Macro to define a variable with L1 d-cache line size alignment

Macro to define a variable with L2 cache line size alignment

Macro to change a value to a given size aligned value

AT_NONCACHEABLE_SECTION(var)

Define a variable *var*, and place it in non-cacheable section.

AT_NONCACHEABLE_SECTION_ALIGN(var, alignbytes)

Define a variable *var*, and place it in non-cacheable section, the start address of the variable is aligned to *alignbytes*.

AT_NONCACHEABLE_SECTION_INIT(var)

Define a variable *var* with initial value, and place it in non-cacheable section.

AT_NONCACHEABLE_SECTION_ALIGN_INIT(var, alignbytes)

Define a variable *var* with initial value, and place it in non-cacheable section, the start address of the variable is aligned to *alignbytes*.

enum _status_groups

Status group numbers.

Values:

enumerator kStatusGroup_Generic

Group number for generic status codes.

enumerator kStatusGroup_FLASH

Group number for FLASH status codes.

enumerator kStatusGroup_LPSPI

Group number for LPSPI status codes.

enumerator kStatusGroup_FLEXIO_SPI

Group number for FLEXIO SPI status codes.

enumerator kStatusGroup_DSPI
Group number for DSPI status codes.

enumerator kStatusGroup_FLEXIO_UART
Group number for FLEXIO UART status codes.

enumerator kStatusGroup_FLEXIO_I2C
Group number for FLEXIO I2C status codes.

enumerator kStatusGroup_LPI2C
Group number for LPI2C status codes.

enumerator kStatusGroup_UART
Group number for UART status codes.

enumerator kStatusGroup_I2C
Group number for UART status codes.

enumerator kStatusGroup_LPSCI
Group number for LPSCI status codes.

enumerator kStatusGroup_LPUART
Group number for LPUART status codes.

enumerator kStatusGroup_SPI
Group number for SPI status code.

enumerator kStatusGroup_XRDC
Group number for XRDC status code.

enumerator kStatusGroup_SEMA42
Group number for SEMA42 status code.

enumerator kStatusGroup_SDHC
Group number for SDHC status code

enumerator kStatusGroup_SDMMC
Group number for SDMMC status code

enumerator kStatusGroup_SAI
Group number for SAI status code

enumerator kStatusGroup_MCG
Group number for MCG status codes.

enumerator kStatusGroup_SCG
Group number for SCG status codes.

enumerator kStatusGroup_SDSPI
Group number for SDSPI status codes.

enumerator kStatusGroup_FLEXIO_I2S
Group number for FLEXIO I2S status codes

enumerator kStatusGroup_FLEXIO_MCULCD
Group number for FLEXIO LCD status codes

enumerator kStatusGroup_FLASHIAP
Group number for FLASHIAP status codes

enumerator kStatusGroup_FLEXCOMM_I2C
Group number for FLEXCOMM I2C status codes

enumerator kStatusGroup_I2S
Group number for I2S status codes

enumerator kStatusGroup_IUART
Group number for IUART status codes

enumerator kStatusGroup_CSI
Group number for CSI status codes

enumerator kStatusGroup_MIPI_DSI
Group number for MIPI DSI status codes

enumerator kStatusGroup_SDRAMC
Group number for SDRAMC status codes.

enumerator kStatusGroup_POWER
Group number for POWER status codes.

enumerator kStatusGroup_ENET
Group number for ENET status codes.

enumerator kStatusGroup_PHY
Group number for PHY status codes.

enumerator kStatusGroup_TRGMUX
Group number for TRGMUX status codes.

enumerator kStatusGroup_SMARTCARD
Group number for SMARTCARD status codes.

enumerator kStatusGroup_LMEM
Group number for LMEM status codes.

enumerator kStatusGroup_QSPI
Group number for QSPI status codes.

enumerator kStatusGroup_DMA
Group number for DMA status codes.

enumerator kStatusGroup_EDMA
Group number for EDMA status codes.

enumerator kStatusGroup_DMAMGR
Group number for DMAMGR status codes.

enumerator kStatusGroup_FLEXCAN
Group number for FlexCAN status codes.

enumerator kStatusGroup_LTC
Group number for LTC status codes.

enumerator kStatusGroup_FLEXIO_CAMERA
Group number for FLEXIO CAMERA status codes.

enumerator kStatusGroup_LPC_SPI
Group number for LPC_SPI status codes.

enumerator kStatusGroup_LPC_USART
Group number for LPC_USART status codes.

enumerator kStatusGroup_DMIC
Group number for DMIC status codes.

enumerator kStatusGroup_SDIF
Group number for SDIF status codes.

enumerator kStatusGroup_SPIFI
Group number for SPIFI status codes.

enumerator kStatusGroup_OTP
Group number for OTP status codes.

enumerator kStatusGroup_MCAN
Group number for MCAN status codes.

enumerator kStatusGroup_CAAM
Group number for CAAM status codes.

enumerator kStatusGroup_ECSPi
Group number for ECSPi status codes.

enumerator kStatusGroup_USDHC
Group number for USDHC status codes.

enumerator kStatusGroup_LPC_I2C
Group number for LPC_I2C status codes.

enumerator kStatusGroup_DCP
Group number for DCP status codes.

enumerator kStatusGroup_MSCAN
Group number for MSCAN status codes.

enumerator kStatusGroup_ESAI
Group number for ESAI status codes.

enumerator kStatusGroup_FLEXSPI
Group number for FLEXSPI status codes.

enumerator kStatusGroup_MMDC
Group number for MMDC status codes.

enumerator kStatusGroup_PDM
Group number for MIC status codes.

enumerator kStatusGroup_SDMA
Group number for SDMA status codes.

enumerator kStatusGroup_ICS
Group number for ICS status codes.

enumerator kStatusGroup_SPDIF
Group number for SPDIF status codes.

enumerator kStatusGroup_LPC_MINISPI
Group number for LPC_MINISPI status codes.

enumerator kStatusGroup_HASHCRYPT
Group number for Hashcrypt status codes

enumerator kStatusGroup_LPC_SPI_SSP
Group number for LPC_SPI_SSP status codes.

enumerator kStatusGroup_I3C
Group number for I3C status codes

enumerator `kStatusGroup_LPC_I2C_1`
Group number for LPC_I2C_1 status codes.

enumerator `kStatusGroup_NOTIFIER`
Group number for NOTIFIER status codes.

enumerator `kStatusGroup_DebugConsole`
Group number for debug console status codes.

enumerator `kStatusGroup_SEMC`
Group number for SEMC status codes.

enumerator `kStatusGroup_ApplicationRangeStart`
Starting number for application groups.

enumerator `kStatusGroup_IAP`
Group number for IAP status codes

enumerator `kStatusGroup_SFA`
Group number for SFA status codes

enumerator `kStatusGroup_SPC`
Group number for SPC status codes.

enumerator `kStatusGroup_PUF`
Group number for PUF status codes.

enumerator `kStatusGroup_TOUCH_PANEL`
Group number for touch panel status codes

enumerator `kStatusGroup_VBAT`
Group number for VBAT status codes

enumerator `kStatusGroup_XSPI`
Group number for XSPI status codes

enumerator `kStatusGroup_PNGDEC`
Group number for PNGDEC status codes

enumerator `kStatusGroup_JPEGDEC`
Group number for JPEGDEC status codes

enumerator `kStatusGroup_AUDMIX`
Group number for AUDMIX status codes

enumerator `kStatusGroup_HAL_GPIO`
Group number for HAL GPIO status codes.

enumerator `kStatusGroup_HAL_UART`
Group number for HAL UART status codes.

enumerator `kStatusGroup_HAL_TIMER`
Group number for HAL TIMER status codes.

enumerator `kStatusGroup_HAL_SPI`
Group number for HAL SPI status codes.

enumerator `kStatusGroup_HAL_I2C`
Group number for HAL I2C status codes.

enumerator `kStatusGroup_HAL_FLASH`
Group number for HAL FLASH status codes.

enumerator kStatusGroup_HAL_PWM
Group number for HAL PWM status codes.

enumerator kStatusGroup_HAL_RNG
Group number for HAL RNG status codes.

enumerator kStatusGroup_HAL_I2S
Group number for HAL I2S status codes.

enumerator kStatusGroup_HAL_ADC_SENSOR
Group number for HAL ADC SENSOR status codes.

enumerator kStatusGroup_TIMERMANAGER
Group number for TiMER MANAGER status codes.

enumerator kStatusGroup_SERIALMANAGER
Group number for SERIAL MANAGER status codes.

enumerator kStatusGroup_LED
Group number for LED status codes.

enumerator kStatusGroup_BUTTON
Group number for BUTTON status codes.

enumerator kStatusGroup_EXTERN_EEPROM
Group number for EXTERN EEPROM status codes.

enumerator kStatusGroup_SHELL
Group number for SHELL status codes.

enumerator kStatusGroup_MEM_MANAGER
Group number for MEM MANAGER status codes.

enumerator kStatusGroup_LIST
Group number for List status codes.

enumerator kStatusGroup_OSA
Group number for OSA status codes.

enumerator kStatusGroup_COMMON_TASK
Group number for Common task status codes.

enumerator kStatusGroup_MSG
Group number for messaging status codes.

enumerator kStatusGroup_SDK_OCOTP
Group number for OCOTP status codes.

enumerator kStatusGroup_SDK_FLEXSPINOR
Group number for FLEXSPINOR status codes.

enumerator kStatusGroup_CODEC
Group number for codec status codes.

enumerator kStatusGroup_ASRC
Group number for codec status ASRC.

enumerator kStatusGroup_OTFAD
Group number for codec status codes.

enumerator kStatusGroup_SDIOSLV
Group number for SDIOSLV status codes.

enumerator kStatusGroup_MECC
Group number for MECC status codes.

enumerator kStatusGroup_ENET_QOS
Group number for ENET_QOS status codes.

enumerator kStatusGroup_LOG
Group number for LOG status codes.

enumerator kStatusGroup_I3CBUS
Group number for I3CBUS status codes.

enumerator kStatusGroup_QSCI
Group number for QSCI status codes.

enumerator kStatusGroup_ELEMU
Group number for ELEMU status codes.

enumerator kStatusGroup_QUEUEDSPI
Group number for QSPI status codes.

enumerator kStatusGroup_POWER_MANAGER
Group number for POWER_MANAGER status codes.

enumerator kStatusGroup_IPED
Group number for IPED status codes.

enumerator kStatusGroup_ELS_PKC
Group number for ELS PKC status codes.

enumerator kStatusGroup_CSS_PKC
Group number for CSS PKC status codes.

enumerator kStatusGroup_HOSTIF
Group number for HOSTIF status codes.

enumerator kStatusGroup_CLIF
Group number for CLIF status codes.

enumerator kStatusGroup_BMA
Group number for BMA status codes.

enumerator kStatusGroup_NETC
Group number for NETC status codes.

enumerator kStatusGroup_ELE
Group number for ELE status codes.

enumerator kStatusGroup_GLIKEY
Group number for GLIKEY status codes.

enumerator kStatusGroup_AON_POWER
Group number for AON_POWER status codes.

enumerator kStatusGroup_AON_COMMON
Group number for AON_COMMON status codes.

enumerator kStatusGroup_ENDAT3
Group number for ENDAT3 status codes.

enumerator kStatusGroup_HIPERFACE
Group number for HIPERFACE status codes.

enumerator kStatusGroup_NPX

Group number for NPX status codes.

enumerator kStatusGroup_ELA_CSEC

Group number for ELA_CSEC status codes.

enumerator kStatusGroup_FLEXIO_T_FORMAT

Group number for T-format status codes.

enumerator kStatusGroup_FLEXIO_A_FORMAT

Group number for A-format status codes.

Generic status return codes.

Values:

enumerator kStatus_Success

Generic status for Success.

enumerator kStatus_Fail

Generic status for Fail.

enumerator kStatus_ReadOnly

Generic status for read only failure.

enumerator kStatus_OutOfRange

Generic status for out of range access.

enumerator kStatus_InvalidArgument

Generic status for invalid argument check.

enumerator kStatus_Timeout

Generic status for timeout.

enumerator kStatus_NoTransferInProgress

Generic status for no transfer in progress.

enumerator kStatus_Busy

Generic status for module is busy.

enumerator kStatus_NoData

Generic status for no data is found for the operation.

typedef int32_t status_t

Type used for all status and error return values.

void *SDK_Malloc(size_t size, size_t alignbytes)

Allocate memory with given alignment and aligned size.

This is provided to support the dynamically allocated memory used in cache-able region.

Parameters

- size – The length required to malloc.
- alignbytes – The alignment size.

Return values

The – allocated memory.

void SDK_Free(void *ptr)

Free memory.

Parameters

- ptr – The memory to be release.

void SDK_DelayAtLeastUs(uint32_t delayTime_us, uint32_t coreClock_Hz)

Delay at least for some time. Please note that, this API uses while loop for delay, different run-time environments make the time not precise, if precise delay count was needed, please implement a new delay function with hardware timer.

Parameters

- delayTime_us – Delay time in unit of microsecond.
- coreClock_Hz – Core clock frequency with Hz.

static inline *status_t* EnableIRQ(IRQn_Type interrupt)

Enable specific interrupt.

Enable LEVEL1 interrupt. For some devices, there might be multiple interrupt levels. For example, there are NVIC and intmux. Here the interrupts connected to NVIC are the LEVEL1 interrupts, because they are routed to the core directly. The interrupts connected to intmux are the LEVEL2 interrupts, they are routed to NVIC first then routed to core.

This function only enables the LEVEL1 interrupts. The number of LEVEL1 interrupts is indicated by the feature macro FSL_FEATURE_NUMBER_OF_LEVEL1_INT_VECTORS.

Parameters

- interrupt – The IRQ number.

Return values

- kStatus_Success – Interrupt enabled successfully
- kStatus_Fail – Failed to enable the interrupt

static inline *status_t* DisableIRQ(IRQn_Type interrupt)

Disable specific interrupt.

Disable LEVEL1 interrupt. For some devices, there might be multiple interrupt levels. For example, there are NVIC and intmux. Here the interrupts connected to NVIC are the LEVEL1 interrupts, because they are routed to the core directly. The interrupts connected to intmux are the LEVEL2 interrupts, they are routed to NVIC first then routed to core.

This function only disables the LEVEL1 interrupts. The number of LEVEL1 interrupts is indicated by the feature macro FSL_FEATURE_NUMBER_OF_LEVEL1_INT_VECTORS.

Parameters

- interrupt – The IRQ number.

Return values

- kStatus_Success – Interrupt disabled successfully
- kStatus_Fail – Failed to disable the interrupt

static inline *status_t* EnableIRQWithPriority(IRQn_Type interrupt, uint8_t priNum)

Enable the IRQ, and also set the interrupt priority.

Only handle LEVEL1 interrupt. For some devices, there might be multiple interrupt levels. For example, there are NVIC and intmux. Here the interrupts connected to NVIC are the LEVEL1 interrupts, because they are routed to the core directly. The interrupts connected to intmux are the LEVEL2 interrupts, they are routed to NVIC first then routed to core.

This function only handles the LEVEL1 interrupts. The number of LEVEL1 interrupts is indicated by the feature macro FSL_FEATURE_NUMBER_OF_LEVEL1_INT_VECTORS.

Parameters

- interrupt – The IRQ to Enable.

- priNum – Priority number set to interrupt controller register.

Return values

- kStatus__Success – Interrupt priority set successfully
- kStatus__Fail – Failed to set the interrupt priority.

static inline *status_t* IRQ_SetPriority(IRQn_Type interrupt, uint8_t priNum)

Set the IRQ priority.

Only handle LEVEL1 interrupt. For some devices, there might be multiple interrupt levels. For example, there are NVIC and intmux. Here the interrupts connected to NVIC are the LEVEL1 interrupts, because they are routed to the core directly. The interrupts connected to intmux are the LEVEL2 interrupts, they are routed to NVIC first then routed to core.

This function only handles the LEVEL1 interrupts. The number of LEVEL1 interrupts is indicated by the feature macro FSL_FEATURE_NUMBER_OF_LEVEL1_INT_VECTORS.

Parameters

- interrupt – The IRQ to set.
- priNum – Priority number set to interrupt controller register.

Return values

- kStatus__Success – Interrupt priority set successfully
- kStatus__Fail – Failed to set the interrupt priority.

static inline *status_t* IRQ_ClearPendingIRQ(IRQn_Type interrupt)

Clear the pending IRQ flag.

Only handle LEVEL1 interrupt. For some devices, there might be multiple interrupt levels. For example, there are NVIC and intmux. Here the interrupts connected to NVIC are the LEVEL1 interrupts, because they are routed to the core directly. The interrupts connected to intmux are the LEVEL2 interrupts, they are routed to NVIC first then routed to core.

This function only handles the LEVEL1 interrupts. The number of LEVEL1 interrupts is indicated by the feature macro FSL_FEATURE_NUMBER_OF_LEVEL1_INT_VECTORS.

Parameters

- interrupt – The flag which IRQ to clear.

Return values

- kStatus__Success – Interrupt priority set successfully
- kStatus__Fail – Failed to set the interrupt priority.

static inline uint32_t DisableGlobalIRQ(void)

Disable the global IRQ.

Disable the global interrupt and return the current primask register. User is required to provided the primask register for the EnableGlobalIRQ().

Returns

Current primask value.

static inline void EnableGlobalIRQ(uint32_t primask)

Enable the global IRQ.

Set the primask register with the provided primask value but not just enable the primask. The idea is for the convenience of integration of RTOS. some RTOS get its own management mechanism of primask. User is required to use the EnableGlobalIRQ() and DisableGlobalIRQ() in pair.

Parameters

- `primask` – value of primask register to be restored. The primask value is supposed to be provided by the `DisableGlobalIRQ()`.

`static inline bool __SDK_AtomicLocalCompareAndSet(uint32_t *addr, uint32_t expected, uint32_t newValue)`

`static inline uint32_t __SDK_AtomicTestAndSet(uint32_t *addr, uint32_t newValue)`

`FSL_DRIVER_TRANSFER_DOUBLE_WEAK_IRQ`

Macro to use the default weak IRQ handler in drivers.

`MAKE_STATUS(group, code)`

Construct a status code value from a group and code number.

`MAKE_VERSION(major, minor, bugfix)`

Construct the version number for drivers.

The driver version is a 32-bit number, for both 32-bit platforms(such as Cortex M) and 16-bit platforms(such as DSC).

Unused	Major Version		Minor Version		Bug Fix		
31	25	24	17	16	9	8	0

`ARRAY_SIZE(x)`

Computes the number of elements in an array.

`UINT64_H(X)`

Macro to get upper 32 bits of a 64-bit value

`UINT64_L(X)`

Macro to get lower 32 bits of a 64-bit value

`SUPPRESS_FALL_THROUGH_WARNING()`

For switch case code block, if case section ends without “break;” statement, there will be fallthrough warning with compiler flag `-Wextra` or `-Wimplicit-fallthrough=n` when using `armgcc`. To suppress this warning, “`SUPPRESS_FALL_THROUGH_WARNING()`,” need to be added at the end of each case section which misses “break;”statement.

`MSDK_REG_SECURE_ADDR(x)`

Convert the register address to the one used in secure mode.

`MSDK_REG_NONSECURE_ADDR(x)`

Convert the register address to the one used in non-secure mode.

`MSDK_INVALID_IRQ_HANDLER`

Invalid IRQ handler address.

2.30 Lin_lpuart_driver

`FSL_LIN_LPUART_DRIVER_VERSION`

LIN LPUART driver version.

`enum _lin_lpuart_stop_bit_count`

Values:

enumerator `kLPUART_OneStopBit`

One stop bit

enumerator `kLPUART_TwoStopBit`

Two stop bits

enum _lin_lpuart_flags

Values:

enumerator kLPUART_TxDataRegEmptyFlag

Transmit data register empty flag, sets when transmit buffer is empty

enumerator kLPUART_TransmissionCompleteFlag

Transmission complete flag, sets when transmission activity complete

enumerator kLPUART_RxDataRegFullFlag

Receive data register full flag, sets when the receive data buffer is full

enumerator kLPUART_IdleLineFlag

Idle line detect flag, sets when idle line detected

enumerator kLPUART_RxOverrunFlag

Receive Overrun, sets when new data is received before data is read from receive register

enumerator kLPUART_NoiseErrorFlag

Receive takes 3 samples of each received bit. If any of these samples differ, noise flag sets

enumerator kLPUART_FramingErrorFlag

Frame error flag, sets if logic 0 was detected where stop bit expected

enumerator kLPUART_ParityErrorFlag

If parity enabled, sets upon parity error detection

enumerator kLPUART_LinBreakFlag

LIN break detect interrupt flag, sets when LIN break char detected and LIN circuit enabled

enumerator kLPUART_RxActiveEdgeFlag

Receive pin active edge interrupt flag, sets when active edge detected

enumerator kLPUART_RxActiveFlag

Receiver Active Flag (RAF), sets at beginning of valid start bit

enumerator kLPUART_DataMatch1Flag

The next character to be read from LPUART_DATA matches MA1

enumerator kLPUART_DataMatch2Flag

The next character to be read from LPUART_DATA matches MA2

enumerator kLPUART_NoiseErrorInRxDataRegFlag

NOISY bit, sets if noise detected in current data word

enumerator kLPUART_ParityErrorInRxDataRegFlag

PARITY bit, sets if noise detected in current data word

enumerator kLPUART_TxFifoEmptyFlag

TXEMPT bit, sets if transmit buffer is empty

enumerator kLPUART_RxFifoEmptyFlag

RXEMPT bit, sets if receive buffer is empty

enumerator kLPUART_TxFifoOverflowFlag

TXOF bit, sets if transmit buffer overflow occurred

enumerator kLPUART_RxFifoUnderflowFlag

RXUF bit, sets if receive buffer underflow occurred

enum _lin_lpuart_interrupt_enable

Values:

enumerator kLPUART_LinBreakInterruptEnable

LIN break detect.

enumerator kLPUART_RxActiveEdgeInterruptEnable

Receive Active Edge.

enumerator kLPUART_TxDataRegEmptyInterruptEnable

Transmit data register empty.

enumerator kLPUART_TransmissionCompleteInterruptEnable

Transmission complete.

enumerator kLPUART_RxDataRegFullInterruptEnable

Receiver data register full.

enumerator kLPUART_IdleLineInterruptEnable

Idle line.

enumerator kLPUART_RxOverrunInterruptEnable

Receiver Overrun.

enumerator kLPUART_NoiseErrorInterruptEnable

Noise error flag.

enumerator kLPUART_FramingErrorInterruptEnable

Framing error flag.

enumerator kLPUART_ParityErrorInterruptEnable

Parity error flag.

enumerator kLPUART_TxFifoOverflowInterruptEnable

Transmit FIFO Overflow.

enumerator kLPUART_RxFifoUnderflowInterruptEnable

Receive FIFO Underflow.

enum _lin_lpuart_status

Values:

enumerator kStatus_LPUART_TxBusy

TX busy

enumerator kStatus_LPUART_RxBusy

RX busy

enumerator kStatus_LPUART_TxIdle

LPUART transmitter is idle.

enumerator kStatus_LPUART_RxIdle

LPUART receiver is idle.

enumerator kStatus_LPUART_TxWatermarkTooLarge

TX FIFO watermark too large

enumerator kStatus_LPUART_RxWatermarkTooLarge

RX FIFO watermark too large

enumerator kStatus_LPUART_FlagCannotClearManually

Some flag can't manually clear

```

enumerator kStatus_LPUART_Error
    Error happens on LPUART.
enumerator kStatus_LPUART_RxRingBufferOverrun
    LPUART RX software ring buffer overrun.
enumerator kStatus_LPUART_RxHardwareOverrun
    LPUART RX receiver overrun.
enumerator kStatus_LPUART_NoiseError
    LPUART noise error.
enumerator kStatus_LPUART_FramingError
    LPUART framing error.
enumerator kStatus_LPUART_ParityError
    LPUART parity error.
enum lin_lpuart_bit_count_per_char_t
    Values:
        enumerator LPUART_8_BITS_PER_CHAR
            8-bit data characters
        enumerator LPUART_9_BITS_PER_CHAR
            9-bit data characters
        enumerator LPUART_10_BITS_PER_CHAR
            10-bit data characters
typedef enum _lin_lpuart_stop_bit_count lin_lpuart_stop_bit_count_t
static inline bool LIN_LPUART_GetRxDataPolarity(const LPUART_Type *base)
static inline void LIN_LPUART_SetRxDataPolarity(LPUART_Type *base, bool polarity)
static inline void LIN_LPUART_WriteByte(LPUART_Type *base, uint8_t data)
static inline void LIN_LPUART_ReadByte(const LPUART_Type *base, uint8_t *readData)
status_t LIN_LPUART_CalculateBaudRate(LPUART_Type *base, uint32_t baudRate_Bps,
                                     uint32_t srcClock_Hz, uint32_t *osr, uint16_t *sbr)
    Calculates the best osr and sbr value for configured baudrate.

```

Parameters

- base – LPUART peripheral base address
- baudRate_Bps – user configuration structure of type #lin_user_config_t
- srcClock_Hz – pointer to the LIN_LPUART driver state structure
- osr – pointer to osr value
- sbr – pointer to sbr value

Returns

An error code or lin_status_t

```
void LIN_LPUART_SetBaudRate(LPUART_Type *base, uint32_t *osr, uint16_t *sbr)
```

Configure baudrate according to osr and sbr value.

Parameters

- base – LPUART peripheral base address
- osr – pointer to osr value

- sbr – pointer to sbr value

```
lin_status_t LIN_LPUART_Init(LPUART_Type *base, lin_user_config_t *linUserConfig,  
                             lin_state_t *linCurrentState, uint32_t linSourceClockFreq)
```

Initializes an LIN_LPUART instance for LIN Network.

The caller provides memory for the driver state structures during initialization. The user must select the LIN_LPUART clock source in the application to initialize the LIN_LPUART. This function initializes a LPUART instance for operation. This function will initialize the run-time state structure to keep track of the on-going transfers, initialize the module to user defined settings and default settings, set break field length to be 13 bit times minimum, enable the break detect interrupt, Rx complete interrupt, frame error detect interrupt, and enable the LPUART module transmitter and receiver

Parameters

- base – LPUART peripheral base address
- linUserConfig – user configuration structure of type #lin_user_config_t
- linCurrentState – pointer to the LIN_LPUART driver state structure

Returns

An error code or lin_status_t

```
lin_status_t LIN_LPUART_Deinit(LPUART_Type *base)
```

Shuts down the LIN_LPUART by disabling interrupts and transmitter/receiver.

Parameters

- base – LPUART peripheral base address

Returns

An error code or lin_status_t

```
lin_status_t LIN_LPUART_SendFrameDataBlocking(LPUART_Type *base, const uint8_t *txBuff,  
                                                uint8_t txSize, uint32_t timeoutMSec)
```

Sends Frame data out through the LIN_LPUART module using blocking method. This function will calculate the checksum byte and send it with the frame data. Blocking means that the function does not return until the transmission is complete.

Parameters

- base – LPUART peripheral base address
- txBuff – source buffer containing 8-bit data chars to send
- txSize – the number of bytes to send
- timeoutMSec – timeout value in milli seconds

Returns

An error code or lin_status_t

```
lin_status_t LIN_LPUART_SendFrameData(LPUART_Type *base, const uint8_t *txBuff, uint8_t  
                                       txSize)
```

Sends frame data out through the LIN_LPUART module using non-blocking method. This enables an a-sync method for transmitting data. Non-blocking means that the function returns immediately. The application has to get the transmit status to know when the transmit is complete. This function will calculate the checksum byte and send it with the frame data.

Parameters

- base – LPUART peripheral base address
- txBuff – source buffer containing 8-bit data chars to send

- txSize – the number of bytes to send

Returns

An error code or `lin_status_t`

`lin_status_t LIN_LPUART_GetTransmitStatus(LPUART_Type *base, uint8_t *bytesRemaining)`

Get status of an on-going non-blocking transmission. While sending frame data using non-blocking method, users can use this function to get status of that transmission. This function return `LIN_TX_BUSY` while sending, or `LIN_TIMEOUT` if timeout has occurred, or return `LIN_SUCCESS` when the transmission is complete. The `bytesRemaining` shows number of bytes that still needed to transmit.

Parameters

- base – LPUART peripheral base address
- bytesRemaining – Number of bytes still needed to transmit

Returns

`lin_status_t LIN_TX_BUSY`, `LIN_SUCCESS` or `LIN_TIMEOUT`

`lin_status_t LIN_LPUART_RecvFrmDataBlocking(LPUART_Type *base, uint8_t *rxBuff, uint8_t rxSize, uint32_t timeoutMSec)`

Receives frame data through the `LIN_LPUART` module using blocking method. This function will check the checksum byte. If the checksum is correct, it will receive the frame data. Blocking means that the function does not return until the reception is complete.

Parameters

- base – LPUART peripheral base address
- rxBuff – buffer containing 8-bit received data
- rxSize – the number of bytes to receive
- timeoutMSec – timeout value in milli seconds

Returns

An error code or `lin_status_t`

`lin_status_t LIN_LPUART_RecvFrmData(LPUART_Type *base, uint8_t *rxBuff, uint8_t rxSize)`

Receives frame data through the `LIN_LPUART` module using non-blocking method. This function will check the checksum byte. If the checksum is correct, it will receive it with the frame data. Non-blocking means that the function returns immediately. The application has to get the receive status to know when the reception is complete.

Parameters

- base – LPUART peripheral base address
- rxBuff – buffer containing 8-bit received data
- rxSize – the number of bytes to receive

Returns

An error code or `lin_status_t`

`lin_status_t LIN_LPUART_AbortTransferData(LPUART_Type *base)`

Aborts an on-going non-blocking transmission/reception. While performing a non-blocking transferring data, users can call this function to terminate immediately the transferring.

Parameters

- base – LPUART peripheral base address

Returns

An error code or `lin_status_t`

`lin_status_t LIN_LPUART_GetReceiveStatus(LPUART_Type *base, uint8_t *bytesRemaining)`

Get status of an on-going non-blocking reception While receiving frame data using non-blocking method, users can use this function to get status of that receiving. This function return the current event ID, LIN_RX_BUSY while receiving and return LIN_SUCCESS, or timeout (LIN_TIMEOUT) when the reception is complete. The bytesRemaining shows number of bytes that still needed to receive.

Parameters

- base – LPUART peripheral base address
- bytesRemaining – Number of bytes still needed to receive

Returns

`lin_status_t` LIN_RX_BUSY, LIN_TIMEOUT or LIN_SUCCESS

`lin_status_t LIN_LPUART_GoToSleepMode(LPUART_Type *base)`

This function puts current node to sleep mode This function changes current node state to LIN_NODE_STATE_SLEEP_MODE.

Parameters

- base – LPUART peripheral base address

Returns

An error code or `lin_status_t`

`lin_status_t LIN_LPUART_GotoIdleState(LPUART_Type *base)`

Puts current LIN node to Idle state This function changes current node state to LIN_NODE_STATE_IDLE.

Parameters

- base – LPUART peripheral base address

Returns

An error code or `lin_status_t`

`lin_status_t LIN_LPUART_SendWakeupSignal(LPUART_Type *base)`

Sends a wakeup signal through the LIN_LPUART interface.

Parameters

- base – LPUART peripheral base address

Returns

An error code or `lin_status_t`

`lin_status_t LIN_LPUART_MasterSendHeader(LPUART_Type *base, uint8_t id)`

Sends frame header out through the LIN_LPUART module using a non-blocking method. This function sends LIN Break field, sync field then the ID with correct parity.

Parameters

- base – LPUART peripheral base address
- id – Frame Identifier

Returns

An error code or `lin_status_t`

`lin_status_t LIN_LPUART_EnableIRQ(LPUART_Type *base)`

Enables LIN_LPUART hardware interrupts.

Parameters

- base – LPUART peripheral base address

Returns

An error code or `lin_status_t`

`lin_status_t` LIN_LPUART_DisableIRQ(LPUART_Type *base)

Disables LIN_LPUART hardware interrupts.

Parameters

- base – LPUART peripheral base address

Returns

An error code or `lin_status_t`

`lin_status_t` LIN_LPUART_AutoBaudCapture(uint32_t instance)

This function capture bits time to detect break char, calculate baudrate from sync bits and enable transceiver if autobaud successful. This function should only be used in Slave. The timer should be in mode input capture of both rising and falling edges. The timer input capture pin should be externally connected to RXD pin.

Parameters

- instance – LPUART instance

Returns

`lin_status_t`

`void` LIN_LPUART_IRQHandler(LPUART_Type *base)

LIN_LPUART RX TX interrupt handler.

Parameters

- base – LPUART peripheral base address

Returns

`void`

`LIN_LPUART_TRANSMISSION_COMPLETE_TIMEOUT`

Max loops to wait for LPUART transmission complete.

When de-initializing the LIN LPUART module, the program shall wait for the previous transmission to complete. This parameter defines how many loops to check completion before return error. If defined as 0, driver will wait forever until completion.

`AUTOBAUD_BAUDRATE_TOLERANCE`

`BIT_RATE_TOLERANCE_UNSYNC`

`BIT_DURATION_MAX_19200`

`BIT_DURATION_MIN_19200`

`BIT_DURATION_MAX_14400`

`BIT_DURATION_MIN_14400`

`BIT_DURATION_MAX_9600`

`BIT_DURATION_MIN_9600`

`BIT_DURATION_MAX_4800`

`BIT_DURATION_MIN_4800`

`BIT_DURATION_MAX_2400`

`BIT_DURATION_MIN_2400`

TWO_BIT_DURATION_MAX_19200
TWO_BIT_DURATION_MIN_19200
TWO_BIT_DURATION_MAX_14400
TWO_BIT_DURATION_MIN_14400
TWO_BIT_DURATION_MAX_9600
TWO_BIT_DURATION_MIN_9600
TWO_BIT_DURATION_MAX_4800
TWO_BIT_DURATION_MIN_4800
TWO_BIT_DURATION_MAX_2400
TWO_BIT_DURATION_MIN_2400
AUTOBAUD_BREAK_TIME_MIN

2.31 LPI2C: Low Power Inter-Integrated Circuit Driver

void LPI2C_DriverIRQHandler(uint32_t instance)

LPI2C driver IRQ handler common entry.

This function provides the common IRQ request entry for LPI2C.

Parameters

- instance – LPI2C instance.

FSL_LPI2C_DRIVER_VERSION

LPI2C driver version.

LPI2C status return codes.

Values:

enumerator kStatus_LPI2C_Busy

The master is already performing a transfer.

enumerator kStatus_LPI2C_Idle

The slave driver is idle.

enumerator kStatus_LPI2C_Nak

The slave device sent a NAK in response to a byte.

enumerator kStatus_LPI2C_FifoError

FIFO under run or overrun.

enumerator kStatus_LPI2C_BitError

Transferred bit was not seen on the bus.

enumerator kStatus_LPI2C_ArbitrationLost

Arbitration lost error.

enumerator kStatus_LPI2C_PinLowTimeout

SCL or SDA were held low longer than the timeout.

enumerator `kStatus_LPI2C_NoTransferInProgress`

Attempt to abort a transfer when one is not in progress.

enumerator `kStatus_LPI2C_DmaRequestFail`

DMA request failed.

enumerator `kStatus_LPI2C_Timeout`

Timeout polling status flags.

`IRQn_Type` `const kLpi2cIrqs[]`

Array to map LPI2C instance number to IRQ number, used internally for LPI2C master interrupt and EDMA transactional APIs.

`lpi2c_master_isr_t` `s_lpi2cMasterIsr`

Pointer to master IRQ handler for each instance, used internally for LPI2C master interrupt and EDMA transactional APIs.

`void *``s_lpi2cMasterHandle[]`

Pointers to master handles for each instance, used internally for LPI2C master interrupt and EDMA transactional APIs.

`uint32_t` `LPI2C_GetInstance(LPI2C_Type *base)`

Returns an instance number given a base address.

If an invalid base address is passed, debug builds will assert. Release builds will just return instance number 0.

Parameters

- `base` – The LPI2C peripheral base address.

Returns

LPI2C instance number starting from 0.

`I2C_RETRY_TIMES`

Retry times for waiting flag.

2.32 LPI2C Master Driver

`void` `LPI2C_MasterGetDefaultConfig(lpi2c_master_config_t *masterConfig)`

Provides a default configuration for the LPI2C master peripheral.

This function provides the following default configuration for the LPI2C master peripheral:

```
masterConfig->enableMaster      = true;
masterConfig->debugEnable       = false;
masterConfig->ignoreAck         = false;
masterConfig->pinConfig         = kLPI2C_2PinOpenDrain;
masterConfig->baudRate_Hz       = 100000U;
masterConfig->busIdleTimeout_ns = 0;
masterConfig->pinLowTimeout_ns  = 0;
masterConfig->sdaGlitchFilterWidth_ns = 0;
masterConfig->sclGlitchFilterWidth_ns = 0;
masterConfig->hostRequest.enable = false;
masterConfig->hostRequest.source  = kLPI2C_HostRequestExternalPin;
masterConfig->hostRequest.polarity = kLPI2C_HostRequestPinActiveHigh;
```

After calling this function, you can override any settings in order to customize the configuration, prior to initializing the master driver with `LPI2C_MasterInit()`.

Parameters

- `masterConfig` – **[out]** User provided configuration structure for default values. Refer to `lpi2c_master_config_t`.

`void LPI2C_MasterInit(LPI2C_Type *base, const lpi2c_master_config_t *masterConfig, uint32_t sourceClock_Hz)`

Initializes the LPI2C master peripheral.

This function enables the peripheral clock and initializes the LPI2C master peripheral as described by the user provided configuration. A software reset is performed prior to configuration.

Parameters

- `base` – The LPI2C peripheral base address.
- `masterConfig` – User provided peripheral configuration. Use `LPI2C_MasterGetDefaultConfig()` to get a set of defaults that you can override.
- `sourceClock_Hz` – Frequency in Hertz of the LPI2C functional clock. Used to calculate the baud rate divisors, filter widths, and timeout periods.

`void LPI2C_MasterDeinit(LPI2C_Type *base)`

Deinitializes the LPI2C master peripheral.

This function disables the LPI2C master peripheral and gates the clock. It also performs a software reset to restore the peripheral to reset conditions.

Parameters

- `base` – The LPI2C peripheral base address.

`void LPI2C_MasterConfigureDataMatch(LPI2C_Type *base, const lpi2c_data_match_config_t *matchConfig)`

Configures LPI2C master data match feature.

Parameters

- `base` – The LPI2C peripheral base address.
- `matchConfig` – Settings for the data match feature.

`status_t LPI2C_MasterCheckAndClearError(LPI2C_Type *base, uint32_t status)`

Convert provided flags to status code, and clear any errors if present.

Parameters

- `base` – The LPI2C peripheral base address.
- `status` – Current status flags value that will be checked.

Return values

- `kStatus_Success` –
- `kStatus_LPI2C_PinLowTimeout` –
- `kStatus_LPI2C_ArbitrationLost` –
- `kStatus_LPI2C_Nak` –
- `kStatus_LPI2C_FifoError` –

`status_t LPI2C_CheckForBusyBus(LPI2C_Type *base)`

Make sure the bus isn't already busy.

A busy bus is allowed if we are the one driving it.

Parameters

- `base` – The LPI2C peripheral base address.

Return values

- kStatus__Success –
- kStatus_LPI2C_Busy –

static inline void LPI2C_MasterReset(LPI2C_Type *base)

Performs a software reset.

Restores the LPI2C master peripheral to reset conditions.

Parameters

- base – The LPI2C peripheral base address.

static inline void LPI2C_MasterEnable(LPI2C_Type *base, bool enable)

Enables or disables the LPI2C module as master.

Parameters

- base – The LPI2C peripheral base address.
- enable – Pass true to enable or false to disable the specified LPI2C as master.

static inline uint32_t LPI2C_MasterGetStatusFlags(LPI2C_Type *base)

Gets the LPI2C master status flags.

A bit mask with the state of all LPI2C master status flags is returned. For each flag, the corresponding bit in the return value is set if the flag is asserted.

See also:

[_lpi2c_master_flags](#)

Parameters

- base – The LPI2C peripheral base address.

Returns

State of the status flags:

- 1: related status flag is set.
- 0: related status flag is not set.

static inline void LPI2C_MasterClearStatusFlags(LPI2C_Type *base, uint32_t statusMask)

Clears the LPI2C master status flag state.

The following status register flags can be cleared:

- kLPI2C_MasterEndOfPacketFlag
- kLPI2C_MasterStopDetectFlag
- kLPI2C_MasterNackDetectFlag
- kLPI2C_MasterArbitrationLostFlag
- kLPI2C_MasterFifoErrFlag
- kLPI2C_MasterPinLowTimeoutFlag
- kLPI2C_MasterDataMatchFlag

Attempts to clear other flags has no effect.

See also:

[_lpi2c_master_flags](#).

Parameters

- base – The LPI2C peripheral base address.
- statusMask – A bitmask of status flags that are to be cleared. The mask is composed of `_lpi2c_master_flags` enumerators OR'd together. You may pass the result of a previous call to `LPI2C_MasterGetStatusFlags()`.

`static inline void LPI2C_MasterEnableInterrupts(LPI2C_Type *base, uint32_t interruptMask)`

Enables the LPI2C master interrupt requests.

All flags except `kLPI2C_MasterBusyFlag` and `kLPI2C_MasterBusBusyFlag` can be enabled as interrupts.

Parameters

- base – The LPI2C peripheral base address.
- interruptMask – Bit mask of interrupts to enable. See `_lpi2c_master_flags` for the set of constants that should be OR'd together to form the bit mask.

`static inline void LPI2C_MasterDisableInterrupts(LPI2C_Type *base, uint32_t interruptMask)`

Disables the LPI2C master interrupt requests.

All flags except `kLPI2C_MasterBusyFlag` and `kLPI2C_MasterBusBusyFlag` can be enabled as interrupts.

Parameters

- base – The LPI2C peripheral base address.
- interruptMask – Bit mask of interrupts to disable. See `_lpi2c_master_flags` for the set of constants that should be OR'd together to form the bit mask.

`static inline uint32_t LPI2C_MasterGetEnabledInterrupts(LPI2C_Type *base)`

Returns the set of currently enabled LPI2C master interrupt requests.

Parameters

- base – The LPI2C peripheral base address.

Returns

A bitmask composed of `_lpi2c_master_flags` enumerators OR'd together to indicate the set of enabled interrupts.

`static inline void LPI2C_MasterEnableDMA(LPI2C_Type *base, bool enableTx, bool enableRx)`

Enables or disables LPI2C master DMA requests.

Parameters

- base – The LPI2C peripheral base address.
- enableTx – Enable flag for transmit DMA request. Pass true for enable, false for disable.
- enableRx – Enable flag for receive DMA request. Pass true for enable, false for disable.

`static inline uint32_t LPI2C_MasterGetTxFifoAddress(LPI2C_Type *base)`

Gets LPI2C master transmit data register address for DMA transfer.

Parameters

- base – The LPI2C peripheral base address.

Returns

The LPI2C Master Transmit Data Register address.

```
static inline uint32_t LPI2C_MasterGetRxFifoAddress(LPI2C_Type *base)
```

Gets LPI2C master receive data register address for DMA transfer.

Parameters

- `base` – The LPI2C peripheral base address.

Returns

The LPI2C Master Receive Data Register address.

```
static inline void LPI2C_MasterSetWatermarks(LPI2C_Type *base, size_t txWords, size_t rxWords)
```

Sets the watermarks for LPI2C master FIFOs.

Parameters

- `base` – The LPI2C peripheral base address.
- `txWords` – Transmit FIFO watermark value in words. The `kLPI2C_MasterTxReadyFlag` flag is set whenever the number of words in the transmit FIFO is equal or less than `txWords`. Writing a value equal or greater than the FIFO size is truncated.
- `rxWords` – Receive FIFO watermark value in words. The `kLPI2C_MasterRxReadyFlag` flag is set whenever the number of words in the receive FIFO is greater than `rxWords`. Writing a value equal or greater than the FIFO size is truncated.

```
static inline void LPI2C_MasterGetFifoCounts(LPI2C_Type *base, size_t *rxCount, size_t *txCount)
```

Gets the current number of words in the LPI2C master FIFOs.

Parameters

- `base` – The LPI2C peripheral base address.
- `txCount` – **[out]** Pointer through which the current number of words in the transmit FIFO is returned. Pass NULL if this value is not required.
- `rxCount` – **[out]** Pointer through which the current number of words in the receive FIFO is returned. Pass NULL if this value is not required.

```
void LPI2C_MasterSetBaudRate(LPI2C_Type *base, uint32_t sourceClock_Hz, uint32_t baudRate_Hz)
```

Sets the I2C bus frequency for master transactions.

The LPI2C master is automatically disabled and re-enabled as necessary to configure the baud rate. Do not call this function during a transfer, or the transfer is aborted.

Note: Please note that the second parameter is the clock frequency of LPI2C module, the third parameter means user configured bus baudrate, this implementation is different from other I2C drivers which use baudrate configuration as second parameter and source clock frequency as third parameter.

Parameters

- `base` – The LPI2C peripheral base address.
- `sourceClock_Hz` – LPI2C functional clock frequency in Hertz.
- `baudRate_Hz` – Requested bus frequency in Hertz.

static inline bool LPI2C_MasterGetBusIdleState(LPI2C_Type *base)

Returns whether the bus is idle.

Requires the master mode to be enabled.

Parameters

- base – The LPI2C peripheral base address.

Return values

- true – Bus is busy.
- false – Bus is idle.

status_t LPI2C_MasterStart(LPI2C_Type *base, uint8_t address, lpi2c_direction_t dir)

Sends a START signal and slave address on the I2C bus.

This function is used to initiate a new master mode transfer. First, the bus state is checked to ensure that another master is not occupying the bus. Then a START signal is transmitted, followed by the 7-bit address specified in the *address* parameter. Note that this function does not actually wait until the START and address are successfully sent on the bus before returning.

Parameters

- base – The LPI2C peripheral base address.
- address – 7-bit slave device address, in bits [6:0].
- dir – Master transfer direction, either kLPI2C_Read or kLPI2C_Write. This parameter is used to set the R/w bit (bit 0) in the transmitted slave address.

Return values

- kStatus_Success – START signal and address were successfully enqueued in the transmit FIFO.
- kStatus_LPI2C_Busy – Another master is currently utilizing the bus.

static inline status_t LPI2C_MasterRepeatedStart(LPI2C_Type *base, uint8_t address,
lpi2c_direction_t dir)

Sends a repeated START signal and slave address on the I2C bus.

This function is used to send a Repeated START signal when a transfer is already in progress. Like LPI2C_MasterStart(), it also sends the specified 7-bit address.

Note: This function exists primarily to maintain compatible APIs between LPI2C and I2C drivers, as well as to better document the intent of code that uses these APIs.

Parameters

- base – The LPI2C peripheral base address.
- address – 7-bit slave device address, in bits [6:0].
- dir – Master transfer direction, either kLPI2C_Read or kLPI2C_Write. This parameter is used to set the R/w bit (bit 0) in the transmitted slave address.

Return values

- kStatus_Success – Repeated START signal and address were successfully enqueued in the transmit FIFO.
- kStatus_LPI2C_Busy – Another master is currently utilizing the bus.

status_t LPI2C_MasterSend(LPI2C_Type *base, void *txBuff, size_t txSize)

Performs a polling send transfer on the I2C bus.

Sends up to *txSize* number of bytes to the previously addressed slave device. The slave may reply with a NAK to any byte in order to terminate the transfer early. If this happens, this function returns *kStatus_LPI2C_Nak*.

Parameters

- *base* – The LPI2C peripheral base address.
- *txBuff* – The pointer to the data to be transferred.
- *txSize* – The length in bytes of the data to be transferred.

Return values

- *kStatus_Success* – Data was sent successfully.
- *kStatus_LPI2C_Busy* – Another master is currently utilizing the bus.
- *kStatus_LPI2C_Nak* – The slave device sent a NAK in response to a byte.
- *kStatus_LPI2C_FifoError* – FIFO under run or over run.
- *kStatus_LPI2C_ArbitrationLost* – Arbitration lost error.
- *kStatus_LPI2C_PinLowTimeout* – SCL or SDA were held low longer than the timeout.

status_t LPI2C_MasterReceive(LPI2C_Type *base, void *rxBuff, size_t rxSize)

Performs a polling receive transfer on the I2C bus.

Parameters

- *base* – The LPI2C peripheral base address.
- *rxBuff* – The pointer to the data to be transferred.
- *rxSize* – The length in bytes of the data to be transferred.

Return values

- *kStatus_Success* – Data was received successfully.
- *kStatus_LPI2C_Busy* – Another master is currently utilizing the bus.
- *kStatus_LPI2C_Nak* – The slave device sent a NAK in response to a byte.
- *kStatus_LPI2C_FifoError* – FIFO under run or overrun.
- *kStatus_LPI2C_ArbitrationLost* – Arbitration lost error.
- *kStatus_LPI2C_PinLowTimeout* – SCL or SDA were held low longer than the timeout.

status_t LPI2C_MasterStop(LPI2C_Type *base)

Sends a STOP signal on the I2C bus.

This function does not return until the STOP signal is seen on the bus, or an error occurs.

Parameters

- *base* – The LPI2C peripheral base address.

Return values

- *kStatus_Success* – The STOP signal was successfully sent on the bus and the transaction terminated.
- *kStatus_LPI2C_Busy* – Another master is currently utilizing the bus.
- *kStatus_LPI2C_Nak* – The slave device sent a NAK in response to a byte.

- kStatus_LPI2C_FifoError – FIFO under run or overrun.
- kStatus_LPI2C_ArbitrationLost – Arbitration lost error.
- kStatus_LPI2C_PinLowTimeout – SCL or SDA were held low longer than the timeout.

status_t LPI2C_MasterTransferBlocking(LPI2C_Type *base, *lpi2c_master_transfer_t* *transfer)
Performs a master polling transfer on the I2C bus.

Note: The API does not return until the transfer succeeds or fails due to error happens during transfer.

Parameters

- base – The LPI2C peripheral base address.
- transfer – Pointer to the transfer structure.

Return values

- kStatus_Success – Data was received successfully.
- kStatus_LPI2C_Busy – Another master is currently utilizing the bus.
- kStatus_LPI2C_Nak – The slave device sent a NAK in response to a byte.
- kStatus_LPI2C_FifoError – FIFO under run or overrun.
- kStatus_LPI2C_ArbitrationLost – Arbitration lost error.
- kStatus_LPI2C_PinLowTimeout – SCL or SDA were held low longer than the timeout.

void LPI2C_MasterTransferCreateHandle(LPI2C_Type *base, *lpi2c_master_handle_t* *handle, *lpi2c_master_transfer_callback_t* callback, void *userData)

Creates a new handle for the LPI2C master non-blocking APIs.

The creation of a handle is for use with the non-blocking APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the LPI2C_MasterTransferAbort() API shall be called.

Note: The function also enables the NVIC IRQ for the input LPI2C. Need to notice that on some SoCs the LPI2C IRQ is connected to INTMUX, in this case user needs to enable the associated INTMUX IRQ in application.

Parameters

- base – The LPI2C peripheral base address.
- handle – **[out]** Pointer to the LPI2C master driver handle.
- callback – User provided pointer to the asynchronous callback function.
- userData – User provided pointer to the application callback data.

status_t LPI2C_MasterTransferNonBlocking(LPI2C_Type *base, *lpi2c_master_handle_t* *handle, *lpi2c_master_transfer_t* *transfer)

Performs a non-blocking transaction on the I2C bus.

Parameters

- base – The LPI2C peripheral base address.

- `handle` – Pointer to the LPI2C master driver handle.
- `transfer` – The pointer to the transfer descriptor.

Return values

- `kStatus__Success` – The transaction was started successfully.
- `kStatus__LPI2C__Busy` – Either another master is currently utilizing the bus, or a non-blocking transaction is already in progress.

`status_t` LPI2C_MasterTransferGetCount(LPI2C_Type *base, *lpi2c_master_handle_t* *handle, size_t *count)

Returns number of bytes transferred so far.

Parameters

- `base` – The LPI2C peripheral base address.
- `handle` – Pointer to the LPI2C master driver handle.
- `count` – **[out]** Number of bytes transferred so far by the non-blocking transaction.

Return values

- `kStatus__Success` –
- `kStatus__NoTransferInProgress` – There is not a non-blocking transaction currently in progress.

`void` LPI2C_MasterTransferAbort(LPI2C_Type *base, *lpi2c_master_handle_t* *handle)

Terminates a non-blocking LPI2C master transmission early.

Note: It is not safe to call this function from an IRQ handler that has a higher priority than the LPI2C peripheral's IRQ priority.

Parameters

- `base` – The LPI2C peripheral base address.
- `handle` – Pointer to the LPI2C master driver handle.

`void` LPI2C_MasterTransferHandleIRQ(LPI2C_Type *base, void *lpi2cMasterHandle)

Reusable routine to handle master interrupts.

Note: This function does not need to be called unless you are reimplementing the non-blocking API's interrupt handler routines to add special functionality.

Parameters

- `base` – The LPI2C peripheral base address.
- `lpi2cMasterHandle` – Pointer to the LPI2C master driver handle.

`enum` `_lpi2c_master_flags`

LPI2C master peripheral flags.

The following status register flags can be cleared:

- `kLPI2C_MasterEndOfPacketFlag`
- `kLPI2C_MasterStopDetectFlag`
- `kLPI2C_MasterNackDetectFlag`

- kLPI2C_MasterArbitrationLostFlag
- kLPI2C_MasterFifoErrFlag
- kLPI2C_MasterPinLowTimeoutFlag
- kLPI2C_MasterDataMatchFlag

All flags except kLPI2C_MasterBusyFlag and kLPI2C_MasterBusBusyFlag can be enabled as interrupts.

Note: These enums are meant to be OR'd together to form a bit mask.

Values:

enumerator kLPI2C_MasterTxReadyFlag

Transmit data flag

enumerator kLPI2C_MasterRxReadyFlag

Receive data flag

enumerator kLPI2C_MasterEndOfPacketFlag

End Packet flag

enumerator kLPI2C_MasterStopDetectFlag

Stop detect flag

enumerator kLPI2C_MasterNackDetectFlag

NACK detect flag

enumerator kLPI2C_MasterArbitrationLostFlag

Arbitration lost flag

enumerator kLPI2C_MasterFifoErrFlag

FIFO error flag

enumerator kLPI2C_MasterPinLowTimeoutFlag

Pin low timeout flag

enumerator kLPI2C_MasterDataMatchFlag

Data match flag

enumerator kLPI2C_MasterBusyFlag

Master busy flag

enumerator kLPI2C_MasterBusBusyFlag

Bus busy flag

enumerator kLPI2C_MasterClearFlags

All flags which are cleared by the driver upon starting a transfer.

enumerator kLPI2C_MasterIrqFlags

IRQ sources enabled by the non-blocking transactional API.

enumerator kLPI2C_MasterErrorFlags

Errors to check for.

enum _lpi2c_direction

Direction of master and slave transfers.

Values:

enumerator kLPI2C_Write

Master transmit.

enumerator kLPI2C_Read

Master receive.

enum _lpi2c_master_pin_config

LPI2C pin configuration.

Values:

enumerator kLPI2C_2PinOpenDrain

LPI2C Configured for 2-pin open drain mode

enumerator kLPI2C_2PinOutputOnly

LPI2C Configured for 2-pin output only mode (ultra-fast mode)

enumerator kLPI2C_2PinPushPull

LPI2C Configured for 2-pin push-pull mode

enumerator kLPI2C_4PinPushPull

LPI2C Configured for 4-pin push-pull mode

enumerator kLPI2C_2PinOpenDrainWithSeparateSlave

LPI2C Configured for 2-pin open drain mode with separate LPI2C slave

enumerator kLPI2C_2PinOutputOnlyWithSeparateSlave

LPI2C Configured for 2-pin output only mode(ultra-fast mode) with separate LPI2C slave

enumerator kLPI2C_2PinPushPullWithSeparateSlave

LPI2C Configured for 2-pin push-pull mode with separate LPI2C slave

enumerator kLPI2C_4PinPushPullWithInvertedOutput

LPI2C Configured for 4-pin push-pull mode(inverted outputs)

enum _lpi2c_host_request_source

LPI2C master host request selection.

Values:

enumerator kLPI2C_HostRequestExternalPin

Select the LPI2C_HREQ pin as the host request input

enumerator kLPI2C_HostRequestInputTrigger

Select the input trigger as the host request input

enum _lpi2c_host_request_polarity

LPI2C master host request pin polarity configuration.

Values:

enumerator kLPI2C_HostRequestPinActiveLow

Configure the LPI2C_HREQ pin active low

enumerator kLPI2C_HostRequestPinActiveHigh

Configure the LPI2C_HREQ pin active high

enum _lpi2c_data_match_config_mode

LPI2C master data match configuration modes.

Values:

enumerator kLPI2C_MatchDisabled

LPI2C Match Disabled

enumerator kLPI2C_1stWordEqualsM0OrM1

LPI2C Match Enabled and 1st data word equals MATCH0 OR MATCH1

enumerator kLPI2C_AnyWordEqualsM0OrM1

LPI2C Match Enabled and any data word equals MATCH0 OR MATCH1

enumerator kLPI2C_1stWordEqualsM0And2ndWordEqualsM1

LPI2C Match Enabled and 1st data word equals MATCH0, 2nd data equals MATCH1

enumerator kLPI2C_AnyWordEqualsM0AndNextWordEqualsM1

LPI2C Match Enabled and any data word equals MATCH0, next data equals MATCH1

enumerator kLPI2C_1stWordAndM1EqualsM0AndM1

LPI2C Match Enabled and 1st data word and MATCH0 equals MATCH0 and MATCH1

enumerator kLPI2C_AnyWordAndM1EqualsM0AndM1

LPI2C Match Enabled and any data word and MATCH0 equals MATCH0 and MATCH1

enum _lpi2c_master_transfer_flags

Transfer option flags.

Note: These enumerations are intended to be OR'd together to form a bit mask of options for the `_lpi2c_master_transfer::flags` field.

Values:

enumerator kLPI2C_TransferDefaultFlag

Transfer starts with a start signal, stops with a stop signal.

enumerator kLPI2C_TransferNoStartFlag

Don't send a start condition, address, and sub address

enumerator kLPI2C_TransferRepeatedStartFlag

Send a repeated start condition

enumerator kLPI2C_TransferNoStopFlag

Don't send a stop condition.

typedef enum _lpi2c_direction lpi2c_direction_t

Direction of master and slave transfers.

typedef enum _lpi2c_master_pin_config lpi2c_master_pin_config_t

LPI2C pin configuration.

typedef enum _lpi2c_host_request_source lpi2c_host_request_source_t

LPI2C master host request selection.

typedef enum _lpi2c_host_request_polarity lpi2c_host_request_polarity_t

LPI2C master host request pin polarity configuration.

typedef struct _lpi2c_master_config lpi2c_master_config_t

Structure with settings to initialize the LPI2C master module.

This structure holds configuration settings for the LPI2C peripheral. To initialize this structure to reasonable defaults, call the `LPI2C_MasterGetDefaultConfig()` function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

typedef enum _lpi2c_data_match_config_mode lpi2c_data_match_config_mode_t

LPI2C master data match configuration modes.

```
typedef struct _lpi2c_match_config lpi2c_data_match_config_t
```

LPI2C master data match configuration structure.

```
typedef struct _lpi2c_master_transfer lpi2c_master_transfer_t
```

LPI2C master descriptor of the transfer.

```
typedef struct _lpi2c_master_handle lpi2c_master_handle_t
```

LPI2C master handle of the transfer.

```
typedef void (*lpi2c_master_transfer_callback_t)(LPI2C_Type *base, lpi2c_master_handle_t
*handle, status_t completionStatus, void *userData)
```

Master completion callback function pointer type.

This callback is used only for the non-blocking master transfer API. Specify the callback you wish to use in the call to LPI2C_MasterTransferCreateHandle().

Param base

The LPI2C peripheral base address.

Param handle

Pointer to the LPI2C master driver handle.

Param completionStatus

Either kStatus_Success or an error code describing how the transfer completed.

Param userData

Arbitrary pointer-sized value passed from the application.

```
typedef void (*lpi2c_master_isr_t)(LPI2C_Type *base, void *handle)
```

Typedef for master interrupt handler, used internally for LPI2C master interrupt and EDMA transactional APIs.

```
struct _lpi2c_master_config
```

#include <fsl_lpi2c.h> Structure with settings to initialize the LPI2C master module.

This structure holds configuration settings for the LPI2C peripheral. To initialize this structure to reasonable defaults, call the LPI2C_MasterGetDefaultConfig() function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

Public Members

```
bool enableMaster
```

Whether to enable master mode.

```
bool enableDoze
```

Whether master is enabled in doze mode.

```
bool debugEnable
```

Enable transfers to continue when halted in debug mode.

```
bool ignoreAck
```

Whether to ignore ACK/NACK.

```
lpi2c_master_pin_config_t pinConfig
```

The pin configuration option.

```
uint32_t baudRate_Hz
```

Desired baud rate in Hertz.

uint32_t busIdleTimeout_ns

Bus idle timeout in nanoseconds. Set to 0 to disable.

uint32_t pinLowTimeout_ns

Pin low timeout in nanoseconds. Set to 0 to disable.

uint8_t sdaGlitchFilterWidth_ns

Width in nanoseconds of glitch filter on SDA pin. Set to 0 to disable.

uint8_t sclGlitchFilterWidth_ns

Width in nanoseconds of glitch filter on SCL pin. Set to 0 to disable.

struct *_lpi2c_master_config* hostRequest

Host request options.

struct *_lpi2c_match_config*

#include <fsl_lpi2c.h> LPI2C master data match configuration structure.

Public Members

lpi2c_data_match_config_mode_t matchMode

Data match configuration setting.

bool rxDataMatchOnly

When set to true, received data is ignored until a successful match.

uint32_t match0

Match value 0.

uint32_t match1

Match value 1.

struct *_lpi2c_master_transfer*

#include <fsl_lpi2c.h> Non-blocking transfer descriptor structure.

This structure is used to pass transaction parameters to the LPI2C_MasterTransferNonBlocking() API.

Public Members

uint32_t flags

Bit mask of options for the transfer. See enumeration *_lpi2c_master_transfer_flags* for available options. Set to 0 or *kLPI2C_TransferDefaultFlag* for normal transfers.

uint16_t slaveAddress

The 7-bit slave address.

lpi2c_direction_t direction

Either *kLPI2C_Read* or *kLPI2C_Write*.

uint32_t subaddress

Sub address. Transferred MSB first.

size_t subaddressSize

Length of sub address to send in bytes. Maximum size is 4 bytes.

void *data

Pointer to data to transfer.

size_t dataSize

Number of bytes to transfer.

struct _lpi2c_master_handle

#include <fsl_lpi2c.h> Driver handle for master non-blocking APIs.

Note: The contents of this structure are private and subject to change.

Public Members

uint8_t state

Transfer state machine current state.

uint16_t remainingBytes

Remaining byte count in current state.

uint8_t *buf

Buffer pointer for current state.

uint16_t commandBuffer[6]

LPI2C command sequence. When all 6 command words are used: Start&addr&write[1 word] + subaddr[4 words] + restart&addr&read[1 word]

lpi2c_master_transfer_t transfer

Copy of the current transfer info.

lpi2c_master_transfer_callback_t completionCallback

Callback function pointer.

void *userData

Application data passed to callback.

struct hostRequest

Public Members

bool enable

Enable host request.

lpi2c_host_request_source_t source

Host request source.

lpi2c_host_request_polarity_t polarity

Host request pin polarity.

2.33 LPI2C Master DMA Driver

```
void LPI2C_MasterCreateEDMAHandle(LPI2C_Type *base, lpi2c_master_edma_handle_t *handle,
                                   edma_handle_t *rxDmaHandle, edma_handle_t
                                   *txDmaHandle, lpi2c_master_edma_transfer_callback_t
                                   callback, void *userData)
```

Create a new handle for the LPI2C master DMA APIs.

The creation of a handle is for use with the DMA APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the LPI2C_MasterTransferAbortEDMA() API shall be called.

For devices where the LPI2C send and receive DMA requests are OR'd together, the *txDmaHandle* parameter is ignored and may be set to NULL.

Parameters

- *base* – The LPI2C peripheral base address.
- *handle* – **[out]** Pointer to the LPI2C master driver handle.
- *rxDmaHandle* – Handle for the eDMA receive channel. Created by the user prior to calling this function.
- *txDmaHandle* – Handle for the eDMA transmit channel. Created by the user prior to calling this function.
- *callback* – User provided pointer to the asynchronous callback function.
- *userData* – User provided pointer to the application callback data.

status_t LPI2C_MasterTransferEDMA(LPI2C_Type **base*, *lpi2c_master_edma_handle_t* **handle*, *lpi2c_master_transfer_t* **transfer*)

Performs a non-blocking DMA-based transaction on the I2C bus.

The callback specified when the *handle* was created is invoked when the transaction has completed.

Parameters

- *base* – The LPI2C peripheral base address.
- *handle* – Pointer to the LPI2C master driver handle.
- *transfer* – The pointer to the transfer descriptor.

Return values

- *kStatus_Success* – The transaction was started successfully.
- *kStatus_LPI2C_Busy* – Either another master is currently utilizing the bus, or another DMA transaction is already in progress.

status_t LPI2C_MasterTransferGetCountEDMA(LPI2C_Type **base*, *lpi2c_master_edma_handle_t* **handle*, *size_t* **count*)

Returns number of bytes transferred so far.

Parameters

- *base* – The LPI2C peripheral base address.
- *handle* – Pointer to the LPI2C master driver handle.
- *count* – **[out]** Number of bytes transferred so far by the non-blocking transaction.

Return values

- *kStatus_Success* –
- *kStatus_NoTransferInProgress* – There is not a DMA transaction currently in progress.

status_t LPI2C_MasterTransferAbortEDMA(LPI2C_Type **base*, *lpi2c_master_edma_handle_t* **handle*)

Terminates a non-blocking LPI2C master transmission early.

Note: It is not safe to call this function from an IRQ handler that has a higher priority than the eDMA peripheral's IRQ priority.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to the LPI2C master driver handle.

Return values

- kStatus_Success – A transaction was successfully aborted.
- kStatus_LPI2C_Idle – There is not a DMA transaction currently in progress.

```
typedef struct _lpi2c_master_edma_handle lpi2c_master_edma_handle_t
```

LPI2C master EDMA handle of the transfer.

```
typedef void (*lpi2c_master_edma_transfer_callback_t)(LPI2C_Type *base,  
lpi2c_master_edma_handle_t *handle, status_t completionStatus, void *userData)
```

Master DMA completion callback function pointer type.

This callback is used only for the non-blocking master transfer API. Specify the callback you wish to use in the call to LPI2C_MasterCreateEDMAHandle().

Param base

The LPI2C peripheral base address.

Param handle

Handle associated with the completed transfer.

Param completionStatus

Either kStatus_Success or an error code describing how the transfer completed.

Param userData

Arbitrary pointer-sized value passed from the application.

```
struct _lpi2c_master_edma_handle
```

```
#include <fsl_lpi2c_edma.h> Driver handle for master DMA APIs.
```

Note: The contents of this structure are private and subject to change.

Public Members

LPI2C_Type *base

LPI2C base pointer.

bool isBusy

Transfer state machine current state.

uint8_t nbytes

eDMA minor byte transfer count initially configured.

uint16_t commandBuffer[20]

LPI2C command sequence. When all 10 command words are used:
Start&addr&write[1 word] + subaddr[4 words] + restart&addr&read[1 word] +
receive&Size[4 words]

lpi2c_master_transfer_t transfer

Copy of the current transfer info.

lpi2c_master_edma_transfer_callback_t completionCallback

Callback function pointer.

`void *userData`

Application data passed to callback.

`edma_handle_t *rx`

Handle for receive DMA channel.

`edma_handle_t *tx`

Handle for transmit DMA channel.

`edma_tcd_t tcds[3]`

Software TCD. Three are allocated to provide enough room to align to 32-bytes.

2.34 LPI2C Slave Driver

`void LPI2C_SlaveGetDefaultConfig(lpi2c_slave_config_t *slaveConfig)`

Provides a default configuration for the LPI2C slave peripheral.

This function provides the following default configuration for the LPI2C slave peripheral:

```
slaveConfig->enableSlave      = true;
slaveConfig->address0         = 0U;
slaveConfig->address1         = 0U;
slaveConfig->addressMatchMode = kLPI2C_MatchAddress0;
slaveConfig->filterDozeEnable = true;
slaveConfig->filterEnable     = true;
slaveConfig->enableGeneralCall = false;
slaveConfig->sclStall.enableAck = false;
slaveConfig->sclStall.enableTx  = true;
slaveConfig->sclStall.enableRx  = true;
slaveConfig->sclStall.enableAddress = true;
slaveConfig->ignoreAck         = false;
slaveConfig->enableReceivedAddressRead = false;
slaveConfig->sdaGlitchFilterWidth_ns = 0;
slaveConfig->sclGlitchFilterWidth_ns = 0;
slaveConfig->dataValidDelay_ns   = 0;
slaveConfig->clockHoldTime_ns    = 0;
```

After calling this function, override any settings to customize the configuration, prior to initializing the master driver with `LPI2C_SlaveInit()`. Be sure to override at least the *address0* member of the configuration structure with the desired slave address.

Parameters

- *slaveConfig* – **[out]** User provided configuration structure that is set to default values. Refer to `lpi2c_slave_config_t`.

`void LPI2C_SlaveInit(LPI2C_Type *base, const lpi2c_slave_config_t *slaveConfig, uint32_t sourceClock_Hz)`

Initializes the LPI2C slave peripheral.

This function enables the peripheral clock and initializes the LPI2C slave peripheral as described by the user provided configuration.

Parameters

- *base* – The LPI2C peripheral base address.
- *slaveConfig* – User provided peripheral configuration. Use `LPI2C_SlaveGetDefaultConfig()` to get a set of defaults that you can override.

- `sourceClock_Hz` – Frequency in Hertz of the LPI2C functional clock. Used to calculate the filter widths, data valid delay, and clock hold time.

`void LPI2C_SlaveDeinit(LPI2C_Type *base)`

Deinitializes the LPI2C slave peripheral.

This function disables the LPI2C slave peripheral and gates the clock. It also performs a software reset to restore the peripheral to reset conditions.

Parameters

- `base` – The LPI2C peripheral base address.

`static inline void LPI2C_SlaveReset(LPI2C_Type *base)`

Performs a software reset of the LPI2C slave peripheral.

Parameters

- `base` – The LPI2C peripheral base address.

`static inline void LPI2C_SlaveEnable(LPI2C_Type *base, bool enable)`

Enables or disables the LPI2C module as slave.

Parameters

- `base` – The LPI2C peripheral base address.
- `enable` – Pass true to enable or false to disable the specified LPI2C as slave.

`static inline uint32_t LPI2C_SlaveGetStatusFlags(LPI2C_Type *base)`

Gets the LPI2C slave status flags.

A bit mask with the state of all LPI2C slave status flags is returned. For each flag, the corresponding bit in the return value is set if the flag is asserted.

See also:

`_lpi2c_slave_flags`

Parameters

- `base` – The LPI2C peripheral base address.

Returns

State of the status flags:

- 1: related status flag is set.
- 0: related status flag is not set.

`static inline void LPI2C_SlaveClearStatusFlags(LPI2C_Type *base, uint32_t statusMask)`

Clears the LPI2C status flag state.

The following status register flags can be cleared:

- `kLPI2C_SlaveRepeatedStartDetectFlag`
- `kLPI2C_SlaveStopDetectFlag`
- `kLPI2C_SlaveBitErrFlag`
- `kLPI2C_SlaveFifoErrFlag`

Attempts to clear other flags has no effect.

See also:

`_lpi2c_slave_flags`.

Parameters

- `base` – The LPI2C peripheral base address.
- `statusMask` – A bitmask of status flags that are to be cleared. The mask is composed of `_lpi2c_slave_flags` enumerators OR'd together. You may pass the result of a previous call to `LPI2C_SlaveGetStatusFlags()`.

`static inline void LPI2C_SlaveEnableInterrupts(LPI2C_Type *base, uint32_t interruptMask)`

Enables the LPI2C slave interrupt requests.

All flags except `kLPI2C_SlaveBusyFlag` and `kLPI2C_SlaveBusBusyFlag` can be enabled as interrupts.

Parameters

- `base` – The LPI2C peripheral base address.
- `interruptMask` – Bit mask of interrupts to enable. See `_lpi2c_slave_flags` for the set of constants that should be OR'd together to form the bit mask.

`static inline void LPI2C_SlaveDisableInterrupts(LPI2C_Type *base, uint32_t interruptMask)`

Disables the LPI2C slave interrupt requests.

All flags except `kLPI2C_SlaveBusyFlag` and `kLPI2C_SlaveBusBusyFlag` can be enabled as interrupts.

Parameters

- `base` – The LPI2C peripheral base address.
- `interruptMask` – Bit mask of interrupts to disable. See `_lpi2c_slave_flags` for the set of constants that should be OR'd together to form the bit mask.

`static inline uint32_t LPI2C_SlaveGetEnabledInterrupts(LPI2C_Type *base)`

Returns the set of currently enabled LPI2C slave interrupt requests.

Parameters

- `base` – The LPI2C peripheral base address.

Returns

A bitmask composed of `_lpi2c_slave_flags` enumerators OR'd together to indicate the set of enabled interrupts.

`static inline void LPI2C_SlaveEnableDMA(LPI2C_Type *base, bool enableAddressValid, bool enableRx, bool enableTx)`

Enables or disables the LPI2C slave peripheral DMA requests.

Parameters

- `base` – The LPI2C peripheral base address.
- `enableAddressValid` – Enable flag for the address valid DMA request. Pass true for enable, false for disable. The address valid DMA request is shared with the receive data DMA request.
- `enableRx` – Enable flag for the receive data DMA request. Pass true for enable, false for disable.
- `enableTx` – Enable flag for the transmit data DMA request. Pass true for enable, false for disable.

`static inline bool LPI2C_SlaveGetBusIdleState(LPI2C_Type *base)`

Returns whether the bus is idle.

Requires the slave mode to be enabled.

Parameters

- `base` – The LPI2C peripheral base address.

Return values

- `true` – Bus is busy.
- `false` – Bus is idle.

`static inline void LPI2C_SlaveTransmitAck(LPI2C_Type *base, bool ackOrNack)`

Transmits either an ACK or NAK on the I2C bus in response to a byte from the master.

Use this function to send an ACK or NAK when the `kLPI2C_SlaveTransmitAckFlag` is asserted. This only happens if you enable the `sclStall.enableAck` field of the `lpi2c_slave_config_t` configuration structure used to initialize the slave peripheral.

Parameters

- `base` – The LPI2C peripheral base address.
- `ackOrNack` – Pass true for an ACK or false for a NAK.

`static inline void LPI2C_SlaveEnableAckStall(LPI2C_Type *base, bool enable)`

Enables or disables ACKSTALL.

When enables ACKSTALL, software can transmit either an ACK or NAK on the I2C bus in response to a byte from the master.

Parameters

- `base` – The LPI2C peripheral base address.
- `enable` – True will enable ACKSTALL, false will disable ACKSTALL.

`static inline uint32_t LPI2C_SlaveGetReceivedAddress(LPI2C_Type *base)`

Returns the slave address sent by the I2C master.

This function should only be called if the `kLPI2C_SlaveAddressValidFlag` is asserted.

Parameters

- `base` – The LPI2C peripheral base address.

Returns

The 8-bit address matched by the LPI2C slave. Bit 0 contains the R/w direction bit, and the 7-bit slave address is in the upper 7 bits.

`status_t LPI2C_SlaveSend(LPI2C_Type *base, void *txBuff, size_t txSize, size_t *actualTxSize)`

Performs a polling send transfer on the I2C bus.

Parameters

- `base` – The LPI2C peripheral base address.
- `txBuff` – The pointer to the data to be transferred.
- `txSize` – The length in bytes of the data to be transferred.
- `actualTxSize` – **[out]**

Returns

Error or success status returned by API.

`status_t LPI2C_SlaveReceive(LPI2C_Type *base, void *rxBuff, size_t rxSize, size_t *actualRxSize)`

Performs a polling receive transfer on the I2C bus.

Parameters

- `base` – The LPI2C peripheral base address.
- `rxBuff` – The pointer to the data to be transferred.
- `rxSize` – The length in bytes of the data to be transferred.

- actualRxSize – **[out]**

Returns

Error or success status returned by API.

```
void LPI2C__SlaveTransferCreateHandle(LPI2C_Type *base, lpi2c_slave_handle_t *handle,  
                                     lpi2c_slave_transfer_callback_t callback, void *userData)
```

Creates a new handle for the LPI2C slave non-blocking APIs.

The creation of a handle is for use with the non-blocking APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the LPI2C_SlaveTransferAbort() API shall be called.

Note: The function also enables the NVIC IRQ for the input LPI2C. Need to notice that on some SoCs the LPI2C IRQ is connected to INTMUX, in this case user needs to enable the associated INTMUX IRQ in application.

Parameters

- base – The LPI2C peripheral base address.
- handle – **[out]** Pointer to the LPI2C slave driver handle.
- callback – User provided pointer to the asynchronous callback function.
- userData – User provided pointer to the application callback data.

```
status_t LPI2C__SlaveTransferNonBlocking(LPI2C_Type *base, lpi2c_slave_handle_t *handle,  
                                         uint32_t eventMask)
```

Starts accepting slave transfers.

Call this API after calling I2C_SlaveInit() and LPI2C_SlaveTransferCreateHandle() to start processing transactions driven by an I2C master. The slave monitors the I2C bus and pass events to the callback that was passed into the call to LPI2C_SlaveTransferCreateHandle(). The callback is always invoked from the interrupt context.

The set of events received by the callback is customizable. To do so, set the *eventMask* parameter to the OR'd combination of *lpi2c_slave_transfer_event_t* enumerators for the events you wish to receive. The *kLPI2C_SlaveTransmitEvent* and *kLPI2C_SlaveReceiveEvent* events are always enabled and do not need to be included in the mask. Alternatively, you can pass 0 to get a default set of only the transmit and receive events that are always enabled. In addition, the *kLPI2C_SlaveAllEvents* constant is provided as a convenient way to enable all events.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to *lpi2c_slave_handle_t* structure which stores the transfer state.
- eventMask – Bit mask formed by OR'ing together *lpi2c_slave_transfer_event_t* enumerators to specify which events to send to the callback. Other accepted values are 0 to get a default set of only the transmit and receive events, and *kLPI2C_SlaveAllEvents* to enable all events.

Return values

- *kStatus_Success* – Slave transfers were successfully started.
- *kStatus_LPI2C_Busy* – Slave transfers have already been started on this handle.

status_t LPI2C_SlaveTransferGetCount(LPI2C_Type *base, *lpi2c_slave_handle_t* *handle, size_t *count)

Gets the slave transfer status during a non-blocking transfer.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to *i2c_slave_handle_t* structure.
- count – **[out]** Pointer to a value to hold the number of bytes transferred. May be NULL if the count is not required.

Return values

- kStatus_Success –
- kStatus_NoTransferInProgress –

void LPI2C_SlaveTransferAbort(LPI2C_Type *base, *lpi2c_slave_handle_t* *handle)

Aborts the slave non-blocking transfers.

Note: This API could be called at any time to stop slave for handling the bus events.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to *lpi2c_slave_handle_t* structure which stores the transfer state.

void LPI2C_SlaveTransferHandleIRQ(LPI2C_Type *base, *lpi2c_slave_handle_t* *handle)

Reusable routine to handle slave interrupts.

Note: This function does not need to be called unless you are reimplementing the non blocking API's interrupt handler routines to add special functionality.

Parameters

- base – The LPI2C peripheral base address.
- handle – Pointer to *lpi2c_slave_handle_t* structure which stores the transfer state.

enum *_lpi2c_slave_flags*

LPI2C slave peripheral flags.

The following status register flags can be cleared:

- kLPI2C_SlaveRepeatedStartDetectFlag
- kLPI2C_SlaveStopDetectFlag
- kLPI2C_SlaveBitErrFlag
- kLPI2C_SlaveFifoErrFlag

All flags except kLPI2C_SlaveBusyFlag and kLPI2C_SlaveBusBusyFlag can be enabled as interrupts.

Note: These enumerations are meant to be OR'd together to form a bit mask.

Values:

enumerator kLPI2C_SlaveTxReadyFlag

Transmit data flag

enumerator kLPI2C_SlaveRxReadyFlag

Receive data flag

enumerator kLPI2C_SlaveAddressValidFlag

Address valid flag

enumerator kLPI2C_SlaveTransmitAckFlag

Transmit ACK flag

enumerator kLPI2C_SlaveRepeatedStartDetectFlag

Repeated start detect flag

enumerator kLPI2C_SlaveStopDetectFlag

Stop detect flag

enumerator kLPI2C_SlaveBitErrFlag

Bit error flag

enumerator kLPI2C_SlaveFifoErrFlag

FIFO error flag

enumerator kLPI2C_SlaveAddressMatch0Flag

Address match 0 flag

enumerator kLPI2C_SlaveAddressMatch1Flag

Address match 1 flag

enumerator kLPI2C_SlaveGeneralCallFlag

General call flag

enumerator kLPI2C_SlaveBusyFlag

Master busy flag

enumerator kLPI2C_SlaveBusBusyFlag

Bus busy flag

enumerator kLPI2C_SlaveClearFlags

All flags which are cleared by the driver upon starting a transfer.

enumerator kLPI2C_SlaveIrqFlags

IRQ sources enabled by the non-blocking transactional API.

enumerator kLPI2C_SlaveErrorFlags

Errors to check for.

enum _lpi2c_slave_address_match

LPI2C slave address match options.

Values:

enumerator kLPI2C_MatchAddress0

Match only address 0.

enumerator kLPI2C_MatchAddress0OrAddress1

Match either address 0 or address 1.

enumerator kLPI2C_MatchAddress0ThroughAddress1

Match a range of slave addresses from address 0 through address 1.

enum `_lpi2c_slave_transfer_event`

Set of events sent to the callback for non blocking slave transfers.

These event enumerations are used for two related purposes. First, a bit mask created by OR'ing together events is passed to `LPI2C_SlaveTransferNonBlocking()` in order to specify which events to enable. Then, when the slave callback is invoked, it is passed the current event through its *transfer* parameter.

Note: These enumerations are meant to be OR'd together to form a bit mask of events.

Values:

enumerator `kLPI2C_SlaveAddressMatchEvent`

Received the slave address after a start or repeated start.

enumerator `kLPI2C_SlaveTransmitEvent`

Callback is requested to provide data to transmit (slave-transmitter role).

enumerator `kLPI2C_SlaveReceiveEvent`

Callback is requested to provide a buffer in which to place received data (slave-receiver role).

enumerator `kLPI2C_SlaveTransmitAckEvent`

Callback needs to either transmit an ACK or NACK.

enumerator `kLPI2C_SlaveRepeatedStartEvent`

A repeated start was detected.

enumerator `kLPI2C_SlaveCompletionEvent`

A stop was detected, completing the transfer.

enumerator `kLPI2C_SlaveAllEvents`

Bit mask of all available events.

typedef enum `_lpi2c_slave_address_match` `lpi2c_slave_address_match_t`

LPI2C slave address match options.

typedef struct `_lpi2c_slave_config` `lpi2c_slave_config_t`

Structure with settings to initialize the LPI2C slave module.

This structure holds configuration settings for the LPI2C slave peripheral. To initialize this structure to reasonable defaults, call the `LPI2C_SlaveGetDefaultConfig()` function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

typedef enum `_lpi2c_slave_transfer_event` `lpi2c_slave_transfer_event_t`

Set of events sent to the callback for non blocking slave transfers.

These event enumerations are used for two related purposes. First, a bit mask created by OR'ing together events is passed to `LPI2C_SlaveTransferNonBlocking()` in order to specify which events to enable. Then, when the slave callback is invoked, it is passed the current event through its *transfer* parameter.

Note: These enumerations are meant to be OR'd together to form a bit mask of events.

typedef struct `_lpi2c_slave_transfer` `lpi2c_slave_transfer_t`

LPI2C slave transfer structure.

```
typedef struct _lpi2c_slave_handle lpi2c_slave_handle_t
```

LPI2C slave handle structure.

```
typedef void (*lpi2c_slave_transfer_callback_t)(LPI2C_Type *base, lpi2c_slave_transfer_t *transfer, void *userData)
```

Slave event callback function pointer type.

This callback is used only for the slave non-blocking transfer API. To install a callback, use the LPI2C_SlaveSetCallback() function after you have created a handle.

Param base

Base address for the LPI2C instance on which the event occurred.

Param transfer

Pointer to transfer descriptor containing values passed to and/or from the callback.

Param userData

Arbitrary pointer-sized value passed from the application.

```
struct _lpi2c_slave_config
```

#include <fsl_lpi2c.h> Structure with settings to initialize the LPI2C slave module.

This structure holds configuration settings for the LPI2C slave peripheral. To initialize this structure to reasonable defaults, call the LPI2C_SlaveGetDefaultConfig() function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

Public Members

bool enableSlave

Enable slave mode.

uint8_t address0

Slave's 7-bit address.

uint8_t address1

Alternate slave 7-bit address.

lpi2c_slave_address_match_t addressMatchMode

Address matching options.

bool filterDozeEnable

Enable digital glitch filter in doze mode.

bool filterEnable

Enable digital glitch filter.

bool enableGeneralCall

Enable general call address matching.

struct *_lpi2c_slave_config* sclStall

SCL stall enable options.

bool ignoreAck

Continue transfers after a NACK is detected.

bool enableReceivedAddressRead

Enable reading the address received address as the first byte of data.

uint32_t sdaGlitchFilterWidth_ns

Width in nanoseconds of the digital filter on the SDA signal. Set to 0 to disable.

uint32_t sclGlitchFilterWidth_ns

Width in nanoseconds of the digital filter on the SCL signal. Set to 0 to disable.

uint32_t dataValidDelay_ns

Width in nanoseconds of the data valid delay.

uint32_t clockHoldTime_ns

Width in nanoseconds of the clock hold time.

struct __lpi2c_slave_transfer

#include <fsl_lpi2c.h> LPI2C slave transfer structure.

Public Members

lpi2c_slave_transfer_event_t event

Reason the callback is being invoked.

uint8_t receivedAddress

Matching address send by master.

uint8_t *data

Transfer buffer

size_t dataSize

Transfer size

status_t completionStatus

Success or error code describing how the transfer completed. Only applies for kLPI2C_SlaveCompletionEvent.

size_t transferredCount

Number of bytes actually transferred since start or last repeated start.

struct __lpi2c_slave_handle

#include <fsl_lpi2c.h> LPI2C slave handle structure.

Note: The contents of this structure are private and subject to change.

Public Members

lpi2c_slave_transfer_t transfer

LPI2C slave transfer copy.

bool isBusy

Whether transfer is busy.

bool wasTransmit

Whether the last transfer was a transmit.

uint32_t eventMask

Mask of enabled events.

uint32_t transferredCount

Count of bytes transferred.

lpi2c_slave_transfer_callback_t callback

Callback function called at transfer event.

void *userData

Callback parameter passed to callback.

struct sclStall

Public Members

bool enableAck

Enables SCL clock stretching during slave-transmit address byte(s) and slave-receiver address and data byte(s) to allow software to write the Transmit ACK Register before the ACK or NACK is transmitted. Clock stretching occurs when transmitting the 9th bit. When enableAckSCLStall is enabled, there is no need to set either enableRxDataSCLStall or enableAddressSCLStall.

bool enableTx

Enables SCL clock stretching when the transmit data flag is set during a slave-transmit transfer.

bool enableRx

Enables SCL clock stretching when receive data flag is set during a slave-receive transfer.

bool enableAddress

Enables SCL clock stretching when the address valid flag is asserted.

2.35 LPIT: Low-Power Interrupt Timer

enum _lpit_chnl

List of LPIT channels.

Note: Actual number of available channels is SoC-dependent

Values:

enumerator kLPIT_Chnl_0

LPIT channel number 0

enumerator kLPIT_Chnl_1

LPIT channel number 1

enumerator kLPIT_Chnl_2

LPIT channel number 2

enumerator kLPIT_Chnl_3

LPIT channel number 3

enum _lpit_timer_modes

Mode options available for the LPIT timer.

Values:

enumerator kLPIT_PeriodicCounter

Use the all 32-bits, counter loads and decrements to zero

enumerator kLPIT_DualPeriodicCounter

Counter loads, lower 16-bits decrement to zero, then upper 16-bits decrement

enumerator kLPIT_TriggerAccumulator

Counter loads on first trigger and decrements on each trigger

enumerator kLPIT_InputCapture

Counter loads with 0xFFFFFFFF, decrements to zero. It stores the inverse of the current value when a input trigger is detected

enum _lpit_trigger_select

Trigger options available.

This is used for both internal and external trigger sources. The actual trigger options available is SoC-specific, user should refer to the reference manual.

Values:

enumerator kLPIT_Trigger_TimerChn0

Channel 0 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn1

Channel 1 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn2

Channel 2 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn3

Channel 3 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn4

Channel 4 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn5

Channel 5 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn6

Channel 6 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn7

Channel 7 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn8

Channel 8 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn9

Channel 9 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn10

Channel 10 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn11

Channel 11 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn12

Channel 12 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn13

Channel 13 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn14

Channel 14 is selected as a trigger source

enumerator kLPIT_Trigger_TimerChn15

Channel 15 is selected as a trigger source

enum `_lpit_trigger_source`

Trigger source options available.

Values:

enumerator `kLPIT_TriggerSource_External`

Use external trigger input

enumerator `kLPIT_TriggerSource_Internal`

Use internal trigger

enum `_lpit_interrupt_enable`

List of LPIT interrupts.

Note: Number of timer channels are SoC-specific. See the SoC Reference Manual.

Values:

enumerator `kLPIT_Channel0TimerInterruptEnable`

Channel 0 Timer interrupt

enumerator `kLPIT_Channel1TimerInterruptEnable`

Channel 1 Timer interrupt

enumerator `kLPIT_Channel2TimerInterruptEnable`

Channel 2 Timer interrupt

enumerator `kLPIT_Channel3TimerInterruptEnable`

Channel 3 Timer interrupt

enum `_lpit_status_flags`

List of LPIT status flags.

Note: Number of timer channels are SoC-specific. See the SoC Reference Manual.

Values:

enumerator `kLPIT_Channel0TimerFlag`

Channel 0 Timer interrupt flag

enumerator `kLPIT_Channel1TimerFlag`

Channel 1 Timer interrupt flag

enumerator `kLPIT_Channel2TimerFlag`

Channel 2 Timer interrupt flag

enumerator `kLPIT_Channel3TimerFlag`

Channel 3 Timer interrupt flag

typedef enum `_lpit_chnl` `lpit_chnl_t`

List of LPIT channels.

Note: Actual number of available channels is SoC-dependent

typedef enum `_lpit_timer_modes` `lpit_timer_modes_t`

Mode options available for the LPIT timer.

```
typedef enum _lpit_trigger_select lpit_trigger_select_t
```

Trigger options available.

This is used for both internal and external trigger sources. The actual trigger options available is SoC-specific, user should refer to the reference manual.

```
typedef enum _lpit_trigger_source lpit_trigger_source_t
```

Trigger source options available.

```
typedef enum _lpit_interrupt_enable lpit_interrupt_enable_t
```

List of LPIT interrupts.

Note: Number of timer channels are SoC-specific. See the SoC Reference Manual.

```
typedef enum _lpit_status_flags lpit_status_flags_t
```

List of LPIT status flags.

Note: Number of timer channels are SoC-specific. See the SoC Reference Manual.

```
typedef struct _lpit_chnl_params lpit_chnl_params_t
```

Structure to configure the channel timer.

```
typedef struct _lpit_config lpit_config_t
```

LPIT configuration structure.

This structure holds the configuration settings for the LPIT peripheral. To initialize this structure to reasonable defaults, call the LPIT_GetDefaultConfig() function and pass a pointer to the configuration structure instance.

The configuration structure can be made constant so as to reside in flash.

```
FSL_LPIT_DRIVER_VERSION
```

Version 2.1.2

```
LPIT_RESET_STATE_DELAY
```

Delay used in LPIT_Reset.

The macro value should be larger than $4 * \text{core clock} / \text{LPIT peripheral clock}$.

```
void LPIT_Init(LPIT_Type *base, const lpit_config_t *config)
```

Ungates the LPIT clock and configures the peripheral for a basic operation.

This function issues a software reset to reset all channels and registers except the Module Control register.

Note: This API should be called at the beginning of the application using the LPIT driver.

Parameters

- base – LPIT peripheral base address.
- config – Pointer to the user configuration structure.

```
void LPIT_Deinit(LPIT_Type *base)
```

Disables the module and gates the LPIT clock.

Parameters

- base – LPIT peripheral base address.

void LPIT_GetDefaultConfig(*lpit_config_t* *config)

Fills in the LPIT configuration structure with default settings.

The default values are:

```
config->enableRunInDebug = false;
config->enableRunInDoze = false;
```

Parameters

- config – Pointer to the user configuration structure.

status_t LPIT_SetupChannel(LPIT_Type *base, *lpit_chnl_t* channel, const *lpit_chnl_params_t* *chnlSetup)

Sets up an LPIT channel based on the user's preference.

This function sets up the operation mode to one of the options available in the enumeration *lpit_timer_modes_t*. It sets the trigger source as either internal or external, trigger selection and the timers behaviour when a timeout occurs. It also chains the timer if a prior timer if requested by the user.

Parameters

- base – LPIT peripheral base address.
- channel – Channel that is being configured.
- chnlSetup – Configuration parameters.

static inline void LPIT_EnableInterrupts(LPIT_Type *base, uint32_t mask)

Enables the selected PIT interrupts.

Parameters

- base – LPIT peripheral base address.
- mask – The interrupts to enable. This is a logical OR of members of the enumeration *lpit_interrupt_enable_t*

static inline void LPIT_DisableInterrupts(LPIT_Type *base, uint32_t mask)

Disables the selected PIT interrupts.

Parameters

- base – LPIT peripheral base address.
- mask – The interrupts to enable. This is a logical OR of members of the enumeration *lpit_interrupt_enable_t*

static inline uint32_t LPIT_GetEnabledInterrupts(LPIT_Type *base)

Gets the enabled LPIT interrupts.

Parameters

- base – LPIT peripheral base address.

Returns

The enabled interrupts. This is the logical OR of members of the enumeration *lpit_interrupt_enable_t*

static inline uint32_t LPIT_GetStatusFlags(LPIT_Type *base)

Gets the LPIT status flags.

Parameters

- base – LPIT peripheral base address.

Returns

The status flags. This is the logical OR of members of the enumeration `lpit_status_flags_t`

```
static inline void LPIT_ClearStatusFlags(LPIT_Type *base, uint32_t mask)
```

Clears the LPIT status flags.

Parameters

- `base` – LPIT peripheral base address.
- `mask` – The status flags to clear. This is a logical OR of members of the enumeration `lpit_status_flags_t`

```
static inline void LPIT_SetTimerPeriod(LPIT_Type *base, lpit_chnl_t channel, uint32_t ticks)
```

Sets the timer period in units of count.

Timers begin counting down from the value set by this function until it reaches 0, at which point it generates an interrupt and loads this register value again. Writing a new value to this register does not restart the timer. Instead, the value is loaded after the timer expires.

Note: User can call the utility macros provided in `fsl_common.h` to convert to ticks.

Parameters

- `base` – LPIT peripheral base address.
- `channel` – Timer channel number.
- `ticks` – Timer period in units of ticks.

```
static inline void LPIT_SetTimerValue(LPIT_Type *base, lpit_chnl_t channel, uint32_t ticks)
```

Sets the timer period in units of count.

In the Dual 16-bit Periodic Counter mode, the counter will load and then the lower 16-bits will decrement down to zero, which will assert the output pre-trigger. The upper 16-bits will then decrement down to zero, which will negate the output pre-trigger and set the timer interrupt flag.

Note: Set TVAL register to 0 or 1 is invalid in compare mode.

Parameters

- `base` – LPIT peripheral base address.
- `channel` – Timer channel number.
- `ticks` – Timer period in units of ticks.

```
static inline uint32_t LPIT_GetCurrentTimerCount(LPIT_Type *base, lpit_chnl_t channel)
```

Reads the current timer counting value.

This function returns the real-time timer counting value, in a range from 0 to a timer period.

Note: User can call the utility macros provided in `fsl_common.h` to convert ticks to microseconds or milliseconds.

Parameters

- `base` – LPIT peripheral base address.
- `channel` – Timer channel number.

Returns

Current timer counting value in ticks.

static inline void LPIT_StartTimer(LPIT_Type *base, *lpit_chnl_t* channel)

Starts the timer counting.

After calling this function, timers load the period value and count down to 0. When the timer reaches 0, it generates a trigger pulse and sets the timeout interrupt flag.

Parameters

- base – LPIT peripheral base address.
- channel – Timer channel number.

static inline void LPIT_StopTimer(LPIT_Type *base, *lpit_chnl_t* channel)

Stops the timer counting.

Parameters

- base – LPIT peripheral base address.
- channel – Timer channel number.

static void LPIT_ResetStateDelay(void)

Short wait for LPIT state reset.

After clear or set LPIT_EN, there should be delay longer than 4 LPIT functional clock.

Parameters

- count – Delay count.

static inline void LPIT_Reset(LPIT_Type *base)

Performs a software reset on the LPIT module.

This resets all channels and registers except the Module Control Register.

Parameters

- base – LPIT peripheral base address.

struct *_lpit_chnl_params*

#include <fsl_lpit.h> Structure to configure the channel timer.

Public Members

bool chainChannel

true: Timer chained to previous timer; false: Timer not chained

lpit_timer_modes_t timerMode

Timers mode of operation.

lpit_trigger_select_t triggerSelect

Trigger selection for the timer

lpit_trigger_source_t triggerSource

Decides if we use external or internal trigger.

bool enableReloadOnTrigger

true: Timer reloads when a trigger is detected; false: No effect

bool enableStopOnTimeout

true: Timer will stop after timeout; false: does not stop after timeout

bool enableStartOnTrigger

true: Timer starts when a trigger is detected; false: decrement immediately

struct __lpit__config

#include <fsl_lpit.h> LPIT configuration structure.

This structure holds the configuration settings for the LPIT peripheral. To initialize this structure to reasonable defaults, call the LPIT_GetDefaultConfig() function and pass a pointer to the configuration structure instance.

The configuration structure can be made constant so as to reside in flash.

Public Members

bool enableRunInDebug

true: Timers run in debug mode; false: Timers stop in debug mode

bool enableRunInDoze

true: Timers run in doze mode; false: Timers stop in doze mode

2.36 LPSPI: Low Power Serial Peripheral Interface

2.37 LPSPI Peripheral driver

```
void LPSPI_MasterInit(LPSPI_Type *base, const lpspi_master_config_t *masterConfig, uint32_t
srcClock_Hz)
```

Initializes the LPSPI master.

Parameters

- base – LPSPI peripheral address.
- masterConfig – Pointer to structure *lpspi_master_config_t*.
- srcClock_Hz – Module source input clock in Hertz

```
void LPSPI_MasterGetDefaultConfig(lpspi_master_config_t *masterConfig)
```

Sets the *lpspi_master_config_t* structure to default values.

This API initializes the configuration structure for LPSPI_MasterInit(). The initialized structure can remain unchanged in LPSPI_MasterInit(), or can be modified before calling the LPSPI_MasterInit(). Example:

```
lpspi_master_config_t masterConfig;
LPSPI_MasterGetDefaultConfig(&masterConfig);
```

Parameters

- masterConfig – pointer to *lpspi_master_config_t* structure

```
void LPSPI_SlaveInit(LPSPI_Type *base, const lpspi_slave_config_t *slaveConfig)
```

LPSPI slave configuration.

Parameters

- base – LPSPI peripheral address.
- slaveConfig – Pointer to a structure *lpspi_slave_config_t*.

`void LPSPI_SlaveGetDefaultConfig(lpspi_slave_config_t *slaveConfig)`

Sets the `lpspi_slave_config_t` structure to default values.

This API initializes the configuration structure for `LPSPI_SlaveInit()`. The initialized structure can remain unchanged in `LPSPI_SlaveInit()` or can be modified before calling the `LPSPI_SlaveInit()`. Example:

```
lpspi_slave_config_t slaveConfig;  
LPSPI_SlaveGetDefaultConfig(&slaveConfig);
```

Parameters

- `slaveConfig` – pointer to `lpspi_slave_config_t` structure.

`void LPSPI_Deinit(LPSPI_Type *base)`

De-initializes the LPSPI peripheral. Call this API to disable the LPSPI clock.

Parameters

- `base` – LPSPI peripheral address.

`void LPSPI_Reset(LPSPI_Type *base)`

Restores the LPSPI peripheral to reset state. Note that this function sets all registers to reset state. As a result, the LPSPI module can't work after calling this API.

Parameters

- `base` – LPSPI peripheral address.

`uint32_t LPSPI_GetInstance(LPSPI_Type *base)`

Get the LPSPI instance from peripheral base address.

Parameters

- `base` – LPSPI peripheral base address.

Returns

LPSPI instance.

`static inline void LPSPI_Enable(LPSPI_Type *base, bool enable)`

Enables the LPSPI peripheral and sets the MCR MDIS to 0.

Parameters

- `base` – LPSPI peripheral address.
- `enable` – Pass true to enable module, false to disable module.

`static inline uint32_t LPSPI_GetStatusFlags(LPSPI_Type *base)`

Gets the LPSPI status flag state.

Parameters

- `base` – LPSPI peripheral address.

Returns

The LPSPI status(in SR register).

`static inline uint8_t LPSPI_GetTxFifoSize(LPSPI_Type *base)`

Gets the LPSPI Tx FIFO size.

Parameters

- `base` – LPSPI peripheral address.

Returns

The LPSPI Tx FIFO size.

```
static inline uint8_t LPSPI_GetRxFifoSize(LPSPI_Type *base)
```

Gets the LPSPI Rx FIFO size.

Parameters

- base – LPSPI peripheral address.

Returns

The LPSPI Rx FIFO size.

```
static inline uint32_t LPSPI_GetTxFifoCount(LPSPI_Type *base)
```

Gets the LPSPI Tx FIFO count.

Parameters

- base – LPSPI peripheral address.

Returns

The number of words in the transmit FIFO.

```
static inline uint32_t LPSPI_GetRxFifoCount(LPSPI_Type *base)
```

Gets the LPSPI Rx FIFO count.

Parameters

- base – LPSPI peripheral address.

Returns

The number of words in the receive FIFO.

```
static inline void LPSPI_ClearStatusFlags(LPSPI_Type *base, uint32_t statusFlags)
```

Clears the LPSPI status flag.

This function clears the desired status bit by using a write-1-to-clear. The user passes in the base and the desired status flag bit to clear. The list of status flags is defined in the `_lpspi_flags`. Example usage:

```
LPSPI_ClearStatusFlags(base, kLPSPI_TxDataRequestFlag | kLPSPI_RxDataReadyFlag);
```

Parameters

- base – LPSPI peripheral address.
- statusFlags – The status flag used from type `_lpspi_flags`.

```
static inline uint32_t LPSPI_GetTcr(LPSPI_Type *base)
```

```
static inline void LPSPI_EnableInterrupts(LPSPI_Type *base, uint32_t mask)
```

Enables the LPSPI interrupts.

This function configures the various interrupt masks of the LPSPI. The parameters are base and an interrupt mask. Note that, for Tx fill and Rx FIFO drain requests, enabling the interrupt request disables the DMA request.

```
LPSPI_EnableInterrupts(base, kLPSPI_TxInterruptEnable | kLPSPI_RxInterruptEnable );
```

Parameters

- base – LPSPI peripheral address.
- mask – The interrupt mask; Use the enum `_lpspi_interrupt_enable`.

```
static inline void LPSPI_DisableInterrupts(LPSPI_Type *base, uint32_t mask)
```

Disables the LPSPI interrupts.

```
LPSPI_DisableInterrupts(base, kLPSPI_TxInterruptEnable | kLPSPI_RxInterruptEnable );
```

Parameters

- base – LPSPI peripheral address.
- mask – The interrupt mask; Use the enum `_lpspi_interrupt_enable`.

```
static inline void LPSPI_EnableDMA(LPSPI_Type *base, uint32_t mask)
```

Enables the LPSPI DMA request.

This function configures the Rx and Tx DMA mask of the LPSPI. The parameters are base and a DMA mask.

```
LPSPI_EnableDMA(base, kLPSPI_TxDmaEnable | kLPSPI_RxDmaEnable);
```

Parameters

- base – LPSPI peripheral address.
- mask – The interrupt mask; Use the enum `_lpspi_dma_enable`.

```
static inline void LPSPI_DisableDMA(LPSPI_Type *base, uint32_t mask)
```

Disables the LPSPI DMA request.

This function configures the Rx and Tx DMA mask of the LPSPI. The parameters are base and a DMA mask.

```
LPSPI_DisableDMA(base, kLPSPI_TxDmaEnable | kLPSPI_RxDmaEnable);
```

Parameters

- base – LPSPI peripheral address.
- mask – The interrupt mask; Use the enum `_lpspi_dma_enable`.

```
static inline uint32_t LPSPI_GetTxRegisterAddress(LPSPI_Type *base)
```

Gets the LPSPI Transmit Data Register address for a DMA operation.

This function gets the LPSPI Transmit Data Register address because this value is needed for the DMA operation. This function can be used for either master or slave mode.

Parameters

- base – LPSPI peripheral address.

Returns

The LPSPI Transmit Data Register address.

```
static inline uint32_t LPSPI_GetRxRegisterAddress(LPSPI_Type *base)
```

Gets the LPSPI Receive Data Register address for a DMA operation.

This function gets the LPSPI Receive Data Register address because this value is needed for the DMA operation. This function can be used for either master or slave mode.

Parameters

- base – LPSPI peripheral address.

Returns

The LPSPI Receive Data Register address.

```
bool LPSPI_CheckTransferArgument(LPSPI_Type *base, lpspi_transfer_t *transfer, bool isEdma)
```

Check the argument for transfer .

Parameters

- base – LPSPI peripheral address.
- transfer – the transfer struct to be used.

- `isEdma` – True to check for EDMA transfer, false to check interrupt non-blocking transfer

Returns

Return true for right and false for wrong.

```
static inline void LPSPI_SetMasterSlaveMode(LPSPI_Type *base, lpspi_master_slave_mode_t mode)
```

Configures the LPSPI for either master or slave.

Note that the CFGR1 should only be written when the LPSPI is disabled (LPSPIx_CR_MEN = 0).

Parameters

- `base` – LPSPI peripheral address.
- `mode` – Mode setting (master or slave) of type `lpspi_master_slave_mode_t`.

```
static inline void LPSPI_SelectTransferPCS(LPSPI_Type *base, lpspi_which_pcs_t select)
```

Configures the peripheral chip select used for the transfer.

Parameters

- `base` – LPSPI peripheral address.
- `select` – LPSPI Peripheral Chip Select (PCS) configuration.

```
static inline void LPSPI_SetPCSContinuous(LPSPI_Type *base, bool IsContinuous)
```

Set the PCS signal to continuous or uncontinuous mode.

Note: In master mode, continuous transfer will keep the PCS asserted at the end of the frame size, until a command word is received that starts a new frame. So PCS must be set back to uncontinuous when transfer finishes. In slave mode, when continuous transfer is enabled, the LPSPI will only transmit the first frame size bits, after that the LPSPI will transmit received data back (assuming a 32-bit shift register).

Parameters

- `base` – LPSPI peripheral address.
- `IsContinuous` – True to set the transfer PCS to continuous mode, false to set to uncontinuous mode.

```
static inline bool LPSPI_IsMaster(LPSPI_Type *base)
```

Returns whether the LPSPI module is in master mode.

Parameters

- `base` – LPSPI peripheral address.

Returns

Returns true if the module is in master mode or false if the module is in slave mode.

```
static inline void LPSPI_FlushFifo(LPSPI_Type *base, bool flushTxFifo, bool flushRxFifo)
```

Flushes the LPSPI FIFOs.

Parameters

- `base` – LPSPI peripheral address.
- `flushTxFifo` – Flushes (true) the Tx FIFO, else do not flush (false) the Tx FIFO.
- `flushRxFifo` – Flushes (true) the Rx FIFO, else do not flush (false) the Rx FIFO.

```
static inline void LPSPI_SetFifoWatermarks(LPSPI_Type *base, uint32_t txWater, uint32_t rxWater)
```

Sets the transmit and receive FIFO watermark values.

This function allows the user to set the receive and transmit FIFO watermarks. The function does not compare the watermark settings to the FIFO size. The FIFO watermark should not be equal to or greater than the FIFO size. It is up to the higher level driver to make this check.

Parameters

- `base` – LPSPI peripheral address.
- `txWater` – The TX FIFO watermark value. Writing a value equal or greater than the FIFO size is truncated.
- `rxWater` – The RX FIFO watermark value. Writing a value equal or greater than the FIFO size is truncated.

```
static inline void LPSPI_SetAllPcsPolarity(LPSPI_Type *base, uint32_t mask)
```

Configures all LPSPI peripheral chip select polarities simultaneously.

Note that the CFGR1 should only be written when the LPSPI is disabled (LPSPIx_CR_MEN = 0).

This is an example: PCS0 and PCS1 set to active low and other PCSs set to active high. Note that the number of PCS is device-specific.

```
LPSPI_SetAllPcsPolarity(base, kLPSPI_Pcs0ActiveLow | kLPSPI_Pcs1ActiveLow);
```

Parameters

- `base` – LPSPI peripheral address.
- `mask` – The PCS polarity mask; Use the enum `_lpspi_pcs_polarity`.

```
static inline void LPSPI_SetFrameSize(LPSPI_Type *base, uint32_t frameSize)
```

Configures the frame size.

The minimum frame size is 8-bits and the maximum frame size is 4096-bits. If the frame size is less than or equal to 32-bits, the word size and frame size are identical. If the frame size is greater than 32-bits, the word size is 32-bits for each word except the last (the last word contains the remainder bits if the frame size is not divisible by 32). The minimum word size is 2-bits. A frame size of 33-bits (or similar) is not supported.

Note 1: The transmit command register should be initialized before enabling the LPSPI in slave mode, although the command register does not update until after the LPSPI is enabled. After it is enabled, the transmit command register should only be changed if the LPSPI is idle.

Note 2: The transmit and command FIFO is a combined FIFO that includes both transmit data and command words. That means the TCR register should be written to when the Tx FIFO is not full.

Parameters

- `base` – LPSPI peripheral address.
- `frameSize` – The frame size in number of bits.

```
uint32_t LPSPI_MasterSetBaudRate(LPSPI_Type *base, uint32_t baudRate_Bps, uint32_t srcClock_Hz, uint32_t *tcrPrescaleValue)
```

Sets the LPSPI baud rate in bits per second.

This function takes in the desired bitsPerSec (baud rate) and calculates the nearest possible baud rate without exceeding the desired baud rate and returns the calculated baud rate

in bits-per-second. It requires the caller to provide the frequency of the module source clock (in Hertz). Note that the baud rate does not go into effect until the Transmit Control Register (TCR) is programmed with the prescale value. Hence, this function returns the prescale `tcrPrescaleValue` parameter for later programming in the TCR. The higher level peripheral driver should alert the user of an out of range baud rate input.

Note that the LPSPI module must first be disabled before configuring this. Note that the LPSPI module must be configured for master mode before configuring this.

Parameters

- `base` – LPSPI peripheral address.
- `baudRate_Bps` – The desired baud rate in bits per second.
- `srcClock_Hz` – Module source input clock in Hertz.
- `tcrPrescaleValue` – The TCR prescale value needed to program the TCR.

Returns

The actual calculated baud rate. This function may also return a “0” if the LPSPI is not configured for master mode or if the LPSPI module is not disabled.

```
void LPSPI_MasterSetDelayScaler(LPSPI_Type *base, uint32_t scaler, lpspi_delay_type_t
                               whichDelay)
```

Manually configures a specific LPSPI delay parameter (module must be disabled to change the delay values).

This function configures the following: SCK to PCS delay, or PCS to SCK delay, or The configurations must occur between the transfer delay.

The delay names are available in type `lpspi_delay_type_t`.

The user passes the desired delay along with the delay value. This allows the user to directly set the delay values if they have pre-calculated them or if they simply wish to manually increment the value.

Note that the LPSPI module must first be disabled before configuring this. Note that the LPSPI module must be configured for master mode before configuring this.

Parameters

- `base` – LPSPI peripheral address.
- `scaler` – The 8-bit delay value 0x00 to 0xFF (255).
- `whichDelay` – The desired delay to configure, must be of type `lpspi_delay_type_t`.

```
uint32_t LPSPI_MasterSetDelayTimes(LPSPI_Type *base, uint32_t delayTimeInNanoSec,
                                   lpspi_delay_type_t whichDelay, uint32_t srcClock_Hz)
```

Calculates the delay based on the desired delay input in nanoseconds (module must be disabled to change the delay values).

This function calculates the values for the following: SCK to PCS delay, or PCS to SCK delay, or The configurations must occur between the transfer delay.

The delay names are available in type `lpspi_delay_type_t`.

The user passes the desired delay and the desired delay value in nano-seconds. The function calculates the value needed for the desired delay parameter and returns the actual calculated delay because an exact delay match may not be possible. In this case, the closest match is calculated without going below the desired delay value input. It is possible to input a very large delay value that exceeds the capability of the part, in which case the maximum supported delay is returned. It is up to the higher level peripheral driver to alert the user of an out of range delay input.

Note that the LPSPI module must be configured for master mode before configuring this. And note that the `delayTime = LPSPI_clockSource / (PRESCALE * Delay_scaler)`.

Parameters

- `base` – LPSPI peripheral address.
- `delayTimeInNanoSec` – The desired delay value in nano-seconds.
- `whichDelay` – The desired delay to configuration, which must be of type `lpspi_delay_type_t`.
- `srcClock_Hz` – Module source input clock in Hertz.

Returns

actual Calculated delay value in nano-seconds.

```
static inline void LPSPI_WriteData(LPSPI_Type *base, uint32_t data)
```

Writes data into the transmit data buffer.

This function writes data passed in by the user to the Transmit Data Register (TDR). The user can pass up to 32-bits of data to load into the TDR. If the frame size exceeds 32-bits, the user has to manage sending the data one 32-bit word at a time. Any writes to the TDR result in an immediate push to the transmit FIFO. This function can be used for either master or slave modes.

Parameters

- `base` – LPSPI peripheral address.
- `data` – The data word to be sent.

```
static inline uint32_t LPSPI_ReadData(LPSPI_Type *base)
```

Reads data from the data buffer.

This function reads the data from the Receive Data Register (RDR). This function can be used for either master or slave mode.

Parameters

- `base` – LPSPI peripheral address.

Returns

The data read from the data buffer.

```
void LPSPI_SetDummyData(LPSPI_Type *base, uint8_t dummyData)
```

Set up the dummy data.

Parameters

- `base` – LPSPI peripheral address.
- `dummyData` – Data to be transferred when tx buffer is NULL. Note: This API has no effect when LPSPI in slave interrupt mode, because driver will set the TXMSK bit to 1 if txData is NULL, no data is loaded from transmit FIFO and output pin is tristated.

```
void LPSPI_MasterTransferCreateHandle(LPSPI_Type *base, lpspi_master_handle_t *handle,  
                                     lpspi_master_transfer_callback_t callback, void  
                                     *userData)
```

Initializes the LPSPI master handle.

This function initializes the LPSPI handle, which can be used for other LPSPI transactional APIs. Usually, for a specified LPSPI instance, call this API once to get the initialized handle.

Parameters

- `base` – LPSPI peripheral address.
- `handle` – LPSPI handle pointer to `lpspi_master_handle_t`.

- callback – DSPI callback.
- userData – callback function parameter.

status_t LPSPI_MasterTransferBlocking(LPSPI_Type *base, *lpspi_transfer_t* *transfer)

LPSPI master transfer data using a polling method.

This function transfers data using a polling method. This is a blocking function, which does not return until all transfers have been completed.

Note: The transfer data size should be integer multiples of bytesPerFrame if bytesPerFrame is less than or equal to 4. For bytesPerFrame greater than 4: The transfer data size should be equal to bytesPerFrame if the bytesPerFrame is not integer multiples of 4. Otherwise, the transfer data size can be an integer multiple of bytesPerFrame.

Parameters

- base – LPSPI peripheral address.
- transfer – pointer to *lpspi_transfer_t* structure.

Returns

status of *status_t*.

status_t LPSPI_MasterTransferNonBlocking(LPSPI_Type *base, *lpspi_master_handle_t* *handle, *lpspi_transfer_t* *transfer)

LPSPI master transfer data using an interrupt method.

This function transfers data using an interrupt method. This is a non-blocking function, which returns right away. When all data is transferred, the callback function is called.

Note: The transfer data size should be integer multiples of bytesPerFrame if bytesPerFrame is less than or equal to 4. For bytesPerFrame greater than 4: The transfer data size should be equal to bytesPerFrame if the bytesPerFrame is not integer multiples of 4. Otherwise, the transfer data size can be an integer multiple of bytesPerFrame.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to *lpspi_master_handle_t* structure which stores the transfer state.
- transfer – pointer to *lpspi_transfer_t* structure.

Returns

status of *status_t*.

status_t LPSPI_MasterTransferGetCount(LPSPI_Type *base, *lpspi_master_handle_t* *handle, *size_t* *count)

Gets the master transfer remaining bytes.

This function gets the master transfer remaining bytes.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to *lpspi_master_handle_t* structure which stores the transfer state.
- count – Number of bytes transferred so far by the non-blocking transaction.

Returns

status of *status_t*.

void LPSPI_MasterTransferAbort(LPSPI_Type *base, *lpspi_master_handle_t* *handle)

LPSPI master abort transfer which uses an interrupt method.

This function aborts a transfer which uses an interrupt method.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to `lpspi_master_handle_t` structure which stores the transfer state.

`void LPSPI_MasterTransferHandleIRQ(LPSPI_Type *base, lpspi_master_handle_t *handle)`
LPSPI Master IRQ handler function.

This function processes the LPSPI transmit and receive IRQ.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to `lpspi_master_handle_t` structure which stores the transfer state.

`void LPSPI_SlaveTransferCreateHandle(LPSPI_Type *base, lpspi_slave_handle_t *handle, lpspi_slave_transfer_callback_t callback, void *userData)`

Initializes the LPSPI slave handle.

This function initializes the LPSPI handle, which can be used for other LPSPI transactional APIs. Usually, for a specified LPSPI instance, call this API once to get the initialized handle.

Parameters

- base – LPSPI peripheral address.
- handle – LPSPI handle pointer to `lpspi_slave_handle_t`.
- callback – DSPI callback.
- userData – callback function parameter.

`status_t LPSPI_SlaveTransferNonBlocking(LPSPI_Type *base, lpspi_slave_handle_t *handle, lpspi_transfer_t *transfer)`

LPSPI slave transfer data using an interrupt method.

This function transfer data using an interrupt method. This is a non-blocking function, which returns right away. When all data is transferred, the callback function is called.

Note: The transfer data size should be integer multiples of bytesPerFrame if bytesPerFrame is less than or equal to 4. For bytesPerFrame greater than 4: The transfer data size should be equal to bytesPerFrame if the bytesPerFrame is not an integer multiple of 4. Otherwise, the transfer data size can be an integer multiple of bytesPerFrame.

Parameters

- base – LPSPI peripheral address.
- handle – pointer to `lpspi_slave_handle_t` structure which stores the transfer state.
- transfer – pointer to `lpspi_transfer_t` structure.

Returns

status of `status_t`.

`status_t LPSPI_SlaveTransferGetCount(LPSPI_Type *base, lpspi_slave_handle_t *handle, size_t *count)`

Gets the slave transfer remaining bytes.

This function gets the slave transfer remaining bytes.

Parameters

- base – LPSPI peripheral address.

- `handle` – pointer to `lpspi_slave_handle_t` structure which stores the transfer state.
- `count` – Number of bytes transferred so far by the non-blocking transaction.

Returns

status of `status_t`.

`void LPSPI_SlaveTransferAbort(LPSPI_Type *base, lpspi_slave_handle_t *handle)`

LPSPI slave aborts a transfer which uses an interrupt method.

This function aborts a transfer which uses an interrupt method.

Parameters

- `base` – LPSPI peripheral address.
- `handle` – pointer to `lpspi_slave_handle_t` structure which stores the transfer state.

`void LPSPI_SlaveTransferHandleIRQ(LPSPI_Type *base, lpspi_slave_handle_t *handle)`

LPSPI Slave IRQ handler function.

This function processes the LPSPI transmit and receives an IRQ.

Parameters

- `base` – LPSPI peripheral address.
- `handle` – pointer to `lpspi_slave_handle_t` structure which stores the transfer state.

`bool LPSPI_WaitTxFifoEmpty(LPSPI_Type *base)`

Wait for tx FIFO to be empty.

This function wait the tx fifo empty

Parameters

- `base` – LPSPI peripheral address.

Returns

true for the tx FIFO is ready, false is not.

`void LPSPI_DriverIRQHandler(uint32_t instance)`

LPSPI driver IRQ handler common entry.

This function provides the common IRQ request entry for LPSPI.

Parameters

- `instance` – LPSPI instance.

`FSL_LPSPI_DRIVER_VERSION`

LPSPI driver version.

Status for the LPSPI driver.

Values:

enumerator `kStatus_LPSPI_Busy`

LPSPI transfer is busy.

enumerator `kStatus_LPSPI_Error`

LPSPI driver error.

enumerator `kStatus_LPSPI_Idle`

LPSPI is idle.

enumerator kStatus_LPSPi_OutOfRange
LPSPi transfer out Of range.

enumerator kStatus_LPSPi_Timeout
LPSPi timeout polling status flags.

enum _lpspi_flags

LPSPi status flags in SPIx_SR register.

Values:

enumerator kLPSPi_TxDataRequestFlag
Transmit data flag

enumerator kLPSPi_RxDataReadyFlag
Receive data flag

enumerator kLPSPi_WordCompleteFlag
Word Complete flag

enumerator kLPSPi_FrameCompleteFlag
Frame Complete flag

enumerator kLPSPi_TransferCompleteFlag
Transfer Complete flag

enumerator kLPSPi_TransmitErrorFlag
Transmit Error flag (FIFO underrun)

enumerator kLPSPi_ReceiveErrorFlag
Receive Error flag (FIFO overrun)

enumerator kLPSPi_DataMatchFlag
Data Match flag

enumerator kLPSPi_ModuleBusyFlag
Module Busy flag

enumerator kLPSPi_AllStatusFlag
Used for clearing all w1c status flags

enum _lpspi_interrupt_enable

LPSPi interrupt source.

Values:

enumerator kLPSPi_TxInterruptEnable
Transmit data interrupt enable

enumerator kLPSPi_RxInterruptEnable
Receive data interrupt enable

enumerator kLPSPi_WordCompleteInterruptEnable
Word complete interrupt enable

enumerator kLPSPi_FrameCompleteInterruptEnable
Frame complete interrupt enable

enumerator kLPSPi_TransferCompleteInterruptEnable
Transfer complete interrupt enable

enumerator kLPSPi_TransmitErrorInterruptEnable
Transmit error interrupt enable(FIFO underrun)

enumerator kLPSPI_ReceiveErrorInterruptEnable
Receive Error interrupt enable (FIFO overrun)

enumerator kLPSPI_DataMatchInterruptEnable
Data Match interrupt enable

enumerator kLPSPI_AllInterruptEnable
All above interrupts enable.

enum _lpspi_dma_enable
LPSPI DMA source.

Values:

enumerator kLPSPI_TxDmaEnable
Transmit data DMA enable

enumerator kLPSPI_RxDmaEnable
Receive data DMA enable

enum _lpspi_master_slave_mode
LPSPI master or slave mode configuration.

Values:

enumerator kLPSPI_Master
LPSPI peripheral operates in master mode.

enumerator kLPSPI_Slave
LPSPI peripheral operates in slave mode.

enum _lpspi_which_pcs_config
LPSPI Peripheral Chip Select (PCS) configuration (which PCS to configure).

Values:

enumerator kLPSPI_Pcs0
PCS[0]

enumerator kLPSPI_Pcs1
PCS[1]

enumerator kLPSPI_Pcs2
PCS[2]

enumerator kLPSPI_Pcs3
PCS[3]

enum _lpspi_pcs_polarity_config
LPSPI Peripheral Chip Select (PCS) Polarity configuration.

Values:

enumerator kLPSPI_PcsActiveHigh
PCS Active High (idles low)

enumerator kLPSPI_PcsActiveLow
PCS Active Low (idles high)

enum _lpspi_pcs_polarity
LPSPI Peripheral Chip Select (PCS) Polarity.

Values:

enumerator kLPSPi_Pcs0ActiveLow
Pcs0 Active Low (idles high).

enumerator kLPSPi_Pcs1ActiveLow
Pcs1 Active Low (idles high).

enumerator kLPSPi_Pcs2ActiveLow
Pcs2 Active Low (idles high).

enumerator kLPSPi_Pcs3ActiveLow
Pcs3 Active Low (idles high).

enumerator kLPSPi_PcsAllActiveLow
Pcs0 to Pcs5 Active Low (idles high).

enum _lpspi_clock_polarity
LPSPi clock polarity configuration.

Values:

enumerator kLPSPi_ClockPolarityActiveHigh
CPOL=0. Active-high LPSPi clock (idles low)

enumerator kLPSPi_ClockPolarityActiveLow
CPOL=1. Active-low LPSPi clock (idles high)

enum _lpspi_clock_phase
LPSPi clock phase configuration.

Values:

enumerator kLPSPi_ClockPhaseFirstEdge
CPHA=0. Data is captured on the leading edge of the SCK and changed on the following edge.

enumerator kLPSPi_ClockPhaseSecondEdge
CPHA=1. Data is changed on the leading edge of the SCK and captured on the following edge.

enum _lpspi_shift_direction
LPSPi data shifter direction options.

Values:

enumerator kLPSPi_MsbFirst
Data transfers start with most significant bit.

enumerator kLPSPi_LsbFirst
Data transfers start with least significant bit.

enum _lpspi_host_request_select
LPSPi Host Request select configuration.

Values:

enumerator kLPSPi_HostReqExtPin
Host Request is an ext pin.

enumerator kLPSPi_HostReqInternalTrigger
Host Request is an internal trigger.

enum _lpspi_match_config
LPSPi Match configuration options.

Values:

enumerator kLPSI_MatchDisabled

LPSPI Match Disabled.

enumerator kLPSI_1stWordEqualsM0orM1

LPSPI Match Enabled.

enumerator kLPSI_AnyWordEqualsM0orM1

LPSPI Match Enabled.

enumerator kLPSI_1stWordEqualsM0and2ndWordEqualsM1

LPSPI Match Enabled.

enumerator kLPSI_AnyWordEqualsM0andNxtWordEqualsM1

LPSPI Match Enabled.

enumerator kLPSI_1stWordAndM1EqualsM0andM1

LPSPI Match Enabled.

enumerator kLPSI_AnyWordAndM1EqualsM0andM1

LPSPI Match Enabled.

enum _lpspi_pin_config

LPSPI pin (SDO and SDI) configuration.

Values:

enumerator kLPSPi_SdiInSdoOut

LPSPI SDI input, SDO output.

enumerator kLPSPi_SdiInSdiOut

LPSPI SDI input, SDI output.

enumerator kLPSPi_SdoInSdoOut

LPSPI SDO input, SDO output.

enumerator kLPSPi_SdoInSdiOut

LPSPI SDO input, SDI output.

enum _lpspi_data_out_config

LPSPI data output configuration.

Values:

enumerator kLpspiDataOutRetained

Data out retains last value when chip select is de-asserted

enumerator kLpspiDataOutTristate

Data out is tristated when chip select is de-asserted

enum _lpspi_pcs_function_config

LPSPI cs function configuration.

Values:

enumerator kLPSPi_PcsAsCs

PCS pin select as cs function

enumerator kLPSPi_PcsAsData

PCS pin select as date function

enum _lpspi_transfer_width

LPSPI transfer width configuration.

Values:

enumerator kLPSPI_SingleBitXfer

1-bit shift at a time, data out on SDO, in on SDI (normal mode)

enumerator kLPSPI_TwoBitXfer

2-bits shift out on SDO/SDI and in on SDO/SDI

enumerator kLPSPI_FourBitXfer

4-bits shift out on SDO/SDI/PCS[3:2] and in on SDO/SDI/PCS[3:2]

enum _lpspi_delay_type

LPSPI delay type selection.

Values:

enumerator kLPSPI_PcsToSck

PCS-to-SCK delay.

enumerator kLPSPI_LastSckToPcs

Last SCK edge to PCS delay.

enumerator kLPSPI_BetweenTransfer

Delay between transfers.

enum _lpspi_transfer_config_flag_for_master

Use this enumeration for LPSPI master transfer configFlags.

Values:

enumerator kLPSPI_MasterPcs0

LPSPI master PCS shift macro , internal used. LPSPI master transfer use PCS0 signal

enumerator kLPSPI_MasterPcs1

LPSPI master PCS shift macro , internal used. LPSPI master transfer use PCS1 signal

enumerator kLPSPI_MasterPcs2

LPSPI master PCS shift macro , internal used. LPSPI master transfer use PCS2 signal

enumerator kLPSPI_MasterPcs3

LPSPI master PCS shift macro , internal used. LPSPI master transfer use PCS3 signal

enumerator kLPSPI_MasterWidth1

LPSPI master width shift macro, internal used LPSPI master transfer 1bit

enumerator kLPSPI_MasterWidth2

LPSPI master width shift macro, internal used LPSPI master transfer 2bit

enumerator kLPSPI_MasterWidth4

LPSPI master width shift macro, internal used LPSPI master transfer 4bit

enumerator kLPSPI_MasterPcsContinuous

Is PCS signal continuous

enumerator kLPSPI_MasterByteSwap

Is master swap the byte. For example, when want to send data 1 2 3 4 5 6 7 8 (suppose you set lpspi_shift_direction_t to MSB).

- i. If you set bitPerFrame = 8 , no matter the kLPSPI_MasterByteSwapyou flag is used or not, the waveform is 1 2 3 4 5 6 7 8.
- ii. If you set bitPerFrame = 16 : (1) the waveform is 2 1 4 3 6 5 8 7 if you do not use the kLPSPI_MasterByteSwap flag. (2) the waveform is 1 2 3 4 5 6 7 8 if you use the kLPSPI_MasterByteSwap flag.

- iii. If you set bitPerFrame = 32 : (1) the waveform is 4 3 2 1 8 7 6 5 if you do not use the kLPSPi_MasterByteSwap flag. (2) the waveform is 1 2 3 4 5 6 7 8 if you use the kLPSPi_MasterByteSwap flag.

enum _lpspi_transfer_config_flag_for_slave

Use this enumeration for LPSPi slave transfer configFlags.

Values:

enumerator kLPSPi_SlavePcs0

LPSPi slave PCS shift macro , internal used. LPSPi slave transfer use PCS0 signal

enumerator kLPSPi_SlavePcs1

LPSPi slave PCS shift macro , internal used. LPSPi slave transfer use PCS1 signal

enumerator kLPSPi_SlavePcs2

LPSPi slave PCS shift macro , internal used. LPSPi slave transfer use PCS2 signal

enumerator kLPSPi_SlavePcs3

LPSPi slave PCS shift macro , internal used. LPSPi slave transfer use PCS3 signal

enumerator kLPSPi_SlaveByteSwap

Is slave swap the byte. For example, when want to send data 1 2 3 4 5 6 7 8 (suppose you set lpspi_shift_direction_t to MSB).

- i. If you set bitPerFrame = 8 , no matter the kLPSPi_SlaveByteSwap flag is used or not, the waveform is 1 2 3 4 5 6 7 8.
- ii. If you set bitPerFrame = 16 : (1) the waveform is 2 1 4 3 6 5 8 7 if you do not use the kLPSPi_SlaveByteSwap flag. (2) the waveform is 1 2 3 4 5 6 7 8 if you use the kLPSPi_SlaveByteSwap flag.
- iii. If you set bitPerFrame = 32 : (1) the waveform is 4 3 2 1 8 7 6 5 if you do not use the kLPSPi_SlaveByteSwap flag. (2) the waveform is 1 2 3 4 5 6 7 8 if you use the kLPSPi_SlaveByteSwap flag.

enum _lpspi_transfer_state

LPSPi transfer state, which is used for LPSPi transactional API state machine.

Values:

enumerator kLPSPi_Idle

Nothing in the transmitter/receiver.

enumerator kLPSPi_Busy

Transfer queue is not finished.

enumerator kLPSPi_Error

Transfer error.

typedef enum _lpspi_master_slave_mode lpspi_master_slave_mode_t

LPSPi master or slave mode configuration.

typedef enum _lpspi_which_pcs_config lpspi_which_pcs_t

LPSPi Peripheral Chip Select (PCS) configuration (which PCS to configure).

typedef enum _lpspi_pcs_polarity_config lpspi_pcs_polarity_config_t

LPSPi Peripheral Chip Select (PCS) Polarity configuration.

typedef enum _lpspi_clock_polarity lpspi_clock_polarity_t

LPSPi clock polarity configuration.

typedef enum _lpspi_clock_phase lpspi_clock_phase_t

LPSPi clock phase configuration.

typedef enum *_lpspi_shift_direction* lpspi_shift_direction_t

LPSPI data shifter direction options.

typedef enum *_lpspi_host_request_select* lpspi_host_request_select_t

LPSPI Host Request select configuration.

typedef enum *_lpspi_match_config* lpspi_match_config_t

LPSPI Match configuration options.

typedef enum *_lpspi_pin_config* lpspi_pin_config_t

LPSPI pin (SDO and SDI) configuration.

typedef enum *_lpspi_data_out_config* lpspi_data_out_config_t

LPSPI data output configuration.

typedef enum *_lpspi_pcs_function_config* lpspi_pcs_function_config_t

LPSPI cs function configuration.

typedef enum *_lpspi_transfer_width* lpspi_transfer_width_t

LPSPI transfer width configuration.

typedef enum *_lpspi_delay_type* lpspi_delay_type_t

LPSPI delay type selection.

typedef struct *_lpspi_master_config* lpspi_master_config_t

LPSPI master configuration structure.

typedef struct *_lpspi_slave_config* lpspi_slave_config_t

LPSPI slave configuration structure.

typedef struct *_lpspi_master_handle* lpspi_master_handle_t

Forward declaration of the *_lpspi_master_handle* typedefs.

typedef struct *_lpspi_slave_handle* lpspi_slave_handle_t

Forward declaration of the *_lpspi_slave_handle* typedefs.

typedef void (*lpspi_master_transfer_callback_t)(LP_SPI_Type *base, *lpspi_master_handle_t* *handle, *status_t* status, void *userData)

Master completion callback function pointer type.

Param base

LPSPI peripheral address.

Param handle

Pointer to the handle for the LP SPI master.

Param status

Success or error code describing whether the transfer is completed.

Param userData

Arbitrary pointer-dataSized value passed from the application.

typedef void (*lpspi_slave_transfer_callback_t)(LP_SPI_Type *base, *lpspi_slave_handle_t* *handle, *status_t* status, void *userData)

Slave completion callback function pointer type.

Param base

LPSPI peripheral address.

Param handle

Pointer to the handle for the LP SPI slave.

Param status

Success or error code describing whether the transfer is completed.

Param userData

Arbitrary pointer-dataSized value passed from the application.

```
typedef struct _lpspi_transfer lpspi_transfer_t
    LPSPI master/slave transfer structure.

volatile uint8_t g_lpspiDummyData[]
    Global variable for dummy data value setting.

LPSPI_DUMMY_DATA
    LPSPI dummy data if no Tx data.
    Dummy data used for tx if there is not txData.

SPI_RETRY_TIMES
    Retry times for waiting flag.

LPSPI_MASTER_PCS_SHIFT
    LPSPI master PCS shift macro , internal used.

LPSPI_MASTER_PCS_MASK
    LPSPI master PCS shift macro , internal used.

LPSPI_MASTER_WIDTH_SHIFT
    LPSPI master width shift macro, internal used

LPSPI_MASTER_WIDTH_MASK
    LPSPI master width shift mask, internal used

LPSPI_SLAVE_PCS_SHIFT
    LPSPI slave PCS shift macro , internal used.

LPSPI_SLAVE_PCS_MASK
    LPSPI slave PCS shift macro , internal used.

struct _lpspi_master_config
    #include <fsl_lpspi.h> LPSPI master configuration structure.
```

Public Members

```
uint32_t baudRate
    Baud Rate for LPSPI.

uint32_t bitsPerFrame
    Bits per frame, minimum 8, maximum 4096.

lpspi_clock_polarity_t cpol
    Clock polarity.

lpspi_clock_phase_t cpha
    Clock phase.

lpspi_shift_direction_t direction
    MSB or LSB data shift direction.

uint32_t pcsToSckDelayInNanoSec
    PCS to SCK delay time in nanoseconds, setting to 0 sets the minimum delay. It sets the
    boundary value if out of range.

uint32_t lastSckToPcsDelayInNanoSec
    Last SCK to PCS delay time in nanoseconds, setting to 0 sets the minimum delay. It sets
    the boundary value if out of range.
```

uint32_t betweenTransferDelayInNanoSec

After the SCK delay time with nanoseconds, setting to 0 sets the minimum delay. It sets the boundary value if out of range.

lpspi_which_pcs_t whichPcs

Desired Peripheral Chip Select (PCS).

lpspi_pcs_polarity_config_t pcsActiveHighOrLow

Desired PCS active high or low

lpspi_pin_config_t pinCfg

Configures which pins are used for input and output data during single bit transfers.

lpspi_pcs_function_config_t pcsFunc

Configures cs pins function.

lpspi_data_out_config_t dataOutConfig

Configures if the output data is tristated between accesses (LPSPi_PCS is negated).

bool enableInputDelay

Enable master to sample the input data on a delayed SCK. This can help improve slave setup time. Refer to device data sheet for specific time length.

struct _lpspi_slave_config

#include <fsl_lpspi.h> LPSPi slave configuration structure.

Public Members

uint32_t bitsPerFrame

Bits per frame, minimum 8, maximum 4096.

lpspi_clock_polarity_t cpol

Clock polarity.

lpspi_clock_phase_t cpha

Clock phase.

lpspi_shift_direction_t direction

MSB or LSB data shift direction.

lpspi_which_pcs_t whichPcs

Desired Peripheral Chip Select (pcs)

lpspi_pcs_polarity_config_t pcsActiveHighOrLow

Desired PCS active high or low

lpspi_pin_config_t pinCfg

Configures which pins are used for input and output data during single bit transfers.

lpspi_data_out_config_t dataOutConfig

Configures if the output data is tristated between accesses (LPSPi_PCS is negated).

struct _lpspi_transfer

#include <fsl_lpspi.h> LPSPi master/slave transfer structure.

Public Members

const uint8_t *txData

Send buffer.

uint8_t *rxData

Receive buffer.

volatile size_t dataSize

Transfer bytes.

uint32_t configFlags

Transfer transfer configuration flags. Set from `_lpspi_transfer_config_flag_for_master` if the transfer is used for master or `_lpspi_transfer_config_flag_for_slave` enumeration if the transfer is used for slave.

struct _lpspi_master_handle

#include <fsl_lpspi.h> LPSPi master transfer handle structure used for transactional API.

Public Members

volatile bool isPcsContinuous

Is PCS continuous in transfer.

volatile bool writeTcrInIsr

A flag that whether should write TCR in ISR.

volatile bool isByteSwap

A flag that whether should byte swap.

volatile bool isTxMask

A flag that whether TCR[TXMSK] is set.

volatile uint16_t bytesPerFrame

Number of bytes in each frame

volatile uint16_t frameSize

Backup of TCR[FRAMESZ]

volatile uint8_t fifoSize

FIFO dataSize.

volatile uint8_t rxWatermark

Rx watermark.

volatile uint8_t bytesEachWrite

Bytes for each write TDR.

volatile uint8_t bytesEachRead

Bytes for each read RDR.

const uint8_t *volatile txData

Send buffer.

uint8_t *volatile rxData

Receive buffer.

volatile size_t txRemainingByteCount

Number of bytes remaining to send.

volatile size_t rxRemainingByteCount

Number of bytes remaining to receive.

volatile uint32_t writeRegRemainingTimes

Write TDR register remaining times.

`volatile uint32_t readRegRemainingTimes`
Read RDR register remaining times.

`uint32_t totalByteCount`
Number of transfer bytes

`uint32_t txBuffIfNull`
Used if the txData is NULL.

`volatile uint8_t state`
LPSPI transfer state , `_lpspi_transfer_state`.

`lpspi_master_transfer_callback_t callback`
Completion callback.

`void *userData`
Callback user data.

`struct _lpspi_slave_handle`
#include <fsl_lpspi.h> LPSPI slave transfer handle structure used for transactional API.

Public Members

`volatile bool isByteSwap`
A flag that whether should byte swap.

`volatile uint8_t fifoSize`
FIFO dataSize.

`volatile uint8_t rxWatermark`
Rx watermark.

`volatile uint8_t bytesEachWrite`
Bytes for each write TDR.

`volatile uint8_t bytesEachRead`
Bytes for each read RDR.

`const uint8_t *volatile txData`
Send buffer.

`uint8_t *volatile rxData`
Receive buffer.

`volatile size_t txRemainingByteCount`
Number of bytes remaining to send.

`volatile size_t rxRemainingByteCount`
Number of bytes remaining to receive.

`volatile uint32_t writeRegRemainingTimes`
Write TDR register remaining times.

`volatile uint32_t readRegRemainingTimes`
Read RDR register remaining times.

`uint32_t totalByteCount`
Number of transfer bytes

`volatile uint8_t state`
LPSPI transfer state , `_lpspi_transfer_state`.

volatile uint32_t errorCount
 Error count for slave transfer.

lpspi_slave_transfer_callback_t callback
 Completion callback.

void *userData
 Callback user data.

2.38 LPSPI eDMA Driver

FSL_LPSPI_EDMA_DRIVER_VERSION

LPSPI EDMA driver version.

DMA_MAX_TRANSFER_COUNT

DMA max transfer size.

typedef struct *lpspi_master_edma_handle* lpspi_master_edma_handle_t
 Forward declaration of the *lpspi_master_edma_handle* typedefs.

typedef struct *lpspi_slave_edma_handle* lpspi_slave_edma_handle_t
 Forward declaration of the *lpspi_slave_edma_handle* typedefs.

typedef void (*lpspi_master_edma_transfer_callback_t)(LPSPI_Type *base,
lpspi_master_edma_handle_t *handle, *status_t* status, void *userData)

Completion callback function pointer type.

Param base

LPSPI peripheral base address.

Param handle

Pointer to the handle for the LPSPI master.

Param status

Success or error code describing whether the transfer completed.

Param userData

Arbitrary pointer-dataSized value passed from the application.

typedef void (*lpspi_slave_edma_transfer_callback_t)(LPSPI_Type *base,
lpspi_slave_edma_handle_t *handle, *status_t* status, void *userData)

Completion callback function pointer type.

Param base

LPSPI peripheral base address.

Param handle

Pointer to the handle for the LPSPI slave.

Param status

Success or error code describing whether the transfer completed.

Param userData

Arbitrary pointer-dataSized value passed from the application.

void LPSPI_MasterTransferCreateHandleEDMA(LPSPI_Type *base, *lpspi_master_edma_handle_t*
 *handle, *lpspi_master_edma_transfer_callback_t*
 callback, void *userData, *edma_handle_t*
 *edmaRxRegToRxDataHandle, *edma_handle_t*
 *edmaTxDataToTxRegHandle)

Initializes the LPSPI master eDMA handle.

This function initializes the LPSPI eDMA handle which can be used for other LPSPI transactional APIs. Usually, for a specified LPSPI instance, call this API once to get the initialized handle.

Note that the LPSPI eDMA has a separated (Rx and Tx as two sources) or shared (Rx and Tx are the same source) DMA request source. (1) For a separated DMA request source, enable and set the Rx DMAMUX source for `edmaRxRegToRxDataHandle` and Tx DMAMUX source for `edmaTxDataToTxRegHandle`. (2) For a shared DMA request source, enable and set the Rx/Tx DMAMUX source for `edmaRxRegToRxDataHandle`.

Parameters

- `base` – LPSPI peripheral base address.
- `handle` – LPSPI handle pointer to `lpspi_master_edma_handle_t`.
- `callback` – LPSPI callback.
- `userData` – callback function parameter.
- `edmaRxRegToRxDataHandle` – `edmaRxRegToRxDataHandle` pointer to `edma_handle_t`.
- `edmaTxDataToTxRegHandle` – `edmaTxDataToTxRegHandle` pointer to `edma_handle_t`.

`status_t` LPSPI_MasterTransferEDMA(LPSPI_Type *base, *lpspi_master_edma_handle_t* *handle, *lpspi_transfer_t* *transfer)

LPSPI master transfer data using eDMA.

This function transfers data using eDMA. This is a non-blocking function, which returns right away. When all data is transferred, the callback function is called.

Note: The transfer data size should be an integer multiple of `bytesPerFrame` if `bytesPerFrame` is less than or equal to 4. For `bytesPerFrame` greater than 4: The transfer data size should be equal to `bytesPerFrame` if the `bytesPerFrame` is not an integer multiple of 4. Otherwise, the transfer data size can be an integer multiple of `bytesPerFrame`.

Parameters

- `base` – LPSPI peripheral base address.
- `handle` – pointer to `lpspi_master_edma_handle_t` structure which stores the transfer state.
- `transfer` – pointer to `lpspi_transfer_t` structure.

Returns

status of `status_t`.

`status_t` LPSPI_MasterTransferPrepareEDMALite(LPSPI_Type *base, *lpspi_master_edma_handle_t* *handle, `uint32_t` configFlags)

LPSPI master config transfer parameter while using eDMA.

This function is preparing to transfer data using eDMA, work with LPSPI_MasterTransferEDMALite.

Parameters

- `base` – LPSPI peripheral base address.
- `handle` – pointer to `lpspi_master_edma_handle_t` structure which stores the transfer state.
- `configFlags` – transfer configuration flags. `_lpspi_transfer_config_flag_for_master`.

Return values

- `kStatus_Success` – Execution successfully.
- `kStatus_LPSPi_Busy` – The LPSPi device is busy.

Returns

Indicates whether LPSPi master transfer was successful or not.

status_t LPSPi_MasterTransferEDMALite(LPSPi_Type *base, *lpspi_master_edma_handle_t* *handle, *lpspi_transfer_t* *transfer)

LPSPi master transfer data using eDMA without configs.

This function transfers data using eDMA. This is a non-blocking function, which returns right away. When all data is transferred, the callback function is called.

Note: This API is only for transfer through DMA without configuration. Before calling this API, you must call LPSPi_MasterTransferPrepareEDMALite to configure it once. The transfer data size should be an integer multiple of bytesPerFrame if bytesPerFrame is less than or equal to 4. For bytesPerFrame greater than 4: The transfer data size should be equal to bytesPerFrame if the bytesPerFrame is not an integer multiple of 4. Otherwise, the transfer data size can be an integer multiple of bytesPerFrame.

Parameters

- *base* – LPSPi peripheral base address.
- *handle* – pointer to *lpspi_master_edma_handle_t* structure which stores the transfer state.
- *transfer* – pointer to *lpspi_transfer_t* structure, config field is not used.

Return values

- `kStatus_Success` – Execution successfully.
- `kStatus_LPSPi_Busy` – The LPSPi device is busy.
- `kStatus_InvalidArgument` – The transfer structure is invalid.

Returns

Indicates whether LPSPi master transfer was successful or not.

void LPSPi_MasterTransferAbortEDMA(LPSPi_Type *base, *lpspi_master_edma_handle_t* *handle)

LPSPi master aborts a transfer which is using eDMA.

This function aborts a transfer which is using eDMA.

Parameters

- *base* – LPSPi peripheral base address.
- *handle* – pointer to *lpspi_master_edma_handle_t* structure which stores the transfer state.

status_t LPSPi_MasterTransferGetCountEDMA(LPSPi_Type *base, *lpspi_master_edma_handle_t* *handle, *size_t* *count)

Gets the master eDMA transfer remaining bytes.

This function gets the master eDMA transfer remaining bytes.

Parameters

- *base* – LPSPi peripheral base address.
- *handle* – pointer to *lpspi_master_edma_handle_t* structure which stores the transfer state.
- *count* – Number of bytes transferred so far by the EDMA transaction.

Returns

status of status_t.

```
void LPSPI_SlaveTransferCreateHandleEDMA(LPSPI_Type *base, lpspi_slave_edma_handle_t
                                         *handle, lpspi_slave_edma_transfer_callback_t
                                         callback, void *userData, edma_handle_t
                                         *edmaRxRegToRxDataHandle, edma_handle_t
                                         *edmaTxDataToTxRegHandle)
```

Initializes the LPSPI slave eDMA handle.

This function initializes the LPSPI eDMA handle which can be used for other LPSPI transactional APIs. Usually, for a specified LPSPI instance, call this API once to get the initialized handle.

Note that LPSPI eDMA has a separated (Rx and Tx as two sources) or shared (Rx and Tx as the same source) DMA request source.

(1) For a separated DMA request source, enable and set the Rx DMAMUX source for edmaRxRegToRxDataHandle and Tx DMAMUX source for edmaTxDataToTxRegHandle. (2) For a shared DMA request source, enable and set the Rx/Rx DMAMUX source for edmaRxRegToRxDataHandle .

Parameters

- base – LPSPI peripheral base address.
- handle – LPSPI handle pointer to lpspi_slave_edma_handle_t.
- callback – LPSPI callback.
- userData – callback function parameter.
- edmaRxRegToRxDataHandle – edmaRxRegToRxDataHandle pointer to edma_handle_t.
- edmaTxDataToTxRegHandle – edmaTxDataToTxRegHandle pointer to edma_handle_t.

```
status_t LPSPI_SlaveTransferEDMA(LPSPI_Type *base, lpspi_slave_edma_handle_t *handle,
                                  lpspi_transfer_t *transfer)
```

LPSPI slave transfers data using eDMA.

This function transfers data using eDMA. This is a non-blocking function, which return right away. When all data is transferred, the callback function is called.

Note: The transfer data size should be an integer multiple of bytesPerFrame if bytesPerFrame is less than or equal to 4. For bytesPerFrame greater than 4: The transfer data size should be equal to bytesPerFrame if the bytesPerFrame is not an integer multiple of 4. Otherwise, the transfer data size can be an integer multiple of bytesPerFrame.

Parameters

- base – LPSPI peripheral base address.
- handle – pointer to lpspi_slave_edma_handle_t structure which stores the transfer state.
- transfer – pointer to lpspi_transfer_t structure.

Returns

status of status_t.

```
void LPSPI_SlaveTransferAbortEDMA(LPSPI_Type *base, lpspi_slave_edma_handle_t *handle)
LPSPI slave aborts a transfer which is using eDMA.
```

This function aborts a transfer which is using eDMA.

Parameters

- base – LPSPI peripheral base address.
- handle – pointer to `lpspi_slave_edma_handle_t` structure which stores the transfer state.

`status_t` LPSPI_SlaveTransferGetCountEDMA(LPSPI_Type *base, *lpspi_slave_edma_handle_t* *handle, size_t *count)

Gets the slave eDMA transfer remaining bytes.

This function gets the slave eDMA transfer remaining bytes.

Parameters

- base – LPSPI peripheral base address.
- handle – pointer to `lpspi_slave_edma_handle_t` structure which stores the transfer state.
- count – Number of bytes transferred so far by the eDMA transaction.

Returns

status of `status_t`.

struct `_lpspi_master_edma_handle`

#include <fsl_lpspi_edma.h> LPSPI master eDMA transfer handle structure used for transactional API.

Public Members

volatile bool `isPcsContinuous`

Is PCS continuous in transfer.

volatile bool `isByteSwap`

A flag that whether should byte swap.

volatile uint8_t `fifoSize`

FIFO dataSize.

volatile uint8_t `rxWatermark`

Rx watermark.

volatile uint8_t `bytesEachWrite`

Bytes for each write TDR.

volatile uint8_t `bytesEachRead`

Bytes for each read RDR.

volatile uint8_t `bytesLastRead`

Bytes for last read RDR.

volatile bool `isThereExtraRxBytes`

Is there extra RX byte.

const uint8_t *volatile `txData`

Send buffer.

uint8_t *volatile `rxData`

Receive buffer.

volatile size_t `txRemainingByteCount`

Number of bytes remaining to send.

volatile size_t `rxRemainingByteCount`

Number of bytes remaining to receive.

`volatile uint32_t writeRegRemainingTimes`
Write TDR register remaining times.

`volatile uint32_t readRegRemainingTimes`
Read RDR register remaining times.

`uint32_t totalByteCount`
Number of transfer bytes

`edma_tcd_t *lastTimeTCD`
Pointer to the lastTime TCD

`bool isMultiDMATransmit`
Is there multi DMA transmit

`volatile uint8_t dmaTransmitTime`
DMA Transfer times.

`uint32_t lastTimeDataBytes`
DMA transmit last Time data Bytes

`uint32_t dataBytesEveryTime`
Bytes in a time for DMA transfer, default is DMA_MAX_TRANSFER_COUNT

`edma_transfer_config_t transferConfigRx`
Config of DMA rx channel.

`edma_transfer_config_t transferConfigTx`
Config of DMA tx channel.

`uint32_t txBuffIfNull`
Used if there is not txData for DMA purpose.

`uint32_t rxBuffIfNull`
Used if there is not rxData for DMA purpose.

`uint32_t transmitCommand`
Used to write TCR for DMA purpose.

`volatile uint8_t state`
LPSPI transfer state , `_lpspi_transfer_state`.

`uint8_t nbytes`
eDMA minor byte transfer count initially configured.

`lpspi_master_edma_transfer_callback_t callback`
Completion callback.

`void *userData`
Callback user data.

`edma_handle_t *edmaRxRegToRxDataHandle`
edma_handle_t handle point used for RxReg to RxData buff

`edma_handle_t *edmaTxDataToTxRegHandle`
edma_handle_t handle point used for TxData to TxReg buff

`edma_tcd_t lpspiSoftwareTCD[3]`
SoftwareTCD, internal used

`struct _lpspi_slave_edma_handle`
`#include <fsl_lpspi_edma.h>` LPSPI slave eDMA transfer handle structure used for transactional API.

Public Members

volatile bool isByteSwap

A flag that whether should byte swap.

volatile uint8_t fifoSize

FIFO dataSize.

volatile uint8_t rxWatermark

Rx watermark.

volatile uint8_t bytesEachWrite

Bytes for each write TDR.

volatile uint8_t bytesEachRead

Bytes for each read RDR.

volatile uint8_t bytesLastRead

Bytes for last read RDR.

volatile bool isThereExtraRxBytes

Is there extra RX byte.

uint8_t nbytes

eDMA minor byte transfer count initially configured.

const uint8_t *volatile txData

Send buffer.

uint8_t *volatile rxData

Receive buffer.

volatile size_t txRemainingByteCount

Number of bytes remaining to send.

volatile size_t rxRemainingByteCount

Number of bytes remaining to receive.

volatile uint32_t writeRegRemainingTimes

Write TDR register remaining times.

volatile uint32_t readRegRemainingTimes

Read RDR register remaining times.

uint32_t totalByteCount

Number of transfer bytes

uint32_t txBuffIfNull

Used if there is not txData for DMA purpose.

uint32_t rxBuffIfNull

Used if there is not rxData for DMA purpose.

volatile uint8_t state

LPSPi transfer state.

uint32_t errorCount

Error count for slave transfer.

lpspi_slave_edma_transfer_callback_t callback

Completion callback.

`void *userData`

Callback user data.

`edma_handle_t *edmaRxRegToRxDataHandle`

`edma_handle_t` handle point used for RxReg to RxData buff

`edma_handle_t *edmaTxDataToTxRegHandle`

`edma_handle_t` handle point used for TxData to TxReg

`edma_tcd_t` `lpspiSoftwareTCD[2]`

SoftwareTCD, internal used

2.39 LPTMR: Low-Power Timer

`void LPTMR_Init(LPTMR_Type *base, const lptmr_config_t *config)`

Ungates the LPTMR clock and configures the peripheral for a basic operation.

Note: This API should be called at the beginning of the application using the LPTMR driver.

Parameters

- `base` – LPTMR peripheral base address
- `config` – A pointer to the LPTMR configuration structure.

`void LPTMR_Deinit(LPTMR_Type *base)`

Gates the LPTMR clock.

Parameters

- `base` – LPTMR peripheral base address

`void LPTMR_GetDefaultConfig(lptmr_config_t *config)`

Fills in the LPTMR configuration structure with default settings.

The default values are as follows.

```
config->timerMode = kLPTMR_TimerModeTimeCounter;
config->pinSelect = kLPTMR_PinSelectInput_0;
config->pinPolarity = kLPTMR_PinPolarityActiveHigh;
config->enableFreeRunning = false;
config->bypassPrescaler = true;
config->prescalerClockSource = kLPTMR_PrescalerClock_1;
config->value = kLPTMR_Prescale_Glitch_0;
```

Parameters

- `config` – A pointer to the LPTMR configuration structure.

`static inline void LPTMR_EnableInterrupts(LPTMR_Type *base, uint32_t mask)`

Enables the selected LPTMR interrupts.

Parameters

- `base` – LPTMR peripheral base address
- `mask` – The interrupts to enable. This is a logical OR of members of the enumeration `lptmr_interrupt_enable_t`

```
static inline void LPTMR_DisableInterrupts(LPTMR_Type *base, uint32_t mask)
```

Disables the selected LPTMR interrupts.

Parameters

- base – LPTMR peripheral base address
- mask – The interrupts to disable. This is a logical OR of members of the enumeration `lptmr_interrupt_enable_t`.

```
static inline uint32_t LPTMR_GetEnabledInterrupts(LPTMR_Type *base)
```

Gets the enabled LPTMR interrupts.

Parameters

- base – LPTMR peripheral base address

Returns

The enabled interrupts. This is the logical OR of members of the enumeration `lptmr_interrupt_enable_t`

```
static inline uint32_t LPTMR_GetStatusFlags(LPTMR_Type *base)
```

Gets the LPTMR status flags.

Parameters

- base – LPTMR peripheral base address

Returns

The status flags. This is the logical OR of members of the enumeration `lptmr_status_flags_t`

```
static inline void LPTMR_ClearStatusFlags(LPTMR_Type *base, uint32_t mask)
```

Clears the LPTMR status flags.

Parameters

- base – LPTMR peripheral base address
- mask – The status flags to clear. This is a logical OR of members of the enumeration `lptmr_status_flags_t`.

```
static inline void LPTMR_SetTimerPeriod(LPTMR_Type *base, uint32_t ticks)
```

Sets the timer period in units of count.

Timers counts from 0 until it equals the count value set here. The count value is written to the CMR register.

Note:

- a. The TCF flag is set with the CNR equals the count provided here and then increments.
 - b. Call the utility macros provided in the `fsl_common.h` to convert to ticks.
-

Parameters

- base – LPTMR peripheral base address
- ticks – A timer period in units of ticks

```
static inline uint32_t LPTMR_GetCurrentTimerCount(LPTMR_Type *base)
```

Reads the current timer counting value.

This function returns the real-time timer counting value in a range from 0 to a timer period.

Note: Call the utility macros provided in the `fsl_common.h` to convert ticks to usec or msec.

Parameters

- base – LPTMR peripheral base address

Returns

The current counter value in ticks

static inline void LPTMR_StartTimer(LPTMR_Type *base)

Starts the timer.

After calling this function, the timer counts up to the CMR register value. Each time the timer reaches the CMR value and then increments, it generates a trigger pulse and sets the timeout interrupt flag. An interrupt is also triggered if the timer interrupt is enabled.

Parameters

- base – LPTMR peripheral base address

static inline void LPTMR_StopTimer(LPTMR_Type *base)

Stops the timer.

This function stops the timer and resets the timer's counter register.

Parameters

- base – LPTMR peripheral base address

FSL_LPTMR_DRIVER_VERSION

Driver Version

enum _lptmr_pin_select

LPTMR pin selection used in pulse counter mode.

Values:

enumerator kLPTMR_PinSelectInput_0

Pulse counter input 0 is selected

enumerator kLPTMR_PinSelectInput_1

Pulse counter input 1 is selected

enumerator kLPTMR_PinSelectInput_2

Pulse counter input 2 is selected

enumerator kLPTMR_PinSelectInput_3

Pulse counter input 3 is selected

enum _lptmr_pin_polarity

LPTMR pin polarity used in pulse counter mode.

Values:

enumerator kLPTMR_PinPolarityActiveHigh

Pulse Counter input source is active-high

enumerator kLPTMR_PinPolarityActiveLow

Pulse Counter input source is active-low

enum _lptmr_timer_mode

LPTMR timer mode selection.

Values:

enumerator kLPTMR_TimerModeTimeCounter

Time Counter mode

enumerator kLPTMR_TimerModePulseCounter
Pulse Counter mode

enum _lptmr_prescaler_glitch_value
LPTMR prescaler/glitch filter values.

Values:

enumerator kLPTMR_Prescale_Glitch_0
Prescaler divide 2, glitch filter does not support this setting

enumerator kLPTMR_Prescale_Glitch_1
Prescaler divide 4, glitch filter 2

enumerator kLPTMR_Prescale_Glitch_2
Prescaler divide 8, glitch filter 4

enumerator kLPTMR_Prescale_Glitch_3
Prescaler divide 16, glitch filter 8

enumerator kLPTMR_Prescale_Glitch_4
Prescaler divide 32, glitch filter 16

enumerator kLPTMR_Prescale_Glitch_5
Prescaler divide 64, glitch filter 32

enumerator kLPTMR_Prescale_Glitch_6
Prescaler divide 128, glitch filter 64

enumerator kLPTMR_Prescale_Glitch_7
Prescaler divide 256, glitch filter 128

enumerator kLPTMR_Prescale_Glitch_8
Prescaler divide 512, glitch filter 256

enumerator kLPTMR_Prescale_Glitch_9
Prescaler divide 1024, glitch filter 512

enumerator kLPTMR_Prescale_Glitch_10
Prescaler divide 2048 glitch filter 1024

enumerator kLPTMR_Prescale_Glitch_11
Prescaler divide 4096, glitch filter 2048

enumerator kLPTMR_Prescale_Glitch_12
Prescaler divide 8192, glitch filter 4096

enumerator kLPTMR_Prescale_Glitch_13
Prescaler divide 16384, glitch filter 8192

enumerator kLPTMR_Prescale_Glitch_14
Prescaler divide 32768, glitch filter 16384

enumerator kLPTMR_Prescale_Glitch_15
Prescaler divide 65536, glitch filter 32768

enum _lptmr_prescaler_clock_select
LPTMR prescaler/glitch filter clock select.

Note: Clock connections are SoC-specific

Values:

enumerator kLPTMR_PrescalerClock_0

Prescaler/glitch filter clock 0 selected.

enumerator kLPTMR_PrescalerClock_1

Prescaler/glitch filter clock 1 selected.

enumerator kLPTMR_PrescalerClock_2

Prescaler/glitch filter clock 2 selected.

enumerator kLPTMR_PrescalerClock_3

Prescaler/glitch filter clock 3 selected.

enum _lptmr_interrupt_enable

List of the LPTMR interrupts.

Values:

enumerator kLPTMR_TimerInterruptEnable

Timer interrupt enable

enum _lptmr_status_flags

List of the LPTMR status flags.

Values:

enumerator kLPTMR_TimerCompareFlag

Timer compare flag

typedef enum _lptmr_pin_select lptmr_pin_select_t

LPTMR pin selection used in pulse counter mode.

typedef enum _lptmr_pin_polarity lptmr_pin_polarity_t

LPTMR pin polarity used in pulse counter mode.

typedef enum _lptmr_timer_mode lptmr_timer_mode_t

LPTMR timer mode selection.

typedef enum _lptmr_prescaler_glitch_value lptmr_prescaler_glitch_value_t

LPTMR prescaler/glitch filter values.

typedef enum _lptmr_prescaler_clock_select lptmr_prescaler_clock_select_t

LPTMR prescaler/glitch filter clock select.

Note: Clock connections are SoC-specific

typedef enum _lptmr_interrupt_enable lptmr_interrupt_enable_t

List of the LPTMR interrupts.

typedef enum _lptmr_status_flags lptmr_status_flags_t

List of the LPTMR status flags.

typedef struct _lptmr_config lptmr_config_t

LPTMR config structure.

This structure holds the configuration settings for the LPTMR peripheral. To initialize this structure to reasonable defaults, call the LPTMR_GetDefaultConfig() function and pass a pointer to your configuration structure instance.

The configuration struct can be made constant so it resides in flash.

```
static inline void LPTMR_EnableTimerDMA(LPTMR_Type *base, bool enable)
```

Enable or disable timer DMA request.

Parameters

- base – base LPTMR peripheral base address
- enable – Switcher of timer DMA feature. “true” means to enable, “false” means to disable.

```
struct __lptmr_config
```

#include <fsl_lptmr.h> LPTMR config structure.

This structure holds the configuration settings for the LPTMR peripheral. To initialize this structure to reasonable defaults, call the `LPTMR_GetDefaultConfig()` function and pass a pointer to your configuration structure instance.

The configuration struct can be made constant so it resides in flash.

Public Members

lptmr_timer_mode_t timerMode

Time counter mode or pulse counter mode

lptmr_pin_select_t pinSelect

LPTMR pulse input pin select; used only in pulse counter mode

lptmr_pin_polarity_t pinPolarity

LPTMR pulse input pin polarity; used only in pulse counter mode

bool enableFreeRunning

True: enable free running, counter is reset on overflow False: counter is reset when the compare flag is set

bool bypassPrescaler

True: bypass prescaler; false: use clock from prescaler

lptmr_prescaler_clock_select_t prescalerClockSource

LPTMR clock source

lptmr_prescaler_glitch_value_t value

Prescaler or glitch filter value

2.40 LPUART: Low Power Universal Asynchronous Receiver/Transmitter Driver

2.41 LPUART Driver

```
static inline void LPUART_SoftwareReset(LPUART_Type *base)
```

Resets the LPUART using software.

This function resets all internal logic and registers except the Global Register. Remains set until cleared by software.

Parameters

- base – LPUART peripheral base address.

status_t LPUART_Init(LPUART_Type *base, const *lpuart_config_t* *config, uint32_t srcClock_Hz)
Initializes an LPUART instance with the user configuration structure and the peripheral clock.

This function configures the LPUART module with user-defined settings. Call the LPUART_GetDefaultConfig() function to configure the configuration structure and get the default configuration. The example below shows how to use this API to configure the LPUART.

```
lpuart_config_t lpuartConfig;  
lpuartConfig.baudRate_Bps = 115200U;  
lpuartConfig.parityMode = kLPUART_ParityDisabled;  
lpuartConfig.dataBitsCount = kLPUART_EightDataBits;  
lpuartConfig.isMsb = false;  
lpuartConfig.stopBitCount = kLPUART_OneStopBit;  
lpuartConfig.txFifoWatermark = 0;  
lpuartConfig.rxFifoWatermark = 1;  
LPUART_Init(LPUART1, &lpuartConfig, 2000000U);
```

Parameters

- base – LPUART peripheral base address.
- config – Pointer to a user-defined configuration structure.
- srcClock_Hz – LPUART clock source frequency in HZ.

Return values

- kStatus_LPUART_BaudrateNotSupport – Baudrate is not support in current clock source.
- kStatus_Success – LPUART initialize succeed

void LPUART_Deinit(LPUART_Type *base)

Deinitializes a LPUART instance.

This function waits for transmit to complete, disables TX and RX, and disables the LPUART clock.

Parameters

- base – LPUART peripheral base address.

void LPUART_GetDefaultConfig(*lpuart_config_t* *config)

Gets the default configuration structure.

This function initializes the LPUART configuration structure to a default value. The default values are: lpuartConfig->baudRate_Bps = 115200U; lpuartConfig->parityMode = kLPUART_ParityDisabled; lpuartConfig->dataBitsCount = kLPUART_EightDataBits; lpuartConfig->isMsb = false; lpuartConfig->stopBitCount = kLPUART_OneStopBit; lpuartConfig->txFifoWatermark = 0; lpuartConfig->rxFifoWatermark = 1; lpuartConfig->rxIdleType = kLPUART_IdleTypeStartBit; lpuartConfig->rxIdleConfig = kLPUART_IdleCharacter1; lpuartConfig->enableTx = false; lpuartConfig->enableRx = false;

Parameters

- config – Pointer to a configuration structure.

status_t LPUART_SetBaudRate(LPUART_Type *base, uint32_t baudRate_Bps, uint32_t srcClock_Hz)

Sets the LPUART instance baudrate.

This function configures the LPUART module baudrate. This function is used to update the LPUART module baudrate after the LPUART module is initialized by the LPUART_Init.

```
LPUART_SetBaudRate(LPUART1, 115200U, 20000000U);
```

Parameters

- base – LPUART peripheral base address.
- baudRate_Bps – LPUART baudrate to be set.
- srcClock_Hz – LPUART clock source frequency in HZ.

Return values

- kStatus_LPUART_BaudrateNotSupport – Baudrate is not supported in the current clock source.
- kStatus_Success – Set baudrate succeeded.

```
void LPUART_Enable9bitMode(LPUART_Type *base, bool enable)
```

Enable 9-bit data mode for LPUART.

This function set the 9-bit mode for LPUART module. The 9th bit is not used for parity thus can be modified by user.

Parameters

- base – LPUART peripheral base address.
- enable – true to enable, false to disable.

```
static inline void LPUART_SetMatchAddress(LPUART_Type *base, uint16_t address1, uint16_t address2)
```

Set the LPUART address.

This function configures the address for LPUART module that works as slave in 9-bit data mode. One or two address fields can be configured. When the address field's match enable bit is set, the frame it receives with MSB being 1 is considered as an address frame, otherwise it is considered as data frame. Once the address frame matches one of slave's own addresses, this slave is addressed. This address frame and its following data frames are stored in the receive buffer; otherwise the frames will be discarded. To un-address a slave, just send an address frame with unmatched address.

Note: Any LPUART instance joined in the multi-slave system can work as slave. The position of the address mark is the same as the parity bit when parity is enabled for 8 bit and 9 bit data formats.

Parameters

- base – LPUART peripheral base address.
- address1 – LPUART slave address1.
- address2 – LPUART slave address2.

```
static inline void LPUART_EnableMatchAddress(LPUART_Type *base, bool match1, bool match2)
```

Enable the LPUART match address feature.

Parameters

- base – LPUART peripheral base address.
- match1 – true to enable match address1, false to disable.
- match2 – true to enable match address2, false to disable.

static inline void LPUART_SetRxFifoWatermark(LPUART_Type *base, uint8_t water)

Sets the rx FIFO watermark.

Parameters

- base – LPUART peripheral base address.
- water – Rx FIFO watermark.

static inline void LPUART_SetTxFifoWatermark(LPUART_Type *base, uint8_t water)

Sets the tx FIFO watermark.

Parameters

- base – LPUART peripheral base address.
- water – Tx FIFO watermark.

static inline void LPUART_TransferEnable16Bit(*lpuart_handle_t* *handle, bool enable)

Sets the LPUART using 16bit transmit, only for 9bit or 10bit mode.

This function Enable 16bit Data transmit in *lpuart_handle_t*.

Parameters

- handle – LPUART handle pointer.
- enable – true to enable, false to disable.

uint32_t LPUART_GetStatusFlags(LPUART_Type *base)

Gets LPUART status flags.

This function gets all LPUART status flags. The flags are returned as the logical OR value of the enumerators *_lpuart_flags*. To check for a specific status, compare the return value with enumerators in the *_lpuart_flags*. For example, to check whether the TX is empty:

```
if (kLPUART_TxDataRegEmptyFlag & LPUART_GetStatusFlags(LPUART1))
{
    ...
}
```

Parameters

- base – LPUART peripheral base address.

Returns

LPUART status flags which are ORed by the enumerators in the *_lpuart_flags*.

status_t LPUART_ClearStatusFlags(LPUART_Type *base, uint32_t mask)

Clears status flags with a provided mask.

This function clears LPUART status flags with a provided mask. Automatically cleared flags can't be cleared by this function. Flags that can only be cleared or set by hardware are: *kLPUART_TxDataRegEmptyFlag*, *kLPUART_TransmissionCompleteFlag*, *kLPUART_RxDataRegFullFlag*, *kLPUART_RxActiveFlag*, *kLPUART_NoiseErrorFlag*, *kLPUART_ParityErrorFlag*, *kLPUART_TxFifoEmptyFlag*, *kLPUART_RxFifoEmptyFlag*. Note: This API should be called when the Tx/Rx is idle, otherwise it takes no effects.

Parameters

- base – LPUART peripheral base address.
- mask – the status flags to be cleared. The user can use the enumerators in the *_lpuart_status_flag_t* to do the OR operation and get the mask.

Return values

- *kStatus_LPUART_FlagCannotClearManually* – The flag can't be cleared by this function but it is cleared automatically by hardware.

- kStatus_Success – Status in the mask are cleared.

Returns

0 succeed, others failed.

void LPUART_EnableInterrupts(LPUART_Type *base, uint32_t mask)

Enables LPUART interrupts according to a provided mask.

This function enables the LPUART interrupts according to a provided mask. The mask is a logical OR of enumeration members. See the `_lpuart_interrupt_enable`. This examples shows how to enable TX empty interrupt and RX full interrupt:

```
LPUART_EnableInterrupts(LPUART1, kLPUART_TxDataRegEmptyInterruptEnable | kLPUART_
↳ RxDataRegFullInterruptEnable);
```

Parameters

- base – LPUART peripheral base address.
- mask – The interrupts to enable. Logical OR of `_lpuart_interrupt_enable`.

void LPUART_DisableInterrupts(LPUART_Type *base, uint32_t mask)

Disables LPUART interrupts according to a provided mask.

This function disables the LPUART interrupts according to a provided mask. The mask is a logical OR of enumeration members. See `_lpuart_interrupt_enable`. This example shows how to disable the TX empty interrupt and RX full interrupt:

```
LPUART_DisableInterrupts(LPUART1, kLPUART_TxDataRegEmptyInterruptEnable | kLPUART_
↳ RxDataRegFullInterruptEnable);
```

Parameters

- base – LPUART peripheral base address.
- mask – The interrupts to disable. Logical OR of `_lpuart_interrupt_enable`.

uint32_t LPUART_GetEnabledInterrupts(LPUART_Type *base)

Gets enabled LPUART interrupts.

This function gets the enabled LPUART interrupts. The enabled interrupts are returned as the logical OR value of the enumerators `_lpuart_interrupt_enable`. To check a specific interrupt enable status, compare the return value with enumerators in `_lpuart_interrupt_enable`. For example, to check whether the TX empty interrupt is enabled:

```
uint32_t enabledInterrupts = LPUART_GetEnabledInterrupts(LPUART1);

if (kLPUART_TxDataRegEmptyInterruptEnable & enabledInterrupts)
{
    ...
}
```

Parameters

- base – LPUART peripheral base address.

Returns

LPUART interrupt flags which are logical OR of the enumerators in `_lpuart_interrupt_enable`.

```
static inline uintptr_t LPUART_GetDataRegisterAddress(LPUART_Type *base)
```

Gets the LPUART data register address.

This function returns the LPUART data register address, which is mainly used by the DMA/eDMA.

Parameters

- base – LPUART peripheral base address.

Returns

LPUART data register addresses which are used both by the transmitter and receiver.

```
static inline void LPUART_EnableTxDMA(LPUART_Type *base, bool enable)
```

Enables or disables the LPUART transmitter DMA request.

This function enables or disables the transmit data register empty flag, STAT[TDRE], to generate DMA requests.

Parameters

- base – LPUART peripheral base address.
- enable – True to enable, false to disable.

```
static inline void LPUART_EnableRxDMA(LPUART_Type *base, bool enable)
```

Enables or disables the LPUART receiver DMA.

This function enables or disables the receiver data register full flag, STAT[RDRF], to generate DMA requests.

Parameters

- base – LPUART peripheral base address.
- enable – True to enable, false to disable.

```
uint32_t LPUART_GetInstance(LPUART_Type *base)
```

Get the LPUART instance from peripheral base address.

Parameters

- base – LPUART peripheral base address.

Returns

LPUART instance.

```
static inline void LPUART_EnableTx(LPUART_Type *base, bool enable)
```

Enables or disables the LPUART transmitter.

This function enables or disables the LPUART transmitter.

Parameters

- base – LPUART peripheral base address.
- enable – True to enable, false to disable.

```
static inline void LPUART_EnableRx(LPUART_Type *base, bool enable)
```

Enables or disables the LPUART receiver.

This function enables or disables the LPUART receiver.

Parameters

- base – LPUART peripheral base address.
- enable – True to enable, false to disable.

```
static inline void LPUART_WriteByte(LPUART_Type *base, uint8_t data)
```

Writes to the transmitter register.

This function writes data to the transmitter register directly. The upper layer must ensure that the TX register is empty or that the TX FIFO has room before calling this function.

Parameters

- base – LPUART peripheral base address.
- data – Data write to the TX register.

```
static inline uint8_t LPUART_ReadByte(LPUART_Type *base)
```

Reads the receiver register.

This function reads data from the receiver register directly. The upper layer must ensure that the receiver register is full or that the RX FIFO has data before calling this function.

Parameters

- base – LPUART peripheral base address.

Returns

Data read from data register.

```
static inline uint8_t LPUART_GetRxFifoCount(LPUART_Type *base)
```

Gets the rx FIFO data count.

Parameters

- base – LPUART peripheral base address.

Returns

rx FIFO data count.

```
static inline uint8_t LPUART_GetTxFifoCount(LPUART_Type *base)
```

Gets the tx FIFO data count.

Parameters

- base – LPUART peripheral base address.

Returns

tx FIFO data count.

```
void LPUART_SendAddress(LPUART_Type *base, uint8_t address)
```

Transmit an address frame in 9-bit data mode.

Parameters

- base – LPUART peripheral base address.
- address – LPUART slave address.

```
status_t LPUART_WriteBlocking(LPUART_Type *base, const uint8_t *data, size_t length)
```

Writes to the transmitter register using a blocking method.

This function polls the transmitter register, first waits for the register to be empty or TX FIFO to have room, and writes data to the transmitter buffer, then waits for the data to be sent out to the bus.

Parameters

- base – LPUART peripheral base address.
- data – Start address of the data to write.
- length – Size of the data to write.

Return values

- kStatus_LPUART_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully wrote all data.

status_t LPUART_WriteBlocking16bit(LPUART_Type *base, const uint16_t *data, size_t length)

Writes to the transmitter register using a blocking method in 9bit or 10bit mode.

Note: This function only support 9bit or 10bit transfer. Please make sure only 10bit of data is valid and other bits are 0.

Parameters

- base – LPUART peripheral base address.
- data – Start address of the data to write.
- length – Size of the data to write.

Return values

- kStatus_LPUART_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully wrote all data.

status_t LPUART_ReadBlocking(LPUART_Type *base, uint8_t *data, size_t length)

Reads the receiver data register using a blocking method.

This function polls the receiver register, waits for the receiver register full or receiver FIFO has data, and reads data from the TX register.

Parameters

- base – LPUART peripheral base address.
- data – Start address of the buffer to store the received data.
- length – Size of the buffer.

Return values

- kStatus_LPUART_RxHardwareOverrun – Receiver overrun happened while receiving data.
- kStatus_LPUART_NoiseError – Noise error happened while receiving data.
- kStatus_LPUART_FramingError – Framing error happened while receiving data.
- kStatus_LPUART_ParityError – Parity error happened while receiving data.
- kStatus_LPUART_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully received all data.

status_t LPUART_ReadBlocking16bit(LPUART_Type *base, uint16_t *data, size_t length)

Reads the receiver data register in 9bit or 10bit mode.

Note: This function only support 9bit or 10bit transfer.

Parameters

- base – LPUART peripheral base address.
- data – Start address of the buffer to store the received data by 16bit, only 10bit is valid.

- length – Size of the buffer.

Return values

- kStatus_LPUART_RxHardwareOverrun – Receiver overrun happened while receiving data.
- kStatus_LPUART_NoiseError – Noise error happened while receiving data.
- kStatus_LPUART_FramingError – Framing error happened while receiving data.
- kStatus_LPUART_ParityError – Parity error happened while receiving data.
- kStatus_LPUART_Timeout – Transmission timed out and was aborted.
- kStatus_Success – Successfully received all data.

```
void LPUART_TransferCreateHandle(LPUART_Type *base, lpuart_handle_t *handle,  
                                lpuart_transfer_callback_t callback, void *userData)
```

Initializes the LPUART handle.

This function initializes the LPUART handle, which can be used for other LPUART transactional APIs. Usually, for a specified LPUART instance, call this API once to get the initialized handle.

The LPUART driver supports the “background” receiving, which means that user can set up an RX ring buffer optionally. Data received is stored into the ring buffer even when the user doesn’t call the LPUART_TransferReceiveNonBlocking() API. If there is already data received in the ring buffer, the user can get the received data from the ring buffer directly. The ring buffer is disabled if passing NULL as ringBuffer.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- callback – Callback function.
- userData – User data.

```
status_t LPUART_TransferSendNonBlocking(LPUART_Type *base, lpuart_handle_t *handle,  
                                         lpuart_transfer_t *xfer)
```

Transmits a buffer of data using the interrupt method.

This function send data using an interrupt method. This is a non-blocking function, which returns directly without waiting for all data written to the transmitter register. When all data is written to the TX register in the ISR, the LPUART driver calls the callback function and passes the kStatus_LPUART_TxIdle as status parameter.

Note: The kStatus_LPUART_TxIdle is passed to the upper layer when all data are written to the TX register. However, there is no check to ensure that all the data sent out. Before disabling the TX, check the kLPUART_TransmissionCompleteFlag to ensure that the transmit is finished.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- xfer – LPUART transfer structure, see lpuart_transfer_t.

Return values

- `kStatus_Success` – Successfully start the data transmission.
- `kStatus_LPUART_TxBusy` – Previous transmission still not finished, data not all written to the TX register.
- `kStatus_InvalidArgument` – Invalid argument.

```
void LPUART_TransferStartRingBuffer(LPUART_Type *base, lpuart_handle_t *handle, uint8_t  
                                   *ringBuffer, size_t ringBufferSize)
```

Sets up the RX ring buffer.

This function sets up the RX ring buffer to a specific UART handle.

When the RX ring buffer is used, data received is stored into the ring buffer even when the user doesn't call the `UART_TransferReceiveNonBlocking()` API. If there is already data received in the ring buffer, the user can get the received data from the ring buffer directly.

Note: When using RX ring buffer, one byte is reserved for internal use. In other words, if `ringBufferSize` is 32, then only 31 bytes are used for saving data.

Parameters

- `base` – LPUART peripheral base address.
- `handle` – LPUART handle pointer.
- `ringBuffer` – Start address of ring buffer for background receiving. Pass `NULL` to disable the ring buffer.
- `ringBufferSize` – size of the ring buffer.

```
void LPUART_TransferStopRingBuffer(LPUART_Type *base, lpuart_handle_t *handle)
```

Aborts the background transfer and uninstalls the ring buffer.

This function aborts the background transfer and uninstalls the ring buffer.

Parameters

- `base` – LPUART peripheral base address.
- `handle` – LPUART handle pointer.

```
size_t LPUART_TransferGetRxRingBufferLength(LPUART_Type *base, lpuart_handle_t *handle)
```

Get the length of received data in RX ring buffer.

Parameters

- `base` – LPUART peripheral base address.
- `handle` – LPUART handle pointer.

Returns

Length of received data in RX ring buffer.

```
void LPUART_TransferAbortSend(LPUART_Type *base, lpuart_handle_t *handle)
```

Aborts the interrupt-driven data transmit.

This function aborts the interrupt driven data sending. The user can get the `remainBytes` to find out how many bytes are not sent out.

Parameters

- `base` – LPUART peripheral base address.
- `handle` – LPUART handle pointer.

```
status_t LPUART_TransferGetSendCount(LPUART_Type *base, lpuart_handle_t *handle, uint32_t *count)
```

Gets the number of bytes that have been sent out to bus.

This function gets the number of bytes that have been sent out to bus by an interrupt method.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- count – Send bytes count.

Return values

- kStatus_NoTransferInProgress – No send in progress.
- kStatus_InvalidArgument – Parameter is invalid.
- kStatus_Success – Get successfully through the parameter count;

```
status_t LPUART_TransferReceiveNonBlocking(LPUART_Type *base, lpuart_handle_t *handle, lpuart_transfer_t *xfer, size_t *receivedBytes)
```

Receives a buffer of data using the interrupt method.

This function receives data using an interrupt method. This is a non-blocking function which returns without waiting to ensure that all data are received. If the RX ring buffer is used and not empty, the data in the ring buffer is copied and the parameter `receivedBytes` shows how many bytes are copied from the ring buffer. After copying, if the data in the ring buffer is not enough for read, the receive request is saved by the LPUART driver. When the new data arrives, the receive request is serviced first. When all data is received, the LPUART driver notifies the upper layer through a callback function and passes a status parameter `kStatus_UART_RxIdle`. For example, the upper layer needs 10 bytes but there are only 5 bytes in ring buffer. The 5 bytes are copied to `xfer->data`, which returns with the parameter `receivedBytes` set to 5. For the remaining 5 bytes, the newly arrived data is saved from `xfer->data[5]`. When 5 bytes are received, the LPUART driver notifies the upper layer. If the RX ring buffer is not enabled, this function enables the RX and RX interrupt to receive data to `xfer->data`. When all data is received, the upper layer is notified.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- xfer – LPUART transfer structure, see `uart_transfer_t`.
- receivedBytes – Bytes received from the ring buffer directly.

Return values

- kStatus_Success – Successfully queue the transfer into the transmit queue.
- kStatus_LPUART_RxBusy – Previous receive request is not finished.
- kStatus_InvalidArgument – Invalid argument.

```
void LPUART_TransferAbortReceive(LPUART_Type *base, lpuart_handle_t *handle)
```

Aborts the interrupt-driven data receiving.

This function aborts the interrupt-driven data receiving. The user can get the `remainBytes` to find out how many bytes not received yet.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.

status_t LPUART_TransferGetReceiveCount(LPUART_Type *base, *lpuart_handle_t* *handle, uint32_t *count)

Gets the number of bytes that have been received.

This function gets the number of bytes that have been received.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- count – Receive bytes count.

Return values

- kStatus_NoTransferInProgress – No receive in progress.
- kStatus_InvalidArgument – Parameter is invalid.
- kStatus_Success – Get successfully through the parameter count;

void LPUART_TransferHandleIRQ(LPUART_Type *base, void *irqHandle)

LPUART IRQ handle function.

This function handles the LPUART transmit and receive IRQ request.

Parameters

- base – LPUART peripheral base address.
- irqHandle – LPUART handle pointer.

void LPUART_TransferHandleErrorIRQ(LPUART_Type *base, void *irqHandle)

LPUART Error IRQ handle function.

This function handles the LPUART error IRQ request.

Parameters

- base – LPUART peripheral base address.
- irqHandle – LPUART handle pointer.

void LPUART_DriverIRQHandler(uint32_t instance)

LPUART driver IRQ handler common entry.

This function provides the common IRQ request entry for LPUART.

Parameters

- instance – LPUART instance.

FSL_LPUART_DRIVER_VERSION

LPUART driver version.

Error codes for the LPUART driver.

Values:

enumerator kStatus_LPUART_TxBusy
TX busy

enumerator kStatus_LPUART_RxBusy
RX busy

enumerator kStatus_LPUART_TxIdle
LPUART transmitter is idle.

enumerator kStatus_LPUART_RxIdle

LPUART receiver is idle.

enumerator kStatus_LPUART_TxWatermarkTooLarge

TX FIFO watermark too large

enumerator kStatus_LPUART_RxWatermarkTooLarge

RX FIFO watermark too large

enumerator kStatus_LPUART_FlagCannotClearManually

Some flag can't manually clear

enumerator kStatus_LPUART_Error

Error happens on LPUART.

enumerator kStatus_LPUART_RxRingBufferOverrun

LPUART RX software ring buffer overrun.

enumerator kStatus_LPUART_RxHardwareOverrun

LPUART RX receiver overrun.

enumerator kStatus_LPUART_NoiseError

LPUART noise error.

enumerator kStatus_LPUART_FramingError

LPUART framing error.

enumerator kStatus_LPUART_ParityError

LPUART parity error.

enumerator kStatus_LPUART_BaudrateNotSupport

Baudrate is not support in current clock source

enumerator kStatus_LPUART_IdleLineDetected

IDLE flag.

enumerator kStatus_LPUART_Timeout

LPUART times out.

enum _lpuart_parity_mode

LPUART parity mode.

Values:

enumerator kLPUART_ParityDisabled

Parity disabled

enumerator kLPUART_ParityEven

Parity enabled, type even, bit setting: PE|PT = 10

enumerator kLPUART_ParityOdd

Parity enabled, type odd, bit setting: PE|PT = 11

enum _lpuart_data_bits

LPUART data bits count.

Values:

enumerator kLPUART_EightDataBits

Eight data bit

enumerator kLPUART_SevenDataBits

Seven data bit

enum `_lpuart_stop_bit_count`

LPUART stop bit count.

Values:

enumerator `kLPUART_OneStopBit`

One stop bit

enumerator `kLPUART_TwoStopBit`

Two stop bits

enum `_lpuart_transmit_cts_source`

LPUART transmit CTS source.

Values:

enumerator `kLPUART_CtsSourcePin`

CTS resource is the LPUART_CTS pin.

enumerator `kLPUART_CtsSourceMatchResult`

CTS resource is the match result.

enum `_lpuart_transmit_cts_config`

LPUART transmit CTS configure.

Values:

enumerator `kLPUART_CtsSampleAtStart`

CTS input is sampled at the start of each character.

enumerator `kLPUART_CtsSampleAtIdle`

CTS input is sampled when the transmitter is idle

enum `_lpuart_idle_type_select`

LPUART idle flag type defines when the receiver starts counting.

Values:

enumerator `kLPUART_IdleTypeStartBit`

Start counting after a valid start bit.

enumerator `kLPUART_IdleTypeStopBit`

Start counting after a stop bit.

enum `_lpuart_idle_config`

LPUART idle detected configuration. This structure defines the number of idle characters that must be received before the IDLE flag is set.

Values:

enumerator `kLPUART_IdleCharacter1`

the number of idle characters.

enumerator `kLPUART_IdleCharacter2`

the number of idle characters.

enumerator `kLPUART_IdleCharacter4`

the number of idle characters.

enumerator `kLPUART_IdleCharacter8`

the number of idle characters.

enumerator `kLPUART_IdleCharacter16`

the number of idle characters.

enumerator kLPUART_IdleCharacter32
the number of idle characters.

enumerator kLPUART_IdleCharacter64
the number of idle characters.

enumerator kLPUART_IdleCharacter128
the number of idle characters.

enum __lpuart_interrupt_enable

LPUART interrupt configuration structure, default settings all disabled.

This structure contains the settings for all LPUART interrupt configurations.

Values:

enumerator kLPUART_LinBreakInterruptEnable
LIN break detect. bit 7

enumerator kLPUART_RxActiveEdgeInterruptEnable
Receive Active Edge. bit 6

enumerator kLPUART_TxDataRegEmptyInterruptEnable
Transmit data register empty. bit 23

enumerator kLPUART_TransmissionCompleteInterruptEnable
Transmission complete. bit 22

enumerator kLPUART_RxDataRegFullInterruptEnable
Receiver data register full. bit 21

enumerator kLPUART_IdleLineInterruptEnable
Idle line. bit 20

enumerator kLPUART_RxOverrunInterruptEnable
Receiver Overrun. bit 27

enumerator kLPUART_NoiseErrorInterruptEnable
Noise error flag. bit 26

enumerator kLPUART_FramingErrorInterruptEnable
Framing error flag. bit 25

enumerator kLPUART_ParityErrorInterruptEnable
Parity error flag. bit 24

enumerator kLPUART_Match1InterruptEnable
Parity error flag. bit 15

enumerator kLPUART_Match2InterruptEnable
Parity error flag. bit 14

enumerator kLPUART_TxFifoOverflowInterruptEnable
Transmit FIFO Overflow. bit 9

enumerator kLPUART_RxFifoUnderflowInterruptEnable
Receive FIFO Underflow. bit 8

enumerator kLPUART_AllInterruptEnable

enum `_lpuart_flags`

LPUART status flags.

This provides constants for the LPUART status flags for use in the LPUART functions.

Values:

enumerator `kLPUART_TxDataRegEmptyFlag`

Transmit data register empty flag, sets when transmit buffer is empty. bit 23

enumerator `kLPUART_TransmissionCompleteFlag`

Transmission complete flag, sets when transmission activity complete. bit 22

enumerator `kLPUART_RxDataRegFullFlag`

Receive data register full flag, sets when the receive data buffer is full. bit 21

enumerator `kLPUART_IdleLineFlag`

Idle line detect flag, sets when idle line detected. bit 20

enumerator `kLPUART_RxOverrunFlag`

Receive Overrun, sets when new data is received before data is read from receive register. bit 19

enumerator `kLPUART_NoiseErrorFlag`

Receive takes 3 samples of each received bit. If any of these samples differ, noise flag sets. bit 18

enumerator `kLPUART_FramingErrorFlag`

Frame error flag, sets if logic 0 was detected where stop bit expected. bit 17

enumerator `kLPUART_ParityErrorFlag`

If parity enabled, sets upon parity error detection. bit 16

enumerator `kLPUART_LinBreakFlag`

LIN break detect interrupt flag, sets when LIN break char detected and LIN circuit enabled. bit 31

enumerator `kLPUART_RxActiveEdgeFlag`

Receive pin active edge interrupt flag, sets when active edge detected. bit 30

enumerator `kLPUART_RxActiveFlag`

Receiver Active Flag (RAF), sets at beginning of valid start. bit 24

enumerator `kLPUART_DataMatch1Flag`

The next character to be read from LPUART_DATA matches MA1. bit 15

enumerator `kLPUART_DataMatch2Flag`

The next character to be read from LPUART_DATA matches MA2. bit 14

enumerator `kLPUART_TxFifoEmptyFlag`

TXEMPT bit, sets if transmit buffer is empty. bit 7

enumerator `kLPUART_RxFifoEmptyFlag`

RXEMPT bit, sets if receive buffer is empty. bit 6

enumerator `kLPUART_TxFifoOverflowFlag`

TXOF bit, sets if transmit buffer overflow occurred. bit 1

enumerator `kLPUART_RxFifoUnderflowFlag`

RXUF bit, sets if receive buffer underflow occurred. bit 0

enumerator `kLPUART_AllClearFlags`

```

    enumerator kLPUART_AllFlags

typedef enum _lpuart_parity_mode lpuart__parity__mode__t
    LPUART parity mode.

typedef enum _lpuart_data_bits lpuart__data__bits__t
    LPUART data bits count.

typedef enum _lpuart_stop_bit_count lpuart__stop__bit__count__t
    LPUART stop bit count.

typedef enum _lpuart_transmit_cts_source lpuart__transmit__cts__source__t
    LPUART transmit CTS source.

typedef enum _lpuart_transmit_cts_config lpuart__transmit__cts__config__t
    LPUART transmit CTS configure.

typedef enum _lpuart_idle_type_select lpuart__idle__type__select__t
    LPUART idle flag type defines when the receiver starts counting.

typedef enum _lpuart_idle_config lpuart__idle__config__t
    LPUART idle detected configuration. This structure defines the number of idle characters
    that must be received before the IDLE flag is set.

typedef struct _lpuart_config lpuart__config__t
    LPUART configuration structure.

typedef struct _lpuart_transfer lpuart__transfer__t
    LPUART transfer structure.

typedef struct _lpuart_handle lpuart__handle__t

typedef void (*lpuart__transfer_callback__t)(LPUART_Type *base, lpuart_handle_t *handle,
status_t status, void *userData)
    LPUART transfer callback function.

typedef void (*lpuart__isr__t)(LPUART_Type *base, void *handle)

void *s_lpuartHandle[]

const IRQn_Type s_lpuartTxIRQ[]

lpuart_isr_t s_lpuartIsr[]

UART_RETRY_TIMES
    Retry times for waiting flag.

struct _lpuart_config
    #include <fsl_lpuart.h> LPUART configuration structure.

```

Public Members

```

uint32_t baudRate_Bps
    LPUART baud rate

lpuart_parity_mode_t parityMode
    Parity mode, disabled (default), even, odd

lpuart_data_bits_t dataBitsCount
    Data bits count, eight (default), seven

```

bool isMsb

Data bits order, LSB (default), MSB

lpuart_stop_bit_count_t stopBitCount

Number of stop bits, 1 stop bit (default) or 2 stop bits

uint8_t txFifoWatermark

TX FIFO watermark

uint8_t rxFifoWatermark

RX FIFO watermark

bool enableRxRTS

RX RTS enable

bool enableTxCTS

TX CTS enable

lpuart_transmit_cts_source_t txCtsSource

TX CTS source

lpuart_transmit_cts_config_t txCtsConfig

TX CTS configure

lpuart_idle_type_select_t rxIdleType

RX IDLE type.

lpuart_idle_config_t rxIdleConfig

RX IDLE configuration.

bool enableTx

Enable TX

bool enableRx

Enable RX

struct *_lpuart_transfer*

#include <fsl_lpuart.h> LPUART transfer structure.

Public Members

size_t dataSize

The byte count to be transfer.

struct *_lpuart_handle*

#include <fsl_lpuart.h> LPUART handle structure.

Public Members

volatile size_t txDataSize

Size of the remaining data to send.

size_t txDataSizeAll

Size of the data to send out.

volatile size_t rxDataSize

Size of the remaining data to receive.

size_t rxDataSizeAll

Size of the data to receive.

size_t rxRingBufferSize

Size of the ring buffer.

volatile uint16_t rxRingBufferHead

Index for the driver to store received data into ring buffer.

volatile uint16_t rxRingBufferTail

Index for the user to get data from the ring buffer.

lpuart_transfer_callback_t callback

Callback function.

void *userData

LPUART callback function parameter.

volatile uint8_t txState

TX transfer state.

volatile uint8_t rxState

RX transfer state.

bool isSevenDataBits

Seven data bits flag.

bool is16bitData

16bit data bits flag, only used for 9bit or 10bit data

union __unnamed24__

Public Members

uint8_t *data

The buffer of data to be transfer.

uint8_t *rxData

The buffer to receive data.

uint16_t *rxData16

The buffer to receive data.

const uint8_t *txData

The buffer of data to be sent.

const uint16_t *txData16

The buffer of data to be sent.

union __unnamed26__

Public Members

const uint8_t *volatile txData

Address of remaining data to send.

const uint16_t *volatile txData16

Address of remaining data to send.

union __unnamed28__

Public Members

`uint8_t *volatile rxData`
Address of remaining data to receive.

`uint16_t *volatile rxData16`
Address of remaining data to receive.

`union __unnamed30__`

Public Members

`uint8_t *rxRingBuffer`
Start address of the receiver ring buffer.

`uint16_t *rxRingBuffer16`
Start address of the receiver ring buffer.

2.42 LPUART eDMA Driver

```
void LPUART_TransferCreateHandleEDMA(LPUART_Type *base, lpuart_edma_handle_t *handle,
                                     lpuart_edma_transfer_callback_t callback, void
                                     *userData, edma_handle_t *txEdmaHandle,
                                     edma_handle_t *rxEdmaHandle)
```

Initializes the LPUART handle which is used in transactional functions.

Note: This function disables all LPUART interrupts.

Parameters

- `base` – LPUART peripheral base address.
- `handle` – Pointer to `lpuart_edma_handle_t` structure.
- `callback` – Callback function.
- `userData` – User data.
- `txEdmaHandle` – User requested DMA handle for TX DMA transfer.
- `rxEdmaHandle` – User requested DMA handle for RX DMA transfer.

```
status_t LPUART_SendEDMA(LPUART_Type *base, lpuart_edma_handle_t *handle,
                         lpuart_transfer_t *xfer)
```

Sends data using eDMA.

This function sends data using eDMA. This is a non-blocking function, which returns right away. When all data is sent, the send callback function is called.

Parameters

- `base` – LPUART peripheral base address.
- `handle` – LPUART handle pointer.
- `xfer` – LPUART eDMA transfer structure. See `lpuart_transfer_t`.

Return values

- `kStatus_Success` – if succeed, others failed.

- `kStatus_LPUART_TxBusy` – Previous transfer on going.
- `kStatus_InvalidArgument` – Invalid argument.

`status_t` LPUART_ReceiveEDMA(LPUART_Type *base, *lpuart_edma_handle_t* *handle, *lpuart_transfer_t* *xfer)

Receives data using eDMA.

This function receives data using eDMA. This is non-blocking function, which returns right away. When all data is received, the receive callback function is called.

Parameters

- `base` – LPUART peripheral base address.
- `handle` – Pointer to `lpuart_edma_handle_t` structure.
- `xfer` – LPUART eDMA transfer structure, see `lpuart_transfer_t`.

Return values

- `kStatus_Success` – if succeed, others fail.
- `kStatus_LPUART_RxBusy` – Previous transfer ongoing.
- `kStatus_InvalidArgument` – Invalid argument.

`void` LPUART_TransferAbortSendEDMA(LPUART_Type *base, *lpuart_edma_handle_t* *handle)

Aborts the sent data using eDMA.

This function aborts the sent data using eDMA.

Parameters

- `base` – LPUART peripheral base address.
- `handle` – Pointer to `lpuart_edma_handle_t` structure.

`void` LPUART_TransferAbortReceiveEDMA(LPUART_Type *base, *lpuart_edma_handle_t* *handle)

Aborts the received data using eDMA.

This function aborts the received data using eDMA.

Parameters

- `base` – LPUART peripheral base address.
- `handle` – Pointer to `lpuart_edma_handle_t` structure.

`status_t` LPUART_TransferGetSendCountEDMA(LPUART_Type *base, *lpuart_edma_handle_t* *handle, `uint32_t` *count)

Gets the number of bytes written to the LPUART TX register.

This function gets the number of bytes written to the LPUART TX register by DMA.

Parameters

- `base` – LPUART peripheral base address.
- `handle` – LPUART handle pointer.
- `count` – Send bytes count.

Return values

- `kStatus_NoTransferInProgress` – No send in progress.
- `kStatus_InvalidArgument` – Parameter is invalid.
- `kStatus_Success` – Get successfully through the parameter count;

```
status_t LPUART_TransferGetReceiveCountEDMA(LPUART_Type *base, lpuart_edma_handle_t
                                             *handle, uint32_t *count)
```

Gets the number of received bytes.

This function gets the number of received bytes.

Parameters

- base – LPUART peripheral base address.
- handle – LPUART handle pointer.
- count – Receive bytes count.

Return values

- kStatus_NoTransferInProgress – No receive in progress.
- kStatus_InvalidArgument – Parameter is invalid.
- kStatus_Success – Get successfully through the parameter count;

```
void LPUART_TransferEdmaHandleIRQ(LPUART_Type *base, void *lpuartEdmaHandle)
```

LPUART eDMA IRQ handle function.

This function handles the LPUART tx complete IRQ request and invoke user callback. It is not set to static so that it can be used in user application.

Note: This function is used as default IRQ handler by double weak mechanism. If user's specific IRQ handler is implemented, make sure this function is invoked in the handler.

Parameters

- base – LPUART peripheral base address.
- lpuartEdmaHandle – LPUART handle pointer.

```
FSL_LPUART_EDMA_DRIVER_VERSION
```

LPUART EDMA driver version.

```
typedef struct _lpuart_edma_handle lpuart_edma_handle_t
```

```
typedef void (*lpuart_edma_transfer_callback_t)(LPUART_Type *base, lpuart_edma_handle_t
*handle, status_t status, void *userData)
```

LPUART transfer callback function.

```
struct _lpuart_edma_handle
```

```
#include <fsl_lpuart_edma.h> LPUART eDMA handle.
```

Public Members

```
lpuart_edma_transfer_callback_t callback
```

Callback function.

```
void *userData
```

LPUART callback function parameter.

```
size_t rxDataSizeAll
```

Size of the data to receive.

```
size_t txDataSizeAll
```

Size of the data to send out.

edma_handle_t *txEdmaHandle
The eDMA TX channel used.

edma_handle_t *rxEdmaHandle
The eDMA RX channel used.

uint8_t nbytes
eDMA minor byte transfer count initially configured.

volatile uint8_t txState
TX transfer state.

volatile uint8_t rxState
RX transfer state

2.43 MCM: Miscellaneous Control Module

FSL_MCM_DRIVER_VERSION
MCM driver version.

Enum _mcm_interrupt_flag. Interrupt status flag mask. .

Values:

enumerator kMCM_CacheWriteBuffer
Cache Write Buffer Error Enable.

enumerator kMCM_ParityError
Cache Parity Error Enable.

enumerator kMCM_FPUInvalidOperation
FPU Invalid Operation Interrupt Enable.

enumerator kMCM_FPUDivideByZero
FPU Divide-by-zero Interrupt Enable.

enumerator kMCM_FPUOverflow
FPU Overflow Interrupt Enable.

enumerator kMCM_FPUUnderflow
FPU Underflow Interrupt Enable.

enumerator kMCM_FPUInexact
FPU Inexact Interrupt Enable.

enumerator kMCM_FPUInputDenormalInterrupt
FPU Input Denormal Interrupt Enable.

typedef union *_mcm_buffer_fault_attribute* mcm_buffer_fault_attribute_t
The union of buffer fault attribute.

typedef union *_mcm_lmem_fault_attribute* mcm_lmem_fault_attribute_t
The union of LMEM fault attribute.

static inline void MCM_EnableCrossbarRoundRobin(MCM_Type *base, bool enable)
Enables/Disables crossbar round robin.

Parameters

- base – MCM peripheral base address.

- `enable` – Used to enable/disable crossbar round robin.
 - **true** Enable crossbar round robin.
 - **false** disable crossbar round robin.

static inline void MCM_EnableInterruptStatus(MCM_Type *base, uint32_t mask)

Enables the interrupt.

Parameters

- `base` – MCM peripheral base address.
- `mask` – Interrupt status flags mask(`_mcm_interrupt_flag`).

static inline void MCM_DisableInterruptStatus(MCM_Type *base, uint32_t mask)

Disables the interrupt.

Parameters

- `base` – MCM peripheral base address.
- `mask` – Interrupt status flags mask(`_mcm_interrupt_flag`).

static inline uint16_t MCM_GetInterruptStatus(MCM_Type *base)

Gets the Interrupt status .

Parameters

- `base` – MCM peripheral base address.

static inline void MCM_ClearCacheWriteBufferErrorStatus(MCM_Type *base)

Clears the Interrupt status .

Parameters

- `base` – MCM peripheral base address.

static inline uint32_t MCM_GetBufferFaultAddress(MCM_Type *base)

Gets buffer fault address.

Parameters

- `base` – MCM peripheral base address.

static inline void MCM_GetBufferFaultAttribute(MCM_Type *base, *mcm_buffer_fault_attribute_t* *bufferfault)

Gets buffer fault attributes.

Parameters

- `base` – MCM peripheral base address.

static inline uint32_t MCM_GetBufferFaultData(MCM_Type *base)

Gets buffer fault data.

Parameters

- `base` – MCM peripheral base address.

static inline void MCM_LimitCodeCachePeripheralWriteBuffering(MCM_Type *base, bool enable)

Limit code cache peripheral write buffering.

Parameters

- `base` – MCM peripheral base address.
- `enable` – Used to enable/disable limit code cache peripheral write buffering.
 - **true** Enable limit code cache peripheral write buffering.
 - **false** disable limit code cache peripheral write buffering.

static inline void MCM_BypassFixedCodeCacheMap(MCM_Type *base, bool enable)
Bypass fixed code cache map.

Parameters

- base – MCM peripheral base address.
- enable – Used to enable/disable bypass fixed code cache map.
 - **true** Enable bypass fixed code cache map.
 - **false** disable bypass fixed code cache map.

static inline void MCM_EnableCodeBusCache(MCM_Type *base, bool enable)
Enables/Disables code bus cache.

Parameters

- base – MCM peripheral base address.
- enable – Used to disable/enable code bus cache.
 - **true** Enable code bus cache.
 - **false** disable code bus cache.

static inline void MCM_ForceCodeCacheToNoAllocation(MCM_Type *base, bool enable)
Force code cache to no allocation.

Parameters

- base – MCM peripheral base address.
- enable – Used to force code cache to allocation or no allocation.
 - **true** Force code cache to no allocation.
 - **false** Force code cache to allocation.

static inline void MCM_EnableCodeCacheWriteBuffer(MCM_Type *base, bool enable)
Enables/Disables code cache write buffer.

Parameters

- base – MCM peripheral base address.
- enable – Used to enable/disable code cache write buffer.
 - **true** Enable code cache write buffer.
 - **false** Disable code cache write buffer.

static inline void MCM_ClearCodeBusCache(MCM_Type *base)
Clear code bus cache.

Parameters

- base – MCM peripheral base address.

static inline void MCM_EnablePcParityFaultReport(MCM_Type *base, bool enable)
Enables/Disables PC Parity Fault Report.

Parameters

- base – MCM peripheral base address.
- enable – Used to enable/disable PC Parity Fault Report.
 - **true** Enable PC Parity Fault Report.
 - **false** disable PC Parity Fault Report.

```
static inline void MCM_EnablePcParity(MCM_Type *base, bool enable)
```

Enables/Disables PC Parity.

Parameters

- base – MCM peripheral base address.
- enable – Used to enable/disable PC Parity.
 - **true** Enable PC Parity.
 - **false** disable PC Parity.

```
static inline void MCM_LockConfigState(MCM_Type *base)
```

Lock the configuration state.

Parameters

- base – MCM peripheral base address.

```
static inline void MCM_EnableCacheParityReporting(MCM_Type *base, bool enable)
```

Enables/Disables cache parity reporting.

Parameters

- base – MCM peripheral base address.
- enable – Used to enable/disable cache parity reporting.
 - **true** Enable cache parity reporting.
 - **false** disable cache parity reporting.

```
static inline uint32_t MCM_GetLmemFaultAddress(MCM_Type *base)
```

Gets LMEM fault address.

Parameters

- base – MCM peripheral base address.

```
static inline void MCM_GetLmemFaultAttribute(MCM_Type *base, mcm_lmem_fault_attribute_t  
                                             *lmemFault)
```

Get LMEM fault attributes.

Parameters

- base – MCM peripheral base address.

```
static inline uint64_t MCM_GetLmemFaultData(MCM_Type *base)
```

Gets LMEM fault data.

Parameters

- base – MCM peripheral base address.

MCM_LMFATR_TYPE_MASK

MCM_LMFATR_MODE_MASK

MCM_LMFATR_BUFF_MASK

MCM_LMFATR_CACH_MASK

MCM_ISCR_STAT_MASK

FSL_COMPONENT_ID

```
union __mcm_buffer_fault_attribute
```

#include <fsl_mcm.h> The union of buffer fault attribute.

Public Members

uint32_t attribute

Indicates the faulting attributes, when a properly-enabled cache write buffer error interrupt event is detected.

struct *_mcm_buffer_fault_attribute._mcm_buffer_fault_attrib* attribute_memory

struct *_mcm_buffer_fault_attrib*

#include <fsl_mcm.h>

Public Members

uint32_t busErrorDataAccessType

Indicates the type of cache write buffer access.

uint32_t busErrorPrivilegeLevel

Indicates the privilege level of the cache write buffer access.

uint32_t busErrorSize

Indicates the size of the cache write buffer access.

uint32_t busErrorAccess

Indicates the type of system bus access.

uint32_t busErrorMasterID

Indicates the crossbar switch bus master number of the captured cache write buffer bus error.

uint32_t busErrorOverrun

Indicates if another cache write buffer bus error is detected.

union *_mcm_lmem_fault_attribute*

#include <fsl_mcm.h> The union of LMEM fault attribute.

Public Members

uint32_t attribute

Indicates the attributes of the LMEM fault detected.

struct *_mcm_lmem_fault_attribute._mcm_lmem_fault_attrib* attribute_memory

struct *_mcm_lmem_fault_attrib*

#include <fsl_mcm.h>

Public Members

uint32_t parityFaultProtectionSignal

Indicates the features of parity fault protection signal.

uint32_t parityFaultMasterSize

Indicates the parity fault master size.

uint32_t parityFaultWrite

Indicates the parity fault is caused by read or write.

uint32_t backdoorAccess

Indicates the LMEM access fault is initiated by core access or backdoor access.

uint32_t parityFaultSyndrome
Indicates the parity fault syndrome.

uint32_t overrun
Indicates the number of faultss.

2.44 MMDVSQ: Memory-Mapped Divide and Square Root

int32_t MMDVSQ_GetDivideRemainder(MMDVSQ_Type *base, int32_t dividend, int32_t divisor,
bool isUnsigned)

Performs the MMDVSQ division operation and returns the remainder.

Parameters

- base – MMDVSQ peripheral address
- dividend – Dividend value
- divisor – Divisor value
- isUnsigned – Mode of unsigned divide
 - true unsigned divide
 - false signed divide

int32_t MMDVSQ_GetDivideQuotient(MMDVSQ_Type *base, int32_t dividend, int32_t divisor,
bool isUnsigned)

Performs the MMDVSQ division operation and returns the quotient.

Parameters

- base – MMDVSQ peripheral address
- dividend – Dividend value
- divisor – Divisor value
- isUnsigned – Mode of unsigned divide
 - true unsigned divide
 - false signed divide

uint16_t MMDVSQ_Sqrt(MMDVSQ_Type *base, uint32_t radicand)

Performs the MMDVSQ square root operation.

This function performs the MMDVSQ square root operation and returns the square root result of a given radicand value.

Parameters

- base – MMDVSQ peripheral address
- radicand – Radicand value

static inline *mmdvsq_execution_status_t* MMDVSQ_GetExecutionStatus(MMDVSQ_Type *base)

Gets the MMDVSQ execution status.

This function checks the current MMDVSQ execution status of the combined CSR[BUSY, DIV, Sqrt] indicators.

Parameters

- base – MMDVSQ peripheral address

Returns

Current MMDVSQ execution status

```
static inline void MMDVSQ_SetFastStartConfig(MMDVSQ_Type *base,
                                             mmdvsq_fast_start_select_t mode)
```

Configures MMDVSQ fast start mode.

This function sets the MMDVSQ division fast start. The MMDVSQ supports two mechanisms for initiating a division operation. The default mechanism is a “fast start” where a write to the DSOR register begins the division. Alternatively, the start mechanism can begin after a write to the CSR register with CSR[SRT] set.

Parameters

- base – MMDVSQ peripheral address
- mode – Mode of Divide-Fast-Start
 - kMmdvsqDivideFastStart = 0
 - kMmdvsqDivideNormalStart = 1

```
static inline void MMDVSQ_SetDivideByZeroConfig(MMDVSQ_Type *base, bool isDivByZero)
```

Configures the MMDVSQ divide-by-zero mode.

This function configures the MMDVSQ response to divide-by-zero calculations. If both CSR[DZ] and CSR[DZE] are set, then a subsequent read of the RES register is error-terminated to signal the processor of the attempted divide-by-zero. Otherwise, the register contents are returned.

Parameters

- base – MMDVSQ peripheral address
- isDivByZero – Mode of Divide-By-Zero
 - kMmdvsqDivideByZeroDis = 0
 - kMmdvsqDivideByZeroEn = 1

FSL_MMSVSQ_DRIVER_VERSION

Version 2.0.4.

```
enum _mmdvsq_execution_status
```

MMDVSQ execution status.

Values:

```
enumerator kMMDVSQ_IdleSquareRoot
```

MMDVSQ is idle; the last calculation was a square root

```
enumerator kMMDVSQ_IdleDivide
```

MMDVSQ is idle; the last calculation was division

```
enumerator kMMDVSQ_BusySquareRoot
```

MMDVSQ is busy processing a square root calculation

```
enumerator kMMDVSQ_BusyDivide
```

MMDVSQ is busy processing a division calculation

```
enum _mmdvsq_fast_start_select
```

MMDVSQ divide fast start select.

Values:

```
enumerator kMMDVSQ_EnableFastStart
```

Division operation is initiated by a write to the DSOR register

```
enumerator kMMDVSQ_DisableFastStart
```

Division operation is initiated by a write to CSR[SRT] = 1; normal start instead fast start

```
typedef enum _mmdvsq_execution_status mmdvsq_execution_status_t
    MMDVSQ execution status.

typedef enum _mmdvsq_fast_start_select mmdvsq_fast_start_select_t
    MMDVSQ divide fast start select.
```

2.45 PDB: Programmable Delay Block

```
void PDB_Init(PDB_Type *base, const pdb_config_t *config)
    Initializes the PDB module.
```

This function initializes the PDB module. The operations included are as follows.

- Enable the clock for PDB instance.
- Configure the PDB module.
- Enable the PDB module.

Parameters

- base – PDB peripheral base address.
- config – Pointer to the configuration structure. See “pdb_config_t”.

```
void PDB_Deinit(PDB_Type *base)
    De-initializes the PDB module.
```

Parameters

- base – PDB peripheral base address.

```
void PDB_GetDefaultConfig(pdb_config_t *config)
    Initializes the PDB user configuration structure.
```

This function initializes the user configuration structure to a default value. The default values are as follows.

```
config->loadValueMode = kPDB_LoadValueImmediately;
config->prescalerDivider = kPDB_PrescalerDivider1;
config->dividerMultiplicationFactor = kPDB_DividerMultiplicationFactor1;
config->triggerInputSource = kPDB_TriggerSoftware;
config->enableContinuousMode = false;
```

Parameters

- config – Pointer to configuration structure. See “pdb_config_t”.

```
static inline void PDB_Enable(PDB_Type *base, bool enable)
    Enables the PDB module.
```

Parameters

- base – PDB peripheral base address.
- enable – Enable the module or not.

```
static inline void PDB_DoSoftwareTrigger(PDB_Type *base)
    Triggers the PDB counter by software.
```

Parameters

- base – PDB peripheral base address.

static inline void PDB_DoLoadValues(PDB_Type *base)

Loads the counter values.

This function loads the counter values from the internal buffer. See “pdb_load_value_mode_t” about PDB’s load mode.

Parameters

- base – PDB peripheral base address.

static inline void PDB_EnableDMA(PDB_Type *base, bool enable)

Enables the DMA for the PDB module.

Parameters

- base – PDB peripheral base address.
- enable – Enable the feature or not.

static inline void PDB_EnableInterrupts(PDB_Type *base, uint32_t mask)

Enables the interrupts for the PDB module.

Parameters

- base – PDB peripheral base address.
- mask – Mask value for interrupts. See “_pdb_interrupt_enable”.

static inline void PDB_DisableInterrupts(PDB_Type *base, uint32_t mask)

Disables the interrupts for the PDB module.

Parameters

- base – PDB peripheral base address.
- mask – Mask value for interrupts. See “_pdb_interrupt_enable”.

static inline uint32_t PDB_GetStatusFlags(PDB_Type *base)

Gets the status flags of the PDB module.

Parameters

- base – PDB peripheral base address.

Returns

Mask value for asserted flags. See “_pdb_status_flags”.

static inline void PDB_ClearStatusFlags(PDB_Type *base, uint32_t mask)

Clears the status flags of the PDB module.

Parameters

- base – PDB peripheral base address.
- mask – Mask value of flags. See “_pdb_status_flags”.

static inline void PDB_SetModulusValue(PDB_Type *base, uint32_t value)

Specifies the counter period.

Parameters

- base – PDB peripheral base address.
- value – Setting value for the modulus. 16-bit is available.

static inline uint32_t PDB_GetCounterValue(PDB_Type *base)

Gets the PDB counter’s current value.

Parameters

- base – PDB peripheral base address.

Returns

PDB counter's current value.

```
static inline void PDB_SetCounterDelayValue(PDB_Type *base, uint32_t value)
```

Sets the value for the PDB counter delay event.

Parameters

- base – PDB peripheral base address.
- value – Setting value for PDB counter delay event. 16-bit is available.

```
static inline void PDB_SetADCPreTriggerConfig(PDB_Type *base, pdb_adc_trigger_channel_t  
channel, pdb_adc_pretrigger_config_t *config)
```

Configures the ADC pre-trigger in the PDB module.

Parameters

- base – PDB peripheral base address.
- channel – Channel index for ADC instance.
- config – Pointer to the configuration structure. See “pdb_adc_pretrigger_config_t”.

```
static inline void PDB_SetADCPreTriggerDelayValue(PDB_Type *base, pdb_adc_trigger_channel_t  
channel, pdb_adc_pretrigger_t  
pretriggerNumber, uint32_t value)
```

Sets the value for the ADC pre-trigger delay event.

This function sets the value for ADC pre-trigger delay event. It specifies the delay value for the channel's corresponding pre-trigger. The pre-trigger asserts when the PDB counter is equal to the set value.

Parameters

- base – PDB peripheral base address.
- channel – Channel index for ADC instance.
- pretriggerNumber – Channel group index for ADC instance.
- value – Setting value for ADC pre-trigger delay event. 16-bit is available.

```
static inline uint32_t PDB_GetADCPreTriggerStatusFlags(PDB_Type *base,  
pdb_adc_trigger_channel_t channel)
```

Gets the ADC pre-trigger's status flags.

Parameters

- base – PDB peripheral base address.
- channel – Channel index for ADC instance.

Returns

Mask value for asserted flags. See “_pdb_adc_pretrigger_flags”.

```
static inline void PDB_ClearADCPreTriggerStatusFlags(PDB_Type *base,  
pdb_adc_trigger_channel_t channel,  
uint32_t mask)
```

Clears the ADC pre-trigger status flags.

Parameters

- base – PDB peripheral base address.
- channel – Channel index for ADC instance.
- mask – Mask value for flags. See “_pdb_adc_pretrigger_flags”.

```
void PDB_SetDACTriggerConfig(PDB_Type *base, pdb_dac_trigger_channel_t channel,  
                             pdb_dac_trigger_config_t *config)
```

Configures the DAC trigger in the PDB module.

Parameters

- base – PDB peripheral base address.
- channel – Channel index for DAC instance.
- config – Pointer to the configuration structure. See “*pdb_dac_trigger_config_t*”.

```
static inline void PDB_SetDACTriggerIntervalValue(PDB_Type *base, pdb_dac_trigger_channel_t  
                                                  channel, uint32_t value)
```

Sets the value for the DAC interval event.

This function sets the value for DAC interval event. DAC interval trigger triggers the DAC module to update the buffer when the DAC interval counter is equal to the set value.

Parameters

- base – PDB peripheral base address.
- channel – Channel index for DAC instance.
- value – Setting value for the DAC interval event.

```
static inline void PDB_EnablePulseOutTrigger(PDB_Type *base, pdb_pulse_out_channel_mask_t  
                                              channelMask, bool enable)
```

Enables the pulse out trigger channels.

Parameters

- base – PDB peripheral base address.
- channelMask – Channel mask value for multiple pulse out trigger channel.
- enable – Whether the feature is enabled or not.

```
static inline void PDB_SetPulseOutTriggerDelayValue(PDB_Type *base,  
                                                    pdb_pulse_out_trigger_channel_t channel,  
                                                    uint32_t value1, uint32_t value2)
```

Sets event values for the pulse out trigger.

This function is used to set event values for the pulse output trigger. These pulse output trigger delay values specify the delay for the PDB Pulse-out. Pulse-out goes high when the PDB counter is equal to the pulse output high value (value1). Pulse-out goes low when the PDB counter is equal to the pulse output low value (value2).

Parameters

- base – PDB peripheral base address.
- channel – Channel index for pulse out trigger channel.
- value1 – Setting value for pulse out high.
- value2 – Setting value for pulse out low.

FSL_PDB_DRIVER_VERSION

PDB driver version 2.0.4.

enum *_pdb_status_flags*

PDB flags.

Values:

enumerator kPDB_LoadOKFlag

This flag is automatically cleared when the values in buffers are loaded into the internal registers after the LDOK bit is set or the PDBEN is cleared.

enumerator kPDB_DelayEventFlag

PDB timer delay event flag.

enum __pdb_adc_pretrigger_flags

PDB ADC PreTrigger channel flags.

Values:

enumerator kPDB_ADPreTriggerChannel0Flag

Pre-trigger 0 flag.

enumerator kPDB_ADPreTriggerChannel1Flag

Pre-trigger 1 flag.

enumerator kPDB_ADPreTriggerChannel0ErrorFlag

Pre-trigger 0 Error.

enumerator kPDB_ADPreTriggerChannel1ErrorFlag

Pre-trigger 1 Error.

enum __pdb_interrupt_enable

PDB buffer interrupts.

Values:

enumerator kPDB_SequenceErrorInterruptEnable

PDB sequence error interrupt enable.

enumerator kPDB_DelayInterruptEnable

PDB delay interrupt enable.

enum __pdb_load_value_mode

PDB load value mode.

Selects the mode to load the internal values after doing the load operation (write 1 to PDBx_SC[LDOK]). These values are for the following operations.

- PDB counter (PDBx_MOD, PDBx_IDLY)
- ADC trigger (PDBx_CHnDLYm)
- DAC trigger (PDBx_DACINTx)
- CMP trigger (PDBx_POyDLY)

Values:

enumerator kPDB_LoadValueImmediately

Load immediately after 1 is written to LDOK.

enumerator kPDB_LoadValueOnCounterOverflow

Load when the PDB counter overflows (reaches the MOD register value).

enumerator kPDB_LoadValueOnTriggerInput

Load a trigger input event is detected.

enumerator kPDB_LoadValueOnCounterOverflowOrTriggerInput

Load either when the PDB counter overflows or a trigger input is detected.

enum __pdb_prescaler_divider

Prescaler divider.

Counting uses the peripheral clock divided by multiplication factor selected by times of MULT.

Values:

enumerator kPDB_PrescalerDivider1

Divider x1.

enumerator kPDB_PrescalerDivider2

Divider x2.

enumerator kPDB_PrescalerDivider4

Divider x4.

enumerator kPDB_PrescalerDivider8

Divider x8.

enumerator kPDB_PrescalerDivider16

Divider x16.

enumerator kPDB_PrescalerDivider32

Divider x32.

enumerator kPDB_PrescalerDivider64

Divider x64.

enumerator kPDB_PrescalerDivider128

Divider x128.

enum __pdb_divider_multiplication_factor

Multiplication factor select for prescaler.

Selects the multiplication factor of the prescaler divider for the counter clock.

Values:

enumerator kPDB_DividerMultiplicationFactor1

Multiplication factor is 1.

enumerator kPDB_DividerMultiplicationFactor10

Multiplication factor is 10.

enumerator kPDB_DividerMultiplicationFactor20

Multiplication factor is 20.

enumerator kPDB_DividerMultiplicationFactor40

Multiplication factor is 40.

enum __pdb_trigger_input_source

Trigger input source.

Selects the trigger input source for the PDB. The trigger input source can be internal or external (EXTRG pin), or the software trigger. See chip configuration details for the actual PDB input trigger connections.

Values:

enumerator kPDB_TriggerInput0

Trigger-In 0.

enumerator kPDB_TriggerInput1

Trigger-In 1.

enumerator kPDB_TriggerInput2
Trigger-In 2.

enumerator kPDB_TriggerInput3
Trigger-In 3.

enumerator kPDB_TriggerInput4
Trigger-In 4.

enumerator kPDB_TriggerInput5
Trigger-In 5.

enumerator kPDB_TriggerInput6
Trigger-In 6.

enumerator kPDB_TriggerInput7
Trigger-In 7.

enumerator kPDB_TriggerInput8
Trigger-In 8.

enumerator kPDB_TriggerInput9
Trigger-In 9.

enumerator kPDB_TriggerInput10
Trigger-In 10.

enumerator kPDB_TriggerInput11
Trigger-In 11.

enumerator kPDB_TriggerInput12
Trigger-In 12.

enumerator kPDB_TriggerInput13
Trigger-In 13.

enumerator kPDB_TriggerInput14
Trigger-In 14.

enumerator kPDB_TriggerSoftware
Trigger-In 15, software trigger.

enum _pdb_adc_trigger_channel
List of PDB ADC trigger channels.

Note: Actual number of available channels is SoC dependent

Values:

enumerator kPDB_ADCTriggerChannel0
PDB ADC trigger channel number 0

enumerator kPDB_ADCTriggerChannel1
PDB ADC trigger channel number 1

enumerator kPDB_ADCTriggerChannel2
PDB ADC trigger channel number 2

enumerator kPDB_ADCTriggerChannel3
PDB ADC trigger channel number 3

enum _pdb_adc_pretrigger

List of PDB ADC pretrigger.

Note: Actual number of available pretrigger channels is SoC dependent

Values:

enumerator kPDB_ADPreTrigger0

PDB ADC pretrigger number 0

enumerator kPDB_ADPreTrigger1

PDB ADC pretrigger number 1

enumerator kPDB_ADPreTrigger2

PDB ADC pretrigger number 2

enumerator kPDB_ADPreTrigger3

PDB ADC pretrigger number 3

enumerator kPDB_ADPreTrigger4

PDB ADC pretrigger number 4

enumerator kPDB_ADPreTrigger5

PDB ADC pretrigger number 5

enumerator kPDB_ADPreTrigger6

PDB ADC pretrigger number 6

enumerator kPDB_ADPreTrigger7

PDB ADC pretrigger number 7

enum _pdb_dac_trigger_channel

List of PDB DAC trigger channels.

Note: Actual number of available channels is SoC dependent

Values:

enumerator kPDB_DACTriggerChannel0

PDB DAC trigger channel number 0

enumerator kPDB_DACTriggerChannel1

PDB DAC trigger channel number 1

enum _pdb_pulse_out_trigger_channel

List of PDB pulse out trigger channels.

Note: Actual number of available channels is SoC dependent

Values:

enumerator kPDB_PulseOutTriggerChannel0

PDB pulse out trigger channel number 0

enumerator kPDB_PulseOutTriggerChannel1

PDB pulse out trigger channel number 1

enumerator kPDB_PulseOutTriggerChannel2
PDB pulse out trigger channel number 2

enumerator kPDB_PulseOutTriggerChannel3
PDB pulse out trigger channel number 3

enum __pdb_pulse_out_channel_mask
List of PDB pulse out trigger channels mask.

Note: Actual number of available channels mask is SoC dependent

Values:

enumerator kPDB_PulseOutChannel0Mask
PDB pulse out trigger channel number 0 mask

enumerator kPDB_PulseOutChannel1Mask
PDB pulse out trigger channel number 1 mask

enumerator kPDB_PulseOutChannel2Mask
PDB pulse out trigger channel number 2 mask

enumerator kPDB_PulseOutChannel3Mask
PDB pulse out trigger channel number 3 mask

typedef enum __pdb_load_value_mode pdb_load_value_mode_t
PDB load value mode.

Selects the mode to load the internal values after doing the load operation (write 1 to PDBx_SC[LDOK]). These values are for the following operations.

- PDB counter (PDBx_MOD, PDBx_IDLY)
- ADC trigger (PDBx_CHnDLYm)
- DAC trigger (PDBx_DACINTx)
- CMP trigger (PDBx_POyDLY)

typedef enum __pdb_prescaler_divider pdb_prescaler_divider_t
Prescaler divider.

Counting uses the peripheral clock divided by multiplication factor selected by times of MULT.

typedef enum __pdb_divider_multiplication_factor pdb_divider_multiplication_factor_t
Multiplication factor select for prescaler.

Selects the multiplication factor of the prescaler divider for the counter clock.

typedef enum __pdb_trigger_input_source pdb_trigger_input_source_t
Trigger input source.

Selects the trigger input source for the PDB. The trigger input source can be internal or external (EXTRG pin), or the software trigger. See chip configuration details for the actual PDB input trigger connections.

typedef enum __pdb_adc_trigger_channel pdb_adc_trigger_channel_t
List of PDB ADC trigger channels.

Note: Actual number of available channels is SoC dependent

```
typedef enum _pdb_adc_pretrigger pdb_adc_pretrigger_t
```

List of PDB ADC pretrigger.

Note: Actual number of available pretrigger channels is SoC dependent

```
typedef enum _pdb_dac_trigger_channel pdb_dac_trigger_channel_t
```

List of PDB DAC trigger channels.

Note: Actual number of available channels is SoC dependent

```
typedef enum _pdb_pulse_out_trigger_channel pdb_pulse_out_trigger_channel_t
```

List of PDB pulse out trigger channels.

Note: Actual number of available channels is SoC dependent

```
typedef enum _pdb_pulse_out_channel_mask pdb_pulse_out_channel_mask_t
```

List of PDB pulse out trigger channels mask.

Note: Actual number of available channels mask is SoC dependent

```
typedef struct _pdb_config pdb_config_t
```

PDB module configuration.

```
typedef struct _pdb_adc_pretrigger_config pdb_adc_pretrigger_config_t
```

PDB ADC Pre-trigger configuration.

```
typedef struct _pdb_dac_trigger_config pdb_dac_trigger_config_t
```

PDB DAC trigger configuration.

```
struct _pdb_config
```

```
#include <fsl_pdb.h> PDB module configuration.
```

Public Members

pdb_load_value_mode_t loadValueMode

Select the load value mode.

pdb_prescaler_divider_t prescalerDivider

Select the prescaler divider.

pdb_divider_multiplication_factor_t dividerMultiplicationFactor

Multiplication factor select for prescaler.

pdb_trigger_input_source_t triggerInputSource

Select the trigger input source.

bool enableContinuousMode

Enable the PDB operation in Continuous mode.

```
struct _pdb_adc_pretrigger_config
```

```
#include <fsl_pdb.h> PDB ADC Pre-trigger configuration.
```


Public Members

uint32_t enablePreTriggerMask
PDB Channel Pre-trigger Enable.

uint32_t enableOutputMask
PDB Channel Pre-trigger Output Select. PDB channel's corresponding pre-trigger asserts when the counter reaches the channel delay register.

uint32_t enableBackToBackOperationMask
PDB Channel pre-trigger Back-to-Back Operation Enable. Back-to-back operation enables the ADC conversions complete to trigger the next PDB channel pre-trigger and trigger output, so that the ADC conversions can be triggered on next set of configuration and results registers.

struct __pdb_dac_trigger_config
#include <fsl_pdb.h> PDB DAC trigger configuration.

Public Members

bool enableExternalTriggerInput
Enables the external trigger for DAC interval counter.

bool enableIntervalTrigger
Enables the DAC interval trigger.

2.46 PMC: Power Management Controller

static inline void PMC_GetVersionId(PMC_Type *base, pmc_version_id_t *versionId)
Gets the PMC version ID.

This function gets the PMC version ID, including major version number, minor version number, and a feature specification number.

Parameters

- base – PMC peripheral base address.
- versionId – Pointer to version ID structure.

void PMC_GetParam(PMC_Type *base, pmc_param_t *param)
Gets the PMC parameter.

This function gets the PMC parameter including the VLPO enable and the HVD enable.

Parameters

- base – PMC peripheral base address.
- param – Pointer to PMC param structure.

void PMC_ConfigureLowVoltDetect(PMC_Type *base, const pmc_low_volt_detect_config_t *config)

Configures the low-voltage detect setting.

This function configures the low-voltage detect setting, including the trip point voltage setting, enables or disables the interrupt, enables or disables the system reset.

Parameters

- base – PMC peripheral base address.
- config – Low-voltage detect configuration structure.

```
static inline bool PMC_GetLowVoltDetectFlag(PMC_Type *base)
```

Gets the Low-voltage Detect Flag status.

This function reads the current LVDF status. If it returns 1, a low-voltage event is detected.

Parameters

- base – PMC peripheral base address.

Returns

Current low-voltage detect flag

- true: Low-voltage detected
- false: Low-voltage not detected

```
static inline void PMC_ClearLowVoltDetectFlag(PMC_Type *base)
```

Acknowledges clearing the Low-voltage Detect flag.

This function acknowledges the low-voltage detection errors (write 1 to clear LVDF).

Parameters

- base – PMC peripheral base address.

```
void PMC_ConfigureLowVoltWarning(PMC_Type *base, const pmc_low_volt_warning_config_t  
                                *config)
```

Configures the low-voltage warning setting.

This function configures the low-voltage warning setting, including the trip point voltage setting and enabling or disabling the interrupt.

Parameters

- base – PMC peripheral base address.
- config – Low-voltage warning configuration structure.

```
static inline bool PMC_GetLowVoltWarningFlag(PMC_Type *base)
```

Gets the Low-voltage Warning Flag status.

This function polls the current LVWF status. When 1 is returned, it indicates a low-voltage warning event. LVWF is set when V Supply transitions below the trip point or after reset and V Supply is already below the V LVW.

Parameters

- base – PMC peripheral base address.

Returns

Current LVWF status

- true: Low-voltage Warning Flag is set.
- false: the Low-voltage Warning does not happen.

```
static inline void PMC_ClearLowVoltWarningFlag(PMC_Type *base)
```

Acknowledges the Low-voltage Warning flag.

This function acknowledges the low voltage warning errors (write 1 to clear LVWF).

Parameters

- base – PMC peripheral base address.

```
void PMC_ConfigureHighVoltDetect(PMC_Type *base, const pmc_high_volt_detect_config_t  
                                *config)
```

Configures the high-voltage detect setting.

This function configures the high-voltage detect setting, including the trip point voltage setting, enabling or disabling the interrupt, enabling or disabling the system reset.

Parameters

- base – PMC peripheral base address.
- config – High-voltage detect configuration structure.

```
static inline bool PMC_GetHighVoltDetectFlag(PMC_Type *base)
```

Gets the High-voltage Detect Flag status.

This function reads the current HVDF status. If it returns 1, a low voltage event is detected.

Parameters

- base – PMC peripheral base address.

Returns

Current high-voltage detect flag

- true: High-voltage detected
- false: High-voltage not detected

```
static inline void PMC_ClearHighVoltDetectFlag(PMC_Type *base)
```

Acknowledges clearing the High-voltage Detect flag.

This function acknowledges the high-voltage detection errors (write 1 to clear HVDF).

Parameters

- base – PMC peripheral base address.

```
void PMC_ConfigureBandgapBuffer(PMC_Type *base, const pmc_bandgap_buffer_config_t  
                                *config)
```

Configures the PMC bandgap.

This function configures the PMC bandgap, including the drive select and behavior in low-power mode.

Parameters

- base – PMC peripheral base address.
- config – Pointer to the configuration structure

```
static inline bool PMC_GetPeriphIOIsolationFlag(PMC_Type *base)
```

Gets the acknowledge Peripherals and I/O pads isolation flag.

This function reads the Acknowledge Isolation setting that indicates whether certain peripherals and the I/O pads are in a latched state as a result of having been in the VLLS mode.

Parameters

- base – PMC peripheral base address.
- base – Base address for current PMC instance.

Returns

ACK isolation 0 - Peripherals and I/O pads are in a normal run state. 1 - Certain peripherals and I/O pads are in an isolated and latched state.

```
static inline void PMC_ClearPeriphIOIsolationFlag(PMC_Type *base)
```

Acknowledges the isolation flag to Peripherals and I/O pads.

This function clears the ACK Isolation flag. Writing one to this setting when it is set releases the I/O pads and certain peripherals to their normal run mode state.

Parameters

- base – PMC peripheral base address.

static inline bool PMC_IsRegulatorInRunRegulation(PMC_Type *base)

Gets the regulator regulation status.

This function returns the regulator to run a regulation status. It provides the current status of the internal voltage regulator.

Parameters

- base – PMC peripheral base address.
- base – Base address for current PMC instance.

Returns

Regulation status 0 - Regulator is in a stop regulation or in transition to/from the regulation. 1 - Regulator is in a run regulation.

FSL_PMC_DRIVER_VERSION

PMC driver version.

Version 2.0.3.

enum __pmc_low_volt_detect_volt_select

Low-voltage Detect Voltage Select.

Values:

enumerator kPMC_LowVoltDetectLowTrip

Low-trip point selected (VLVD = VLVDL)

enumerator kPMC_LowVoltDetectHighTrip

High-trip point selected (VLVD = VLVDH)

enum __pmc_low_volt_warning_volt_select

Low-voltage Warning Voltage Select.

Values:

enumerator kPMC_LowVoltWarningLowTrip

Low-trip point selected (VLVW = VLVW1)

enumerator kPMC_LowVoltWarningMid1Trip

Mid 1 trip point selected (VLVW = VLVW2)

enumerator kPMC_LowVoltWarningMid2Trip

Mid 2 trip point selected (VLVW = VLVW3)

enumerator kPMC_LowVoltWarningHighTrip

High-trip point selected (VLVW = VLVW4)

enum __pmc_high_volt_detect_volt_select

High-voltage Detect Voltage Select.

Values:

enumerator kPMC_HighVoltDetectLowTrip

Low-trip point selected (VHVD = VHVDL)

enumerator kPMC_HighVoltDetectHighTrip

High-trip point selected (VHVD = VHVDH)

enum __pmc_bandgap_buffer_drive_select

Bandgap Buffer Drive Select.

Values:

enumerator kPMC_BandgapBufferDriveLow
Low-drive.

enumerator kPMC_BandgapBufferDriveHigh
High-drive.

enum __pmc_vlp_freq_option
VLPx Option.

Values:

enumerator kPMC_FreqRestrict
Frequency is restricted in VLPx mode.

enumerator kPMC_FreqUnrestrict
Frequency is unrestricted in VLPx mode.

typedef enum __pmc_low_volt_detect_volt_select pmc_low_volt_detect_volt_select_t
Low-voltage Detect Voltage Select.

typedef enum __pmc_low_volt_warning_volt_select pmc_low_volt_warning_volt_select_t
Low-voltage Warning Voltage Select.

typedef enum __pmc_high_volt_detect_volt_select pmc_high_volt_detect_volt_select_t
High-voltage Detect Voltage Select.

typedef enum __pmc_bandgap_buffer_drive_select pmc_bandgap_buffer_drive_select_t
Bandgap Buffer Drive Select.

typedef enum __pmc_vlp_freq_option pmc_vlp_freq_mode_t
VLPx Option.

typedef struct __pmc_version_id pmc_version_id_t
IP version ID definition.

typedef struct __pmc_param pmc_param_t
IP parameter definition.

typedef struct __pmc_low_volt_detect_config pmc_low_volt_detect_config_t
Low-voltage Detect Configuration Structure.

typedef struct __pmc_low_volt_warning_config pmc_low_volt_warning_config_t
Low-voltage Warning Configuration Structure.

typedef struct __pmc_high_volt_detect_config pmc_high_volt_detect_config_t
High-voltage Detect Configuration Structure.

typedef struct __pmc_bandgap_buffer_config pmc_bandgap_buffer_config_t
Bandgap Buffer configuration.

struct __pmc_version_id
#include <fsl_pmc.h> IP version ID definition.

Public Members

uint16_t feature
Feature Specification Number.

uint8_t minor
Minor version number.

uint8_t major

Major version number.

struct __pmc_param

#include <fsl_pmc.h> IP parameter definition.

Public Members

bool vlpoEnable

VLPO enable.

bool hvdEnable

HVD enable.

struct __pmc_low_volt_detect_config

#include <fsl_pmc.h> Low-voltage Detect Configuration Structure.

Public Members

bool enableInt

Enable interrupt when Low-voltage detect

bool enableReset

Enable system reset when Low-voltage detect

pmc_low_volt_detect_volt_select_t voltSelect

Low-voltage detect trip point voltage selection

struct __pmc_low_volt_warning_config

#include <fsl_pmc.h> Low-voltage Warning Configuration Structure.

Public Members

bool enableInt

Enable interrupt when low-voltage warning

pmc_low_volt_warning_volt_select_t voltSelect

Low-voltage warning trip point voltage selection

struct __pmc_high_volt_detect_config

#include <fsl_pmc.h> High-voltage Detect Configuration Structure.

Public Members

bool enableInt

Enable interrupt when high-voltage detect

bool enableReset

Enable system reset when high-voltage detect

pmc_high_volt_detect_volt_select_t voltSelect

High-voltage detect trip point voltage selection

struct __pmc_bandgap_buffer_config

#include <fsl_pmc.h> Bandgap Buffer configuration.

Public Members

bool enable

Enable bandgap buffer.

bool enableInLowPowerMode

Enable bandgap buffer in low-power mode.

pmc_bandgap_buffer_drive_select_t drive

Bandgap buffer drive select.

2.47 PORT: Port Control and Interrupts

```
static inline void PORT_SetPinConfig(PORT_Type *base, uint32_t pin, const port_pin_config_t
                                     *config)
```

Sets the port PCR register.

This is an example to define an input pin or output pin PCR configuration.

```
// Define a digital input pin PCR configuration
port_pin_config_t config = {
    kPORT_PullUp,
    kPORT_FastSlewRate,
    kPORT_PassiveFilterDisable,
    kPORT_OpenDrainDisable,
    kPORT_LowDriveStrength,
    kPORT_MuxAsGpio,
    kPORT_UnLockRegister,
};
```

Parameters

- base – PORT peripheral base pointer.
- pin – PORT pin number.
- config – PORT PCR register configuration structure.

```
static inline void PORT_SetMultiplePinsConfig(PORT_Type *base, uint32_t mask, const
                                              port_pin_config_t *config)
```

Sets the port PCR register for multiple pins.

This is an example to define input pins or output pins PCR configuration.

```
Define a digital input pin PCR configuration
port_pin_config_t config = {
    kPORT_PullUp ,
    kPORT_PullEnable,
    kPORT_FastSlewRate,
    kPORT_PassiveFilterDisable,
    kPORT_OpenDrainDisable,
    kPORT_LowDriveStrength,
    kPORT_MuxAsGpio,
    kPORT_UnlockRegister,
};
```

Parameters

- base – PORT peripheral base pointer.
- mask – PORT pin number macro.

- config – PORT PCR register configuration structure.

```
static inline void PORT_SetMultipleInterruptPinsConfig(PORT_Type *base, uint32_t mask,  
                                                    port_interrupt_t config)
```

Sets the port interrupt configuration in PCR register for multiple pins.

Parameters

- base – PORT peripheral base pointer.
- mask – PORT pin number macro.
- config – PORT pin interrupt configuration.
 - kPORT_InterruptOrDMADisabled: Interrupt/DMA request disabled.
 - kPORT_DMARisingEdge : DMA request on rising edge(if the DMA requests exit).
 - kPORT_DMAFallingEdge: DMA request on falling edge(if the DMA requests exit).
 - kPORT_DMAEitherEdge : DMA request on either edge(if the DMA requests exit).
 - kPORT_FlagRisingEdge : Flag sets on rising edge(if the Flag states exit).
 - kPORT_FlagFallingEdge : Flag sets on falling edge(if the Flag states exit).
 - kPORT_FlagEitherEdge : Flag sets on either edge(if the Flag states exit).
 - kPORT_InterruptLogicZero : Interrupt when logic zero.
 - kPORT_InterruptRisingEdge : Interrupt on rising edge.
 - kPORT_InterruptFallingEdge: Interrupt on falling edge.
 - kPORT_InterruptEitherEdge : Interrupt on either edge.
 - kPORT_InterruptLogicOne : Interrupt when logic one.
 - kPORT_ActiveHighTriggerOutputEnable : Enable active high-trigger output (if the trigger states exit).
 - kPORT_ActiveLowTriggerOutputEnable : Enable active low-trigger output (if the trigger states exit)..

```
static inline void PORT_SetPinMux(PORT_Type *base, uint32_t pin, port_mux_t mux)
```

Configures the pin muxing.

Note: : This function is NOT recommended to use together with the PORT_SetPinsConfig, because the PORT_SetPinsConfig need to configure the pin mux anyway (Otherwise the pin mux is reset to zero : kPORT_PinDisabledOrAnalog). This function is recommended to use to reset the pin mux

Parameters

- base – PORT peripheral base pointer.
- pin – PORT pin number.
- mux – pin muxing slot selection.
 - kPORT_PinDisabledOrAnalog: Pin disabled or work in analog function.
 - kPORT_MuxAsGpio : Set as GPIO.
 - kPORT_MuxAlt2 : chip-specific.
 - kPORT_MuxAlt3 : chip-specific.

- kPORT_MuxAlt4 : chip-specific.
- kPORT_MuxAlt5 : chip-specific.
- kPORT_MuxAlt6 : chip-specific.
- kPORT_MuxAlt7 : chip-specific.

static inline void PORT__EnablePinsDigitalFilter(PORT_Type *base, uint32_t mask, bool enable)

Enables the digital filter in one port, each bit of the 32-bit register represents one pin.

Parameters

- base – PORT peripheral base pointer.
- mask – PORT pin number macro.
- enable – PORT digital filter configuration.

static inline void PORT__SetDigitalFilterConfig(PORT_Type *base, const
port_digital_filter_config_t *config)

Sets the digital filter in one port, each bit of the 32-bit register represents one pin.

Parameters

- base – PORT peripheral base pointer.
- config – PORT digital filter configuration structure.

static inline void PORT__SetPinInterruptConfig(PORT_Type *base, uint32_t pin, *port_interrupt_t*
config)

Configures the port pin interrupt/DMA request.

Parameters

- base – PORT peripheral base pointer.
- pin – PORT pin number.
- config – PORT pin interrupt configuration.
 - kPORT_InterruptOrDMADisabled: Interrupt/DMA request disabled.
 - kPORT_DMARisingEdge : DMA request on rising edge(if the DMA requests exit).
 - kPORT_DMAFallingEdge: DMA request on falling edge(if the DMA requests exit).
 - kPORT_DMAEitherEdge : DMA request on either edge(if the DMA requests exit).
 - kPORT_FlagRisingEdge : Flag sets on rising edge(if the Flag states exit).
 - kPORT_FlagFallingEdge : Flag sets on falling edge(if the Flag states exit).
 - kPORT_FlagEitherEdge : Flag sets on either edge(if the Flag states exit).
 - kPORT_InterruptLogicZero : Interrupt when logic zero.
 - kPORT_InterruptRisingEdge : Interrupt on rising edge.
 - kPORT_InterruptFallingEdge: Interrupt on falling edge.
 - kPORT_InterruptEitherEdge : Interrupt on either edge.
 - kPORT_InterruptLogicOne : Interrupt when logic one.
 - kPORT_ActiveHighTriggerOutputEnable : Enable active high-trigger output (if the trigger states exit).
 - kPORT_ActiveLowTriggerOutputEnable : Enable active low-trigger output (if the trigger states exit).

static inline void PORT_SetPinDriveStrength(PORT_Type *base, uint32_t pin, uint8_t strength)
Configures the port pin drive strength.

Parameters

- base – PORT peripheral base pointer.
- pin – PORT pin number.
- strength – PORT pin drive strength
 - kPORT_LowDriveStrength = 0U - Low-drive strength is configured.
 - kPORT_HighDriveStrength = 1U - High-drive strength is configured.

static inline uint32_t PORT_GetPinsInterruptFlags(PORT_Type *base)

Reads the whole port status flag.

If a pin is configured to generate the DMA request, the corresponding flag is cleared automatically at the completion of the requested DMA transfer. Otherwise, the flag remains set until a logic one is written to that flag. If configured for a level sensitive interrupt that remains asserted, the flag is set again immediately.

Parameters

- base – PORT peripheral base pointer.

Returns

Current port interrupt status flags, for example, 0x00010001 means the pin 0 and 16 have the interrupt.

static inline void PORT_ClearPinsInterruptFlags(PORT_Type *base, uint32_t mask)

Clears the multiple pin interrupt status flag.

Parameters

- base – PORT peripheral base pointer.
- mask – PORT pin number macro.

FSL_PORT_DRIVER_VERSION

PORT driver version.

enum __port__pull

Internal resistor pull feature selection.

Values:

enumerator kPORT_PullDisable

Internal pull-up/down resistor is disabled.

enumerator kPORT_PullDown

Internal pull-down resistor is enabled.

enumerator kPORT_PullUp

Internal pull-up resistor is enabled.

enum __port__slew_rate

Slew rate selection.

Values:

enumerator kPORT_FastSlewRate

Fast slew rate is configured.

enumerator kPORT_SlowSlewRate

Slow slew rate is configured.

enum __port_open_drain_enable

Open Drain feature enable/disable.

Values:

enumerator kPORT_OpenDrainDisable

Open drain output is disabled.

enumerator kPORT_OpenDrainEnable

Open drain output is enabled.

enum __port_passive_filter_enable

Passive filter feature enable/disable.

Values:

enumerator kPORT_PassiveFilterDisable

Passive input filter is disabled.

enumerator kPORT_PassiveFilterEnable

Passive input filter is enabled.

enum __port_drive_strength

Configures the drive strength.

Values:

enumerator kPORT_LowDriveStrength

Low-drive strength is configured.

enumerator kPORT_HighDriveStrength

High-drive strength is configured.

enum __port_lock_register

Unlock/lock the pin control register field[15:0].

Values:

enumerator kPORT_UnlockRegister

Pin Control Register fields [15:0] are not locked.

enumerator kPORT_LockRegister

Pin Control Register fields [15:0] are locked.

enum __port_mux

Pin mux selection.

Values:

enumerator kPORT_PinDisabledOrAnalog

Corresponding pin is disabled, but is used as an analog pin.

enumerator kPORT_MuxAsGpio

Corresponding pin is configured as GPIO.

enumerator kPORT_MuxAlt0

Chip-specific

enumerator kPORT_MuxAlt1

Chip-specific

enumerator kPORT_MuxAlt2

Chip-specific

enumerator kPORT_MuxAlt3

Chip-specific

enumerator kPORT_MuxAlt4

Chip-specific

enumerator kPORT_MuxAlt5

Chip-specific

enumerator kPORT_MuxAlt6

Chip-specific

enumerator kPORT_MuxAlt7

Chip-specific

enumerator kPORT_MuxAlt8

Chip-specific

enumerator kPORT_MuxAlt9

Chip-specific

enumerator kPORT_MuxAlt10

Chip-specific

enumerator kPORT_MuxAlt11

Chip-specific

enumerator kPORT_MuxAlt12

Chip-specific

enumerator kPORT_MuxAlt13

Chip-specific

enumerator kPORT_MuxAlt14

Chip-specific

enumerator kPORT_MuxAlt15

Chip-specific

enum _port_interrupt

Configures the interrupt generation condition.

Values:

enumerator kPORT_InterruptOrDMADisabled

Interrupt/DMA request is disabled.

enumerator kPORT_DMARisingEdge

DMA request on rising edge.

enumerator kPORT_DMAFallingEdge

DMA request on falling edge.

enumerator kPORT_DMAEitherEdge

DMA request on either edge.

enumerator kPORT_FlagRisingEdge

Flag sets on rising edge.

enumerator kPORT_FlagFallingEdge

Flag sets on falling edge.

enumerator kPORT_FlagEitherEdge

Flag sets on either edge.

enumerator kPORT_InterruptLogicZero

Interrupt when logic zero.

enumerator kPORT_InterruptRisingEdge

Interrupt on rising edge.

enumerator kPORT_InterruptFallingEdge

Interrupt on falling edge.

enumerator kPORT_InterruptEitherEdge

Interrupt on either edge.

enumerator kPORT_InterruptLogicOne

Interrupt when logic one.

enumerator kPORT_ActiveHighTriggerOutputEnable

Enable active high-trigger output.

enumerator kPORT_ActiveLowTriggerOutputEnable

Enable active low-trigger output.

enum _port_digital_filter_clock_source

Digital filter clock source selection.

Values:

enumerator kPORT_BusClock

Digital filters are clocked by the bus clock.

enumerator kPORT_LpoClock

Digital filters are clocked by the 1 kHz LPO clock.

typedef enum _port_mux port_mux_t

Pin mux selection.

typedef enum _port_interrupt port_interrupt_t

Configures the interrupt generation condition.

typedef enum _port_digital_filter_clock_source port_digital_filter_clock_source_t

Digital filter clock source selection.

typedef struct _port_digital_filter_config port_digital_filter_config_t

PORT digital filter feature configuration definition.

typedef struct _port_pin_config port_pin_config_t

PORT pin configuration structure.

FSL_COMPONENT_ID

struct _port_digital_filter_config

#include <fsl_port.h> PORT digital filter feature configuration definition.

Public Members

uint32_t digitalFilterWidth

Set digital filter width

port_digital_filter_clock_source_t clockSource

Set digital filter clockSource

struct __port_pin_config
#include <fsl_port.h> PORT pin configuration structure.

Public Members

uint16_t pullSelect
 No-pull/pull-down/pull-up select

uint16_t slewRate
 Fast/slow slew rate Configure

uint16_t passiveFilterEnable
 Passive filter enable/disable

uint16_t openDrainEnable
 Open drain enable/disable

uint16_t driveStrength
 Fast/slow drive strength configure

uint16_t lockRegister
 Lock/unlock the PCR field[15:0]

2.48 PWT: Pulse Width Timer

void PWT_Init(PWT_Type *base, const *pwt_config_t* *config)
 Ungates the PWT clock and configures the peripheral for basic operation.

Note: This API should be called at the beginning of the application using the PWT driver.

Parameters

- base – PWT peripheral base address
- config – Pointer to the user configuration structure.

void PWT_Deinit(PWT_Type *base)
 Gates the PWT clock.

Parameters

- base – PWT peripheral base address

void PWT_GetDefaultConfig(*pwt_config_t* *config)
 Fills in the PWT configuration structure with the default settings.
 The default values are:

```
config->clockSource = kPWT_BusClock;
config->prescale = kPWT_Prescale_Divide_1;
config->inputSelect = kPWT_InputPort_0;
config->enableFirstCounterLoad = false;
```

Parameters

- config – Pointer to the user configuration structure.

```
static inline void PWT_EnableInterrupts(PWT_Type *base, uint32_t mask)
```

Enables the selected PWT interrupts.

Parameters

- `base` – PWT peripheral base address
- `mask` – The interrupts to enable. This is a logical OR of members of the enumeration `pwt_interrupt_enable_t`

```
static inline void PWT_DisableInterrupts(PWT_Type *base, uint32_t mask)
```

Disables the selected PWT interrupts.

Parameters

- `base` – PWT peripheral base address
- `mask` – The interrupts to enable. This is a logical OR of members of the enumeration `pwt_interrupt_enable_t`

```
static inline uint32_t PWT_GetEnabledInterrupts(PWT_Type *base)
```

Gets the enabled PWT interrupts.

Parameters

- `base` – PWT peripheral base address

Returns

The enabled interrupts. This is the logical OR of members of the enumeration `pwt_interrupt_enable_t`

```
static inline uint32_t PWT_GetStatusFlags(PWT_Type *base)
```

Gets the PWT status flags.

Parameters

- `base` – PWT peripheral base address

Returns

The status flags. This is the logical OR of members of the enumeration `pwt_status_flags_t`

```
static inline void PWT_ClearStatusFlags(PWT_Type *base, uint32_t mask)
```

Clears the PWT status flags.

Parameters

- `base` – PWT peripheral base address
- `mask` – The status flags to clear. This is a logical OR of members of the enumeration `pwt_status_flags_t`

```
static inline void PWT_StartTimer(PWT_Type *base)
```

Starts the PWT counter.

Parameters

- `base` – PWT peripheral base address

```
static inline void PWT_StopTimer(PWT_Type *base)
```

Stops the PWT counter.

Parameters

- `base` – PWT peripheral base address

```
enum __pwt_clock_source
```

PWT clock source selection.

Values:

enumerator kPWT_BusClock

The Bus clock is used as the clock source of PWT counter

enumerator kPWT_AlternativeClock

Alternative clock is used as the clock source of PWT counter

enum __pwt_clock_prescale

PWT prescaler factor selection for clock source.

Values:

enumerator kPWT_Prescale_Divide_1

PWT clock divided by 1

enumerator kPWT_Prescale_Divide_2

PWT clock divided by 2

enumerator kPWT_Prescale_Divide_4

PWT clock divided by 4

enumerator kPWT_Prescale_Divide_8

PWT clock divided by 8

enumerator kPWT_Prescale_Divide_16

PWT clock divided by 16

enumerator kPWT_Prescale_Divide_32

PWT clock divided by 32

enumerator kPWT_Prescale_Divide_64

PWT clock divided by 64

enumerator kPWT_Prescale_Divide_128

PWT clock divided by 128

enum __pwt_input_select

PWT input port selection.

Values:

enumerator kPWT_InputPort_0

PWT input comes from PWTIN[0]

enumerator kPWT_InputPort_1

PWT input comes from PWTIN[1]

enumerator kPWT_InputPort_2

PWT input comes from PWTIN[2]

enumerator kPWT_InputPort_3

PWT input comes from PWTIN[3]

enum __pwt_interrupt_enable

List of PWT interrupts.

Values:

enumerator kPWT_PulseWidthReadyInterruptEnable

Pulse width data ready interrupt

enumerator kPWT_CounterOverflowInterruptEnable

Counter overflow interrupt

enum `_pwt_status_flags`

List of PWT flags.

Values:

enumerator `kPWT_CounterOverflowFlag`

Counter overflow flag

enumerator `kPWT_PulseWidthValidFlag`

Pulse width valid flag

typedef enum `_pwt_clock_source` `pwt_clock_source_t`

PWT clock source selection.

typedef enum `_pwt_clock_prescale` `pwt_clock_prescale_t`

PWT prescaler factor selection for clock source.

typedef enum `_pwt_input_select` `pwt_input_select_t`

PWT input port selection.

typedef struct `_pwt_config` `pwt_config_t`

PWT configuration structure.

This structure holds the configuration settings for the PWT peripheral. To initialize this structure to reasonable defaults, call the `PWT_GetDefaultConfig()` function and pass a pointer to the configuration structure instance.

The configuration structure can be made constant so as to reside in flash.

static inline uint16_t `PWT_GetCurrentTimerCount(PWT_Type *base)`

Reads the current counter value.

This function returns the timer counting value

Parameters

- `base` – PWT peripheral base address

Returns

Current 16-bit timer counter value

static inline uint16_t `PWT_ReadPositivePulseWidth(PWT_Type *base)`

Reads the positive pulse width.

This function reads the low and high registers and returns the 16-bit positive pulse width

Parameters

- `base` – PWT peripheral base address.

Returns

The 16-bit positive pulse width.

static inline uint16_t `PWT_ReadNegativePulseWidth(PWT_Type *base)`

Reads the negative pulse width.

This function reads the low and high registers and returns the 16-bit negative pulse width

Parameters

- `base` – PWT peripheral base address.

Returns

The 16-bit negative pulse width.

```
static inline void PWT_Reset(PWT_Type *base)
```

Performs a software reset on the PWT module.

Parameters

- `base` – PWT peripheral base address

```
FSL_PWT_DRIVER_VERSION
```

Version 2.0.2

```
struct __pwt_config
```

#include <fsl_pwt.h> PWT configuration structure.

This structure holds the configuration settings for the PWT peripheral. To initialize this structure to reasonable defaults, call the `PWT_GetDefaultConfig()` function and pass a pointer to the configuration structure instance.

The configuration structure can be made constant so as to reside in flash.

Public Members

```
pwt_clock_source_t clockSource
```

Clock source for the counter

```
pwt_clock_prescale_t prescale
```

Pre-scaler to divide down the clock

```
pwt_input_select_t inputSelect
```

PWT Pulse input port selection

```
bool enableFirstCounterLoad
```

true: Load the first counter value to registers; false: Do not load first counter value

2.49 RCM: Reset Control Module Driver

```
static inline void RCM_GetVersionId(RCM_Type *base, rcm_version_id_t *versionId)
```

Gets the RCM version ID.

This function gets the RCM version ID including the major version number, the minor version number, and the feature specification number.

Parameters

- `base` – RCM peripheral base address.
- `versionId` – Pointer to the version ID structure.

```
static inline uint32_t RCM_GetResetSourceImplementedStatus(RCM_Type *base)
```

Gets the reset source implemented status.

This function gets the RCM parameter that indicates whether the corresponding reset source is implemented. Use source masks defined in the `rcm_reset_source_t` to get the desired source status.

This is an example.

```
uint32_t status;
```

To test whether the MCU is reset using Watchdog.

```
status = RCM_GetResetSourceImplementedStatus(RCM) & (kRCM_SourceWdog | kRCM_SourcePin);
```

Parameters

- base – RCM peripheral base address.

Returns

All reset source implemented status bit map.

static inline uint32_t RCM_GetPreviousResetSources(RCM_Type *base)

Gets the reset source status which caused a previous reset.

This function gets the current reset source status. Use source masks defined in the `rcm_reset_source_t` to get the desired source status.

This is an example.

```
uint32_t resetStatus;

To get all reset source statuses.
resetStatus = RCM_GetPreviousResetSources(RCM) & kRCM_SourceAll;

To test whether the MCU is reset using Watchdog.
resetStatus = RCM_GetPreviousResetSources(RCM) & kRCM_SourceWdog;

To test multiple reset sources.
resetStatus = RCM_GetPreviousResetSources(RCM) & (kRCM_SourceWdog | kRCM_SourcePin);
```

Parameters

- base – RCM peripheral base address.

Returns

All reset source status bit map.

static inline uint32_t RCM_GetStickyResetSources(RCM_Type *base)

Gets the sticky reset source status.

This function gets the current reset source status that has not been cleared by software for a specific source.

This is an example.

```
uint32_t resetStatus;

To get all reset source statuses.
resetStatus = RCM_GetStickyResetSources(RCM) & kRCM_SourceAll;

To test whether the MCU is reset using Watchdog.
resetStatus = RCM_GetStickyResetSources(RCM) & kRCM_SourceWdog;

To test multiple reset sources.
resetStatus = RCM_GetStickyResetSources(RCM) & (kRCM_SourceWdog | kRCM_SourcePin);
```

Parameters

- base – RCM peripheral base address.

Returns

All reset source status bit map.

static inline void RCM_ClearStickyResetSources(RCM_Type *base, uint32_t sourceMasks)

Clears the sticky reset source status.

This function clears the sticky system reset flags indicated by source masks.

This is an example.

Clears multiple reset sources.

```
RCM_ClearStickyResetSources(kRCM_SourceWdog | kRCM_SourcePin);
```

Parameters

- base – RCM peripheral base address.
- sourceMasks – reset source status bit map

```
void RCM_ConfigureResetPinFilter(RCM_Type *base, const rcm_reset_pin_filter_config_t *config)
```

Configures the reset pin filter.

This function sets the reset pin filter including the filter source, filter width, and so on.

Parameters

- base – RCM peripheral base address.
- config – Pointer to the configuration structure.

```
static inline bool RCM_GetEasyPortModePinStatus(RCM_Type *base)
```

Gets the EZP_MS_B pin assert status.

This function gets the easy port mode status (EZP_MS_B) pin assert status.

Parameters

- base – RCM peripheral base address.

Returns

status true - asserted, false - reasserted

```
static inline rcm_boot_rom_config_t RCM_GetBootRomSource(RCM_Type *base)
```

Gets the ROM boot source.

This function gets the ROM boot source during the last chip reset.

Parameters

- base – RCM peripheral base address.

Returns

The ROM boot source.

```
static inline void RCM_ClearBootRomSource(RCM_Type *base)
```

Clears the ROM boot source flag.

This function clears the ROM boot source flag.

Parameters

- base – Register base address of RCM

```
void RCM_SetForceBootRomSource(RCM_Type *base, rcm_boot_rom_config_t config)
```

Forces the boot from ROM.

This function forces booting from ROM during all subsequent system resets.

Parameters

- base – RCM peripheral base address.
- config – Boot configuration.

```
static inline void RCM_SetSystemResetInterruptConfig(RCM_Type *base, uint32_t intMask,
rsm_reset_delay_t delay)
```

Sets the system reset interrupt configuration.

For a graceful shut down, the RCM supports delaying the assertion of the system reset for a period of time when the reset interrupt is generated. This function can be used to enable the interrupt and the delay period. The interrupts are passed in as bit mask. See `rcm_int_t` for details. For example, to delay a reset for 512 LPO cycles after the WDOG timeout or loss-of-clock occurs, configure as follows: `RCM_SetSystemResetInterruptConfig(kRCM_IntWatchDog | kRCM_IntLossOfClk, kRCM_ResetDelay512Lpo);`

Parameters

- `base` – RCM peripheral base address.
- `intMask` – Bit mask of the system reset interrupts to enable. See `rcm_interrupt_enable_t` for details.
- `delay` – Bit mask of the system reset interrupts to enable.

`FSL_RCM_DRIVER_VERSION`

RCM driver version 2.0.4.

`enum _rcm_reset_source`

System Reset Source Name definitions.

Values:

enumerator `kRCM_SourceWakeup`

Low-leakage wakeup reset

enumerator `kRCM_SourceLvd`

Low-voltage detect reset

enumerator `kRCM_SourceLoc`

Loss of clock reset

enumerator `kRCM_SourceLol`

Loss of lock reset

enumerator `kRCM_SourceWdog`

Watchdog reset

enumerator `kRCM_SourcePin`

External pin reset

enumerator `kRCM_SourcePor`

Power on reset

enumerator `kRCM_SourceJtag`

JTAG generated reset

enumerator `kRCM_SourceLockup`

Core lock up reset

enumerator `kRCM_SourceSw`

Software reset

enumerator `kRCM_SourceMdmmap`

MDM-AP system reset

enumerator `kRCM_SourceEzpt`

EzPort reset

enumerator `kRCM_SourceSackerr`

Parameter could get all reset flags

enumerator kRCM_SourceAll

enum _rcm_run_wait_filter_mode

Reset pin filter select in Run and Wait modes.

Values:

enumerator kRCM_FilterDisable

All filtering disabled

enumerator kRCM_FilterBusClock

Bus clock filter enabled

enumerator kRCM_FilterLpoClock

LPO clock filter enabled

enum _rcm_boot_rom_config

Boot from ROM configuration.

Values:

enumerator kRCM_BootFlash

Boot from flash

enumerator kRCM_BootRomCfg0

Boot from boot ROM due to BOOTCFG0

enumerator kRCM_BootRomFopt

Boot from boot ROM due to FOPT[7]

enumerator kRCM_BootRomBoth

Boot from boot ROM due to both BOOTCFG0 and FOPT[7]

enum _rcm_reset_delay

Maximum delay time from interrupt asserts to system reset.

Values:

enumerator kRCM_ResetDelay8Lpo

Delay 8 LPO cycles.

enumerator kRCM_ResetDelay32Lpo

Delay 32 LPO cycles.

enumerator kRCM_ResetDelay128Lpo

Delay 128 LPO cycles.

enumerator kRCM_ResetDelay512Lpo

Delay 512 LPO cycles.

enum _rcm_interrupt_enable

System reset interrupt enable bit definitions.

Values:

enumerator kRCM_IntNone

No interrupt enabled.

enumerator kRCM_IntLossOfClk

Loss of clock interrupt.

enumerator kRCM_IntLossOfLock

Loss of lock interrupt.

enumerator `kRCM_IntWatchDog`
Watch dog interrupt.

enumerator `kRCM_IntExternalPin`
External pin interrupt.

enumerator `kRCM_IntGlobal`
Global interrupts.

enumerator `kRCM_IntCoreLockup`
Core lock up interrupt

enumerator `kRCM_IntSoftware`
software interrupt

enumerator `kRCM_IntStopModeAckErr`
Stop mode ACK error interrupt.

enumerator `kRCM_IntCore1`
Core 1 interrupt.

enumerator `kRCM_IntAll`
Enable all interrupts.

typedef enum `_rcm_reset_source` `rcm_reset_source_t`
System Reset Source Name definitions.

typedef enum `_rcm_run_wait_filter_mode` `rcm_run_wait_filter_mode_t`
Reset pin filter select in Run and Wait modes.

typedef enum `_rcm_boot_rom_config` `rcm_boot_rom_config_t`
Boot from ROM configuration.

typedef enum `_rcm_reset_delay` `rcm_reset_delay_t`
Maximum delay time from interrupt asserts to system reset.

typedef enum `_rcm_interrupt_enable` `rcm_interrupt_enable_t`
System reset interrupt enable bit definitions.

typedef struct `_rcm_version_id` `rcm_version_id_t`
IP version ID definition.

typedef struct `_rcm_reset_pin_filter_config` `rcm_reset_pin_filter_config_t`
Reset pin filter configuration.

struct `_rcm_version_id`
`#include <fsl_rcm.h>` IP version ID definition.

Public Members

uint16_t `feature`
Feature Specification Number.

uint8_t `minor`
Minor version number.

uint8_t `major`
Major version number.

struct `_rcm_reset_pin_filter_config`
`#include <fsl_rcm.h>` Reset pin filter configuration.

Public Members

`bool enableFilterInStop`

Reset pin filter select in stop mode.

`rcm_run_wait_filter_mode_t filterInRunWait`

Reset pin filter in run/wait mode.

`uint8_t busClockFilterCount`

Reset pin bus clock filter width.

2.50 RTC: Real Time Clock

`void RTC_Init(RTC_Type *base, const rtc_config_t *config)`

Un gates the RTC clock and configures the peripheral for basic operation.

This function issues a software reset if the timer invalid flag is set.

Note: This API should be called at the beginning of the application using the RTC driver.

Parameters

- `base` – RTC peripheral base address
- `config` – Pointer to the user's RTC configuration structure.

`static inline void RTC_Deinit(RTC_Type *base)`

Stops the timer and gate the RTC clock.

Parameters

- `base` – RTC peripheral base address

`void RTC_GetDefaultConfig(rtc_config_t *config)`

Fills in the RTC config struct with the default settings.

The default values are as follows.

```
config->wakeupSelect = false;
config->updateMode = false;
config->supervisorAccess = false;
config->compensationInterval = 0;
config->compensationTime = 0;
```

Parameters

- `config` – Pointer to the user's RTC configuration structure.

`status_t RTC_SetDatetime(RTC_Type *base, const rtc_datetime_t *datetime)`

Sets the RTC date and time according to the given time structure.

The RTC counter must be stopped prior to calling this function because writes to the RTC seconds register fail if the RTC counter is running.

Parameters

- `base` – RTC peripheral base address
- `datetime` – Pointer to the structure where the date and time details are stored.

Returns

kStatus_Success: Success in setting the time and starting the RTC
kStatus_InvalidArgument: Error because the datetime format is incorrect

void RTC_GetDatetime(RTC_Type *base, rtc_datetime_t *datetime)

Gets the RTC time and stores it in the given time structure.

Parameters

- base – RTC peripheral base address
- datetime – Pointer to the structure where the date and time details are stored.

status_t RTC_SetAlarm(RTC_Type *base, const rtc_datetime_t *alarmTime)

Sets the RTC alarm time.

The function checks whether the specified alarm time is greater than the present time. If not, the function does not set the alarm and returns an error.

Parameters

- base – RTC peripheral base address
- alarmTime – Pointer to the structure where the alarm time is stored.

Returns

kStatus_Success: success in setting the RTC alarm
kStatus_InvalidArgument: Error because the alarm datetime format is incorrect
kStatus_Fail: Error because the alarm time has already passed

void RTC_GetAlarm(RTC_Type *base, rtc_datetime_t *datetime)

Returns the RTC alarm time.

Parameters

- base – RTC peripheral base address
- datetime – Pointer to the structure where the alarm date and time details are stored.

void RTC_EnableInterrupts(RTC_Type *base, uint32_t mask)

Enables the selected RTC interrupts.

Parameters

- base – RTC peripheral base address
- mask – The interrupts to enable. This is a logical OR of members of the enumeration rtc_interrupt_enable_t

void RTC_DisableInterrupts(RTC_Type *base, uint32_t mask)

Disables the selected RTC interrupts.

Parameters

- base – RTC peripheral base address
- mask – The interrupts to enable. This is a logical OR of members of the enumeration rtc_interrupt_enable_t

uint32_t RTC_GetEnabledInterrupts(RTC_Type *base)

Gets the enabled RTC interrupts.

Parameters

- base – RTC peripheral base address

Returns

The enabled interrupts. This is the logical OR of members of the enumeration `rtc_interrupt_enable_t`

```
uint32_t RTC_GetStatusFlags(RTC_Type *base)
```

Gets the RTC status flags.

Parameters

- `base` – RTC peripheral base address

Returns

The status flags. This is the logical OR of members of the enumeration `rtc_status_flags_t`

```
void RTC_ClearStatusFlags(RTC_Type *base, uint32_t mask)
```

Clears the RTC status flags.

Parameters

- `base` – RTC peripheral base address
- `mask` – The status flags to clear. This is a logical OR of members of the enumeration `rtc_status_flags_t`

```
static inline void RTC_EnableOscillatorClock(RTC_Type *base, bool enable)
```

Enable/Disable RTC 32kHz Oscillator clock.

Note: After setting this bit, wait the oscillator startup time before enabling the time counter to allow the 32.768 kHz clock time to stabilize.

Parameters

- `base` – RTC peripheral base address
- `enable` – Enable/Disable RTC 32.768 kHz clock

```
static inline void RTC_SetClockSource(RTC_Type *base)
```

Set RTC clock source.

Deprecated:

Do not use this function. It has been superceded by `RTC_EnableOscillatorClock`

Note: After setting this bit, wait the oscillator startup time before enabling the time counter to allow the 32.768 kHz clock time to stabilize.

Parameters

- `base` – RTC peripheral base address

```
static inline void RTC_EnableLPOClock(RTC_Type *base, bool enable)
```

Enable/Disable RTC 1kHz LPO clock.

Note: After setting this bit, RTC prescaler increments using the LPO 1kHz clock and not the RTC 32kHz crystal clock.

Parameters

- `base` – RTC peripheral base address

- enable – Enable/Disable RTC 1kHz LPO clock

static inline void RTC_StartTimer(RTC_Type *base)

Starts the RTC time counter.

After calling this function, the timer counter increments once a second provided SR[TOF] or SR[TIF] are not set.

Parameters

- base – RTC peripheral base address

static inline void RTC_StopTimer(RTC_Type *base)

Stops the RTC time counter.

RTC's seconds register can be written to only when the timer is stopped.

Parameters

- base – RTC peripheral base address

void RTC_GetMonotonicCounter(RTC_Type *base, uint64_t *counter)

Reads the values of the Monotonic Counter High and Monotonic Counter Low and returns them as a single value.

Parameters

- base – RTC peripheral base address
- counter – Pointer to variable where the value is stored.

void RTC_SetMonotonicCounter(RTC_Type *base, uint64_t counter)

Writes values Monotonic Counter High and Monotonic Counter Low by decomposing the given single value. The Monotonic Overflow Flag in RTC_SR is cleared due to the API.

Parameters

- base – RTC peripheral base address
- counter – Counter value

status_t RTC_IncrementMonotonicCounter(RTC_Type *base)

Increments the Monotonic Counter by one.

Increments the Monotonic Counter (registers RTC_MCLR and RTC_MCHR accordingly) by setting the monotonic counter enable (MER[MCE]) and then writing to the RTC_MCLR register. A write to the monotonic counter low that causes it to overflow also increments the monotonic counter high.

Parameters

- base – RTC peripheral base address

Returns

kStatus_Success: success
kStatus_Fail: error occurred, either time invalid or monotonic overflow flag was found

FSL_RTC_DRIVER_VERSION

Version 2.3.3

enum _rtc_interrupt_enable

List of RTC interrupts.

Values:

enumerator kRTC_TimeInvalidInterruptEnable

Time invalid interrupt.

enumerator kRTC_TimeOverflowInterruptEnable
Time overflow interrupt.

enumerator kRTC_AlarmInterruptEnable
Alarm interrupt.

enumerator kRTC_MonotonicOverflowInterruptEnable
Monotonic Overflow Interrupt Enable

enumerator kRTC_SecondsInterruptEnable
Seconds interrupt.

enumerator kRTC_TestModeInterruptEnable

enumerator kRTC_FlashSecurityInterruptEnable

enumerator kRTC_TamperPinInterruptEnable

enumerator kRTC_SecurityModuleInterruptEnable

enumerator kRTC_LossOfClockInterruptEnable

enum _rtc_status_flags
List of RTC flags.

Values:

enumerator kRTC_TimeInvalidFlag
Time invalid flag

enumerator kRTC_TimeOverflowFlag
Time overflow flag

enumerator kRTC_AlarmFlag
Alarm flag

enumerator kRTC_MonotonicOverflowFlag
Monotonic Overflow Flag

enumerator kRTC_TamperInterruptDetectFlag
Tamper interrupt detect flag

enumerator kRTC_TestModeFlag

enumerator kRTC_FlashSecurityFlag

enumerator kRTC_TamperPinFlag

enumerator kRTC_SecurityTamperFlag

enumerator kRTC_LossOfClockTamperFlag

enum _rtc_osc_cap_load
List of RTC Oscillator capacitor load settings.

Values:

enumerator kRTC_Capacitor_2p
2 pF capacitor load

enumerator kRTC_Capacitor_4p
4 pF capacitor load

enumerator kRTC_Capacitor_8p
8 pF capacitor load

enumerator `kRTC_Capacitor_16p`

16 pF capacitor load

typedef enum *rtc_interrupt_enable* `rtc_interrupt_enable_t`

List of RTC interrupts.

typedef enum *rtc_status_flags* `rtc_status_flags_t`

List of RTC flags.

typedef enum *rtc_osc_cap_load* `rtc_osc_cap_load_t`

List of RTC Oscillator capacitor load settings.

typedef struct *rtc_datetime* `rtc_datetime_t`

Structure is used to hold the date and time.

typedef struct *rtc_pin_config* `rtc_pin_config_t`

RTC pin config structure.

typedef struct *rtc_config* `rtc_config_t`

RTC config structure.

This structure holds the configuration settings for the RTC peripheral. To initialize this structure to reasonable defaults, call the `RTC_GetDefaultConfig()` function and pass a pointer to your config structure instance.

The config struct can be made const so it resides in flash

static inline uint32_t `RTC_GetTamperTimeSeconds(RTC_Type *base)`

Get the RTC tamper time seconds.

Parameters

- `base` – RTC peripheral base address

static inline void `RTC_SetOscCapLoad(RTC_Type *base, uint32_t capLoad)`

This function sets the specified capacitor configuration for the RTC oscillator.

Parameters

- `base` – RTC peripheral base address
- `capLoad` – Oscillator loads to enable. This is a logical OR of members of the enumeration `rtc_osc_cap_load_t`

static inline void `RTC_Reset(RTC_Type *base)`

Performs a software reset on the RTC module.

This resets all RTC registers except for the SWR bit and the `RTC_WAR` and `RTC_RAR` registers. The SWR bit is cleared by software explicitly clearing it.

Parameters

- `base` – RTC peripheral base address

static inline void `RTC_EnableWakeUpPin(RTC_Type *base, bool enable)`

Enables or disables the RTC Wakeup Pin Operation.

This function enable or disable RTC Wakeup Pin. The wakeup pin is optional and not available on all devices.

Parameters

- `base` – `RTC_Type` base pointer.
- `enable` – true to enable, false to disable.

struct `_rtc_datetime`

#include <fsl_rtc.h> Structure is used to hold the date and time.

Public Members

uint16_t year

Range from 1970 to 2099.

uint8_t month

Range from 1 to 12.

uint8_t day

Range from 1 to 31 (depending on month).

uint8_t hour

Range from 0 to 23.

uint8_t minute

Range from 0 to 59.

uint8_t second

Range from 0 to 59.

struct _rtc_pin_config

#include <fsl_rtc.h> RTC pin config structure.

Public Members

bool inputLogic

true: Tamper pin input data is logic one. false: Tamper pin input data is logic zero.

bool pinActiveLow

true: Tamper pin is active low. false: Tamper pin is active high.

bool filterEnable

true: Input filter is enabled on the tamper pin. false: Input filter is disabled on the tamper pin.

bool pullSelectNegate

true: Tamper pin pull resistor direction will negate the tamper pin. false: Tamper pin pull resistor direction will assert the tamper pin.

bool pullEnable

true: Pull resistor is enabled on tamper pin. false: Pull resistor is disabled on tamper pin.

struct _rtc_config

#include <fsl_rtc.h> RTC config structure.

This structure holds the configuration settings for the RTC peripheral. To initialize this structure to reasonable defaults, call the `RTC_GetDefaultConfig()` function and pass a pointer to your config structure instance.

The config struct can be made const so it resides in flash

Public Members

bool wakeupSelect

true: Wakeup pin outputs the 32 KHz clock; false: Wakeup pin used to wakeup the chip

bool updateMode

true: Registers can be written even when locked under certain conditions, false: No writes allowed when registers are locked

bool supervisorAccess

true: Non-supervisor accesses are allowed; false: Non-supervisor accesses are not supported

uint32_t compensationInterval

Compensation interval that is written to the CIR field in RTC TCR Register

uint32_t compensationTime

Compensation time that is written to the TCR field in RTC TCR Register

2.51 SIM: System Integration Module Driver

FSL_SIM_DRIVER_VERSION

Driver version.

typedef struct *_sim_uid* sim_uid_t

Unique ID.

void SIM_GetUniqueId(*sim_uid_t* *uid)

Gets the unique identification register value.

Parameters

- uid – Pointer to the structure to save the UID value.

struct *_sim_uid*

#include <*fsl_sim.h*> Unique ID.

Public Members

uint32_t MH

UIDMH.

uint32_t ML

UIDML.

uint32_t L

UIDL.

2.52 SMC: System Mode Controller Driver

static inline void SMC_GetVersionId(SMC_Type *base, *smc_version_id_t* *versionId)

Gets the SMC version ID.

This function gets the SMC version ID, including major version number, minor version number, and feature specification number.

Parameters

- base – SMC peripheral base address.
- versionId – Pointer to the version ID structure.

void SMC_GetParam(SMC_Type *base, *smc_param_t* *param)

Gets the SMC parameter.

This function gets the SMC parameter including the enabled power mdoes.

Parameters

- base – SMC peripheral base address.
- param – Pointer to the SMC param structure.

static inline void SMC_SetPowerModeProtection(SMC_Type *base, uint8_t allowedModes)

Configures all power mode protection settings.

This function configures the power mode protection settings for supported power modes in the specified chip family. The available power modes are defined in the `smc_power_mode_protection_t`. This should be done at an early system level initialization stage. See the reference manual for details. This register can only write once after the power reset.

The allowed modes are passed as bit map. For example, to allow LLS and VLLS, use `SMC_SetPowerModeProtection(kSMC_AllowPowerModeVlls | kSMC_AllowPowerModeVlps)`. To allow all modes, use `SMC_SetPowerModeProtection(kSMC_AllowPowerModeAll)`.

Parameters

- base – SMC peripheral base address.
- allowedModes – Bitmap of the allowed power modes.

static inline *smc_power_state_t* SMC_GetPowerModeState(SMC_Type *base)

Gets the current power mode status.

This function returns the current power mode status. After the application switches the power mode, it should always check the status to check whether it runs into the specified mode or not. The application should check this mode before switching to a different mode. The system requires that only certain modes can switch to other specific modes. See the reference manual for details and the `smc_power_state_t` for information about the power status.

Parameters

- base – SMC peripheral base address.

Returns

Current power mode status.

void SMC_PreEnterStopModes(void)

Prepares to enter stop modes.

This function should be called before entering STOP/VLPS/LLS/VLLS modes.

void SMC_PostExitStopModes(void)

Recovers after wake up from stop modes.

This function should be called after wake up from STOP/VLPS/LLS/VLLS modes. It is used with `SMC_PreEnterStopModes`.

void SMC_PreEnterWaitModes(void)

Prepares to enter wait modes.

This function should be called before entering WAIT/VLPW modes.

void SMC_PostExitWaitModes(void)

Recovers after wake up from stop modes.

This function should be called after wake up from WAIT/VLPW modes. It is used with `SMC_PreEnterWaitModes`.

status_t SMC_SetPowerModeRun(SMC_Type *base)

Configures the system to RUN power mode.

Parameters

- base – SMC peripheral base address.

Returns

SMC configuration error code.

status_t SMC_SetPowerModeHsrn(SMC_Type *base)

Configures the system to HSRUN power mode.

Parameters

- base – SMC peripheral base address.

Returns

SMC configuration error code.

status_t SMC_SetPowerModeWait(SMC_Type *base)

Configures the system to WAIT power mode.

Parameters

- base – SMC peripheral base address.

Returns

SMC configuration error code.

status_t SMC_SetPowerModeStop(SMC_Type *base, *smc_partial_stop_option_t* option)

Configures the system to Stop power mode.

Parameters

- base – SMC peripheral base address.
- option – Partial Stop mode option.

Returns

SMC configuration error code.

status_t SMC_SetPowerModeVlpr(SMC_Type *base, bool wakeupMode)

Configures the system to VLPR power mode.

Parameters

- base – SMC peripheral base address.
- wakeupMode – Enter Normal Run mode if true, else stay in VLPR mode.

Returns

SMC configuration error code.

status_t SMC_SetPowerModeVlpr(SMC_Type *base)

Configures the system to VLPW power mode.

Parameters

- base – SMC peripheral base address.

Returns

SMC configuration error code.

status_t SMC_SetPowerModeVlps(SMC_Type *base)

Configures the system to VLPS power mode.

Parameters

- base – SMC peripheral base address.

Returns

SMC configuration error code.

status_t SMC_SetPowerModeLls(SMC_Type *base, const *smc_power_mode_lls_config_t* *config)
Configures the system to LLS power mode.

Parameters

- base – SMC peripheral base address.
- config – The LLS power mode configuration structure

Returns

SMC configuration error code.

status_t SMC_SetPowerModeVlls(SMC_Type *base, const *smc_power_mode_vlls_config_t* *config)
Configures the system to VLLS power mode.

Parameters

- base – SMC peripheral base address.
- config – The VLLS power mode configuration structure.

Returns

SMC configuration error code.

FSL_SMC_DRIVER_VERSION
SMC driver version.

enum _smc_power_mode_protection
Power Modes Protection.

Values:

enumerator kSMC_AllowPowerModeVlls
Allow Very-low-leakage Stop Mode.

enumerator kSMC_AllowPowerModeLls
Allow Low-leakage Stop Mode.

enumerator kSMC_AllowPowerModeVlp
Allow Very-Low-power Mode.

enumerator kSMC_AllowPowerModeHsrn
Allow High-speed Run mode.

enumerator kSMC_AllowPowerModeAll
Allow all power mode.

enum _smc_power_state
Power Modes in PMSTAT.

Values:

enumerator kSMC_PowerStateRun
0000_0001 - Current power mode is RUN

enumerator kSMC_PowerStateStop
0000_0010 - Current power mode is STOP

enumerator kSMC_PowerStateVlpr
0000_0100 - Current power mode is VLPR

enumerator kSMC_PowerStateVlpw
0000_1000 - Current power mode is VLPW

enumerator kSMC_PowerStateVlps
0001_0000 - Current power mode is VLPS

enumerator kSMC_PowerStateLls
0010_0000 - Current power mode is LLS

enumerator kSMC_PowerStateVlls
0100_0000 - Current power mode is VLLS

enumerator kSMC_PowerStateHsrn
1000_0000 - Current power mode is HSRUN

enum __smc_run_mode
Run mode definition.

Values:

enumerator kSMC_RunNormal
Normal RUN mode.

enumerator kSMC_RunVlpr
Very-low-power RUN mode.

enumerator kSMC_Hsrn
High-speed Run mode (HSRUN).

enum __smc_stop_mode
Stop mode definition.

Values:

enumerator kSMC_StopNormal
Normal STOP mode.

enumerator kSMC_StopVlps
Very-low-power STOP mode.

enumerator kSMC_StopLls
Low-leakage Stop mode.

enumerator kSMC_StopVlls
Very-low-leakage Stop mode.

enum __smc_stop_submode
VLLS/LLS stop sub mode definition.

Values:

enumerator kSMC_StopSub0
Stop submode 0, for VLLS0/LLS0.

enumerator kSMC_StopSub1
Stop submode 1, for VLLS1/LLS1.

enumerator kSMC_StopSub2
Stop submode 2, for VLLS2/LLS2.

enumerator kSMC_StopSub3
Stop submode 3, for VLLS3/LLS3.

enum __smc_partial_stop_mode
Partial STOP option.

Values:

enumerator kSMC_PartialStop
STOP - Normal Stop mode

enumerator kSMC_PartialStop1

Partial Stop with both system and bus clocks disabled

enumerator kSMC_PartialStop2

Partial Stop with system clock disabled and bus clock enabled

_smc_status, SMC configuration status.

Values:

enumerator kStatus_SMC_StopAbort

Entering Stop mode is abort

typedef enum _smc_power_mode_protection smc_power_mode_protection_t

Power Modes Protection.

typedef enum _smc_power_state smc_power_state_t

Power Modes in PMSTAT.

typedef enum _smc_run_mode smc_run_mode_t

Run mode definition.

typedef enum _smc_stop_mode smc_stop_mode_t

Stop mode definition.

typedef enum _smc_stop_submode smc_stop_submode_t

VLLS/LLS stop sub mode definition.

typedef enum _smc_partial_stop_mode smc_partial_stop_option_t

Partial STOP option.

typedef struct _smc_version_id smc_version_id_t

IP version ID definition.

typedef struct _smc_param smc_param_t

IP parameter definition.

typedef struct _smc_power_mode_lls_config smc_power_mode_lls_config_t

SMC Low-Leakage Stop power mode configuration.

typedef struct _smc_power_mode_vlls_config smc_power_mode_vlls_config_t

SMC Very Low-Leakage Stop power mode configuration.

struct _smc_version_id

#include <fsl_smc.h> IP version ID definition.

Public Members

uint16_t feature

Feature Specification Number.

uint8_t minor

Minor version number.

uint8_t major

Major version number.

struct _smc_param

#include <fsl_smc.h> IP parameter definition.

Public Members

bool hsruntimeEnable
HSRUN mode enable.

bool llsEnable
LLS mode enable.

bool lls2Enable
LLS2 mode enable.

bool vlls0Enable
VLLS0 mode enable.

struct __smc_power_mode_lls_config
#include <fsl_smc.h> SMC Low-Leakage Stop power mode configuration.

Public Members

smc_stop_submode_t subMode
Low-leakage Stop sub-mode

bool enableLpoClock
Enable LPO clock in LLS mode

struct __smc_power_mode_vlls_config
#include <fsl_smc.h> SMC Very Low-Leakage Stop power mode configuration.

Public Members

smc_stop_submode_t subMode
Very Low-leakage Stop sub-mode

bool enablePorDetectInVlls0
Enable Power on reset detect in VLLS mode

bool enableRam2InVlls2
Enable RAM2 power in VLLS2

bool enableLpoClock
Enable LPO clock in VLLS mode

2.53 TRGMUX: Trigger Mux Driver

static inline void TRGMUX_LockRegister(TRGMUX_Type *base, uint32_t index)
Sets the flag of the register which is used to mark writeable.

The function sets the flag of the register which is used to mark writeable. Example:

```
TRGMUX_LockRegister(TRGMUX0, kTRGMUX_Trgmux0Dmamux0);
```

Parameters

- base – TRGMUX peripheral base address.
- index – The index of the TRGMUX register, see the enum trgmux_device_t defined in <SOC>.h.

```
status_t TRGMUX_SetTriggerSource(TRGMUX_Type *base, uint32_t index,
                                trgmux_trigger_input_t input, uint32_t trigger_src)
```

Configures the trigger source of the appointed peripheral.

The function configures the trigger source of the appointed peripheral. Example:

```
TRGMUX_SetTriggerSource(TRGMUX0, kTRGMUX_Trgmux0Dmamux0, kTRGMUX_TriggerInput0,
    ↪ kTRGMUX_SourcePortPin);
```

Parameters

- `base` – TRGMUX peripheral base address.
- `index` – The index of the TRGMUX register, see the enum `trgmux_device_t` defined in `<SOC>.h`.
- `input` – The MUX select for peripheral trigger input
- `trigger_src` – The trigger inputs for various peripherals. See the enum `trgmux_source_t` defined in `<SOC>.h`.

Return values

- `kStatus_Success` – Configured successfully.
- `kStatus_TRGMUX_Locked` – Configuration failed because the register is locked.

FSL_TRGMUX_DRIVER_VERSION

TRGMUX driver version.

TRGMUX configure status.

Values:

enumerator `kStatus_TRGMUX_Locked`

Configure failed for register is locked

enum `_trgmux_trigger_input`

Defines the MUX select for peripheral trigger input.

Values:

enumerator `kTRGMUX_TriggerInput0`

The MUX select for peripheral trigger input 0

enumerator `kTRGMUX_TriggerInput1`

The MUX select for peripheral trigger input 1

enumerator `kTRGMUX_TriggerInput2`

The MUX select for peripheral trigger input 2

enumerator `kTRGMUX_TriggerInput3`

The MUX select for peripheral trigger input 3

typedef enum `_trgmux_trigger_input` `trgmux_trigger_input_t`

Defines the MUX select for peripheral trigger input.

2.54 Tsi_v5_driver

enum _tsi_main_clock_selection

TSI main clock selection.

These constants set the tsi main clock.

Values:

enumerator kTSI_MainClockSlection_0

Set TSI main clock frequency to 20.72MHz

enumerator kTSI_MainClockSlection_1

Set TSI main clock frequency to 16.65MHz

enumerator kTSI_MainClockSlection_2

Set TSI main clock frequency to 13.87MHz

enumerator kTSI_MainClockSlection_3

Set TSI main clock frequency to 11.91MHz

enum _tsi_sensing_mode_selection

TSI sensing mode selection.

These constants set the tsi sensing mode.

Values:

enumerator kTSI_SensingModeSlection_Self

Set TSI sensing mode to self-cap mode

enumerator kTSI_SensingModeSlection_Mutual

Set TSI sensing mode to mutual-cap mode

enum _tsi_dvolt_option

TSI DVOLT settings.

These bits indicate the comparator vp, vm and dvolt voltage.

Values:

enumerator kTSI_DvoltOption_0

DVOLT value option 0, the value may differ on different platforms

enumerator kTSI_DvoltOption_1

DVOLT value option 1, the value may differ on different platforms

enumerator kTSI_DvoltOption_2

DVOLT value option 2, the value may differ on different platforms

enumerator kTSI_DvoltOption_3

DVOLT value option 3, the value may differ on different platforms

enum _tsi_sensitivity_xdn_option

TSI sensitivity ajustment (XDN option).

These constants define the tsi sensitivity ajustment in self-cap mode, when TSI_MODE[S_SEN] = 1.

Values:

enumerator kTSI_SensitivityXdnOption_0

Adjust sensitivity in self-cap mode, 1/16

enumerator kTSI_SensitivityXdnOption_1

Adjust sensitivity in self-cap mode, 1/8

enumerator kTSI_SensitivityXdnOption_2
Adjust sensitivity in self-cap mode, 1/4

enumerator kTSI_SensitivityXdnOption_3
Adjust sensitivity in self-cap mode, 1/2

enum __tsi_shield

TSI Shield setting (S_W_SHIELD option).

These constants define the shield pin used for HW shielding functionality. One or more shield pin can be selected. The involved bitfield is not fix can change from device to device (KE16Z7 and KE17Z7 support 3 shield pins, other KE serials only support 1 shield pin).

Values:

enumerator kTSI_shieldAllOff
No pin used

enumerator kTSI_shield0On
Shield 0 pin used

enumerator kTSI_shield1On
Shield 1 pin used

enumerator kTSI_shield1and0On
Shield 0,1 pins used

enumerator kTSI_shield2On
Shield 2 pin used

enumerator kTSI_shield2and0On
Shield 2,0 pins used

enumerator kTSI_shield2and1On
Shield 2,1 pins used

enumerator kTSI_shieldAllOn
Shield 2,1,0 pins used

enum __tsi_sensitivity_ctrim_option

TSI sensitivity ajustment (CTRIM option).

These constants define the tsi sensitivity ajustment in self-cap mode, when TSI_MODE[S_SEN] = 1.

Values:

enumerator kTSI_SensitivityCtrimOption_0
Adjust sensitivity in self-cap mode, 2.5p

enumerator kTSI_SensitivityCtrimOption_1
Adjust sensitivity in self-cap mode, 5.0p

enumerator kTSI_SensitivityCtrimOption_2
Adjust sensitivity in self-cap mode, 7.5p

enumerator kTSI_SensitivityCtrimOption_3
Adjust sensitivity in self-cap mode, 10.0p

enumerator kTSI_SensitivityCtrimOption_4
Adjust sensitivity in self-cap mode, 12.5p

enumerator kTSI_SensitivityCtrimOption_5
Adjust sensitivity in self-cap mode, 15.0p

enumerator kTSI_SensitivityCtrimOption_6
Adjust sensitivity in self-cap mode, 17.5p

enumerator kTSI_SensitivityCtrimOption_7
Adjust sensitivity in self-cap mode, 20.0p

enum _tsi_current_multiple_input
TSI current ajustment (Input current multiple).
These constants set the tsi input current multiple in self-cap mode.

Values:

enumerator kTSI_CurrentMultipleInputValue_0
Adjust input current multiple in self-cap mode, 1/8

enumerator kTSI_CurrentMultipleInputValue_1
Adjust input current multiple in self-cap mode, 1/4

enum _tsi_current_multiple_charge
TSI current ajustment (Charge/Discharge current multiple).
These constants set the tsi charge/discharge current multiple in self-cap mode.

Values:

enumerator kTSI_CurrentMultipleChargeValue_0
Adjust charge/discharge current multiple in self-cap mode, 1/16

enumerator kTSI_CurrentMultipleChargeValue_1
Adjust charge/discharge current multiple in self-cap mode, 1/8

enumerator kTSI_CurrentMultipleChargeValue_2
Adjust charge/discharge current multiple in self-cap mode, 1/4

enumerator kTSI_CurrentMultipleChargeValue_3
Adjust charge/discharge current multiple in self-cap mode, 1/2

enumerator kTSI_CurrentMultipleChargeValue_4
Adjust charge/discharge current multiple in self-cap mode, 1/1

enumerator kTSI_CurrentMultipleChargeValue_5
Adjust charge/discharge current multiple in self-cap mode, 2/1

enumerator kTSI_CurrentMultipleChargeValue_6
Adjust charge/discharge current multiple in self-cap mode, 4/1

enumerator kTSI_CurrentMultipleChargeValue_7
Adjust charge/discharge current multiple in self-cap mode, 8/1

enum _tsi_mutual_pre_current
TSI current used in vref generator.
These constants Choose the current used in vref generator.

Values:

enumerator kTSI_MutualPreCurrent_1uA
Vref generator current is 1uA, used in mutual-cap mode

enumerator kTSI_MutualPreCurrent_2uA
Vref generator current is 2uA, used in mutual-cap mode

enumerator kTSI_MutualPreCurrent_3uA
Vref generator current is 3uA, used in mutual-cap mode

enumerator kTSI_MutualPreCurrent_4uA

Vref generator current is 4uA, used in mutual-cap mode

enumerator kTSI_MutualPreCurrent_5uA

Vref generator current is 5uA, used in mutual-cap mode

enumerator kTSI_MutualPreCurrent_6uA

Vref generator current is 6uA, used in mutual-cap mode

enumerator kTSI_MutualPreCurrent_7uA

Vref generator current is 7uA, used in mutual-cap mode

enumerator kTSI_MutualPreCurrent_8uA

Vref generator current is 8uA, used in mutual-cap mode

enum _tsi_mutual_pre_resistor

TSI resistor used in pre-charge.

These constants Choose the resistor used in pre-charge.

Values:

enumerator kTSI_MutualPreResistor_1k

Vref generator resistor is 1k, used in mutual-cap mode

enumerator kTSI_MutualPreResistor_2k

Vref generator resistor is 2k, used in mutual-cap mode

enumerator kTSI_MutualPreResistor_3k

Vref generator resistor is 3k, used in mutual-cap mode

enumerator kTSI_MutualPreResistor_4k

Vref generator resistor is 4k, used in mutual-cap mode

enumerator kTSI_MutualPreResistor_5k

Vref generator resistor is 5k, used in mutual-cap mode

enumerator kTSI_MutualPreResistor_6k

Vref generator resistor is 6k, used in mutual-cap mode

enumerator kTSI_MutualPreResistor_7k

Vref generator resistor is 7k, used in mutual-cap mode

enumerator kTSI_MutualPreResistor_8k

Vref generator resistor is 8k, used in mutual-cap mode

enum _tsi_mutual_sense_resistor

TSI resistor used in I-sense generator.

These constants Choose the resistor used in I-sense generator.

Values:

enumerator kTSI_MutualSenseResistor_2k5

I-sense resistor is 2.5k , used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_5k

I-sense resistor is 5.0k , used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_7k5

I-sense resistor is 7.5k , used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_10k

I-sense resistor is 10.0k, used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_12k5

I-sense resistor is 12.5k, used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_15k

I-sense resistor is 15.0k, used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_17k5

I-sense resistor is 17.5k, used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_20k

I-sense resistor is 20.0k, used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_22k5

I-sense resistor is 22.5k, used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_25k

I-sense resistor is 25.0k, used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_27k5

I-sense resistor is 27.5k, used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_30k

I-sense resistor is 30.0k, used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_32k5

I-sense resistor is 32.5k, used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_35k

I-sense resistor is 35.0k, used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_37k5

I-sense resistor is 37.5k, used in mutual-cap mode

enumerator kTSI_MutualSenseResistor_40k

I-sense resistor is 40.0k, used in mutual-cap mode

enum _tsi_mutual_tx_channel

TSI TX channel selection in mutual-cap mode.

These constants Choose the TX channel used in mutual-cap mode.

Values:

enumerator kTSI_MutualTxChannel_0

Select channel 0 as tx0, used in mutual-cap mode

enumerator kTSI_MutualTxChannel_1

Select channel 1 as tx1, used in mutual-cap mode

enumerator kTSI_MutualTxChannel_2

Select channel 2 as tx2, used in mutual-cap mode

enumerator kTSI_MutualTxChannel_3

Select channel 3 as tx3, used in mutual-cap mode

enumerator kTSI_MutualTxChannel_4

Select channel 4 as tx4, used in mutual-cap mode

enumerator kTSI_MutualTxChannel_5

Select channel 5 as tx5, used in mutual-cap mode

enum _tsi_mutual_rx_channel

TSI RX channel selection in mutual-cap mode.

These constants Choose the RX channel used in mutual-cap mode.

Values:

enumerator kTSI_MutualRxChannel_6

Select channel 6 as rx6, used in mutual-cap mode

enumerator kTSI_MutualRxChannel_7

Select channel 7 as rx7, used in mutual-cap mode

enumerator kTSI_MutualRxChannel_8

Select channel 8 as rx8, used in mutual-cap mode

enumerator kTSI_MutualRxChannel_9

Select channel 9 as rx9, used in mutual-cap mode

enumerator kTSI_MutualRxChannel_10

Select channel 10 as rx10, used in mutual-cap mode

enumerator kTSI_MutualRxChannel_11

Select channel 11 as rx11, used in mutual-cap mode

enum _tsi_mutual_sense_boost_current

TSI sensitivity boost current settings.

These constants set the sensitivity boost current.

Values:

enumerator kTSI_MutualSenseBoostCurrent_0uA

Sensitivity boost current is 0uA , used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_2uA

Sensitivity boost current is 2uA , used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_4uA

Sensitivity boost current is 4uA , used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_6uA

Sensitivity boost current is 6uA , used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_8uA

Sensitivity boost current is 8uA , used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_10uA

Sensitivity boost current is 10uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_12uA

Sensitivity boost current is 12uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_14uA

Sensitivity boost current is 14uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_16uA

Sensitivity boost current is 16uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_18uA

Sensitivity boost current is 18uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_20uA

Sensitivity boost current is 20uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_22uA
Sensitivity boost current is 22uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_24uA
Sensitivity boost current is 24uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_26uA
Sensitivity boost current is 26uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_28uA
Sensitivity boost current is 28uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_30uA
Sensitivity boost current is 30uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_32uA
Sensitivity boost current is 32uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_34uA
Sensitivity boost current is 34uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_36uA
Sensitivity boost current is 36uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_38uA
Sensitivity boost current is 38uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_40uA
Sensitivity boost current is 40uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_42uA
Sensitivity boost current is 42uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_44uA
Sensitivity boost current is 44uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_46uA
Sensitivity boost current is 46uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_48uA
Sensitivity boost current is 48uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_50uA
Sensitivity boost current is 50uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_52uA
Sensitivity boost current is 52uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_54uA
Sensitivity boost current is 54uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_56uA
Sensitivity boost current is 56uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_58uA
Sensitivity boost current is 58uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_60uA
Sensitivity boost current is 60uA, used in mutual-cap mode

enumerator kTSI_MutualSenseBoostCurrent_62uA
Sensitivity boost current is 62uA, used in mutual-cap mode

enum _tsi_mutual_tx_drive_mode

TSI TX drive mode control.

These constants Choose the TX drive mode control setting.

Values:

enumerator kTSI_MutualTxDriveModeOption_0

TX drive mode is -5v ~ +5v, used in mutual-cap mode

enumerator kTSI_MutualTxDriveModeOption_1

TX drive mode is 0v ~ +5v, used in mutual-cap mode

enum _tsi_mutual_pmos_current_left

TSI Pmos current mirror selection on the left side.

These constants set the Pmos current mirror on the left side used in mutual-cap mode.

Values:

enumerator kTSI_MutualPmosCurrentMirrorLeft_4

Set Pmos current mirror left value as 4, used in mutual-cap mode

enumerator kTSI_MutualPmosCurrentMirrorLeft_8

Set Pmos current mirror left value as 8, used in mutual-cap mode

enumerator kTSI_MutualPmosCurrentMirrorLeft_12

Set Pmos current mirror left value as 12, used in mutual-cap mode

enumerator kTSI_MutualPmosCurrentMirrorLeft_16

Set Pmos current mirror left value as 16, used in mutual-cap mode

enumerator kTSI_MutualPmosCurrentMirrorLeft_20

Set Pmos current mirror left value as 20, used in mutual-cap mode

enumerator kTSI_MutualPmosCurrentMirrorLeft_24

Set Pmos current mirror left value as 24, used in mutual-cap mode

enumerator kTSI_MutualPmosCurrentMirrorLeft_28

Set Pmos current mirror left value as 28, used in mutual-cap mode

enumerator kTSI_MutualPmosCurrentMirrorLeft_32

Set Pmos current mirror left value as 32, used in mutual-cap mode

enum _tsi_mutual_pmos_current_right

TSI Pmos current mirror selection on the right side.

These constants set the Pmos current mirror on the right side used in mutual-cap mode.

Values:

enumerator kTSI_MutualPmosCurrentMirrorRight_1

Set Pmos current mirror right value as 1, used in mutual-cap mode

enumerator kTSI_MutualPmosCurrentMirrorRight_2

Set Pmos current mirror right value as 2, used in mutual-cap mode

enumerator kTSI_MutualPmosCurrentMirrorRight_3

Set Pmos current mirror right value as 3, used in mutual-cap mode

enumerator kTSI_MutualPmosCurrentMirrorRight_4

Set Pmos current mirror right value as 4, used in mutual-cap mode

enum _tsi_mutual_nmos_current

TSI Nmos current mirror selection.

These constants set the Nmos current mirror used in mutual-cap mode.

Values:

enumerator kTSI_MutualNmosCurrentMirror_1

Set Nmos current mirror value as 1, used in mutual-cap mode

enumerator kTSI_MutualNmosCurrentMirror_2

Set Nmos current mirror value as 2, used in mutual-cap mode

enumerator kTSI_MutualNmosCurrentMirror_3

Set Nmos current mirror value as 3, used in mutual-cap mode

enumerator kTSI_MutualNmosCurrentMirror_4

Set Nmos current mirror value as 4, used in mutual-cap mode

enum _tsi_sinc_cutoff_div

TSI SINC cutoff divider setting.

These bits set the SINC cutoff divider.

Values:

enumerator kTSI_SincCutoffDiv_1

Set SINC cutoff divider as 1

enumerator kTSI_SincCutoffDiv_2

Set SINC cutoff divider as 2

enumerator kTSI_SincCutoffDiv_4

Set SINC cutoff divider as 4

enumerator kTSI_SincCutoffDiv_8

Set SINC cutoff divider as 8

enumerator kTSI_SincCutoffDiv_16

Set SINC cutoff divider as 16

enumerator kTSI_SincCutoffDiv_32

Set SINC cutoff divider as 32

enumerator kTSI_SincCutoffDiv_64

Set SINC cutoff divider as 64

enumerator kTSI_SincCutoffDiv_128

Set SINC cutoff divider as 128

enum _tsi_sinc_filter_order

TSI SINC filter order setting.

These bits set the SINC filter order.

Values:

enumerator kTSI_SincFilterOrder_1

Use 1 order SINC filter

enumerator kTSI_SincFilterOrder_2

Use 1 order SINC filter

enum _tsi_sinc_decimation_value

TSI SINC decimation value setting.

These bits set the SINC decimation value.

Values:

enumerator kTSI_SincDecimationValue_1

The TSI_DATA[TSICH] bits is the counter value of 1 trigger period.

enumerator kTSI_SincDecimationValue_2

The TSI_DATA[TSICH] bits is the counter value of 2 trigger period.

enumerator kTSI_SincDecimationValue_3

The TSI_DATA[TSICH] bits is the counter value of 3 trigger period.

enumerator kTSI_SincDecimationValue_4

The TSI_DATA[TSICH] bits is the counter value of 4 trigger period.

enumerator kTSI_SincDecimationValue_5

The TSI_DATA[TSICH] bits is the counter value of 5 trigger period.

enumerator kTSI_SincDecimationValue_6

The TSI_DATA[TSICH] bits is the counter value of 6 trigger period.

enumerator kTSI_SincDecimationValue_7

The TSI_DATA[TSICH] bits is the counter value of 7 trigger period.

enumerator kTSI_SincDecimationValue_8

The TSI_DATA[TSICH] bits is the counter value of 8 trigger period.

enumerator kTSI_SincDecimationValue_9

The TSI_DATA[TSICH] bits is the counter value of 9 trigger period.

enumerator kTSI_SincDecimationValue_10

The TSI_DATA[TSICH] bits is the counter value of 10 trigger period.

enumerator kTSI_SincDecimationValue_11

The TSI_DATA[TSICH] bits is the counter value of 11 trigger period.

enumerator kTSI_SincDecimationValue_12

The TSI_DATA[TSICH] bits is the counter value of 12 trigger period.

enumerator kTSI_SincDecimationValue_13

The TSI_DATA[TSICH] bits is the counter value of 13 trigger period.

enumerator kTSI_SincDecimationValue_14

The TSI_DATA[TSICH] bits is the counter value of 14 trigger period.

enumerator kTSI_SincDecimationValue_15

The TSI_DATA[TSICH] bits is the counter value of 15 trigger period.

enumerator kTSI_SincDecimationValue_16

The TSI_DATA[TSICH] bits is the counter value of 16 trigger period.

enumerator kTSI_SincDecimationValue_17

The TSI_DATA[TSICH] bits is the counter value of 17 trigger period.

enumerator kTSI_SincDecimationValue_18

The TSI_DATA[TSICH] bits is the counter value of 18 trigger period.

enumerator kTSI_SincDecimationValue_19

The TSI_DATA[TSICH] bits is the counter value of 19 trigger period.

enumerator kTSI_SincDecimationValue_20

The TSI_DATA[TSICH] bits is the counter value of 20 trigger period.

enumerator kTSI_SincDecimationValue_21

The TSI_DATA[TSICH] bits is the counter value of 21 trigger period.

enumerator kTSI_SincDecimationValue_22

The TSI_DATA[TSICH] bits is the counter value of 22 trigger period.

enumerator kTSI_SincDecimationValue_23

The TSI_DATA[TSICH] bits is the counter value of 23 trigger period.

enumerator kTSI_SincDecimationValue_24

The TSI_DATA[TSICH] bits is the counter value of 24 trigger period.

enumerator kTSI_SincDecimationValue_25

The TSI_DATA[TSICH] bits is the counter value of 25 trigger period.

enumerator kTSI_SincDecimationValue_26

The TSI_DATA[TSICH] bits is the counter value of 26 trigger period.

enumerator kTSI_SincDecimationValue_27

The TSI_DATA[TSICH] bits is the counter value of 27 trigger period.

enumerator kTSI_SincDecimationValue_28

The TSI_DATA[TSICH] bits is the counter value of 28 trigger period.

enumerator kTSI_SincDecimationValue_29

The TSI_DATA[TSICH] bits is the counter value of 29 trigger period.

enumerator kTSI_SincDecimationValue_30

The TSI_DATA[TSICH] bits is the counter value of 30 trigger period.

enumerator kTSI_SincDecimationValue_31

The TSI_DATA[TSICH] bits is the counter value of 31 trigger period.

enumerator kTSI_SincDecimationValue_32

The TSI_DATA[TSICH] bits is the counter value of 32 trigger period.

enum _tsi_ssc_charge_num

TSI SSC output bit0's period setting(SSC0[CHARGE_NUM])

These bits set the SSC output bit0's period setting.

Values:

enumerator kTSI_SscChargeNumValue_1

The SSC output bit 0's period will be 1 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_2

The SSC output bit 0's period will be 2 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_3

The SSC output bit 0's period will be 3 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_4

The SSC output bit 0's period will be 4 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_5

The SSC output bit 0's period will be 5 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_6

The SSC output bit 0's period will be 6 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_7

The SSC output bit 0's period will be 7 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_8

The SSC output bit 0's period will be 8 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_9

The SSC output bit 0's period will be 9 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_10

The SSC output bit 0's period will be 10 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_11

The SSC output bit 0's period will be 11 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_12

The SSC output bit 0's period will be 12 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_13

The SSC output bit 0's period will be 13 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_14

The SSC output bit 0's period will be 14 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_15

The SSC output bit 0's period will be 15 clock cycle of system clock.

enumerator kTSI_SscChargeNumValue_16

The SSC output bit 0's period will be 16 clock cycle of system clock.

enum _tsi_ssc_nocharge_num

TSI SSC output bit1's period setting(SSC0[BASE_NOCHARGE_NUM])

These bits set the SSC output bit1's period setting.

Values:

enumerator kTSI_SscNoChargeNumValue_1

The SSC output bit 1's basic period will be 1 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_2

The SSC output bit 1's basic period will be 2 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_3

The SSC output bit 1's basic period will be 3 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_4

The SSC output bit 1's basic period will be 4 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_5

The SSC output bit 1's basic period will be 5 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_6

The SSC output bit 1's basic period will be 6 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_7

The SSC output bit 1's basic period will be 7 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_8

The SSC output bit 1's basic period will be 8 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_9

The SSC output bit 1's basic period will be 9 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_10

The SSC output bit 1's basic period will be 10 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_11

The SSC output bit 1's basic period will be 11 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_12

The SSC output bit 1's basic period will be 12 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_13

The SSC output bit 1's basic period will be 13 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_14

The SSC output bit 1's basic period will be 14 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_15

The SSC output bit 1's basic period will be 15 clock cycle of system clock.

enumerator kTSI_SscNoChargeNumValue_16

The SSC output bit 1's basic period will be 16 clock cycle of system clock.

enum _tsi_ssc_prbs_outsel

TSI SSC outsel choosing the length of the PRBS (Pseudo-RandomBinarySequence) method setting(SSC0[TSI_SSC0_PRBS_OUTSEL])

These bits set the SSC PRBS length.

Values:

enumerator kTSI_SscPrbsOutsel_2

The length of the PRBS is 2.

enumerator kTSI_SscPrbsOutsel_3

The length of the PRBS is 3.

enumerator kTSI_SscPrbsOutsel_4

The length of the PRBS is 4.

enumerator kTSI_SscPrbsOutsel_5

The length of the PRBS is 5.

enumerator kTSI_SscPrbsOutsel_6

The length of the PRBS is 6.

enumerator kTSI_SscPrbsOutsel_7

The length of the PRBS is 7.

enumerator kTSI_SscPrbsOutsel_8

The length of the PRBS is 8.

enumerator kTSI_SscPrbsOutsel_9

The length of the PRBS is 9.

enumerator kTSI_SscPrbsOutsel_10

The length of the PRBS is 10.

enumerator kTSI_SscPrbsOutsel_11

The length of the PRBS is 11.

enumerator kTSI_SscPrbsOutsel_12

The length of the PRBS is 12.

enumerator kTSI_SscPrbsOutsel_13

The length of the PRBS is 13.

enumerator kTSI_SscPrbsOutsel_14

The length of the PRBS is 14.

enumerator kTSI_SscPrbsOutsel_15

The length of the PRBS is 15.

enum _tsi_status_flags

TSI status flags.

Values:

enumerator kTSI_EndOfScanFlag

End-Of-Scan flag

enumerator kTSI_OutOfRangeFlag

Out-Of-Range flag

enum _tsi_interrupt_enable

TSI feature interrupt source.

Values:

enumerator kTSI_GlobalInterruptEnable

TSI module global interrupt

enumerator kTSI_OutOfRangeInterruptEnable

Out-Of-Range interrupt

enumerator kTSI_EndOfScanInterruptEnable

End-Of-Scan interrupt

enum _tsi_ssc_mode

TSI SSC mode selection.

These constants set the SSC mode.

Values:

enumerator kTSI_ssc_prbs_method

Using PRBS method generating SSC output bit.

enumerator kTSI_ssc_up_down_counter

Using up-down counter generating SSC output bit.

enumerator kTSI_ssc_disable

SSC function is disabled.

enum _tsi_ssc_prescaler

TSI main clock selection.

These constants set select the divider ratio for the clock used for generating the SSC output bit.

Values:

enumerator kTSI_ssc_div_by_1

Set SSC divider to 00000000 div1(2^0)

enumerator kTSI_ssc_div_by_2

Set SSC divider to 00000001 div2(2^1)

enumerator kTSI_ssc_div_by_4

Set SSC divider to 00000011 div4(2^2)

enumerator kTSI_ssc_div_by_8

Set SSC divider to 00000111 div8(2^3)

enumerator kTSI_ssc_div_by_16

Set SSC divider to 00001111 div16(2^4)

enumerator kTSI_ssc_div_by_32

Set SSC divider to 00011111 div32(2^5)

enumerator kTSI_ssc_div_by_64

Set SSC divider to 00111111 div64(2^6)

enumerator kTSI_ssc_div_by_128

Set SSC divider to 01111111 div128(2^7)

enumerator kTSI_ssc_div_by_256

Set SSC divider to 11111111 div256(2^8)

typedef enum *_tsi_main_clock_selection* tsi_main_clock_selection_t

TSI main clock selection.

These constants set the tsi main clock.

typedef enum *_tsi_sensing_mode_selection* tsi_sensing_mode_selection_t

TSI sensing mode selection.

These constants set the tsi sensing mode.

typedef enum *_tsi_dvolt_option* tsi_dvolt_option_t

TSI DVOLT settings.

These bits indicate the comparator vp, vm and dvolt voltage.

typedef enum *_tsi_sensitivity_xdn_option* tsi_sensitivity_xdn_option_t

TSI sensitivity ajustment (XDN option).

These constants define the tsi sensitivity ajustment in self-cap mode, when TSI_MODE[S_SEN] = 1.

typedef enum *_tsi_shield* tsi_shield_t

TSI Shield setting (S_W_SHIELD option).

These constants define the shield pin used for HW shielding functionality. One or more shield pin can be selected. The involved bitfield is not fix can change from device to device (KE16Z7 and KE17Z7 support 3 shield pins, other KE serials only support 1 shield pin).

typedef enum *_tsi_sensitivity_ctrim_option* tsi_sensitivity_ctrim_option_t

TSI sensitivity ajustment (CTRIM option).

These constants define the tsi sensitivity ajustment in self-cap mode, when TSI_MODE[S_SEN] = 1.

typedef enum *_tsi_current_multiple_input* tsi_current_multiple_input_t

TSI current ajustment (Input current multiple).

These constants set the tsi input current multiple in self-cap mode.

typedef enum *_tsi_current_multiple_charge* tsi_current_multiple_charge_t

TSI current ajustment (Charge/Discharge current multiple).

These constants set the tsi charge/discharge current multiple in self-cap mode.

typedef enum *_tsi_mutual_pre_current* tsi_mutual_pre_current_t

TSI current used in vref generator.

These constants Choose the current used in vref generator.

`typedef enum _tsi_mutual_pre_resistor` `tsi_mutual_pre_resistor_t`

TSI resistor used in pre-charge.

These constants Choose the resistor used in pre-charge.

`typedef enum _tsi_mutual_sense_resistor` `tsi_mutual_sense_resistor_t`

TSI resistor used in I-sense generator.

These constants Choose the resistor used in I-sense generator.

`typedef enum _tsi_mutual_tx_channel` `tsi_mutual_tx_channel_t`

TSI TX channel selection in mutual-cap mode.

These constants Choose the TX channel used in mutual-cap mode.

`typedef enum _tsi_mutual_rx_channel` `tsi_mutual_rx_channel_t`

TSI RX channel selection in mutual-cap mode.

These constants Choose the RX channel used in mutual-cap mode.

`typedef enum _tsi_mutual_sense_boost_current` `tsi_mutual_sense_boost_current_t`

TSI sensitivity boost current settings.

These constants set the sensitivity boost current.

`typedef enum _tsi_mutual_tx_drive_mode` `tsi_mutual_tx_drive_mode_t`

TSI TX drive mode control.

These constants Choose the TX drive mode control setting.

`typedef enum _tsi_mutual_pmos_current_left` `tsi_mutual_pmos_current_left_t`

TSI Pmos current mirror selection on the left side.

These constants set the Pmos current mirror on the left side used in mutual-cap mode.

`typedef enum _tsi_mutual_pmos_current_right` `tsi_mutual_pmos_current_right_t`

TSI Pmos current mirror selection on the right side.

These constants set the Pmos current mirror on the right side used in mutual-cap mode.

`typedef enum _tsi_mutual_nmos_current` `tsi_mutual_nmos_current_t`

TSI Nmos current mirror selection.

These constants set the Nmos current mirror used in mutual-cap mode.

`typedef enum _tsi_sinc_cutoff_div` `tsi_sinc_cutoff_div_t`

TSI SINC cutoff divider setting.

These bits set the SINC cutoff divider.

`typedef enum _tsi_sinc_filter_order` `tsi_sinc_filter_order_t`

TSI SINC filter order setting.

These bits set the SINC filter order.

`typedef enum _tsi_sinc_decimation_value` `tsi_sinc_decimation_value_t`

TSI SINC decimation value setting.

These bits set the SINC decimation value.

`typedef enum _tsi_ssc_charge_num` `tsi_ssc_charge_num_t`

TSI SSC output bit0's period setting(SSC0[CHARGE_NUM])

These bits set the SSC output bit0's period setting.

```
typedef enum _tsi_ssc_nocharge_num tsi_ssc_nocharge_num_t
```

TSI SSC output bit1's period setting(SSC0[BASE_NOCHARGE_NUM])

These bits set the SSC output bit1's period setting.

```
typedef enum _tsi_ssc_prbs_outsel tsi_ssc_prbs_outsel_t
```

TSI SSC outsel choosing the length of the PRBS (Pseudo-RandomBinarySequence) method setting(SSC0[TSI_SSC0_PRBS_OUTSEL])

These bits set the SSC PRBS length.

```
typedef enum _tsi_status_flags tsi_status_flags_t
```

TSI status flags.

```
typedef enum _tsi_interrupt_enable tsi_interrupt_enable_t
```

TSI feature interrupt source.

```
typedef enum _tsi_ssc_mode tsi_ssc_mode_t
```

TSI SSC mode selection.

These constants set the SSC mode.

```
typedef enum _tsi_ssc_prescaler tsi_ssc_prescaler_t
```

TSI main clock selection.

These constants set select the divider ratio for the clock used for generating the SSC output bit.

```
typedef struct _tsi_calibration_data tsi_calibration_data_t
```

TSI calibration data storage.

```
typedef struct _tsi_common_config tsi_common_config_t
```

TSI common configuration structure.

This structure contains the common settings for TSI self-cap or mutual-cap mode, configurations including the TSI module main clock, sensing mode, DVOLT options, SINC and SSC configurations.

```
typedef struct _tsi_selfCap_config tsi_selfCap_config_t
```

TSI configuration structure for self-cap mode.

This structure contains the settings for the most common TSI self-cap configurations including the TSI module charge currents, sensitivity configuration and so on.

```
typedef struct _tsi_mutualCap_config tsi_mutualCap_config_t
```

TSI configuration structure for mutual-cap mode.

This structure contains the settings for the most common TSI mutual-cap configurations including the TSI module generator settings, sensitivity related current settings and so on.

```
const clock_ip_name_t s_tsiClock[]
```

```
const IRQn_Type s_TsiIRQ[]
```

```
TSI_Type *const s_tsiBases[]
```

```
uint32_t TSI_GetInstance(TSI_Type *base)
```

Get the TSI instance from peripheral base address.

Parameters

- base – TSI peripheral base address.

Returns

TSI instance.

```
void TSI_InitSelfCapMode(TSI_Type *base, const tsi_selfCap_config_t *config)
```

Initialize hardware to Self-cap mode.

Initialize the peripheral to the targeted state specified by parameter config, such as sets sensitivity adjustment, current settings.

Parameters

- base – TSI peripheral base address.
- config – Pointer to TSI self-cap configuration structure.

Returns

none

```
void TSI_InitMutualCapMode(TSI_Type *base, const tsi_mutualCap_config_t *config)
```

Initialize hardware to Mutual-cap mode.

Initialize the peripheral to the targeted state specified by parameter config, such as sets Vref generator setting, sensitivity boost settings, Pmos/Nmos settings.

Parameters

- base – TSI peripheral base address.
- config – Pointer to TSI mutual-cap configuration structure.

Returns

none

```
void TSI_Deinit(TSI_Type *base)
```

De-initialize hardware.

De-initialize the peripheral to default state.

Parameters

- base – TSI peripheral base address.

Returns

none

```
void TSI_GetSelfCapModeDefaultConfig(tsi_selfCap_config_t *userConfig)
```

Get TSI self-cap mode user configure structure. This interface sets userConfig structure to a default value. The configuration structure only includes the settings for the whole TSI. The user configure is set to a value:

```
userConfig->commonConfig.mainClock    = kTSI_MainClockSlection_0;
userConfig->commonConfig.mode         = kTSI_SensingModeSlection_Self;
userConfig->commonConfig.dvolt        = kTSI_DvoltOption_2;
userConfig->commonConfig.cutoff       = kTSI_SincCutoffDiv_1;
userConfig->commonConfig.order        = kTSI_SincFilterOrder_1;
userConfig->commonConfig.decimation   = kTSI_SincDecimationValue_8;
userConfig->commonConfig.chargeNum    = kTSI_SscChargeNumValue_3;
userConfig->commonConfig.prbsOutsel   = kTSI_SscPrbsOutsel_2;
userConfig->commonConfig.noChargeNum  = kTSI_SscNoChargeNumValue_2;
userConfig->commonConfig.ssc_mode     = kTSI_ssc_prbs_method;
userConfig->commonConfig.ssc_prescaler = kTSI_ssc_div_by_1;
userConfig->enableSensitivity          = true;
userConfig->enableShield               = false;
userConfig->xdn                       = kTSI_SensitivityXdnOption_1;
userConfig->ctrim                     = kTSI_SensitivityCtrimOption_7;
userConfig->inputCurrent               = kTSI_CurrentMultipleInputValue_0;
userConfig->chargeCurrent              = kTSI_CurrentMultipleChargeValue_1;
```

Parameters

- userConfig – Pointer to TSI user configure structure.

void TSI_GetMutualCapModeDefaultConfig(*tsi_mutualCap_config_t* *userConfig)

Get TSI mutual-cap mode default user configure structure. This interface sets userConfig structure to a default value. The configuration structure only includes the settings for the whole TSI. The user configure is set to a value:

```
userConfig->commonConfig.mainClock    = kTSI_MainClockSlection_1;
userConfig->commonConfig.mode          = kTSI_SensingModeSlection_Mutual;
userConfig->commonConfig.dvoltage      = kTSI_DvoltageOption_0;
userConfig->commonConfig.cutoff        = kTSI_SincCutoffDiv_1;
userConfig->commonConfig.order         = kTSI_SincFilterOrder_1;
userConfig->commonConfig.decimation    = kTSI_SincDecimationValue_8;
userConfig->commonConfig.chargeNum     = kTSI_SscChargeNumValue_4;
userConfig->commonConfig.prbsOutsel    = kTSI_SscPrbsOutsel_2;
userConfig->commonConfig.noChargeNum   = kTSI_SscNoChargeNumValue_5;
userConfig->commonConfig.ssc_mode      = kTSI_ssc_prbs_method;
userConfig->commonConfig.ssc_prescaler = kTSI_ssc_div_by_1;
userConfig->preCurrent                 = kTSI_MutualPreCurrent_4uA;
userConfig->preResistor                = kTSI_MutualPreResistor_4k;
userConfig->senseResistor              = kTSI_MutualSenseResistor_10k;
userConfig->boostCurrent               = kTSI_MutualSenseBoostCurrent_0uA;
userConfig->txDriveMode                = kTSI_MutualTxDriveModeOption_0;
userConfig->pmosLeftCurrent            = kTSI_MutualPmosCurrentMirrorLeft_32;
userConfig->pmosRightCurrent           = kTSI_MutualPmosCurrentMirrorRight_1;
userConfig->enableNmosMirror           = true;
userConfig->nmosCurrent                = kTSI_MutualNmosCurrentMirror_1;
```

Parameters

- userConfig – Pointer to TSI user configure structure.

void TSI_SelfCapCalibrate(TSI_Type *base, *tsi_calibration_data_t* *calBuff)

Hardware base counter value for calibration.

Calibrate the peripheral to fetch the initial counter value of the enabled channels. This API is mostly used at initial application setup, it shall be called after the TSI_Init API, then user can use the calibrated counter values to setup applications(such as to determine

under which counter value we can confirm a touch event occurs).

Note: This API is mainly used for self-cap mode;

Note: The calibration work in mutual-cap mode shall be done in applications due to different board layout.

Parameters

- base – TSI peripheral base address.
- calBuff – Data buffer that store the calibrated counter value.

Returns

none

void TSI_EnableInterrupts(TSI_Type *base, uint32_t mask)

Enables TSI interrupt requests.

Parameters

- base – TSI peripheral base address.
- mask – interrupt source The parameter can be combination of the following source if defined:
 - kTSI_GlobalInterruptEnable
 - kTSI_EndOfScanInterruptEnable
 - kTSI_OutOfRangeInterruptEnable

void TSI_DisableInterrupts(TSI_Type *base, uint32_t mask)

Disables TSI interrupt requests.

Parameters

- base – TSI peripheral base address.
- mask – interrupt source The parameter can be combination of the following source if defined:
 - kTSI_GlobalInterruptEnable
 - kTSI_EndOfScanInterruptEnable
 - kTSI_OutOfRangeInterruptEnable

static inline uint32_t TSI_GetStatusFlags(TSI_Type *base)

Get interrupt flag. This function get tsi interrupt flags.

Parameters

- base – TSI peripheral base address.

Returns

The mask of these status flags combination.

void TSI_ClearStatusFlags(TSI_Type *base, uint32_t mask)

Clear interrupt flag.

This function clear tsi interrupt flag, automatically cleared flags can not be cleared by this function.

Parameters

- base – TSI peripheral base address.
- mask – The status flags to clear.

static inline uint32_t TSI_GetScanTriggerMode(TSI_Type *base)

Get TSI scan trigger mode.

Parameters

- base – TSI peripheral base address.

Returns

Scan trigger mode.

static inline bool TSI_IsScanInProgress(TSI_Type *base)

Get scan in progress flag.

Parameters

- base – TSI peripheral base address.

Returns

True - scan is in progress. False - scan is not in progress.

static inline void TSI_EnableModule(TSI_Type *base, bool enable)

Enables the TSI Module or not.

Parameters

- base – TSI peripheral base address.
- enable – Choose whether to enable or disable module;
 - true Enable TSI module;
 - false Disable TSI module;

Returns

none.

static inline void TSI_EnableLowPower(TSI_Type *base, bool enable)

Sets the TSI low power STOP mode enable or not. This enables TSI module function in low power modes.

Parameters

- base – TSI peripheral base address.
- enable – Choose to enable or disable STOP mode.
 - true Enable module in STOP mode;
 - false Disable module in STOP mode;

Returns

none.

static inline void TSI_EnableHardwareTriggerScan(TSI_Type *base, bool enable)

Enable the hardware trigger scan or not.

Parameters

- base – TSI peripheral base address.
- enable – Choose to enable hardware trigger or software trigger scan.
 - true Enable hardware trigger scan;
 - false Enable software trigger scan;

Returns

none.

static inline void TSI_StartSoftwareTrigger(TSI_Type *base)

Start one software trigger measurement (trigger a new measurement).

Parameters

- base – TSI peripheral base address.

Returns

none.

static inline void TSI_SetSelfCapMeasuredChannel(TSI_Type *base, uint8_t channel)

Set the measured channel number for self-cap mode.

Note: This API can only be used in self-cap mode!

Parameters

- base – TSI peripheral base address.
- channel – Channel number 0 ... 24.

Returns

none.

static inline uint8_t TSI_GetSelfCapMeasuredChannel(TSI_Type *base)

Get the current measured channel number, in self-cap mode.

Note: This API can only be used in self-cap mode!

Parameters

- base – TSI peripheral base address.

Returns

uint8_t Channel number 0 ... 24.

static inline void TSI_EnableDmaTransfer(TSI_Type *base, bool enable)

Enable DMA transfer or not.

Parameters

- base – TSI peripheral base address.
- enable – Choose to enable DMA transfer or not.
 - true Enable DMA transfer;
 - false Disable DMA transfer;

Returns

none.

static inline void TSI_EnableEndOfScanDmaTransferOnly(TSI_Type *base, bool enable)

Decide whether to enable End of Scan DMA transfer request only.

Parameters

- base – TSI peripheral base address.
- enable – Choose whether to enable End of Scan DMA transfer request only.
 - true Enable End of Scan DMA transfer request only;
 - false Both End-of-Scan and Out-of-Range can generate DMA transfer request.

Returns

none.

static inline uint16_t TSI_GetCounter(TSI_Type *base)

Gets the conversion counter value.

Parameters

- base – TSI peripheral base address.

Returns

Accumulated scan counter value ticked by the reference clock.

static inline void TSI_SetLowThreshold(TSI_Type *base, uint16_t low_threshold)

Set the TSI wake-up channel low threshold.

Parameters

- base – TSI peripheral base address.
- low_threshold – Low counter threshold.

Returns

none.

static inline void TSI_SetHighThreshold(TSI_Type *base, uint16_t high_threshold)

Set the TSI wake-up channel high threshold.

Parameters

- base – TSI peripheral base address.
- high_threshold – High counter threshold.

Returns

none.

static inline void TSI_SetMainClock(TSI_Type *base, tsi_main_clock_selection_t mainClock)

Set the main clock of the TSI module.

Parameters

- base – TSI peripheral base address.
- mainClock – clock option value.

Returns

none.

static inline void TSI_SetSensingMode(TSI_Type *base, tsi_sensing_mode_selection_t mode)

Set the sensing mode of the TSI module.

Parameters

- base – TSI peripheral base address.
- mode – Mode value.

Returns

none.

static inline tsi_sensing_mode_selection_t TSI_GetSensingMode(TSI_Type *base)

Get the sensing mode of the TSI module.

Parameters

- base – TSI peripheral base address.

Returns

Currently selected sensing mode.

static inline void TSI_SetDvoltage(TSI_Type *base, tsi_dvoltage_option_t dvolt)

Set the DVOLT settings.

Parameters

- base – TSI peripheral base address.
- dvolt – The voltage rails.

Returns

none.

static inline void TSI_EnableNoiseCancellation(TSI_Type *base, bool enableCancellation)

Enable self-cap mode noise cancellation function or not.

Parameters

- base – TSI peripheral base address.
- enableCancellation – Choose whether to enable noise cancellation in self-cap mode

- true Enable noise cancellation;
- false Disable noise cancellation;

Returns

none.

```
static inline void TSI_SetMutualCapTxChannel(TSI_Type *base, tsi_mutual_tx_channel_t txChannel)
```

Set the mutual-cap mode TX channel.

Parameters

- base – TSI peripheral base address.
- txChannel – Mutual-cap mode TX channel number

Returns

none.

```
static inline tsi_mutual_tx_channel_t TSI_GetTxMutualCapMeasuredChannel(TSI_Type *base)  
Get the current measured TX channel number, in mutual-cap mode.
```

Note: This API can only be used in mutual-cap mode!

Parameters

- base – TSI peripheral base address;

Returns

Tx Channel number 0 ... 5;

```
static inline void TSI_SetMutualCapRxChannel(TSI_Type *base, tsi_mutual_rx_channel_t rxChannel)
```

Set the mutual-cap mode RX channel.

Parameters

- base – TSI peripheral base address.
- rxChannel – Mutual-cap mode RX channel number

Returns

none.

```
static inline tsi_mutual_rx_channel_t TSI_GetRxMutualCapMeasuredChannel(TSI_Type *base)  
Get the current measured RX channel number, in mutual-cap mode.
```

Note: This API can only be used in mutual-cap mode!

Parameters

- base – TSI peripheral base address;

Returns

Rx Channel number 6 ... 11;

```
static inline void TSI_SetSscMode(TSI_Type *base, tsi_ssc_mode_t mode)
```

Set the SSC clock mode of the TSI module.

Parameters

- base – TSI peripheral base address.
- mode – SSC mode option value.

Returns

none.

static inline void TSI_SetSscPrescaler(TSI_Type *base, *tsi_ssc_prescaler_t* prescaler)

Set the SSC prescaler of the TSI module.

Parameters

- base – TSI peripheral base address.
- prescaler – SSC prescaler option value.

Returns

none.

static inline void TSI_SetUsedTxChannel(TSI_Type *base, *tsi_mutual_tx_channel_t* txChannel)

Set used mutual-cap TX channel.

Parameters

- base – TSI peripheral base address.
- txChannel – Mutual-cap mode TX channel number

Returns

none.

static inline void TSI_ClearUsedTxChannel(TSI_Type *base, *tsi_mutual_tx_channel_t* txChannel)

Clear used mutual-cap TX channel.

Parameters

- base – TSI peripheral base address.
- txChannel – Mutual-cap mode TX channel number

Returns

none.

FSL_TSI_DRIVER_VERSION

TSI driver version.

ALL_FLAGS_MASK

TSI status flags macro collection.

struct *_tsi_calibration_data*

#include <fsl_tsi_v5.h> TSI calibration data storage.

Public Members

uint16_t calibratedData[1]

TSI calibration data storage buffer

struct *_tsi_common_config*

#include <fsl_tsi_v5.h> TSI common configuration structure.

This structure contains the common settings for TSI self-cap or mutual-cap mode, configurations including the TSI module main clock, sensing mode, DVOLT options, SINC and SSC configurations.

Public Members

tsi_main_clock_selection_t mainClock

Set main clock.

tsi_sensing_mode_selection_t mode

Choose sensing mode.

tsi_dvolt_option_t dvolt

DVOLT option value.

tsi_sinc_cutoff_div_t cutoff

Cutoff divider.

tsi_sinc_filter_order_t order

SINC filter order.

tsi_sinc_decimation_value_t decimation

SINC decimation value.

tsi_ssc_charge_num_t chargeNum

SSC High Width (t1), SSC output bit0's period setting.

tsi_ssc_prbs_outsel_t prbsOutsel

SSC High Random Width (t2), length of PRBS(Pseudo-RandomBinarySequence),SSC output bit2's period setting.

tsi_ssc_nocharge_num_t noChargeNum

SSC Low Width (t3), SSC output bit1's period setting.

tsi_ssc_mode_t ssc_mode

Clock mode selection (basic - from main clock by divider,advanced - using SSC(Switching Speed Clock) by three configurable intervals.

tsi_ssc_prescaler_t ssc_prescaler

Set clock divider for basic mode.

struct *_tsi_selfCap_config*

#include <fsl_tsi_v5.h> TSI configuration structure for self-cap mode.

This structure contains the settings for the most common TSI self-cap configurations including the TSI module charge currents, sensitivity configuration and so on.

Public Members

tsi_common_config_t commonConfig

Common settings.

bool enableSensitivity

Enable sensitivity boost of self-cap or not.

tsi_shield_t enableShield

Enable shield of self-cap mode or not.

tsi_sensitivity_xdn_option_t xdn

Sensitivity XDN option.

tsi_sensitivity_ctrim_option_t ctrim

Sensitivity CTRIM option.

tsi_current_multiple_input_t inputCurrent

Input current multiple.

tsi_current_multiple_charge_t chargeCurrent

Charge/Discharge current multiple.


```
struct __tsi_mutualCap_config
```

#include <fsl_tsi_v5.h> TSI configuration structure for mutual-cap mode.

This structure contains the settings for the most common TSI mutual-cap configurations including the TSI module generator settings, sensitivity related current settings and so on.

Public Members

tsi_common_config_t commonConfig

Common settings.

tsi_mutual_pre_current_t preCurrent

Vref generator current.

tsi_mutual_pre_resistor_t preResistor

Vref generator resistor.

tsi_mutual_sense_resistor_t senseResistor

I-sense generator resistor.

tsi_mutual_sense_boost_current_t boostCurrent

Sensitivity boost current setting.

tsi_mutual_tx_drive_mode_t txDriveMode

TX drive mode control setting.

tsi_mutual_pmos_current_left_t pmosLeftCurrent

Pmos current mirror on the left side.

tsi_mutual_pmos_current_right_t pmosRightCurrent

Pmos current mirror on the right side.

bool enableNmosMirror

Enable Nmos current mirror setting or not.

tsi_mutual_nmos_current_t nmosCurrent

Nmos current mirror setting.

2.55 WDOG32: 32-bit Watchdog Timer

```
void WDOG32_GetDefaultConfig(wdog32_config_t *config)
```

Initializes the WDOG32 configuration structure.

This function initializes the WDOG32 configuration structure to default values. The default values are:

```
wdog32Config->enableWdog32 = true;
wdog32Config->clockSource = kWDOG32_ClockSource1;
wdog32Config->prescaler = kWDOG32_ClockPrescalerDivide1;
wdog32Config->workMode.enableWait = true;
wdog32Config->workMode.enableStop = false;
wdog32Config->workMode.enableDebug = false;
wdog32Config->testMode = kWDOG32_TestModeDisabled;
wdog32Config->enableUpdate = true;
wdog32Config->enableInterrupt = false;
wdog32Config->enableWindowMode = false;
wdog32Config->windowValue = 0U;
wdog32Config->timeoutValue = 0xFFFFU;
```

See also:

wdog32_config_t

Parameters

- config – Pointer to the WDOG32 configuration structure.

AT_QUICKACCESS_SECTION_CODE (status_t WDOG32_Init(WDOG_Type *base,
const wdog32_config_t *config))

Initializes the WDOG32 module.

This function initializes the WDOG32. To reconfigure the WDOG32 without forcing a reset first, enableUpdate must be set to true in the configuration.

Example:

```
wdog32_config_t config;  
WDOG32_GetDefaultConfig(&config);  
config.timeoutValue = 0x7ffU;  
config.enableUpdate = true;  
WDOG32_Init(wdog_base,&config);
```

Note: If there is errata ERR010536 (FSL_FEATURE_WDOG_HAS_ERRATA_010536 defined as 1), then after calling this function, user need delay at least 4 LPO clock cycles before accessing other WDOG32 registers.

Parameters

- base – WDOG32 peripheral base address.
- config – The configuration of the WDOG32.

Return values

- kStatus_Success – The initialization was successful
- kStatus_Timeout – The initialization timed out

status_t WDOG32_Deinit(WDOG_Type *base)

De-initializes the WDOG32 module.

This function shuts down the WDOG32. Ensure that the WDOG_CS.UPDATE is 1, which means that the register update is enabled.

Parameters

- base – WDOG32 peripheral base address.

Return values

- kStatus_Success – The de-initialization was successful
- kStatus_Timeout – The de-initialization timed out

AT_QUICKACCESS_SECTION_CODE (status_t WDOG32_Unlock(WDOG_Type *base))

Unlocks the WDOG32 register written.

This function unlocks the WDOG32 register written.

Before starting the unlock sequence and following the configuration, disable the global interrupts. Otherwise, an interrupt could effectively invalidate the unlock sequence and the WCT may expire. After the configuration finishes, re-enable the global interrupts.

Parameters

- base – WDOG32 peripheral base address

Return values

- kStatus_Success – The unlock sequence was successful
- kStatus_Timeout – The unlock sequence timed out

AT_QUICKACCESS_SECTION_CODE (void WDOG32_Enable(WDOG_Type *base))

Enables the WDOG32 module.

Disables the WDOG32 module.

This function writes a value into the WDOG_CS register to enable the WDOG32. The WDOG_CS register is a write-once register. Please check the enableUpdate is set to true for calling WDOG32_Init to do wdog initialize. Before call the re-configuration APIs, ensure that the WCT window is still open and this register has not been written in this WCT while the function is called.

This function writes a value into the WDOG_CS register to disable the WDOG32. The WDOG_CS register is a write-once register. Please check the enableUpdate is set to true for calling WDOG32_Init to do wdog initialize. Before call the re-configuration APIs, ensure that the WCT window is still open and this register has not been written in this WCT while the function is called.

Parameters

- base – WDOG32 peripheral base address.
- base – WDOG32 peripheral base address

AT_QUICKACCESS_SECTION_CODE (void WDOG32_EnableInterrupts(WDOG_Type *base, uint32_t mask))

Enables the WDOG32 interrupt.

Clears the WDOG32 flag.

Disables the WDOG32 interrupt.

This function writes a value into the WDOG_CS register to enable the WDOG32 interrupt. The WDOG_CS register is a write-once register. Please check the enableUpdate is set to true for calling WDOG32_Init to do wdog initialize. Before call the re-configuration APIs, ensure that the WCT window is still open and this register has not been written in this WCT while the function is called.

Example to clear an interrupt flag:

```
WDOG32_ClearStatusFlags(wdog_base, kWDOG32_InterruptFlag);
```

Parameters

- base – WDOG32 peripheral base address.
- mask – The interrupts to enable. The parameter can be a combination of the following source if defined:
 - kWDOG32_InterruptEnable

This function writes a value into the WDOG_CS register to disable the WDOG32 interrupt. The WDOG_CS register is a write-once register. Please check the enableUpdate is set to true for calling WDOG32_Init to do wdog initialize. Before call the re-configuration APIs, ensure that the WCT window is still open and this register has not been written in this WCT while the function is called.

- base – WDOG32 peripheral base address.
- mask – The interrupts to disabled. The parameter can be a combination of the following source if defined:
 - kWDOG32_InterruptEnable

This function clears the WDOG32 status flag.

- base – WDOG32 peripheral base address.
- mask – The status flags to clear. The parameter can be any combination of the following values:
 - kWDOG32_InterruptFlag

```
static inline uint32_t WDOG32_GetStatusFlags(WDOG_Type *base)
```

Gets the WDOG32 all status flags.

This function gets all status flags.

Example to get the running flag:

```
uint32_t status;
status = WDOG32_GetStatusFlags(wdog_base) & kWDOG32_RunningFlag;
```

See also:

`_wdog32_status_flags_t`

- true: related status flag has been set.
- false: related status flag is not set.

Parameters

- base – WDOG32 peripheral base address

Returns

State of the status flag: asserted (true) or not-asserted (false).

```
AT_QUICKACCESS_SECTION_CODE (void WDOG32_SetTimeoutValue(WDOG_Type *base,
uint16_t timeoutCount))
```

Sets the WDOG32 timeout value.

This function writes a timeout value into the WDOG_TOVAL register. The WDOG_TOVAL register is a write-once register. To ensure the reconfiguration fits the timing of WCT, unlock function will be called inline.

Parameters

- base – WDOG32 peripheral base address
- timeoutCount – WDOG32 timeout value, count of WDOG32 clock ticks.

```
AT_QUICKACCESS_SECTION_CODE (void WDOG32_SetWindowValue(WDOG_Type *base,
uint16_t windowValue))
```

Sets the WDOG32 window value.

This function writes a window value into the WDOG_WIN register. The WDOG_WIN register is a write-once register. Please check the enableUpdate is set to true for calling WDOG32_Init to do wdog initialize. Before call the re-configuration APIs, ensure that the WCT window is still open and this register has not been written in this WCT while the function is called.

Parameters

- base – WDOG32 peripheral base address.
- windowValue – WDOG32 window value.

static inline void WDOG32_Refresh(WDOG_Type *base)

Refreshes the WDOG32 timer.

This function feeds the WDOG32. This function should be called before the Watchdog timer is in timeout. Otherwise, a reset is asserted.

Parameters

- base – WDOG32 peripheral base address

static inline uint16_t WDOG32_GetCounterValue(WDOG_Type *base)

Gets the WDOG32 counter value.

This function gets the WDOG32 counter value.

Parameters

- base – WDOG32 peripheral base address.

Returns

Current WDOG32 counter value.

WDOG_FIRST_WORD_OF_UNLOCK

First word of unlock sequence

WDOG_SECOND_WORD_OF_UNLOCK

Second word of unlock sequence

WDOG_FIRST_WORD_OF_REFRESH

First word of refresh sequence

WDOG_SECOND_WORD_OF_REFRESH

Second word of refresh sequence

FSL_WDOG32_DRIVER_VERSION

WDOG32 driver version.

enum __wdog32_clock_source

Max loops to wait for WDOG32 unlock sequence complete.

This is the maximum number of loops to wait for the wdog32 unlock sequence to complete. If set to 0, it will wait indefinitely until the unlock sequence is complete.

Max loops to wait for WDOG32 reconfiguration complete.

This is the maximum number of loops to wait for the wdog32 reconfiguration to complete. If set to 0, it will wait indefinitely until the reconfiguration is complete.

Describes WDOG32 clock source.

Values:

enumerator kWDOG32_ClockSource0

Clock source 0

enumerator kWDOG32_ClockSource1

Clock source 1

enumerator kWDOG32_ClockSource2

Clock source 2

enumerator kWDOG32_ClockSource3

Clock source 3

enum __wdog32_clock_prescaler

Describes the selection of the clock prescaler.

Values:

enumerator kWDOG32_ClockPrescalerDivide1

Divided by 1

enumerator kWDOG32_ClockPrescalerDivide256

Divided by 256

enum __wdog32_test_mode

Describes WDOG32 test mode.

Values:

enumerator kWDOG32_TestModeDisabled

Test Mode disabled

enumerator kWDOG32_UserModeEnabled

User Mode enabled

enumerator kWDOG32_LowByteTest

Test Mode enabled, only low byte is used

enumerator kWDOG32_HighByteTest

Test Mode enabled, only high byte is used

enum __wdog32_interrupt_enable_t

WDOG32 interrupt configuration structure.

This structure contains the settings for all of the WDOG32 interrupt configurations.

Values:

enumerator kWDOG32_InterruptEnable

Interrupt is generated before forcing a reset

enum __wdog32_status_flags_t

WDOG32 status flags.

This structure contains the WDOG32 status flags for use in the WDOG32 functions.

Values:

enumerator kWDOG32_RunningFlag

Running flag, set when WDOG32 is enabled

enumerator kWDOG32_InterruptFlag

Interrupt flag, set when interrupt occurs

typedef enum __wdog32_clock_source wdog32_clock_source_t

Max loops to wait for WDOG32 unlock sequence complete.

This is the maximum number of loops to wait for the wdog32 unlock sequence to complete. If set to 0, it will wait indefinitely until the unlock sequence is complete.

Max loops to wait for WDOG32 reconfiguration complete.

This is the maximum number of loops to wait for the wdog32 reconfiguration to complete. If set to 0, it will wait indefinitely until the reconfiguration is complete.

Describes WDOG32 clock source.

typedef enum __wdog32_clock_prescaler wdog32_clock_prescaler_t

Describes the selection of the clock prescaler.

typedef struct __wdog32_work_mode wdog32_work_mode_t

Defines WDOG32 work mode.

```
typedef enum _wdog32_test_mode wdog32_test_mode_t
```

Describes WDOG32 test mode.

```
typedef struct _wdog32_config wdog32_config_t
```

Describes WDOG32 configuration structure.

```
struct _wdog32_work_mode
```

#include <fsl_wdog32.h> Defines WDOG32 work mode.

Public Members

bool enableWait

Enables or disables WDOG32 in wait mode

bool enableStop

Enables or disables WDOG32 in stop mode

bool enableDebug

Enables or disables WDOG32 in debug mode

```
struct _wdog32_config
```

#include <fsl_wdog32.h> Describes WDOG32 configuration structure.

Public Members

bool enableWdog32

Enables or disables WDOG32

wdog32_clock_source_t clockSource

Clock source select

wdog32_clock_prescaler_t prescaler

Clock prescaler value

wdog32_work_mode_t workMode

Configures WDOG32 work mode in debug stop and wait mode

wdog32_test_mode_t testMode

Configures WDOG32 test mode

bool enableUpdate

Update write-once register enable

bool enableInterrupt

Enables or disables WDOG32 interrupt

bool enableWindowMode

Enables or disables WDOG32 window mode

uint16_t windowValue

Window value

uint16_t timeoutValue

Timeout value

Chapter 3

Middleware

3.1 File System

3.1.1 FatFs

MCUXpresso SDK : mcuxsdk-middleware-fatfs

Overview This repository is for FatFs middleware delivery and it contains the components officially provided in NXP MCUXpresso SDK. This repository is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository (mcuxsdk-manifests) for the complete delivery of MCUXpresso SDK.

Documentation Overall details can be reviewed here: [MCUXpresso SDK Online Documentation](#)

Visit [FatFs - Documentation](#) to review details on the contents in this sub-repo.

Setup Instructions on how to install the MCUXpresso SDK provided from GitHub via west manifest [Getting Started with SDK - Detailed Installation Instructions](#)

Contribution Contributions are not currently accepted. Guidelines to contribute will be posted in the future.

Repo Specific Content This is MCUXpresso SDK fork of FatFs (FAT file system created by ChaN). Official documentation is available at <http://elm-chan.org/fsw/ff/>

MCUXpresso version is extending original content by following hardware specific porting layers:

- mmc_disk
- nand_disk
- ram_disk
- sd_disk
- sdspi_disk
- usb_disk

Changelog FatFs

All notable changes to this project will be documented in this file.

The format is based on [Keep a Changelog](#)

[R0.15_rev0]

- Upgraded to version 0.15
- Applied patches from <http://elm-chan.org/fsw/ff/patches.html>

[R0.14b_rev1]

- Applied patches from <http://elm-chan.org/fsw/ff/patches.html>

[R0.14b_rev0]

- Upgraded to version 0.14b

[R0.14a_rev0]

- Upgraded to version 0.14a
- Applied patch ff14a_p1.diff and ff14a_p2.diff

[R0.14_rev0]

- Upgraded to version 0.14
- Applied patch ff14_p1.diff and ff14_p2.diff

[R0.13c_rev0]

- Upgraded to version 0.13c
- Applied patches ff_13c_p1.diff, ff_13c_p2.diff, ff_13c_p3.diff and ff_13c_p4.diff.

[R0.13b_rev0]

- Upgraded to version 0.13b

[R0.13a_rev0]

- Upgraded to version 0.13a. Added patch ff_13a_p1.diff.

[R0.12c_rev1]

- Add NAND disk support.

[R0.12c_rev0]

- Upgraded to version 0.12c and applied patches ff_12c_p1.diff and ff_12c_p2.diff.

[R0.12b_rev0]

- Upgraded to version 0.12b.

[R0.11a]

- Added glue functions for low-level drivers (SDHC, SDSPI, RAM, MMC). Modified diskio.c.
- Added RTOS wrappers to make FatFs thread safe. Modified syscall.c.
- Renamed ffconf.h to ffconf_template.h. Each application should contain its own ffconf.h.
- Included ffconf.h into diskio.c to enable the selection of physical disk from ffconf.h by macro definition.
- Conditional compilation of physical disk interfaces in diskio.c.

3.2 Motor Control

3.2.1 FreeMASTER

Communication Driver User Guide

Introduction

What is FreeMASTER? FreeMASTER is a PC-based application developed by NXP for NXP customers. It is a versatile tool usable as a real-time monitor, visualization tool, and a graphical control panel of embedded applications based on the NXP processing units.

This document describes the embedded-side software driver which implements an interface between the application and the host PC. The interface covers the following communication:

- **Serial** UART communication either over plain RS232 interface or more typically over a USB-to-Serial either external or built in a debugger probe.
- **USB** direct connection to target microcontroller
- **CAN bus**
- **TCP/IP network** wired or WiFi
- **Segger J-Link RTT**
- **JTAG** debug port communication
- ...and all of the above also using a **Zephyr** generic drivers.

The driver also supports so-called “packet-driven BDM” interface which enables a protocol-based communication over a debugging port. The BDM stands for Background Debugging Module and its physical implementation is different on each platform. Some platforms leverage a semi-standard JTAG interface, other platforms provide a custom implementation called BDM. Regardless of the name, this debugging interface enables non-intrusive access to the memory space while the target CPU is running. For basic memory read and write operations, there is no communication driver required on the target when communicating with the host PC. Use this driver to get more advanced FreeMASTER protocol features over the BDM interface. The driver must be configured for the packet-driven BDM mode, in which the host PC uses the debugging interface to write serial command frames directly to the target memory buffer. The same method is then used to read response frames from that memory buffer.

Similar to “packet-driven BDM”, the FreeMASTER also supports a communication over [J-Link RTT](<https://www.segger.com/products/debug-probes/j-link/technology/about-real-time-transfer/>) interface defined by SEGGER Microcontroller GmbH for ARM CortexM-based microcontrollers. This method also uses JTAG physical interface and enables high-speed real time communication to run over the same channel as used for application debugging.

Driver version 3 This document describes version 3 of the FreeMASTER Communication Driver. This version features the implementation of the new Serial Protocol, which significantly extends the features and security of its predecessor. The new protocol internal number is v4 and its specification is available in the documentation accompanying the driver code.

Driver V3 is deployed to modern 32-bit MCU platforms first, so the portfolio of supported platforms is smaller than for the previous V2 versions. It is recommended to keep using the V2 driver for legacy platforms, such as S08, S12, ColdFire, or Power Architecture. Reach out to [FreeMASTER community](#) or to the local NXP representative with requests for more information or to port the V3 driver to legacy MCU devices.

Thanks to a layered approach, the new driver simplifies the porting of the driver to new UART, CAN or networking communication interfaces significantly. Users are encouraged to port the driver to more NXP MCU platforms and contribute the code back to NXP for integration into future releases. Existing code and low-level driver layers may be used as an example when porting to new targets.

Note: Using the FreeMASTER tool and FreeMASTER Communication Driver is only allowed in systems based on NXP microcontroller or microprocessor unit. Use with non-NXP MCU platforms is **not permitted** by the license terms.

Target platforms The driver implementation uses the following abstraction mechanisms which simplify driver porting and supporting new communication modules:

- **General CPU Platform** (see source code in the `src/platforms` directory). The code in this layer is only specific to native data type sizes and CPU architectures (for example; alignment-aware memory copy routines). This driver version brings two generic implementations of 32-bit platforms supporting both little-endian and big-endian architectures. There are also implementations customized for the 56F800E family of digital signal controllers and S12Z MCUs. **Zephyr** is treated as a specific CPU platform as it brings unified user configuration (Kconfig) and generic hardware device drivers. With Zephyr, the transport layer and low-level communication layers described below are configured automatically using Kconfig and Device Tree technologies.
- **Transport Communication Layer** - The Serial, CAN, Networking, PD-BDM, and other methods of transport logic are implemented as a driver layer called `FMSTR_TRANSPORT` with a uniform API. A support of the Network transport also extends single-client modes of operation which are native for Serial, USB and CAN by a concept of multiple client sessions.
- **Low-level Communication Driver** - Each type of transport further defines a low-level API used to access the physical communication module. For example, the Serial transport defines a character-oriented API implemented by different serial communication modules like UART, LPUART, USART, and also USB-CDC. Similarly, the CAN transport defines a message-oriented API implemented by the FlexCAN or MCAN modules. Moreover, there are multiple different implementations for the same kind of communication peripherals. The difference between the implementation is in the way the low-level hardware registers are accessed. The `mcuxsdk` folder contains implementations which use MCUXpresso SDK drivers. These drivers should be used in applications based on the NXP MCUXpresso SDK. The “ampsdk” drivers target automotive-specific MCUs and their respective SDKs. The “dreg” implementations use a plain C-language access to hardware register addresses which makes it a universal and the most portable solution. In this case, users are encouraged to add more drivers for other communication modules or other respective SDKs and contribute the code back to NXP for integration.

The low-level drivers defined for the Networking transport enable datagram-oriented UDP and stream TCP communication. This implementation is demonstrated using the lwIP software stack but shall be portable to other TCP/IP stacks. It may sound surprisingly, but also the Segger J-Link RTT communication driver is linked to the Networking transport (RTT is stream oriented communication handled similarly to TCP).

Replacing existing drivers For all supported platforms, the driver described in this document replaces the V2 implementation and also older driver implementations that were available separately for individual platforms (PC Master SCI drivers).

Clocks, pins, and peripheral initialization The FreeMASTER communication driver is only responsible for runtime processing of the communication and must be integrated with an user application code to function properly. The user application code is responsible for general initialization of clock sources, pin multiplexers, and peripheral registers related to the communication speed. Such initialization should be done before calling the FMSTR_Init function.

It is recommended to develop the user application using one of the Software Development Kits (SDKs) available from third parties or directly from NXP, such as MCUXpresso SDK, MCUXpresso IDE, and related tools. This approach simplifies the general configuration process significantly.

MCUXpresso SDK The MCUXpresso SDK is a software package provided by NXP which contains the device initialization code, linker files, and software drivers with example applications for the NXP family of MCUs. The MCUXpresso Config Tools may be used to generate the clock-setup and pin-multiplexer setup code suitable for the selected processor.

The MCUXpresso SDK also contains this FreeMASTER communication driver as a “middleware” component which may be downloaded along with the example applications from <https://mcuxpresso.nxp.com/en/welcome>.

MCUXpresso SDK on GitHub The FreeMASTER communication driver is also released as one of the middleware components of the MCUXpresso SDK on the GitHub. This release enables direct integration of the FreeMASTER source code Git repository into a target applications including Zephyr applications.

Related links:

- [The official FreeMASTER middleware repository.](#)
- [Online version of this document](#)

FreeMASTER in Zephyr The FreeMASTER middleware repository can be used with MCUXpresso SDK as well as a Zephyr module. Zephyr-specific samples which include examples of Kconfig and Device Tree configurations for Serial, USB and Network communications are available in separate repository. West manifest in this sample repository fetches the full Zephyr package including the FreeMASTER middleware repository used as a Zephyr module.

Example applications

MCUX SDK Example applications There are several example applications available for each supported MCU platform.

- **fmstr_uart** demonstrates a plain serial transmission, typically connecting to a computer’s physical or virtual COM port. The typical transmission speed is 115200 bps.

- **fmstr_can** demonstrates CAN bus communication. This requires a suitable CAN interface connected to the computer and interconnected with the target MCU using a properly terminated CAN bus. The typical transmission speed is 500 kbps. A FreeMASTER-over-CAN communication plug-in must be used.
- **fmstr_usb_cdc** uses an on-chip USB controller to implement a CDC communication class. It is connected directly to a computer's USB port and creates a virtual COM port device. The typical transmission speed is above 1 Mbps.
- **fmstr_net** demonstrates the Network communication over UDP or TCP protocol. Existing examples use lwIP stack to implement the communication, but in general, it shall be possible to use any other TCP/IP stack to achieve the same functionality.
- **fmstr_wifi** is the fmstr_net application modified to use a WiFi network interface instead of a wired Ethernet connection.
- **fmstr_rtt** demonstrates the communication over SEGGER J-Link RTT interface. Both fmstr_net and fmstr_rtt examples require the FreeMASTER TCP/UDP communication plug-in to be used on the PC host side.
- **fmstr_eonce** uses the real-time data unit on the JTAG EOnCE module of the 56F800E family to implement pseudo-serial communication over the JTAG port. The typical transmission speed is around 10 kbps. This communication requires FreeMASTER JTAG/EOnCE communication plug-in.
- **fmstr_pd_bdm** uses JTAG or BDM debugging interface to access the target RAM directly while the CPU is running. Note that such approach can be used with any MCU application, even without any special driver code. The computer reads from and writes into the RAM directly without CPU intervention. The Packet-Driven BDM (PD-BDM) communication uses the same memory access to exchange command and response frames. With PD-BDM, the FreeMASTER tool is able to go beyond basic memory read/write operations and accesses also advanced features like Recorder, TSA, or Pipes. The typical transmission speed is around 10 kbps. A PD-BDM communication plug-in must be used in FreeMASTER and configured properly for the selected debugging interface. Note that this communication cannot be used while a debugging interface is used by a debugger session.
- **fmstr_any** is a special example application which demonstrates how the NXP MCUXpresso Config Tools can be used to configure pins, clocks, peripherals, interrupts, and even the FreeMASTER “middleware” driver features in a graphical and user friendly way. The user can switch between the Serial, CAN, and other ways of communication and generate the required initialization code automatically.

Zephyr sample applications Zephyr sample applications demonstrate Kconfig and Device Tree configuration which configure the FreeMASTER middleware module for a selected communication option (Serial, CAN, Network or RTT).

Refer to *readme.md* files in each sample directory for description of configuration options required to implement FreeMASTER connectivity.

Description

This section shows how to add the FreeMASTER Communication Driver into application and how to configure the connection to the FreeMASTER visualization tool.

Features The FreeMASTER driver implements the FreeMASTER protocol V4 and provides the following features which may be accessed using the FreeMASTER visualization tool:

- Read/write access to any memory location on the target.
- Optional password protection of the read, read/write, and read/write/flash access levels.

- Atomic bit manipulation on the target memory (bit-wise write access).
- Optimal size-aligned access to memory which is also suitable to access the peripheral register space.
- Oscilloscope access—real-time access to target variables. The sample rate may be limited by the communication speed.
- Recorder— access to the fast transient recorder running on the board as a part of the FreeMASTER driver. The sample rate is only limited by the MCU CPU speed. The length of the data recorded depends on the amount of available memory.
- Multiple instances of Oscilloscopes and Recorders without the limitation of maximum number of variables.
- Application commands—high-level message delivery from the PC to the application.
- TSA tables—describing the data types, variables, files, or hyperlinks exported by the target application. The TSA newly supports also non-memory mapped resources like external EEPROM or SD Card files.
- Pipes—enabling the buffered stream-oriented data exchange for a general-purpose terminal-like communication, diagnostic data streaming, or other data exchange.

The FreeMASTER driver features:

- Full FreeMASTER protocol V4 implementation with a new V4 style of CRC used.
- Layered approach supporting Serial, CAN, Network, PD-BDM, and other transports.
- Layered low-level Serial transport driver architecture enabling to select UART, LPUART, USART, and other physical implementations of serial interfaces, including USB-CDC.
- Layered low-level CAN transport driver architecture enabling to select FlexCAN, msCAN, MCAN, and other physical implementations of the CAN interface.
- Layered low-level Networking transport enabling to select TCP, UDP or J-Link RTT communication.
- TSA support to write-protect memory regions or individual variables and to deny the access to the unsafe memory.
- The pipe callback handlers are invoked whenever new data is available for reading from the pipe.
- Two Serial Single-Wire modes of operation are enabled. The “external” mode has the RX and TX shorted on-board. The “true” single-wire mode interconnects internally when the MCU or UART modules support it.

The following sections briefly describe all FreeMASTER features implemented by the driver. See the PC-based FreeMASTER User Manual for more details on how to use the features to monitor, tune, or control an embedded application.

Board Detection The FreeMASTER protocol V4 defines the standard set of configuration values which the host PC tool reads to identify the target and to access other target resources properly. The configuration includes the following parameters:

- Version of the driver and the version of the protocol implemented.
- MTU as the Maximum size of the Transmission Unit (for example; communication buffer size).
- Application name, description, and version strings.
- Application build date and time as a string.
- Target processor byte ordering (little/big endian).
- Protection level that requires password authentication.

- Number of the Recorder and Oscilloscope instances.
- RAM Base Address for optimized memory access commands.

Memory Read This basic feature enables the host PC to read any data memory location by specifying the address and size of the required memory area. The device response frame must be shorter than the MTU to fit into the outgoing communication buffer. To read a device memory of any size, the host uses the information retrieved during the Board Detection and splits the large-block request to multiple partial requests.

The driver uses size-aligned operations to read the target memory (for example; uses proper read-word instruction when an address is aligned to 4 bytes).

Memory Write Similarly to the Memory Read operation, the Memory Write feature enables to write to any RAM memory location on the target device. A single write command frame must be shorter than the MTU to fit into the target communication buffer. Larger requests must be split into smaller ones.

The driver uses size-aligned operations to write to the target memory (for example; uses proper write-word instruction when an address is aligned to 4 bytes).

Masked Memory Write To implement the write access to a single bit or a group of bits of target variables, the Masked Memory Write feature is available in the FreeMASTER protocol and it is supported by the driver using the Read-Modify-Write approach.

Be careful when writing to bit fields of volatile variables that are also modified in an application interrupt. The interrupt may be serviced in the middle of a read-modify-write operation and it may cause data corruption.

Oscilloscope The protocol and driver enables any number of variables to be read at once with a single request from the host. This feature is called Oscilloscope and the FreeMASTER tool uses it to display a real-time graph of variable values.

The driver can be configured to support any number of Oscilloscope instances and enable simultaneously running graphs to be displayed on the host computer screen.

Recorder The protocol enables the host to select target variables whose values are then periodically recorded into a dedicated on-board memory buffer. After such data sampling stops (either on a host request or by evaluating a threshold-crossing condition), the data buffer is downloaded to the host and displayed as a graph. The data sampling rate is not limited by the speed of the communication line, so it enables displaying the variable transitions in a very high resolution.

The driver can be configured to support multiple Recorder instances and enable multiple recorder graphs to be displayed on the host screen. Having multiple recorders also enables setting the recording point differently for each instance. For example; one instance may be recording data in a general timer interrupt while another instance may record at a specific control algorithm time in the PWM interrupt.

TSA With the TSA feature, data types and variables can be described directly in the application source code. Such information is later provided to the FreeMASTER tool which may use it instead of reading symbol data from the application ELF executable file.

The information is encoded as so-called TSA tables which become direct part of the application code. The TSA tables contain descriptors of variables that shall be visible to the host tool. The descriptors can describe the memory areas by specifying the address and size of the memory

block or more conveniently using the C variable names directly. Different set of TSA descriptors can be used to encode information about the structure types, unions, enumerations, or arrays.

The driver also supports special types of TSA table entries to describe user resources like external EEPROM and SD Card files, memory-mapped files, virtual directories, web URL hyperlinks, and constant enumerations.

TSA Safety When the TSA is enabled in the application, the TSA Safety can be enabled and validate the memory accesses directly by the embedded-side driver. When the TSA Safety is turned on, any memory request received from the host is validated and accepted only if it belongs to a TSA-described object. The TSA entries can be declared as Read-Write or Read-Only so that the driver can actively deny the write access to the Read-Only objects.

Application commands The Application Commands are high-level messages that can be delivered from the PC Host to the embedded application for further processing. The embedded application can either poll the status, or be called back when a new Application Command arrives to be processed. After the embedded application acknowledges that the command is handled, the host receives the Result Code and reads the other return data from memory. Both the Application Commands and the Result Codes are specific to a given application and it is user's responsibility to define them. The FreeMASTER protocol and the FreeMASTER driver only implement the delivery channel and a set of API calls to enable the Application Command processing in general.

Pipes The Pipes enable buffered and stream-oriented data exchange between the PC Host and the target application. Any pipe can be written to and read from at both ends (either on the PC or the MCU). The data transmission is acknowledged using the special FreeMASTER protocol commands. It is guaranteed that the data bytes are delivered from the writer to the reader in a proper order and without losses.

Serial single-wire operation The MCU Serial Communication Driver natively supports normal dual-wire operation. Because the protocol is half-duplex only, the driver can also operate in two single-wire modes:

- “External” single-wire operation where the Receiver and Transmitter pins are shorted on the board. This mode is supported by default in the MCU driver because the Receiver and Transmitter units are enabled or disabled whenever needed. It is also easy to extend this operation for the RS485 communication.
- “True” single-wire mode which uses only a single pin and the direction switching is made by the UART module. This mode of operation must be enabled by defining the FMSTR_SERIAL_SINGLEWIRE configuration option.

Multi-session support With networking interface it is possible for multiple clients to access the target MCU simultaneously. Reading and writing of target memory is processed atomically so there is no risk of data corruption. The state-full resources such as Recorders or Oscilloscopes are locked to a client session upon first use and access is denied to other clients until lock is released..

Zephyr-specific

Dedicated communication task FreeMASTER communication may run isolated in a dedicated task. The task automates the FMSTR_Init and FMSTR_Poll calls together with periodic activities enabling the FreeMASTER UI to fetch information about tasks and CPU utilization. The task can be started automatically or manually, and it must be assigned a priority to be able to react on interrupts and other communication events. Refer to Zephyr FreeMASTER sample applications which all use this communication task.

Zephyr shell and logging over FreeMASTER pipe FreeMASTER implements a shell backend which may use FreeMASTER pipe as a I/O terminal and logging output. Refer to Zephyr FreeMASTER sample applications which all use this feature.

Automatic TSA tables TSA tables can be declared as “automatic” in Zephyr which make them automatically registered in the table list. This may be very useful when there are many TSA tables or when the tables are defined in different (often unrelated) libraries linked together. In this case user does not need to build a list of all tables manually.

Driver files The driver source files can be found in a top-level src folder, further divided into the sub-folders:

- **src/platforms** platform-specific folder—one folder exists for each supported processor platform (for example; 32-bit Little Endian platform). Each such folder contains a platform header file with data types and a code which implements the potentially platform-specific operations, such as aligned memory access.
- **src/common** folder—contains the common driver source files shared by the driver for all supported platforms. All the .c files must be added to the project, compiled, and linked together with the application.
 - *freemaster.h* - master driver header file, which declares the common data types, macros, and prototypes of the FreeMASTER driver API functions.
 - *freemaster_cfg.h.example* - this file can serve as an example of the FreeMASTER driver configuration file. Save this file into a project source code folder and rename it to *freemaster_cfg.h*. The FreeMASTER driver code includes this file to get the project-specific configuration options and to optimize the compilation of the driver.
 - *freemaster_defcfg.h* - defines the default values for each FreeMASTER configuration option if the option is not set in the *freemaster_cfg.h* file.
 - *freemaster_protocol.h* - defines the FreeMASTER protocol constants used internally by the driver.
 - *freemaster_protocol.c* - implements the FreeMASTER protocol decoder and handles the basic Get Configuration Value, Memory Read, and Memory Write commands.
 - *freemaster_rec.c* - handles the Recorder-specific commands and implements the Recorder sampling and triggering routines. When the Recorder is disabled by the FreeMASTER driver configuration file, this file only compiles to empty API functions.
 - *freemaster_scope.c* - handles the Oscilloscope-specific commands. If the Oscilloscope is disabled by the FreeMASTER driver configuration file, this file compiles as void.
 - *freemaster_pipes.c* - implements the Pipes functionality when the Pipes feature is enabled.
 - *freemaster_appcmd.c* - handles the communication commands used to deliver and execute the Application Commands within the context of the embedded application. When the Application Commands are disabled by the FreeMASTER driver configuration file, this file only compiles to empty API functions.

- *freemaster_tsa.c* - handles the commands specific to the TSA feature. This feature enables the FreeMASTER host tool to obtain the TSA memory descriptors declared in the embedded application. If the TSA is disabled by the FreeMASTER driver configuration file, this file compiles as void.
- *freemaster_tsa.h* - contains the declaration of the macros used to define the TSA memory descriptors. This file is indirectly included into the user application code (via *freemaster.h*).
- *freemaster_sha.c* - implements the SHA-1 hash code used in the password authentication algorithm.
- *freemaster_private.h* - contains the declarations of functions and data types used internally in the driver. It also contains the C pre-processor statements to perform the compile-time verification of the user configuration provided in the *freemaster_cfg.h* file.
- *freemaster_serial.c* - implements the serial protocol logic including the CRC, FIFO queuing, and other communication-related operations. This code calls the functions of the low-level communication driver indirectly via a character-oriented API exported by the specific low-level driver.
- *freemaster_serial.h* - defines the low-level character-oriented Serial API.
- *freemaster_can.c* - implements the CAN protocol logic including the CAN message preparation, signalling using the first data byte in the CAN frame, and other communication-related operations. This code calls the functions of the low-level communication driver indirectly via a message-oriented API exported by the specific low-level driver.
- *freemaster_can.h* - defines the low-level message-oriented CAN API.
- *freemaster_net.c* - implements the Network protocol transport logic including multiple session management code.
- *freemaster_net.h* - definitions related to the Network transport.
- *freemaster_pdbdm.c* - implements the packet-driven BDM communication buffer and other communication-related operations.
- *freemaster_utils.c* - aligned memory copy routines, circular buffer management and other utility functions
- *freemaster_utils.h* - definitions related to utility code.
- **src/drivers/[sdk]/serial** - contains the code related to the serial communication implemented using one of the supported SDK frameworks.
 - *freemaster_serial_XXX.c* and *.h* - implement low-level access to the communication peripheral registers. Different files exist for the UART, LPUART, USART, and other kinds of Serial communication modules.
- **src/drivers/[sdk]/can** - contains the code related to the serial communication implemented using one of the supported SDK frameworks.
 - *freemaster_XXX.c* and *.h* - implement low-level access to the communication peripheral registers. Different files exist for the FlexCAN, msCAN, MCAN, and other kinds of CAN communication modules.
- **src/drivers/[sdk]/network** - contains low-level code adapting the FreeMASTER Network transport to an underlying TCP/IP or RTT stack.
 - *freemaster_net_lwip_tcp.c* and *_udp.c* - default networking implementation of TCP and UDP transports using lwIP stack.
 - *freemaster_net_segger_rtt.c* - implementation of network transport using Segger J-Link RTT interface

Driver configuration The driver is configured using a single header file (*freemaster_cfg.h*). Create this file and save it together with other project source files before compiling the driver code. All FreeMASTER driver source files include the *freemaster_cfg.h* file and use the macros defined here for the conditional and parameterized compilation. The C compiler must locate the configuration file when compiling the driver files. Typically, it can be achieved by putting this file into a folder where the other project-specific included files are stored.

As a starting point to create the configuration file, get the *freemaster_cfg.h.example* file, rename it to *freemaster_cfg.h*, and save it into the project area.

Note: It is NOT recommended to leave the *freemaster_cfg.h* file in the FreeMASTER driver source code folder. The configuration file must be placed at a project-specific location, so that it does not affect the other applications that use the same driver.

Configurable items This section describes the configuration options which can be defined in *freemaster_cfg.h*.

Interrupt modes

```
#define FMSTR_LONG_INTR    [0|1]
#define FMSTR_SHORT_INTR  [0|1]
#define FMSTR_POLL_DRIVEN [0|1]
```

Value Type boolean (0 or 1)

Description Exactly one of the three macros must be defined to non-zero. The others must be defined to zero or left undefined. The non-zero-defined constant selects the interrupt mode of the driver. See [Driver interrupt modes](#).

- FMSTR_LONG_INTR — long interrupt mode
- FMSTR_SHORT_INTR — short interrupt mode
- FMSTR_POLL_DRIVEN — poll-driven mode

Note: Some options may not be supported by all communication interfaces. For example, the FMSTR_SHORT_INTR option is not supported by the USB_CDC interface.

Protocol transport

```
#define FMSTR_TRANSPORT [identifier]
```

Value Type Driver identifiers are structure instance names defined in FreeMASTER source code. Specify one of existing instances to make use of the protocol transport.

Description Use one of the pre-defined constants, as implemented by the FreeMASTER code. The current driver supports the following transports:

- FMSTR_SERIAL - serial communication protocol
- FMSTR_CAN - using CAN communication
- FMSTR_PDBDM - using packet-driven BDM communication
- FMSTR_NET - network communication using TCP or UDP protocol

Serial transport This section describes configuration parameters used when serial transport is used:

```
#define FMSTR_TRANSPORT FMSTR_SERIAL
```

FMSTR_SERIAL_DRV Select what low-level driver interface will be used when implementing the Serial communication.

```
#define FMSTR_SERIAL_DRV [identifier]
```

Value Type Driver identifiers are structure instance names defined in FreeMASTER drivers code. Specify one of existing serial driver instances.

Description When using MCUXpresso SDK, use one of the following constants (see */drivers/mcuxsdk/serial* implementation):

- **FMSTR_SERIAL_MCUX_UART** - UART driver
- **FMSTR_SERIAL_MCUX_LPUART** - LPUART driver
- **FMSTR_SERIAL_MCUX_USART** - USART driver
- **FMSTR_SERIAL_MCUX_MINIUSART** - miniUSART driver
- **FMSTR_SERIAL_MCUX_QSCI** - DSC QSCI driver
- **FMSTR_SERIAL_MCUX_USB** - USB/CDC class driver (also see code in the */support/mcuxsdk_usb* folder)
- **FMSTR_SERIAL_56F800E_EONCE** - DSC JTAG EOnCE driver

Other SDKs or BSPs may define custom low-level driver interface structure which may be used as **FMSTR_SERIAL_DRV**. For example:

- **FMSTR_SERIAL_DREG_UART** - demonstrates the low-level interface implemented without the MCUXpresso SDK and using direct access to peripheral registers.

FMSTR_SERIAL_BASE

```
#define FMSTR_SERIAL_BASE [address|symbol]
```

Value Type Optional address value (numeric or symbolic)

Description Specify the base address of the UART, LPUART, USART, or other serial peripheral module to be used for the communication. This value is not defined by default. User application should call `FMSTR_SetSerialBaseAddress()` to select the peripheral module.

FMSTR_COMM_BUFFER_SIZE

```
#define FMSTR_COMM_BUFFER_SIZE [number]
```

Value Type 0 or a value in range 32...255

Description Specify the size of the communication buffer to be allocated by the driver. Default value, which suits all driver features, is used when this option is defined as 0.

FMSTR_COMM_RQUEUE_SIZE

```
#define FMSTR_COMM_RQUEUE_SIZE [number]
```

Value Type Value in range 0...255

Description Specify the size of the FIFO receiver queue used to quickly receive and store characters in the FMSTR_SHORT_INTR interrupt mode. The default value is 32 B.

FMSTR_SERIAL_SINGLEWIRE

```
#define FMSTR_SERIAL_SINGLEWIRE [0|1]
```

Value Type Boolean 0 or 1.

Description Set to non-zero to enable the “True” single-wire mode which uses a single MCU pin to communicate. The low-level driver enables the pin direction switching when the MCU peripheral supports it.

CAN Bus transport This section describes configuration parameters used when CAN transport is used:

```
#define FMSTR_TRANSPORT FMSTR_CAN
```

FMSTR_CAN_DRV Select what low-level driver interface will be used when implementing the CAN communication.

```
#define FMSTR_CAN_DRV [identifier]
```

Value Type Driver identifiers are structure instance names defined in FreeMASTER drivers code. Specify one of existing CAN driver instances.

Description When using MCUXpresso SDK, use one of the following constants (see */drivers/mcuxsdk/can implementation*):

- **FMSTR_CAN_MCUX_FLEXCAN** - FlexCAN driver
- **FMSTR_CAN_MCUX_MCAN** - MCAN driver
- **FMSTR_CAN_MCUX_MSCAN** - msCAN driver
- **FMSTR_CAN_MCUX_DSCFLEXCAN** - DSC FlexCAN driver
- **FMSTR_CAN_MCUX_DSCMSCAN** - DSC msCAN driver

Other SDKs or BSPs may define the custom low-level driver interface structure which may be used as FMSTR_CAN_DRV.

FMSTR_CAN_BASE

```
#define FMSTR_CAN_BASE [address|symbol]
```

Value Type Optional address value (numeric or symbolic)

Description Specify the base address of the FlexCAN, msCAN, or other CAN peripheral module to be used for the communication. This value is not defined by default. User application should call `FMSTR_SetCanBaseAddress()` to select the peripheral module.

FMSTR_CAN_CMDID

```
#define FMSTR_CAN_CMDID [number]
```

Value Type CAN identifier (11-bit or 29-bit number)

Description CAN message identifier used for FreeMASTER commands (direction from PC Host tool to target application). When declaring 29-bit identifier, combine the numeric value with `FMSTR_CAN_EXTID` bit. Default value is 0x7AA.

FMSTR_CAN_RSPID

```
#define FMSTR_CAN_RSPID [number]
```

Value Type CAN identifier (11-bit or 29-bit number)

Description CAN message identifier used for responding messages (direction from target application to PC Host tool). When declaring 29-bit identifier, combine the numeric value with `FMSTR_CAN_EXTID` bit. Note that both *CMDID* and *RSPID* values may be the same. Default value is 0x7AA.

FMSTR_FLEXCAN_TXMB

```
#define FMSTR_FLEXCAN_TXMB [number]
```

Value Type Number in range of 0..N where N is number of CAN message-buffers supported by HW module.

Description Only used when the FlexCAN low-level driver is used. Define the FlexCAN message buffer for CAN frame transmission. Default value is 0.

FMSTR_FLEXCAN_RXMB

```
#define FMSTR_FLEXCAN_RXMB [number]
```

Value Type Number in range of 0..N where N is number of CAN message-buffers supported by HW module.

Description Only used when the FlexCAN low-level driver is used. Define the FlexCAN message buffer for CAN frame reception. Note that the FreeMASTER driver may also operate with a common message buffer used by both TX and RX directions. Default value is 1.

Network transport This section describes configuration parameters used when Network transport is used:

```
#define FMSTR_TRANSPORT FMSTR_NET
```

FMSTR_NET_DRV Select network interface implementation.

```
#define FMSTR_NET_DRV [identifier]
```

Value Type Identifiers are structure instance names defined in FreeMASTER drivers code. Specify one of existing NET driver instances.

Description When using MCUXpresso SDK, use one of the following constants (see */drivers/mcuxsdk/network implementation*):

- **FMSTR_NET_LWIP_TCP** - TCP communication using lwIP stack
- **FMSTR_NET_LWIP_UDP** - UDP communication using lwIP stack
- **FMSTR_NET_SEGGER_RTT** - Communication using SEGGER J-Link RTT interface

Other SDKs or BSPs may define the custom networking interface which may be used as FMSTR_CAN_DRV.

Add another row below:

FMSTR_NET_PORT

```
#define FMSTR_NET_PORT [number]
```

Value Type TCP or UDP port number (short integer)

Description Specifies the server port number used by TCP or UDP protocols.

FMSTR_NET_BLOCKING_TIMEOUT

```
#define FMSTR_NET_BLOCKING_TIMEOUT [number]
```

Value Type Timeout as number of milliseconds

Description This value specifies a timeout in milliseconds for which the network socket operations may block the execution inside *FMSTR_Poll*. This may be set high (e.g. 250) when a dedicated RTOS task is used to handle FreeMASTER protocol polling. Set to a lower value when the polling task is also responsible for other operations. Set to 0 to attempt to use non-blocking socket operations.

FMSTR_NET_AUTODISCOVERY

```
#define FMSTR_NET_AUTODISCOVERY [0|1]
```

Value Type Boolean 0 or 1.

Description This option enables the FreeMASTER driver to use a separate UDP socket to broadcast auto-discovery messages to network. This helps the FreeMASTER tool to discover the target device address, port and protocol options.

Debugging options**FMSTR_DISABLE**

```
#define FMSTR_DISABLE [0|1]
```

Value Type boolean (0 or 1)

Description Define as non-zero to disable all FreeMASTER features, exclude the driver code from build, and compile all its API functions empty. This may be useful to remove FreeMASTER without modifying any application source code. Default value is 0 (false).

FMSTR_DEBUG_TX

```
#define FMSTR_DEBUG_TX [0|1]
```

Value Type Boolean 0 or 1.

Description Define as non-zero to enable the driver to periodically transmit test frames out on the selected communication interface (SCI or CAN). With the debug transmission enabled, it is simpler to detect problems in the baudrate or other communication configuration settings.

The test frames are transmitted until the first valid command frame is received from the PC Host tool. The test frame is a valid error status frame, as defined by the protocol format. On the serial line, the test frame consists of three printable characters (+©W) which are easy to capture using the serial terminal tools.

This feature requires the FMSTR_Poll() function to be called periodically. Default value is 0 (false).

FMSTR_APPLICATION_STR

```
#define FMSTR_APPLICATION_STR
```

Value Type String.

Description Name of the application visible in FreeMASTER host application.

Memory access

FMSTR_USE_READMEM

```
#define FMSTR_USE_READMEM [0|1]
```

Value Type Boolean 0 or 1.

Description Define as non-zero to implement the Memory Read command and enable FreeMASTER to have read access to memory and variables. The access can be further restricted by using a TSA feature.
Default value is 1 (true).

FMSTR_USE_WRITEMEM

```
#define FMSTR_USE_WRITEMEM [0|1]
```

Value Type Boolean 0 or 1.

Description Define as non-zero to implement the Memory Write command.
The default value is 1 (true).

Oscilloscope options**FMSTR_USE_SCOPE**

```
#define FMSTR_USE_SCOPE [number]
```

Value Type Integer number.

Description Number of Oscilloscope instances to be supported. Set to 0 to disable the Oscilloscope feature.
Default value is 0.

FMSTR_MAX_SCOPE_VARS

```
#define FMSTR_MAX_SCOPE_VARS [number]
```

Value Type Integer number larger than 2.

Description Number of variables to be supported by each Oscilloscope instance.
Default value is 8.

Recorder options**FMSTR_USE_RECORDER**

```
#define FMSTR_USE_RECORDER [number]
```

Value Type Integer number.

Description Number of Recorder instances to be supported. Set to 0 to disable the Recorder feature.

Default value is 0.

FMSTR_REC_BUFF_SIZE

```
#define FMSTR_REC_BUFF_SIZE [number]
```

Value Type Integer number larger than 2.

Description Defines the size of the memory buffer used by the Recorder instance #0.

Default: not defined, user shall call 'FMSTR_RecorderCreate()' API function to specify this parameter in run time.

FMSTR_REC_TIMEBASE

```
#define FMSTR_REC_TIMEBASE [time specification]
```

Value Type Number (nanoseconds time).

Description Defines the base sampling rate in nanoseconds (sampling speed) Recorder instance #0.

Use one of the following macros:

- FMSTR_REC_BASE_SECONDS(x)
- FMSTR_REC_BASE_MILLISEC(x)
- FMSTR_REC_BASE_MICROSEC(x)
- FMSTR_REC_BASE_NANOSEC(x)

Default: not defined, user shall call 'FMSTR_RecorderCreate()' API function to specify this parameter in run time.

FMSTR_REC_FLOAT_TRIG

```
#define FMSTR_REC_FLOAT_TRIG [0|1]
```

Value Type Boolean 0 or 1.

Description Define as non-zero to implement the floating-point triggering. Be aware that floating-point triggering may grow the code size by linking the floating-point standard library.

Default value is 0 (false).

Application Commands options

FMSTR_USE_APPCMD

```
#define FMSTR_USE_APPCMD [0|1]
```

Value Type Boolean 0 or 1.

Description Define as non-zero to implement the Application Commands feature. Default value is 0 (false).

FMSTR_APPCMD_BUFF_SIZE

```
#define FMSTR_APPCMD_BUFF_SIZE [size]
```

Value Type Numeric buffer size in range 1..255

Description The size of the Application Command data buffer allocated by the driver. The buffer stores the (optional) parameters of the Application Command which waits to be processed.

FMSTR_MAX_APPCMD_CALLS

```
#define FMSTR_MAX_APPCMD_CALLS [number]
```

Value Type Number in range 0..255

Description The number of different Application Commands that can be assigned a callback handler function using FMSTR_RegisterAppCmdCall(). Default value is 0.

TSA options**FMSTR_USE_TSA**

```
#define FMSTR_USE_TSA [0|1]
```

Value Type Boolean 0 or 1.

Description Enable the FreeMASTER TSA feature to be used. With this option enabled, the TSA tables defined in the applications are made available to the FreeMASTER host tool. Default value is 0 (false).

FMSTR_USE_TSA_SAFETY

```
#define FMSTR_USE_TSA_SAFETY [0|1]
```

Value Type Boolean 0 or 1.

Description Enable the memory access validation in the FreeMASTER driver. With this option, the host tool is not able to access the memory which is not described by at least one TSA descriptor. Also a write access is denied for objects defined as read-only in TSA tables. Default value is 0 (false).

FMSTR_USE_TSA_INROM

```
#define FMSTR_USE_TSA_INROM [0|1]
```

Value Type Boolean 0 or 1.

Description Declare all TSA descriptors as *const*, which enables the linker to put the data into the flash memory. The actual result depends on linker settings or the linker commands used in the project. Default value is 0 (false).

FMSTR_USE_TSA_DYNAMIC

```
#define FMSTR_USE_TSA_DYNAMIC [0|1]
```

Value Type Boolean 0 or 1.

Description Enable runtime-defined TSA entries to be added to the TSA table by the FMSTR_SetUpTsaBuff() and FMSTR_TsaAddVar() functions. Default value is 0 (false).

Pipes options

FMSTR_USE_PIPES

```
#define FMSTR_USE_PIPES [0|1]
```

Value Type Boolean 0 or 1.

Description Enable the FreeMASTER Pipes feature to be used. Default value is 0 (false).

FMSTR_MAX_PIPES_COUNT

```
#define FMSTR_MAX_PIPES_COUNT [number]
```

Value Type Number in range 1..63.

Description The number of simultaneous pipe connections to support. The default value is 1.

Driver interrupt modes To implement the communication, the FreeMASTER driver handles the Serial or CAN module's receive and transmit requests. Use the *freemaster_cfg.h* configuration file to select whether the driver processes the communication automatically in the interrupt service routine handler or if it only polls the status of the module (typically during the application idle time).

This section describes each of the interrupt mode in more details.

Completely Interrupt-Driven operation Activated using:

```
#define FMSTR_LONG_INTR 1
```

In this mode, both the communication and the FreeMASTER protocol decoding is done in the *FMSTR_SerialIsr*, *FMSTR_CanIsr*, or other interrupt service routine. Because the protocol execution may be a lengthy task (especially with the TSA-Safety enabled) it is recommended to use this mode only if the interrupt prioritization scheme is possible in the application and the FreeMASTER interrupt is assigned to a lower (the lowest) priority.

In this mode, the application code must register its own interrupt handler for all interrupt vectors related to the selected communication interface and call the *FMSTR_SerialIsr* or *FMSTR_CanIsr* functions from that handler.

Mixed Interrupt and Polling Modes Activated using:

```
#define FMSTR_SHORT_INTR 1
```

In this mode, the communication processing time is split between the interrupt routine and the main application loop or task. The raw communication is handled by the *FMSTR_SerialIsr*, *FMSTR_CanIsr*, or other interrupt service routine, while the protocol decoding and execution is handled by the *FMSTR_Poll* routine. Call *FMSTR_Poll* during the idle time in the application main loop.

The interrupt processing in this mode is relatively fast and deterministic. Upon a serial-receive event, the received character is only placed into a FIFO-like queue and it is not further processed. Upon a CAN receive event, the received frame is stored into a receive buffer. When transmitting, the characters are fetched from the prepared transmit buffer.

In this mode, the application code must register its own interrupt handler for all interrupt vectors related to the selected communication interface and call the *FMSTR_SerialIsr* or *FMSTR_CanIsr* functions from that handler.

When the serial interface is used as the serial communication interface, ensure that the *FMSTR_Poll* function is called at least once per *N* character time periods. *N* is the length of the FreeMASTER FIFO queue (*FMSTR_COMM_QUEUE_SIZE*) and the character time is the time needed to transmit or receive a single byte over the SCI line.

Completely Poll-driven

```
#define FMSTR_POLL_DRIVEN 1
```

In this mode, both the communication and the FreeMASTER protocol decoding are done in the *FMSTR_Poll* routine. No interrupts are needed and the *FMSTR_SerialIsr*, *FMSTR_CanIsr*, and similar handlers compile to an empty code.

When using this mode, ensure that the *FMSTR_Poll* function is called by the application at least once per the serial "character time" which is the time needed to transmit or receive a single character.

In the latter two modes (*FMSTR_SHORT_INTR* and *FMSTR_POLL_DRIVEN*), the protocol handling takes place in the *FMSTR_Poll* routine. An application interrupt can occur in the middle of the

Read Memory or Write Memory commands' execution and corrupt the variable being accessed by the FreeMASTER driver. In these two modes, some issues or glitches may occur when using FreeMASTER to visualize or monitor volatile variables modified in interrupt servicing code.

The same issue may appear even in the full interrupt mode (FMSTR_LONG_INTR), if volatile variables are modified in the interrupt code with a priority higher than the priority of the communication interrupt.

Data types Simple portability was one of the main requirements when writing the FreeMASTER driver. This is why the driver code uses the privately-declared data types and the vast majority of the platform-dependent code is separated in the platform-dependent source files. The data types used in the driver API are all defined in the platform-specific header file.

To prevent name conflicts with the symbols used in the application, all data types, macros, and functions have the FMSTR_ prefix. The only global variables used in the driver are the transport and low-level API structures exported from the driver-implementation layer to upper layers. Other than that, all private variables are declared as static and named using the fmstr_ prefix.

Communication interface initialization The FreeMASTER driver does not perform neither the initialization nor the configuration of the peripheral module that it uses to communicate. It is the application startup code responsibility to configure the communication module before the FreeMASTER driver is initialized by the FMSTR_Init call.

When the Serial communication module is used as the FreeMASTER communication interface, configure the UART receive and transmit pins, the serial communication baud rate, parity (no-parity), the character length (eight bits), and the number of stop bits (one) before initializing the FreeMASTER driver. For either the long or the short interrupt modes of the driver (see [Driver interrupt modes](#)), configure the interrupt controller and register an application-specific interrupt handler for all interrupt sources related to the selected serial peripheral module. Call the FMSTR_SerialIsr function from the application handler.

When a CAN module is used as the FreeMASTER communication interface, configure the CAN receive and transmit pins and the CAN module bit rate before initializing the FreeMASTER driver. For either the long or the short interrupt modes of the driver (see [Driver interrupt modes](#)), configure the interrupt controller and register an application-specific interrupt handler for all interrupt sources related to the selected CAN peripheral module. Call the FMSTR_CanIsr function from the application handler.

Note: It is not necessary to enable or unmask the serial nor the CAN interrupts before initializing the FreeMASTER driver. The driver enables or disables the interrupts and communication lines, as required during runtime.

FreeMASTER Recorder calls When using the FreeMASTER Recorder in the application (FMSTR_USE_RECORDER > 0), call the FMSTR_RecorderCreate function early after FMSTR_Init to set up each recorder instance to be used in the application. Then call the FMSTR_Recorder function periodically in the code where the data recording should occur. A typical place to call the Recorder routine is at the timer or PWM interrupts, but it can be anywhere else. The example applications provided together with the driver code call the FMSTR_Recorder in the main application loop.

In applications where FMSTR_Recorder is called periodically with a constant period, specify the period in the Recorder configuration structure before calling FMSTR_RecorderCreate. This setting enables the PC Host FreeMASTER tool to display the X-axis of the Recorder graph properly scaled for the time domain.

Driver usage Start using or evaluating FreeMASTER by opening some of the example applications available in the driver setup package.

Follow these steps to enable the basic FreeMASTER connectivity in the application:

- Make sure that all *.c files of the FreeMASTER driver from the `src/common/platforms/[your_platform]` folder are a part of the project. See [Driver files](#) for more details.
- Configure the FreeMASTER driver by creating or editing the `freemaster_cfg.h` file and by saving it into the application project directory. See [Driver configuration](#) for more details.
- Include the `freemaster.h` file into any application source file that makes the FreeMASTER API calls.
- Initialize the Serial or CAN modules. Set the baud rate, parity, and other parameters of the communication. Do not enable the communication interrupts in the interrupt mask registers.
- For the FMSTR_LONG_INTR and FMSTR_SHORT_INTR modes, install the application-specific interrupt routine and call the FMSTR_SerialIsr or FMSTR_CanIsr functions from this handler.
- Call the FMSTR_Init function early on in the application initialization code.
- Call the FMSTR_RecorderCreate functions for each Recorder instance to enable the Recorder feature.
- In the main application loop, call the FMSTR_Poll API function periodically when the application is idle.
- For the FMSTR_SHORT_INTR and FMSTR_LONG_INTR modes, enable the interrupts globally so that the interrupts can be handled by the CPU.

Communication troubleshooting The most common problem that causes communication issues is a wrong baud rate setting or a wrong pin multiplexer setting of the target MCU. When a communication between the PC Host running FreeMASTER and the target MCU cannot be established, try enabling the FMSTR_DEBUG_TX option in the `freemaster_cfg.h` file and call the FMSTR_Poll function periodically in the main application task loop.

With this feature enabled, the FreeMASTER driver periodically transmits a test frame through the Serial or CAN lines. Use a logic analyzer or an oscilloscope to monitor the signals at the communication pins of the CPU device to examine whether the bit rate and signal polarity are configured properly.

Driver API

This section describes the driver Application Programmers' Interface (API) needed to initialize and use the FreeMASTER serial communication driver.

Control API There are three key functions to initialize and use the driver.

FMSTR_Init

Prototype

```
FMSTR_BOOL FMSTR_Init(void);
```

- Declaration: `freemaster.h`
- Implementation: `freemaster_protocol.c`

Description This function initializes the internal variables of the FreeMASTER driver and enables the communication interface. This function does not change the configuration of the selected communication module. The hardware module must be initialized before the [FMSTR_Init](#) function is called.

A call to this function must occur before calling any other FreeMASTER driver API functions.

FMSTR_Poll

Prototype

```
void FMSTR_Poll(void);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_protocol.c*

Description In the poll-driven or short interrupt modes, this function handles the protocol decoding and execution (see [Driver interrupt modes](#)). In the poll-driven mode, this function also handles the communication interface with the PC. Typically, the [FMSTR_Poll](#) function is called during the “idle” time in the main application task loop.

To prevent the receive data overflow (loss) on a serial interface, make sure that the FMSTR_Poll function is called at least once per the time calculated as:

$$N * Tchar$$

where:

- *N* is equal to the length of the receive FIFO queue (configured by the FMSTR_COMM_RQUEUE_SIZE macro). *N* is 1 for the poll-driven mode.
- *Tchar* is the character time, which is the time needed to transmit or receive a single byte over the SCI line.

Note: In the long interrupt mode, this function typically compiles as an empty function and can still be called. It is worthwhile to call this function regardless of the interrupt mode used in the application. This approach enables a convenient switching between the different interrupt modes only by changing the configuration macros in the *freemaster_cfg.h* file.

FMSTR_SerialIsr / FMSTR_CanIsr

Prototype

```
void FMSTR_SerialIsr(void);
void FMSTR_CanIsr(void);
```

- Declaration: *freemaster.h*
- Implementation: *hw-specific low-level driver C file*

Description This function contains the interrupt-processing code of the FreeMASTER driver. In long or short interrupt modes (see [Driver interrupt modes](#)), this function must be called from the application interrupt service routine registered for the communication interrupt vector. On platforms where the communication module uses multiple interrupt vectors, the application should register a handler for all vectors and call this function at each interrupt.

Note: In a poll-driven mode, this function is compiled as an empty function and does not have to be used.

Recorder API

FMSTR_RecorderCreate

Prototype

```
FMSTR_BOOL FMSTR_RecorderCreate(FMSTR_INDEX recIndex, FMSTR_REC_BUFF* buffCfg);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_rec.c*

Description This function registers a recorder instance and enables it to be used by the PC Host tool. Call this function for all recorder instances from 0 to the maximum number defined by the FMSTR_USE_RECORDER configuration option (minus one). An exception to this requirement is the recorder of instance 0 which may be automatically configured by FMSTR_Init when the *freemaster_cfg.h* configuration file defines the *FMSTR_REC_BUFF_SIZE* and *FMSTR_REC_TIMEBASE* options.

For more information, see [Configurable items](#).

FMSTR_Recorder

Prototype

```
void FMSTR_Recorder(FMSTR_INDEX recIndex);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_rec.c*

Description This function takes a sample of the variables being recorded using the FreeMASTER Recorder instance *recIndex*. If the selected Recorder is not active when the *FMSTR_Recorder* function is being called, the function returns immediately. When the Recorder is active, the values of the variables being recorded are copied into the recorder buffer and the trigger conditions are evaluated.

If a trigger condition is satisfied, the Recorder enters the post-trigger mode, where it counts down the follow-up samples (number of *FMSTR_Recorder* function calls) and de-activates the Recorder when the required post-trigger samples are finished.

The *FMSTR_Recorder* function is typically called in the timer or PWM interrupt service routines. This function can also be called in the application main loop (for testing purposes).

FMSTR_RecorderTrigger

Prototype

```
void FMSTR_RecorderTrigger(FMSTR_INDEX recIndex);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_rec.c*

Description This function forces the Recorder trigger condition to happen, which causes the Recorder to be automatically deactivated after the post-trigger samples are sampled. Use this function in the application code for programmatic control over the Recorder triggering. This can be useful when a more complex triggering conditions need to be used.

Fast Recorder API The Fast Recorder feature is not available in the FreeMASTER driver version 3. This feature was heavily dependent on the target platform and it was only available for the 56F8xxxx DSCs.

TSA Tables When the TSA is enabled in the FreeMASTER driver configuration file (by setting the FMSTR_USE_TSA macro to a non-zero value), it defines the so-called TSA tables in the application. This section describes the macros that must to be used to define the TSA tables.

There can be any number of TSA tables spread across the application source files. There must be always exactly one TSA Table List defined, which informs the FreeMASTER driver about the active TSA tables.

When there is at least one TSA table and one TSA Table List defined in the application, the TSA information automatically appears in the FreeMASTER symbols list. The symbols can then be used to create FreeMASTER variables for visualization or control.

TSA table definition The TSA table describes the static or global variables together with their address, size, type, and access-protection information. If the TSA-described variables are of a structure type, the TSA table may also describe this type and provide an access to the individual structure members of the variable.

The TSA table definition begins with the FMSTR_TSA_TABLE_BEGIN macro with a *table_id* identifying the table. The *table_id* shall be a valid C-language symbol.

```
FMSTR_TSA_TABLE_BEGIN(table_id)
```

After this opening macro, the TSA descriptors are placed using these macros:

```
/* Adding variable descriptors */
FMSTR_TSA_RW_VAR(name, type) /* read/write variable entry */
FMSTR_TSA_RO_VAR(name, type) /* read-only variable entry */

/* Description of complex data types */
FMSTR_TSA_STRUCT(struct_name) /* structure or union type entry */
FMSTR_TSA_MEMBER(struct_name, member_name, type) /* structure member entry */

/* Memory blocks */
FMSTR_TSA_RW_MEM(name, type, address, size) /* read/write memory block */
FMSTR_TSA_RO_MEM(name, type, address, size) /* read-only memory block */
```

The table is closed using the FMSTR_TSA_TABLE_END macro:

```
FMSTR_TSA_TABLE_END()
```

TSA descriptor parameters The TSA descriptor macros accept these parameters:

- *name* — variable name. The variable must be defined before the TSA descriptor references it.
- *type* — variable or member type. Only one of the pre-defined type constants may be used (see below).
- *struct_name* — structure type name. The type must be defined (typedef) before the TSA descriptor references it.

- *member_name* — structure member name.

Note: The structure member descriptors (FMSTR_TSA_MEMBER) must immediately follow the parent structure descriptor (FMSTR_TSA_STRUCT) in the table.

Note: To write-protect the variables in the FreeMASTER driver (FMSTR_TSA_RO_VAR), enable the TSA-Safety feature in the configuration file.

TSA variable types The table lists *type* identifiers which can be used in TSA descriptors:

Constant	Description
FMSTR_TSA_UINTn	Unsigned integer type of size <i>n</i> bits (n=8,16,32,64)
FMSTR_TSA_SINTn	Signed integer type of size <i>n</i> bits (n=8,16,32,64)
FMSTR_TSA_FRACn	Fractional number of size <i>n</i> bits (n=16,32,64).
FMSTR_TSA_FRAC_Q(<i>m,n</i>)	Signed fractional number in general Q form (m+n+1 total bits)
FMSTR_TSA_FRAC_UQ(<i>m,n</i>)	Unsigned fractional number in general UQ form (m+n total bits)
FMSTR_TSA_FLOAT	4-byte standard IEEE floating-point type
FMSTR_TSA_DOUBLE	8-byte standard IEEE floating-point type
FMSTR_TSA_POINTER	Generic pointer type defined (platform-specific 16 or 32 bit)
FM-STR_TSA_USERTYPE(<i>name</i>)	Structure or union type declared with FMSTR_TSA_STRUCT record

TSA table list There shall be exactly one TSA Table List in the application. The list contains one entry for each TSA table defined anywhere in the application.

The TSA Table List begins with the FMSTR_TSA_TABLE_LIST_BEGIN macro and continues with the TSA table entries for each table.

```
FMSTR_TSA_TABLE_LIST_BEGIN()
```

```
FMSTR_TSA_TABLE(table_id)
FMSTR_TSA_TABLE(table_id2)
FMSTR_TSA_TABLE(table_id3)
...
```

The list is closed with the FMSTR_TSA_TABLE_LIST_END macro:

```
FMSTR_TSA_TABLE_LIST_END()
```

TSA Active Content entries FreeMASTER v2.0 and higher supports TSA Active Content, enabling the TSA tables to describe the memory-mapped files, virtual directories, and URL hyperlinks. FreeMASTER can access such objects similarly to accessing the files and folders on the local hard drive.

With this set of TSA entries, the FreeMASTER pages can be embedded directly into the target MCU flash and accessed by FreeMASTER directly over the communication line. The HTML-coded pages rendered inside the FreeMASTER window can access the TSA Active Content resources using a special URL referencing the *fmaster*: protocol.

This example provides an overview of the supported TSA Active Content entries:

```
FMSTR_TSA_TABLE_BEGIN(files_and_links)
```

```
/* Directory entry applies to all subsequent MEMFILE entries */
```

```
FMSTR_TSA_DIRECTORY("/text_files") /* entering a new virtual directory */
```

(continues on next page)

(continued from previous page)

```

/* The readme.txt file will be accessible at the fmstr://text_files/readme.txt URL */
FMSTR_TSA_MEMFILE("readme.txt", readme_txt, sizeof(readme_txt)) /* memory-mapped file */

/* Files can also be specified with a full path so the DIRECTORY entry does not apply */
FMSTR_TSA_MEMFILE("/index.htm", index, sizeof(index)) /* memory-mapped file */
FMSTR_TSA_MEMFILE("/prj/demo.pmp", demo_pmp, sizeof(demo_pmp)) /* memory-mapped file */

/* Hyperlinks can point to a local MEMFILE object or to the Internet */
FMSTR_TSA_HREF("Board's Built-in Welcome Page", "/index.htm")
FMSTR_TSA_HREF("FreeMASTER Home Page", "http://www.nxp.com/freemaster")

/* Project file links simplify opening the projects from any URLs */
FMSTR_TSA_PROJECT("Demonstration Project (embedded)", "/prj/demo.pmp")
FMSTR_TSA_PROJECT("Full Project (online)", "http://mycompany.com/prj/demo.pmp")

FMSTR_TSA_TABLE_END()

```

TSA API

FMSTR_SetUpTsaBuff

Prototype

```
FMSTR_BOOL FMSTR_SetUpTsaBuff(FMSTR_ADDR buffAddr, FMSTR_SIZE buffSize);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_tsa.c*

Arguments

- *buffAddr* [in] - address of the memory buffer for the dynamic TSA table
- *buffSize* [in] - size of the memory buffer which determines the maximum number of TSA entries to be added in the runtime

Description This function must be used to assign the RAM memory buffer to the TSA subsystem when FMSTR_USE_TSA_DYNAMIC is enabled. The memory buffer is then used to store the TSA entries added dynamically to the runtime TSA table using the FMSTR_TsaAddVar function call. The runtime TSA table is processed by the FreeMASTER PC Host tool along with all static tables as soon as the communication port is open.

The size of the memory buffer determines the number of TSA entries that can be added dynamically. Depending on the MCU platform, one TSA entry takes either 8 or 16 bytes.

FMSTR_TsaAddVar

Prototype

```

FMSTR_BOOL FMSTR_TsaAddVar(FMSTR_TSATBL_STRPTR tsaName, FMSTR_TSATBL_STRPTR
↪ tsaType,
    FMSTR_TSATBL_VOIDPTR varAddr, FMSTR_SIZE32 varSize,
    FMSTR_SIZE flags);

```

- Declaration: *freemaster.h*

- Implementation: *freemaster_tsa.c*

Arguments

- *tsaName* [in] - name of the object
- *tsaType* [in] - name of the object type
- *varAddr* [in] - address of the object
- *varSize* [in] - size of the object
- *flags* [in] - access flags; a combination of these values:
 - *FMSTR_TSA_INFO_RO_VAR* — read-only memory-mapped object (typically a variable)
 - *FMSTR_TSA_INFO_RW_VAR* — read/write memory-mapped object
 - *FMSTR_TSA_INFO_NON_VAR* — other entry, describing structure types, structure members, enumerations, and other types

Description This function can be called only when the dynamic TSA table is enabled by the *FMSTR_USE_TSA_DYNAMIC* configuration option and when the *FMSTR_SetUpTsaBuff* function call is made to assign the dynamic TSA table memory. This function adds an entry into the dynamic TSA table. It can be used to register a read-only or read/write memory object or describe an item of the user-defined type.

See [TSA table definition](#) for more details about the TSA table entries.

Application Commands API

FMSTR_GetAppCmd

Prototype

```
FMSTR_APPCMD_CODE FMSTR_GetAppCmd(void);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_appcmd.c*

Description This function can be used to detect if there is an Application Command waiting to be processed by the application. If no command is pending, this function returns the *FMSTR_APPCMDRESULT_NOCMD* constant. Otherwise, this function returns the code of the Application Command that must be processed. Use the *FMSTR_AppCmdAck* call to acknowledge the Application Command after it is processed and to return the appropriate result code to the host.

The *FMSTR_GetAppCmd* function does not report the commands for which a callback handler function exists. If the *FMSTR_GetAppCmd* function is called when a callback-registered command is pending (and before it is actually processed by the callback function), this function returns *FMSTR_APPCMDRESULT_NOCMD*.

FMSTR_GetAppCmdData

Prototype

```
FMSTR_APPCMD_PDATA FMSTR_GetAppCmdData(FMSTR_SIZE* dataLen);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_appcmd.c*

Arguments

- *dataLen* [out] - pointer to the variable that receives the length of the data available in the buffer. It can be NULL when this information is not needed.

Description This function can be used to retrieve the Application Command data when the application determines that an Application Command is pending (see [FMSTR_GetAppCmd](#)).

There is just a single buffer to hold the Application Command data (the buffer length is FMSTR_APPCMD_BUFF_SIZE bytes). If the data are to be used in the application after the command is processed by the FMSTR_AppCmdAck call, copy the data out to a private buffer.

FMSTR_AppCmdAck

Prototype

```
void FMSTR_AppCmdAck(FMSTR_APPCMD_RESULT resultCode);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_appcmd.c*

Arguments

- *resultCode* [in] - the result code which is to be returned to FreeMASTER

Description This function is used when the Application Command processing finishes in the application. The resultCode passed to this function is returned back to the host and the driver is re-initialized to expect the next Application Command.

After this function is called and before the next Application Command arrives, the return value of the FMSTR_GetAppCmd function is FMSTR_APPCMDRESULT_NOCMD.

FMSTR_AppCmdSetResponseData

Prototype

```
void FMSTR_AppCmdSetResponseData(FMSTR_ADDR resultDataAddr, FMSTR_SIZE resultDataLen);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_appcmd.c*

Arguments

- *resultDataAddr* [in] - pointer to the data buffer that is to be copied to the Application Command data buffer
- *resultDataLen* [in] - length of the data to be copied. It must not exceed the FMSTR_APPCMD_BUFF_SIZE value.

Description This function can be used before the Application Command processing finishes, when there are data to be returned back to the PC.

The response data buffer is copied into the Application Command data buffer, from where it is accessed when the host requires it. Do not use FMSTR_GetAppCmdData and the data buffer after FMSTR_AppCmdSetResponseData is called.

Note: The current version of FreeMASTER does not support the Application Command response data.

FMSTR_RegisterAppCmdCall

Prototype

```
FMSTR_BOOL FMSTR_RegisterAppCmdCall(FMSTR_APPCMD_CODE appCmdCode, FMSTR_
↪PAPPCMDFUNC callbackFunc);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_appcmd.c*

Arguments

- *appCmdCode* [in] - the Application Command code for which the callback is to be registered
- *callbackFunc* [in] - pointer to the callback function that is to be registered. Use NULL to unregister a callback registered previously with this Application Command.

Return value This function returns a non-zero value when the callback function was successfully registered or unregistered. It can return zero when trying to register a callback function for more than FMSTR_MAX_APPCMD_CALLS different Application Commands.

Description This function can be used to register the given function as a callback handler for the Application Command. The Application Command is identified using single-byte code. The callback function is invoked automatically by the FreeMASTER driver when the protocol decoder obtains a request to get the application command result code.

The prototype of the callback function is

```
FMSTR_APPCMD_RESULT HandlerFunction(FMSTR_APPCMD_CODE nAppcmd,
FMSTR_APPCMD_PDATA pData, FMSTR_SIZE nDataLen);
```

Where:

- *nAppcmd* -Application Command code
- *pData* —points to the Application Command data received (if any)
- *nDataLen* —information about the Application Command data length

The return value of the callback function is used as the Application Command Result Code and returned to FreeMASTER.

Note: The FMSTR_MAX_APPCMD_CALLS configuration macro defines how many different Application Commands may be handled by a callback function. When FMSTR_MAX_APPCMD_CALLS is undefined or defined as zero, the FMSTR_RegisterAppCmdCall function always fails.

Pipes API

FMSTR_PipeOpen

Prototype

```
FMSTR_HPIPE FMSTR_PipeOpen(FMSTR_PIPE_PORT pipePort, FMSTR_PPIPEFUNC pipeCallback,
    FMSTR_ADDR pipeRxBuff, FMSTR_PIPE_SIZE pipeRxSize,
    FMSTR_ADDR pipeTxBuff, FMSTR_PIPE_SIZE pipeTxSize,
    FMSTR_U8 type, const FMSTR_CHAR *name);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_pipes.c*

Arguments

- *pipePort* [in] - port number that identifies the pipe for the client
- *pipeCallback* [in] - pointer to the callback function that is called whenever a pipe data status changes
- *pipeRxBuff* [in] - address of the receive memory buffer
- *pipeRxSize* [in] - size of the receive memory buffer
- *pipeTxBuff* [in] - address of the transmit memory buffer
- *pipeTxSize* [in] - size of the transmit memory buffer
- *type* [in] - a combination of FMSTR_PIPE_MODE_XXX and FMSTR_PIPE_SIZE_XXX constants describing primary pipe data format and usage. This type helps FreeMASTER decide how to access the pipe by default. Optional, use 0 when undetermined.
- *name* [in] - user name of the pipe port. This name is visible to the FreeMASTER user when creating the graphical pipe interface.

Description This function initializes a new pipe and makes it ready to accept or send the data to the PC Host client. The receive memory buffer is used to store the received data before they are read out by the FMSTR_PipeRead call. When this buffer gets full, the PC Host client denies the data transmission into this pipe until there is enough free space again. The transmit memory buffer is used to store the data transmitted by the application to the PC Host client using the FMSTR_PipeWrite call. The transmit buffer can get full when the PC Host is disconnected or when it is slow in receiving and reading out the pipe data.

The function returns the pipe handle which must be stored and used in the subsequent calls to manage the pipe object.

The callback function (if specified) is called whenever new data are received through the pipe and available for reading. This callback is also called when the data waiting in the transmit buffer are successfully pushed to the PC Host and the transmit buffer free space increases. The prototype of the callback function provided by the user application must be as follows. The *PipeHandler* name is only a placeholder and must be defined by the application.


```
void PipeHandler(FMSTR_HPIPE pipeHandle);
```

FMSTR_PipeClose

Prototype

```
void FMSTR_PipeClose(FMSTR_HPIPE pipeHandle);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_pipes.c*

Arguments

- *pipeHandle* [in] - pipe handle returned from the FMSTR_PipeOpen function call

Description This function de-initializes the pipe object. No data can be received or sent on the pipe after this call.

FMSTR_PipeWrite

Prototype

```
FMSTR_PIPE_SIZE FMSTR_PipeWrite(FMSTR_HPIPE pipeHandle, FMSTR_ADDR pipeData,  
    FMSTR_PIPE_SIZE pipeDataLen, FMSTR_PIPE_SIZE writeGranularity);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_pipes.c*

Arguments

- *pipeHandle* [in] - pipe handle returned from the FMSTR_PipeOpen function call
- *pipeData* [in] - address of the data to be written
- *pipeDataLen* [in] - length of the data to be written
- *writeGranularity* [in] - size of the minimum unit of data which is to be written

Description This function puts the user-specified data into the pipe's transmit memory buffer and schedules it for transmission. This function returns the number of bytes that were successfully written into the buffer. This number may be smaller than the number of the requested bytes if there is not enough free space in the transmit buffer.

The *writeGranularity* argument can be used to split the data into smaller chunks, each of the size given by the *writeGranularity* value. The FMSTR_PipeWrite function writes as many data chunks as possible into the transmit buffer and does not attempt to write an incomplete chunk. This feature can prove to be useful to avoid the intermediate caching when writing an array of integer values or other multi-byte data items. When making the *nGranularity* value equal to the *nLength* value, all data are considered as one chunk which is either written successfully as a whole or not at all. The *nGranularity* value of 0 or 1 disables the data-chunk approach.

FMSTR_PipeRead

Prototype

```
FMSTR_PIPE_SIZE FMSTR_PipeRead(FMSTR_HPIPE pipeHandle, FMSTR_ADDR pipeData,
    FMSTR_PIPE_SIZE pipeDataLen, FMSTR_PIPE_SIZE readGranularity);
```

- Declaration: *freemaster.h*
- Implementation: *freemaster_pipes.c*

Arguments

- *pipeHandle* [in] - pipe handle returned from the FMSTR_PipeOpen function call
- *pipeData* [in] - address of the data buffer to be filled with the received data
- *pipeDataLen* [in] - length of the data to be read
- *readGranularity* [in] - size of the minimum unit of data which is to be read

Description This function copies the data received from the pipe from its receive buffer to the user buffer for further processing. The function returns the number of bytes that were successfully copied to the buffer. This number may be smaller than the number of the requested bytes if there is not enough data bytes available in the receive buffer.

The readGranularity argument can be used to copy the data in larger chunks in the same way as described in the FMSTR_PipeWrite function.

API data types This section describes the data types used in the FreeMASTER driver. The information provided here can be useful when modifying or porting the FreeMASTER Communication Driver to new NXP platforms.

Note: The licensing conditions prohibit use of FreeMASTER and the FreeMASTER Communication Driver with non-NXP MPU or MCU products.

Public common types The table below describes the public data types used in the FreeMASTER driver API calls. The data types are declared in the *freemaster.h* header file.

Type name	Description
<i>FM-STR_ADDR</i> For example, this type is defined as long integer on the 56F8xxx platform where the 24-bit addresses must be supported, but the C-pointer may be only 16 bits wide in some compiler configurations.	Data type used to hold the memory address. On most platforms, this is normally a C-pointer, but it may also be a pure integer type.
<i>FM-STR_SIZE</i> It is required that this type is unsigned and at least 16 bits wide integer.	Data type used to hold the memory block size.
<i>FM-STR_BOOL</i> This type is used only in zero/non-zero conditions in the driver code.	Data type used as a general boolean type.
<i>FM-STR_APPCM</i> Generally, this is an unsigned 8-bit value.	Data type used to hold the Application Command code.
<i>FM-STR_APPCM</i> Generally, this is an unsigned 8-bit value.	Data type used to create the Application Command data buffer.
<i>FM-STR_APPCM</i> Generally, this is an unsigned 8-bit value.	Data type used to hold the Application Command result code.

Public TSA types The table describes the TSA-specific public data types. These types are declared in the *freemaster_tsa.h* header file, which is included in the user application indirectly by the *freemaster.h* file.

<i>FM-STR_TSA_TII</i>	Data type used to hold a descriptor index in the TSA table or a table index in the list of TSA tables. By default, this is defined as <i>FM-STR_SIZE</i> .
<i>FM-STR_TSA_TS</i>	Data type used to hold a memory block size, as used in the TSA descriptors. By default, this is defined as <i>FM-STR_SIZE</i> .

Public Pipes types The table describes the data types used by the FreeMASTER Pipes API:

<i>FM-STR_HPIPE</i>	Pipe handle that identifies the open-pipe object. Generally, this is a pointer to a void type.
<i>FM-STR_PIPE_PC</i>	Integer type required to hold at least 7 bits of data. Generally, this is an unsigned 8-bit or 16-bit type.
<i>FM-STR_PIPE_SI</i>	Integer type required to hold at least 16 bits of data. This is used to store the data buffer sizes.
<i>FM-STR_PPIPEF</i>	Pointer to the pipe handler function. See FM-STR_PipeOpen for more details.

Internal types The table describes the data types used internally by the FreeMASTER driver. The data types are declared in the platform-specific header file and they are not available in the application code.

<i>FMSTR_U8</i>	The smallest memory entity.
On the vast majority of platforms, this is an unsigned 8-bit integer.	
On the 56F8xx DSP platform, this is defined as an unsigned 16-bit integer.	
<i>FMSTR_U16</i>	Unsigned 16-bit integer.
<i>FMSTR_U32</i>	Unsigned 32-bit integer.
<i>FMSTR_S8</i>	Signed 8-bit integer.
<i>FMSTR_S16</i>	Signed 16-bit integer.
<i>FMSTR_S32</i>	Signed 32-bit integer.
<i>FMSTR_FLOAT</i>	4-byte standard IEEE floating-point type.
<i>FMSTR_FLAGS</i>	Data type forming a union with a structure of flag bit-fields.
<i>FMSTR_SIZE8</i>	Data type holding a general size value, at least 8 bits wide.
<i>FMSTR_INDEX</i>	General for-loop index. Must be signed, at least 16 bits wide.
<i>FMSTR_BCHR</i>	A single character in the communication buffer.
Typically, this is an 8-bit unsigned integer, except for the DSP platforms where it is a 16-bit integer.	
<i>FMSTR_BPTR</i>	A pointer to the communication buffer (an array of <i>FMSTR_BCHR</i>).

Document references

Links

- This document online: <https://mcuxpresso.nxp.com/mcuxsdk/latest/html/middleware/freemaster/doc/index.html>

- FreeMASTER tool home: www.nxp.com/freemaster
- FreeMASTER community area: community.nxp.com/community/freemaster
- FreeMASTER GitHub code repo: <https://github.com/nxp-mcuxpresso/mcux-freemaster>
- MCUXpresso SDK home: www.nxp.com/mcuxpresso
- MCUXpresso SDK builder: mcuxpresso.nxp.com/en

Documents

- *FreeMASTER Usage Serial Driver Implementation* (document [AN4752](#))
- *Integrating FreeMASTER Time Debugging Tool With CodeWarrior For Microcontrollers v10.X Project* (document [AN4771](#))
- *Flash Driver Library For MC56F847xx And MC56F827xx DSC Family* (document [AN4860](#))

Revision history This Table summarizes the changes done to this document since the initial release.

Revision	Date	Description
1.0	03/2006	Limited initial release
2.0	09/2007	Updated for FreeMASTER version. New Freescale document template used.
2.1	12/2007	Added description of the new Fast Recorder feature and its API.
2.2	04/2010	Added support for MPC56xx platform, Added new API for use CAN interface.
2.3	04/2011	Added support for Kxx Kinetis platform and MQX operating system.
2.4	06/2011	Serial driver update, adds support for USB CDC interface.
2.5	08/2011	Added Packet Driven BDM interface.
2.7	12/2013	Added FLEXCAN32 interface, byte access and isr callback configuration option.
2.8	06/2014	Removed obsolete license text, see the software package content for up-to-date license.
2.9	03/2015	Update for driver version 1.8.2 and 1.9: FreeMASTER Pipes, TSA Active Content, LIN Transport Layer support, DEBUG-TX communication troubleshooting, Kinetis SDK support.
3.0	08/2016	Update for driver version 2.0: Added support for MPC56xx, MPC57xx, KEAxx and S32Kxx platforms. New NXP document template as well as new license agreement used. added MCAN interface. Folders structure at the installation destination was rearranged.
4.0	04/2019	Update for driver released as part of FreeMASTER v3.0 and MCUXpresso SDK 2.6. Updated to match new V4 serial communication protocol and new configuration options. This version of the document removes substantial portion of outdated information related to S08, S12, ColdFire, Power and other legacy platforms.
4.1	04/2020	Minor update for FreeMASTER driver included in MCUXpresso SDK 2.8.
4.2	09/2020	Added example applications description and information about the MCUXpresso Config Tools. Fixed the pipe-related API description.
4.3	10/2024	Added description of Network and Segger J-Link RTT interface configuration. Accompanying the MCUXpresso SDK version 24.12.00.
4.4	04/2025	Added Zephyr-specific information. Accompanying the MCUXpresso SDK version 25.06.00.

Chapter 4

RTOS

4.1 FreeRTOS

4.1.1 FreeRTOS kernel

Open source RTOS kernel for small devices.

FreeRTOS kernel for MCUXpresso SDK Readme

FreeRTOS kernel for MCUXpresso SDK

Overview The purpose of this document is to describes the [FreeRTOS kernel repo](#) integration into the [NXP MCUXpresso Software Development Kit: mcuxsdk](#). MCUXpresso SDK provides a comprehensive development solutions designed to optimize, ease, and help accelerate embedded system development of applications based on MCUs from NXP. This project involves the FreeRTOS kernel repo fork with:

- cmake and Kconfig support to allow the configuration and build in MCUXpresso SDK ecosystem
- FreeRTOS OS additions, such as [FreeRTOS driver wrappers](#), RTOS ready FatFs file system, and the implementation of FreeRTOS tickless mode

The history of changes in FreeRTOS kernel repo for MCUXpresso SDK are summarized in [CHANGELOG_mcuxsdk.md](#) file.

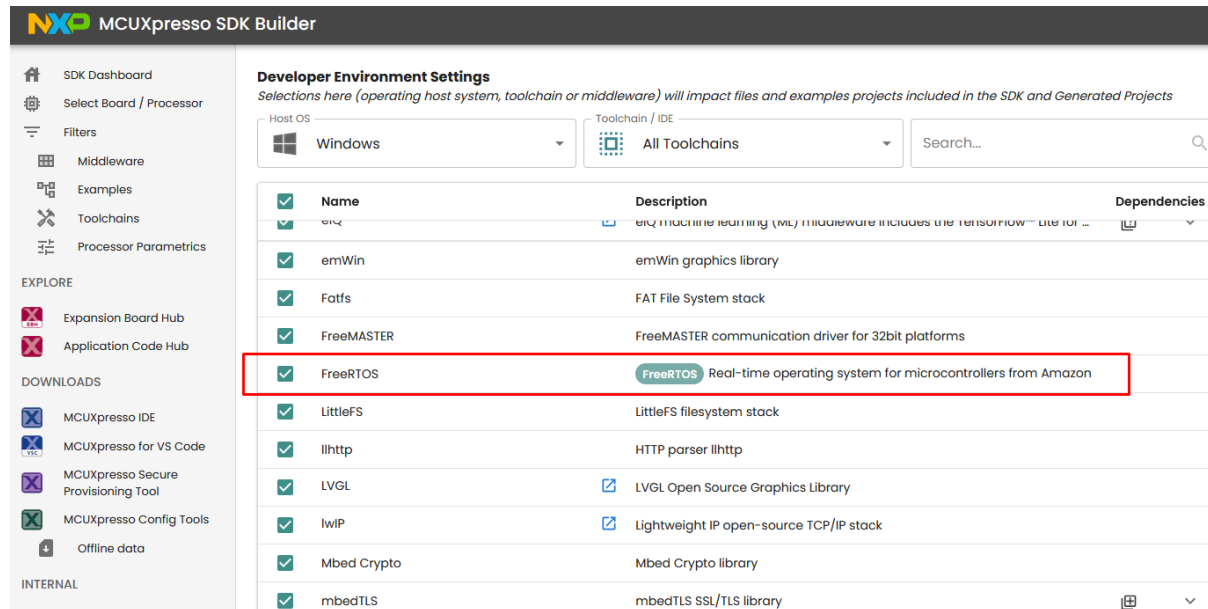
The MCUXpresso SDK framework also contains a set of FreeRTOS examples which show basic FreeRTOS OS features. This makes it easy to start a new FreeRTOS project or begin experimenting with FreeRTOS OS. Selected drivers and middleware are RTOS ready with related FreeRTOS adaptation layer.

FreeRTOS example applications The FreeRTOS examples are written to demonstrate basic FreeRTOS features and the interaction between peripheral drivers and the RTOS.

List of examples The list of freertos_examples, their description and availability for individual supported MCUXpresso SDK development boards can be obtained here: https://mcuxpresso.nxp.com/mcuxsdk/latest/html/examples/freertos_examples/index.html

Location of examples The FreeRTOS examples are located in [mcuxsdk-examples](#) repository, see the `freertos_examples` folder.

Once using MCUXpresso SDK zip packages created via the [MCUXpresso SDK Builder](#) the FreeRTOS kernel library and associated `freertos_examples` are added into final zip package once FreeRTOS components is selected on the Developer Environment Settings page:



The FreeRTOS examples in MCUXpresso SDK zip packages are located in `<MCUXpressoSDK_install_dir>/boards/<board_name>/freertos_examples/` subfolders.

Building a FreeRTOS example application For information how to use the cmake and Kconfig based build and configuration system and how to build `freertos_examples` visit: [MCUXpresso SDK documentation for Build And Configuration MCUXpresso SDK Getting Start Guide](#)

Tip: To list all FreeRTOS example projects and targets that can be built via the west build command, use this `west list_project` command in `mcuxsdk` workspace:

```
west list_project -p examples/freertos_examples
```

FreeRTOS aware debugger plugin NXP provides FreeRTOS task aware debugger for GDB. The plugin is compatible with Eclipse-based (MCUXpressoIDE) and is available after the installation.

Task List (FreeRTOS)							
TCB#	Task Name	Task Handle	Task State	Priority	Stack Usage	Event Object	Runtime
1	task_one	0x1fffecc8	Blocked	1 (1)	0 B / 880 B	MyCountingSemaphore (Rx)	0x0 (0.0%)
2	task_two	0x1ffff130	Blocked	2 (2)	0 B / 888 B	MyCountingSemaphore (Rx)	0x1 (0.1%)
3	IDLE	0x1ffff330	Running	0 (0)	0 B / 296 B		0x3e5 (99.6%)
4	Tmr Svc	0x1ffff6b8	Blocked	17 (17)	28 B / 672 B	TmrQ (Rx)	0x3 (0.3%)

FreeRTOS kernel for MCUXpresso SDK ChangeLog

Changelog FreeRTOS kernel for MCUXpresso SDK All notable changes to this project will be documented in this file.

The format is based on [Keep a Changelog](#), and this project adheres to [Semantic Versioning](#).

[Unreleased]

Added

- Kconfig added CONFIG_FREERTOS_USE_CUSTOM_CONFIG_FRAGMENT config to optionally include custom FreeRTOSConfig fragment include file FreeRTOSConfig_frag.h. File must be provided by application.
- Added missing Kconfig option for configUSE_PICOLIBC_TLS.
- Add correct header files to build when configUSE_NEWLIB_REENTRANT and configUSE_PICOLIBC_TLS is selected in config.

[11.1.0_rev0]

- update amazon freertos version

[11.0.1_rev0]

- update amazon freertos version

[10.5.1_rev0]

- update amazon freertos version

[10.4.3_rev1]

- Apply CM33 security fix from 10.4.3-LTS-Patch-2. See rtos\freertos\freertos_kernel\History.txt
- Apply CM33 security fix from 10.4.3-LTS-Patch-1. See rtos\freertos\freertos_kernel\History.txt

[10.4.3_rev0]

- update amazon freertos version.

[10.4.3_rev0]

- update amazon freertos version.

[9.0.0_rev3]

- New features:
 - Tickless idle mode support for Cortex-A7. Add fsl_tickless_epit.c and fsl_tickless_generic.h in portable/IAR/ARM_CA9 folder.
 - Enabled float context saving in IAR for Cortex-A7. Added configUSE_TASK_FPU_SUPPORT macros. Modified port.c and portmacro.h in portable/IAR/ARM_CA9 folder.
- Other changes:
 - Transformed ARM_CM core specific tickless low power support into generic form under freertos/Source/portable/low_power_tickless/.

[9.0.0_rev2]

- New features:
 - Enabled MCUXpresso thread aware debugging. Add `freertos_tasks_c_additions.h` and `configINCLUDE_FREERTOS_TASK_C_ADDITIONS_H` and `configFREERTOS_MEMORY_SCHEME` macros.

[9.0.0_rev1]

- New features:
 - Enabled `-flto` optimization in GCC by adding `attribute((used))` for `vTaskSwitchContext`.
 - Enabled KDS Task Aware Debugger. Apply FreeRTOS patch to enable `configRECORD_STACK_HIGH_ADDRESS` macro. Modified files are `task.c` and `FreeRTOS.h`.

[9.0.0_rev0]

- New features:
 - Example `freertos_sem_static`.
 - Static allocation support RTOS driver wrappers.
- Other changes:
 - Tickless idle rework. Support for different timers is in separated files (`fsl_tickless_systick.c`, `fsl_tickless_lptmr.c`).
 - Removed configuration option `configSYSTICK_USE_LOW_POWER_TIMER`. Low power timer is now selected by linking of appropriate file `fsl_tickless_lptmr.c`.
 - Removed `configOVERRIDE_DEFAULT_TICK_CONFIGURATION` in RVDS port. Use of `attribute((weak))` is the preferred solution. Not same as `_weak`!

[8.2.3]

- New features:
 - Tickless idle mode support.
 - Added template application for Kinetis Expert (KEx) tool (`template_application`).
- Other changes:
 - Folder structure reduction. Keep only Kinetis related parts.

FreeRTOS kernel Readme

MCUXpresso SDK: FreeRTOS kernel This repository is a fork of FreeRTOS kernel (<https://github.com/FreeRTOS/FreeRTOS-Kernel>)(11.1.0). Modifications have been made to adapt to NXP MCUXpresso SDK. `CMakeLists.txt` and `Kconfig` added to enable FreeRTOS kernel repo sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository `mcuxsdk-manifests`(<https://github.com/nxp-mcuxpresso/mcuxsdk-manifests>) for the complete delivery of MCUXpresso SDK.

For more information about the FreeRTOS kernel repo adoption see [README_mcuxsdk.md: FreeRTOS kernel for MCUXpresso SDK](#) document.



Getting started This repository contains FreeRTOS kernel source/header files and kernel ports only. This repository is referenced as a submodule in [FreeRTOS/FreeRTOS](#) repository, which contains pre-configured demo application projects under [FreeRTOS/Demo](#) directory.

The easiest way to use FreeRTOS is to start with one of the pre-configured demo application projects. That way you will have the correct FreeRTOS source files included, and the correct include paths configured. Once a demo application is building and executing you can remove the demo application files, and start to add in your own application source files. See the [FreeRTOS Kernel Quick Start Guide](#) for detailed instructions and other useful links.

Additionally, for FreeRTOS kernel feature information refer to the [Developer Documentation](#), and [API Reference](#).

Also for contributing and creating a Pull Request please refer to *the instructions here*.

Getting help If you have any questions or need assistance troubleshooting your FreeRTOS project, we have an active community that can help on the [FreeRTOS Community Support Forum](#).

To consume FreeRTOS-Kernel

Consume with CMake If using CMake, it is recommended to use this repository using FetchContent. Add the following into your project's main or a subdirectory's CMakeLists.txt:

- Define the source and version/tag you want to use:

```
FetchContent_Declare( freertos_kernel
  GIT_REPOSITORY https://github.com/FreeRTOS/FreeRTOS-Kernel.git
  GIT_TAG         main #Note: Best practice to use specific git-hash or tagged version
)
```

In case you prefer to add it as a git submodule, do:

```
git submodule add https://github.com/FreeRTOS/FreeRTOS-Kernel.git <path of the submodule>
git submodule update --init
```

- Add a freertos_config library (typically an INTERFACE library) The following assumes the directory structure:

– include/FreeRTOSConfig.h

```
add_library(freertos_config INTERFACE)

target_include_directories(freertos_config SYSTEM
INTERFACE
  include
)

target_compile_definitions(freertos_config
INTERFACE
  projCOVERAGE_TEST=0
)
```

In case you installed FreeRTOS-Kernel as a submodule, you will have to add it as a subdirectory:

```
add_subdirectory(${FREERTOS_PATH})
```

- Configure the FreeRTOS-Kernel and make it available
 - this particular example supports a native and cross-compiled build option.

```
set( FREERTOS_HEAP "4" CACHE STRING "" FORCE)
# Select the native compile PORT
set( FREERTOS_PORT "GCC_POSIX" CACHE STRING "" FORCE)
# Select the cross-compile PORT
if (CMAKE_CROSSCOMPILING)
  set(FREERTOS_PORT "GCC_ARM_CA9" CACHE STRING "" FORCE)
endif()

FetchContent_MakeAvailable(freertos_kernel)
```

- In case of cross compilation, you should also add the following to `freertos_config`:

```
target_compile_definitions(freertos_config INTERFACE ${definitions})
target_compile_options(freertos_config INTERFACE ${options})
```

Consuming stand-alone - Cloning this repository

To clone using HTTPS:

```
git clone https://github.com/FreeRTOS/FreeRTOS-Kernel.git
```

Using SSH:

```
git clone git@github.com:FreeRTOS/FreeRTOS-Kernel.git
```

Repository structure

- The root of this repository contains the three files that are common to every port - `list.c`, `queue.c` and `tasks.c`. The kernel is contained within these three files. `croutine.c` implements the optional co-routine functionality - which is normally only used on very memory limited systems.
- The `./portable` directory contains the files that are specific to a particular microcontroller and/or compiler. See the readme file in the `./portable` directory for more information.
- The `./include` directory contains the real time kernel header files.
- The `./template_configuration` directory contains a sample `FreeRTOSConfig.h` to help jumpstart a new project. See the *FreeRTOSConfig.h* file for instructions.

Code Formatting FreeRTOS files are formatted using the “`uncrustify`” tool. The configuration file used by `uncrustify` can be found in the [FreeRTOS/CI-CD-GitHub-Actions's uncrustify.cfg](#) file.

Line Endings File checked into the FreeRTOS-Kernel repository use unix-style LF line endings for the best compatibility with git.

For optimal compatibility with Microsoft Windows tools, it is best to enable the git `autocrlf` feature. You can enable this setting for the current repository using the following command:

```
git config core.autocrlf true
```

Git History Optimizations Some commits in this repository perform large refactors which touch many lines and lead to unwanted behavior when using the `git blame` command. You can configure git to ignore the list of large refactor commits in this repository with the following command:

```
git config blame.ignoreRevsFile .git-blame-ignore-revs
```

Spelling and Formatting We recommend using [Visual Studio Code](#), commonly referred to as VSCode, when working on the FreeRTOS-Kernel. The FreeRTOS-Kernel also uses [cSpell](#) as part of its spelling check. The config file for which can be found at [cspell.config.yaml](#). There is additionally a [cSpell plugin for VSCode](#) that can be used as well. `.cSpellWords.txt` contains words that are not traditionally found in an English dictionary. It is used by the spellchecker to verify the various jargon, variable names, and other odd words used in the FreeRTOS code base are correct. If your pull request fails to pass the spelling and you believe this is a mistake, then add the word to `.cSpellWords.txt`. When adding a word please then sort the list, which can be done by running the bash command: `sort -u .cSpellWords.txt -o .cSpellWords.txt`. Note that only the FreeRTOS-Kernel Source Files, *include*, *portable/MemMang*, and *portable/Common* files are checked for proper spelling, and formatting at this time.

4.1.2 FreeRTOS drivers

This is set of NXP provided FreeRTOS reentrant bus drivers.

4.1.3 backoffalgorithm

Algorithm for calculating exponential backoff with jitter for network retry attempts.

Readme

MCUXpresso SDK: backoffAlgorithm Library This repository is a fork of backoffAlgorithm library (<https://github.com/FreeRTOS/backoffalgorithm>)(1.3.0). Modifications have been made to adapt to NXP MCUXpresso SDK. `CMakeLists.txt` and `Kconfig` added to enable backoffAlgorithm repo sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository `mcuxsdk-manifests`(<https://github.com/nxp-mcuxpresso/mcuxsdk-manifests>) for the complete delivery of MCUXpresso SDK.

backoffAlgorithm Library This repository contains the backoffAlgorithm library, a utility library to calculate backoff period using an exponential backoff with jitter algorithm for retrying network operations (like failed network connection with server). This library uses the “Full Jitter” strategy for the exponential backoff with jitter algorithm. More information about the algorithm can be seen in the [Exponential Backoff and Jitter](#) AWS blog.

The backoffAlgorithm library is distributed under the *MIT Open Source License*.

Exponential backoff with jitter is typically used when retrying a failed network connection or operation request with the server. An exponential backoff with jitter helps to mitigate failed network operations with servers, that are caused due to network congestion or high request load on the server, by spreading out retry requests across multiple devices attempting network operations. Besides, in an environment with poor connectivity, a client can get disconnected at any time. A backoff strategy helps the client to conserve battery by not repeatedly attempting reconnections when they are unlikely to succeed.

See memory requirements for this library [here](#).

backoffAlgorithm v1.3.0 source code is part of the FreeRTOS 202210.00 LTS release.

backoffAlgorithm v1.0.0 source code is part of the FreeRTOS 202012.00 LTS release.

Reference example The example below shows how to use the backoffAlgorithm library on a POSIX platform to retry a DNS resolution query for amazon.com.

```
#include "backoff_algorithm.h"
#include <stdlib.h>
#include <string.h>
#include <netdb.h>
#include <unistd.h>
#include <time.h>

/* The maximum number of retries for the example code. */
#define RETRY_MAX_ATTEMPTS      ( 5U )

/* The maximum back-off delay (in milliseconds) for between retries in the example. */
#define RETRY_MAX_BACKOFF_DELAY_MS ( 5000U )

/* The base back-off delay (in milliseconds) for retry configuration in the example. */
#define RETRY_BACKOFF_BASE_MS   ( 500U )

int main()
{
    /* Variables used in this example. */
    BackoffAlgorithmStatus_t retryStatus = BackoffAlgorithmSuccess;
    BackoffAlgorithmContext_t retryParams;
    char serverAddress[] = "amazon.com";
    uint16_t nextRetryBackoff = 0;

    int32_t dnsStatus = -1;
    struct addrinfo hints;
    struct addrinfo ** pListHead = NULL;
    struct timespec tp;

    /* Add hints to retrieve only TCP sockets in getaddrinfo. */
    ( void ) memset( &hints, 0, sizeof( hints ) );

    /* Address family of either IPv4 or IPv6. */
    hints.ai_family = AF_UNSPEC;
    /* TCP Socket. */
    hints.ai_socktype = ( int32_t ) SOCK_STREAM;
    hints.ai_protocol = IPPROTO_TCP;

    /* Initialize reconnect attempts and interval. */
    BackoffAlgorithm_InitializeParams( &retryParams,
                                      RETRY_BACKOFF_BASE_MS,
                                      RETRY_MAX_BACKOFF_DELAY_MS,
                                      RETRY_MAX_ATTEMPTS );

    /* Seed the pseudo random number generator used in this example (with call to
     * rand() function provided by ISO C standard library) for use in backoff period
     * calculation when retrying failed DNS resolution. */

    /* Get current time to seed pseudo random number generator. */
    ( void ) clock_gettime( CLOCK_REALTIME, &tp );
    /* Seed pseudo random number generator with seconds. */
    srand( tp.tv_sec );

    do
    {
        /* Perform a DNS lookup on the given host name. */
        dnsStatus = getaddrinfo( serverAddress, NULL, &hints, pListHead );
    }
```

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```

/* Retry if DNS resolution query failed. */
if( dnsStatus != 0 )
{
    /* Generate a random number and get back-off value (in milliseconds) for the next retry.
     * Note: It is recommended to use a random number generator that is seeded with
     * device-specific entropy source so that backoff calculation across devices is different
     * and possibility of network collision between devices attempting retries can be avoided.
     *
     * For the simplicity of this code example, the pseudo random number generator, rand()
     * function is used. */
    retryStatus = BackoffAlgorithm_GetNextBackoff( &retryParams, rand(), &nextRetryBackoff );

    /* Wait for the calculated backoff period before the next retry attempt of querying DNS.
     * As usleep() takes nanoseconds as the parameter, we multiply the backoff period by 1000. */
    ( void ) usleep( nextRetryBackoff * 1000U );
}
} while( ( dnsStatus != 0 ) && ( retryStatus != BackoffAlgorithmRetriesExhausted ) );

return dnsStatus;
}

```

Building the library A compiler that supports **C90 or later** such as *gcc* is required to build the library.

Additionally, the library uses a header file introduced in ISO C99, *stdint.h*. For compilers that do not provide this header file, the *source/include* directory contains *stdint.readme*, which can be renamed to *stdint.h* to build the backoffAlgorithm library.

For instance, if the example above is copied to a file named *example.c*, *gcc* can be used like so:

```
gcc -I source/include example.c source/backoff_algorithm.c -o example
./example
```

gcc can also produce an output file to be linked:

```
gcc -I source/include -c source/backoff_algorithm.c
```

Building unit tests

Checkout Unity Submodule By default, the submodules in this repository are configured with `update=none` in *.gitmodules*, to avoid increasing clone time and disk space usage of other repositories (like [amazon-freertos](#) that submodules this repository).

To build unit tests, the submodule dependency of Unity is required. Use the following command to clone the submodule:

```
git submodule update --checkout --init --recursive test/unit-test/Unity
```

Platform Prerequisites

- For running unit tests
 - C89 or later compiler like *gcc*
 - CMake 3.13.0 or later
- For running the coverage target, *gcov* is additionally required.

Steps to build Unit Tests

1. Go to the root directory of this repository. (Make sure that the **Unity** submodule is cloned as described [above](#).)
2. Create build directory: `mkdir build && cd build`
3. Run `cmake` while inside build directory: `cmake -S ../test`
4. Run this command to build the library and unit tests: `make all`
5. The generated test executables will be present in `build/bin/tests` folder.
6. Run `ctest` to execute all tests and view the test run summary.

Contributing See *CONTRIBUTING.md* for information on contributing.

4.1.4 corehttp

C language HTTP client library designed for embedded platforms.

MCUXpresso SDK: coreHTTP Client Library

This repository is a fork of coreHTTP Client library (<https://github.com/FreeRTOS/corehttp>)(3.0.0). Modifications have been made to adapt to NXP MCUXpresso SDK. CMakeLists.txt and Kconfig added to enable coreHTTP Client repo sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(<https://github.com/nxp-mcuxpresso/mcuxsdk-manifests>) for the complete delivery of MCUXpresso SDK.

coreHTTP Client Library

This repository contains a C language HTTP client library designed for embedded platforms. It has no dependencies on any additional libraries other than the standard C library, [llhttp](#), and a customer-implemented transport interface. This library is distributed under the *MIT Open Source License*.

This library has gone through code quality checks including verification that no function has a [GNU Complexity](#) score over 8. This library has also undergone both static code analysis from [Coverity static analysis](#), and validation of memory safety and data structure invariance through the [CBMC automated reasoning tool](#).

See memory requirements for this library [here](#).

coreHTTP v3.0.0 source code is part of the FreeRTOS 202210.00 LTS release.

coreHTTP v2.0.0 source code is part of the FreeRTOS 202012.00 LTS release.

coreHTTP Config File The HTTP client library exposes configuration macros that are required for building the library. A list of all the configurations and their default values are defined in *core_http_config_defaults.h*. To provide custom values for the configuration macros, a custom config file named *core_http_config.h* can be provided by the user application to the library.

By default, a *core_http_config.h* custom config is required to build the library. To disable this requirement and build the library with default configuration values, provide `HTTP_DO_NOT_USE_CUSTOM_CONFIG` as a compile time preprocessor macro.

The HTTP client library can be built by either:

- Defining a `core_http_config.h` file in the application, and adding it to the include directories for the library build. **OR**
- Defining the `HTTP_DO_NOT_USE_CUSTOM_CONFIG` preprocessor macro for the library build.

Building the Library The `httpFilePaths.cmake` file contains the information of all source files and header include paths required to build the HTTP client library.

As mentioned in the *previous section*, either a custom config file (i.e. `core_http_config.h`) OR `HTTP_DO_NOT_USE_CUSTOM_CONFIG` macro needs to be provided to build the HTTP client library.

For a CMake example of building the HTTP library with the `httpFilePaths.cmake` file, refer to the `coverity_analysis` library target in `test/CMakeLists.txt` file.

Building Unit Tests

Platform Prerequisites

- For running unit tests, the following are required:
 - **C90 compiler** like `gcc`
 - **CMake 3.13.0 or later**
 - **Ruby 2.0.0 or later** is required for this repository's [CMock test framework](#).
- For running the coverage target, the following are required:
 - `gcov`
 - `lcov`

Steps to build Unit Tests

1. Go to the root directory of this repository.
2. Run the `cmake` command: `cmake -S test -B build -DBUILD_CLONE_SUBMODULES=ON`
3. Run this command to build the library and unit tests: `make -C build all`
4. The generated test executables will be present in `build/bin/tests` folder.
5. Run `cd build && ctest` to execute all tests and view the test run summary.

CBMC To learn more about CBMC and proofs specifically, review the training material [here](#).

The `test/cbmc/proofs` directory contains CBMC proofs.

In order to run these proofs you will need to install CBMC and other tools by following the instructions [here](#).

Reference examples The AWS IoT Device SDK for Embedded C repository contains demos of using the HTTP client library [here](#) on a POSIX platform. These can be used as reference examples for the library API.

Documentation

Existing Documentation For pre-generated documentation, please see the documentation linked in the locations below:

Location
AWS IoT Device SDK for Embedded C FreeRTOS.org

Note that the latest included version of coreHTTP may differ across repositories.

Generating Documentation The Doxygen references were created using Doxygen version 1.9.2. To generate the Doxygen pages, please run the following command from the root of this repository:

```
doxygen docs/doxygen/config.doxyfile
```

Contributing See *CONTRIBUTING.md* for information on contributing.

4.1.5 corejson

JSON parser.

Readme

MCUXpresso SDK: coreJSON Library This repository is a fork of coreJSON library (<https://github.com/FreeRTOS/corejson>)(3.2.0). Modifications have been made to adapt to NXP MCUXpresso SDK. CMakeLists.txt and Kconfig added to enable coreJSON repo sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(<https://github.com/nxp-mcuxpresso/mcuxsdk-manifests>) for the complete delivery of MCUXpresso SDK.

coreJSON Library This repository contains the coreJSON library, a parser that strictly enforces the ECMA-404 JSON standard and is suitable for low memory footprint embedded devices. The coreJSON library is distributed under the *MIT Open Source License*.

This library has gone through code quality checks including verification that no function has a [GNU Complexity](#) score over 8, and checks against deviations from mandatory rules in the [MISRA coding standard](#). Deviations from the MISRA C:2012 guidelines are documented under *MISRA Deviations*. This library has also undergone both static code analysis from [Coverity static analysis](#), and validation of memory safety through the [CBMC automated reasoning tool](#).

See memory requirements for this library [here](#).

coreJSON v3.2.0 source code is part of the FreeRTOS 202210.00 LTS release.

coreJSON v3.0.0 source code is part of the FreeRTOS 202012.00 LTS release.

Reference example

```

#include <stdio.h>
#include "core_json.h"

int main()
{
    // Variables used in this example.
    JSONStatus_t result;
    char buffer[] = "{\"foo\":\"abc\", \"bar\":{\"foo\":\"xyz\"}}";
    size_t bufferLength = sizeof( buffer ) - 1;
    char queryKey[] = "bar.foo";
    size_t queryKeyLength = sizeof( queryKey ) - 1;
    char * value;
    size_t valueLength;

    // Calling JSON_Validate() is not necessary if the document is guaranteed to be valid.
    result = JSON_Validate( buffer, bufferLength );

    if( result == JSONSuccess )
    {
        result = JSON_Search( buffer, bufferLength, queryKey, queryKeyLength,
                             &value, &valueLength );
    }

    if( result == JSONSuccess )
    {
        // The pointer "value" will point to a location in the "buffer".
        char save = value[ valueLength ];
        // After saving the character, set it to a null byte for printing.
        value[ valueLength ] = '\0';
        // "Found: bar.foo -> xyz" will be printed.
        printf( "Found: %s -> %s\n", queryKey, value );
        // Restore the original character.
        value[ valueLength ] = save;
    }

    return 0;
}

```

A search may descend through nested objects when the queryKey contains matching key strings joined by a separator, .. In the example above, bar has the value { "foo": "xyz" }. Therefore, a search for query key bar.foo would output xyz.

Building coreJSON A compiler that supports **C90 or later** such as *gcc* is required to build the library.

Additionally, the library uses 2 header files introduced in ISO C99, *stdbool.h* and *stdint.h*. For compilers that do not provide this header file, the *source/include* directory contains *stdbool.readme* and *stdint.readme*, which can be renamed to *stdbool.h* and *stdint.h* respectively.

For instance, if the example above is copied to a file named *example.c*, *gcc* can be used like so:

```
gcc -I source/include example.c source/core_json.c -o example
./example
```

gcc can also produce an output file to be linked:

```
gcc -I source/include -c source/core_json.c
```

Documentation

Existing documentation For pre-generated documentation, please see the documentation linked in the locations below:

Location
AWS IoT Device SDK for Embedded C FreeRTOS.org

Note that the latest included version of the coreJSON library may differ across repositories.

Generating documentation The Doxygen references were created using Doxygen version 1.9.2. To generate the Doxygen pages, please run the following command from the root of this repository:

```
doxygen docs/doxygen/config.doxyfile
```

Building unit tests

Checkout Unity Submodule By default, the submodules in this repository are configured with `update=none` in `.gitmodules`, to avoid increasing clone time and disk space usage of other repositories (like [amazon-freertos](#) that submodules this repository).

To build unit tests, the submodule dependency of Unity is required. Use the following command to clone the submodule:

```
git submodule update --checkout --init --recursive test/unit-test/Unity
```

Platform Prerequisites

- For running unit tests
 - C90 compiler like gcc
 - CMake 3.13.0 or later
 - Ruby 2.0.0 or later is additionally required for the Unity test framework (that we use).
- For running the coverage target, gcov is additionally required.

Steps to build Unit Tests

1. Go to the root directory of this repository. (Make sure that the **Unity** submodule is cloned as described [above](#).)
2. Create build directory: `mkdir build && cd build`
3. Run `cmake` while inside build directory: `cmake -S ../test`
4. Run this command to build the library and unit tests: `make all`
5. The generated test executables will be present in `build/bin/tests` folder.
6. Run `ctest` to execute all tests and view the test run summary.

CBMC To learn more about CBMC and proofs specifically, review the training material [here](#).

The `test/cbmc/proofs` directory contains CBMC proofs.

In order to run these proofs you will need to install CBMC and other tools by following the instructions [here](#).

Contributing See *CONTRIBUTING.md* for information on contributing.

4.1.6 coremqtt

MQTT publish/subscribe messaging library.

MCUXpresso SDK: coreMQTT Library

This repository is a fork of coreMQTT library (<https://github.com/FreeRTOS/coremqtt>)(2.1.1). Modifications have been made to adapt to NXP MCUXpresso SDK. CMakeLists.txt and Kconfig added to enable coreMQTT repo sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(<https://github.com/nxp-mcuxpresso/mcuxsdk-manifests>) for the complete delivery of MCUXpresso SDK.

coreMQTT Client Library

This repository contains the coreMQTT library that has been optimized for a low memory footprint. The coreMQTT library is compliant with the [MQTT 3.1.1](#) standard. It has no dependencies on any additional libraries other than the standard C library, a customer-implemented network transport interface, and *optionally* a user-implemented platform time function. This library is distributed under the *MIT Open Source License*.

This library has gone through code quality checks including verification that no function has a [GNU Complexity](#) score over 8, and checks against deviations from mandatory rules in the [MISRA coding standard](#). Deviations from the MISRA C:2012 guidelines are documented under *MISRA Deviations*. This library has also undergone both static code analysis from [Coverity static analysis](#), and validation of memory safety through the [CBMC automated reasoning tool](#).

See memory requirements for this library [here](#).

coreMQTT v2.1.1 source code is part of the FreeRTOS 20210.01 LTS release.

MQTT Config File The MQTT client library exposes build configuration macros that are required for building the library. A list of all the configurations and their default values are defined in *core_mqtt_config_defaults.h*. To provide custom values for the configuration macros, a custom config file named *core_mqtt_config.h* can be provided by the application to the library.

By default, a *core_mqtt_config.h* custom config is required to build the library. To disable this requirement and build the library with default configuration values, provide `MQTT_DO_NOT_USE_CUSTOM_CONFIG` as a compile time preprocessor macro.

Thus, the MQTT library can be built by either:

- Defining a *core_mqtt_config.h* file in the application, and adding it to the include directories list of the library
- OR**
- Defining the `MQTT_DO_NOT_USE_CUSTOM_CONFIG` preprocessor macro for the library build.

Sending metrics to AWS IoT When establishing a connection with AWS IoT, users can optionally report the Operating System, Hardware Platform and MQTT client version information of their device to AWS. This information can help AWS IoT provide faster issue resolution and technical support. If users want to report this information, they can send a specially formatted string (see below) in the username field of the MQTT CONNECT packet.

Format

The format of the username string with metrics is:

```
<Actual_Username>?SDK=<OS_Name>&Version=<OS_Version>&Platform=<Hardware_Platform>&MQTTLib=<MQTT_Library_name>@<MQTT_Library_version>
```

Where

- <Actual_Username> is the actual username used for authentication, if username and password are used for authentication. When username and password based authentication is not used, this is an empty value.
- <OS_Name> is the Operating System the application is running on (e.g. FreeRTOS)
- <OS_Version> is the version number of the Operating System (e.g. V10.4.3)
- <Hardware_Platform> is the Hardware Platform the application is running on (e.g. WinSim)
- <MQTT_Library_name> is the MQTT Client library being used (e.g. coreMQTT)
- <MQTT_Library_version> is the version of the MQTT Client library being used (e.g. 1.0.2)

Example

- Actual_Username = "iotuser", OS_Name = FreeRTOS, OS_Version = V10.4.3, Hardware_Platform_Name = WinSim, MQTT_Library_Name = coremqtt, MQTT_Library_version = 2.1.1. If username is not used, then "iotuser" can be removed.

```
/* Username string:
 * iotuser?SDK=FreeRTOS&Version=v10.4.3&Platform=WinSim&MQTTLib=coremqtt@2.1.1
 */

#define OS_NAME           "FreeRTOS"
#define OS_VERSION        "V10.4.3"
#define HARDWARE_PLATFORM_NAME  "WinSim"
#define MQTT_LIB          "coremqtt@2.1.1"

#define USERNAME_STRING   "iotuser?SDK=" OS_NAME "&Version=" OS_VERSION "&Platform=" HARDWARE_PLATFORM_NAME "&MQTTLib=" MQTT_LIB
#define USERNAME_STRING_LENGTH  ( ( uint16_t ) ( sizeof( USERNAME_STRING ) - 1 ) )

MQTTConnectInfo_t connectInfo;
connectInfo.userName = USERNAME_STRING;
connectInfo.userNameLength = USERNAME_STRING_LENGTH;
mqttStatus = MQTT_Connect( pMqttContext, &connectInfo, NULL, CONNACK_RECV_TIMEOUT_MS,
↳ pSessionPresent );
```

Upgrading to v2.0.0 and above With coreMQTT versions >=v2.0.0, there are breaking changes. Please refer to the *coreMQTT version >=v2.0.0 Migration Guide*.

Building the Library The *mqttFilePaths.cmake* file contains the information of all source files and the header include path required to build the MQTT library.

Additionally, the MQTT library requires two header files that are not part of the ISO C90 standard library, *stdbool.h* and *stdint.h*. For compilers that do not provide these header files, the

source/include directory contains the files *stdbool.readme* and *stdint.readme*, which can be renamed to *stdbool.h* and *stdint.h*, respectively, to provide the type definitions required by MQTT.

As mentioned in the previous section, either a custom config file (i.e. *core_mqtt_config.h*) OR *MQTT_DO_NOT_USE_CUSTOM_CONFIG* macro needs to be provided to build the MQTT library.

For a CMake example of building the MQTT library with the *mqttFilePaths.cmake* file, refer to the *coverity_analysis* library target in *test/CMakeLists.txt* file.

Building Unit Tests

Checkout CMock Submodule By default, the submodules in this repository are configured with *update=none* in *.gitmodules* to avoid increasing clone time and disk space usage of other repositories (like [amazon-freertos](#) that submodules this repository).

To build unit tests, the submodule dependency of CMock is required. Use the following command to clone the submodule:

```
git submodule update --checkout --init --recursive test/unit-test/CMock
```

Platform Prerequisites

- Docker

or the following:

- For running unit tests
 - **C90 compiler** like gcc
 - **CMake 3.13.0 or later**
 - **Ruby 2.0.0 or later** is additionally required for the CMock test framework (that we use).
- For running the coverage target, **gcov** and **lcov** are additionally required.

Steps to build Unit Tests

1. If using docker, launch the container:
 1. `docker build -t coremqtt .`
 2. `docker run -it -v "$PWD":/workspaces/coreMQTT -w /workspaces/coreMQTT coremqtt`
2. Go to the root directory of this repository. (Make sure that the **CMock** submodule is cloned as described [above](#))
3. Run the *cmake* command: `cmake -S test -B build`
4. Run this command to build the library and unit tests: `make -C build all`
5. The generated test executables will be present in *build/bin/tests* folder.
6. Run `cd build && ctest` to execute all tests and view the test run summary.

CBMC To learn more about CBMC and proofs specifically, review the training material [here](#).

The *test/cbmc/proofs* directory contains CBMC proofs.

In order to run these proofs you will need to install CBMC and other tools by following the instructions [here](#).

Reference examples Please refer to the demos of the MQTT client library in the following locations for reference examples on POSIX and FreeRTOS platforms:

Platform	Location	Transport Interface Implementation
POSIX	AWS IoT Device SDK for Embedded C	POSIX sockets for TCP/IP and OpenSSL for TLS stack
FreeRTOS	FreeRTOS/FreeRTOS	FreeRTOS+TCP for TCP/IP and mbedTLS for TLS stack
FreeRTOS	FreeRTOS AWS Reference Integrations	Based on Secure Sockets Abstraction

Documentation

Existing Documentation For pre-generated documentation, please see the documentation linked in the locations below:

Location
AWS IoT Device SDK for Embedded C
FreeRTOS.org

Note that the latest included version of coreMQTT may differ across repositories.

Generating Documentation The Doxygen references were created using Doxygen version 1.9.2. To generate the Doxygen pages, please run the following command from the root of this repository:

```
doxygen docs/doxygen/config.doxyfile
```

Contributing See *CONTRIBUTING.md* for information on contributing.

4.1.7 coremqtt-agent

The coreMQTT Agent library is a high level API that adds thread safety to the coreMQTT library.

Readme

MCUXpresso SDK: coreMQTT Agent Library This repository is a fork of coreMQTT Agent library (<https://github.com/FreeRTOS/coremqtt-agent>)(1.2.0). Modifications have been made to adapt to NXP MCUXpresso SDK. CMakeLists.txt and Kconfig added to enable coreMQTT Agent repo sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(<https://github.com/nxp-mcuxpresso/mcuxsdk-manifests>) for the complete delivery of MCUXpresso SDK.

coreMQTT Agent Library The coreMQTT Agent library is a high level API that adds thread safety to the [coreMQTT](#) library. The library provides thread safe equivalents to the coreMQTT's APIs, greatly simplifying its use in multi-threaded environments. The coreMQTT Agent library manages the MQTT connection by serializing the access to the coreMQTT library and reducing implementation overhead (e.g., removing the need for the application to repeatedly call to MQTT_ProcessLoop). This allows your multi-threaded applications to share the same MQTT connection, and enables you to design an embedded application without having to worry about coreMQTT thread safety.

This library has gone through code quality checks including verification that no function has a [GNU Complexity](#) score over 8, and checks against deviations from mandatory rules in the [MISRA coding standard](#). Deviations from the MISRA C:2012 guidelines are documented under *MISRA Deviations*. This library has also undergone both static code analysis from [Coverity static analysis](#), and validation of memory safety through the [CBMC automated reasoning tool](#).

See memory requirements for this library [here](#).

Cloning this repository This repo uses [Git Submodules](#) to bring in dependent components.

To clone using HTTPS:

```
git clone https://github.com/FreeRTOS/coreMQTT-Agent.git --recurse-submodules
```

Using SSH:

```
git clone git@github.com:FreeRTOS/coreMQTT-Agent.git --recurse-submodules
```

If you have downloaded the repo without using the `--recurse-submodules` argument, you need to run:

```
git submodule update --init --recursive
```

coreMQTT Agent Library Configurations The MQTT Agent library uses the same `core_mqtt_config.h` configuration file as coreMQTT, with the addition of configuration constants listed at the top of `core_mqtt_agent.h` and `core_mqtt_agent_command_functions.h`. Documentation for these configurations can be found [here](#).

To provide values for these configuration values, they must be either:

- Defined in `core_mqtt_config.h` used by coreMQTT **OR**
- Passed as compile time preprocessor macros

Porting the coreMQTT Agent Library In order to use the MQTT Agent library on a platform, you need to supply thread safe functions for the agent's *messaging interface*.

Messaging Interface Each of the following functions must be thread safe.

Function Pointer	Description
MQTTAgentMessageSend_t	A function that sends commands (as MQTTAgentCommand_t * pointers) to be received by MQTTAgent_CommandLoop. This can be implemented by pushing to a thread safe queue.
MQTTAgentMessageRecv_t	A function used by MQTTAgent_CommandLoop to receive MQTTAgentCommand_t * pointers that were sent by API functions. This can be implemented by receiving from a thread safe queue.
MQTTAgentCommandGet_t	A function that returns a pointer to an allocated MQTTAgentCommand_t structure, which is used to hold information and arguments for a command to be executed in MQTTAgent_CommandLoop(). If using dynamic memory, this can be implemented using malloc().
MQTTAgentCommandRelease_t	A function called to indicate that a command structure that had been allocated with the MQTTAgentCommandGet_t function pointer will no longer be used by the agent, so it may be freed or marked as not in use. If using dynamic memory, this can be implemented with free().

Reference implementations for the interface functions can be found in the [reference examples](#) below.

Additional Considerations

Static Memory If only static allocation is used, then the MQTTAgentCommandGet_t and MQTTAgentCommandRelease_t could instead be implemented with a pool of MQTTAgentCommand_t structures, with a queue or semaphore used to control access and provide thread safety. The below [reference examples](#) use static memory with a command pool.

Subscription Management The MQTT Agent does not track subscriptions for MQTT topics. The receipt of any incoming PUBLISH packet will result in the invocation of a single MQTTAgentIncomingPublishCallback_t callback, which is passed to MQTTAgent_Init() for initialization. If it is desired for different handlers to be invoked for different incoming topics, then the publish callback will have to manage subscriptions and fan out messages. A platform independent subscription manager example is implemented in the [reference examples](#) below.

Building the Library You can build the MQTT Agent source files that are in the *source* directory, and add *source/include* to your compiler's include path. Additionally, the MQTT Agent library requires the coreMQTT library, whose files follow the same *source/* and *source/include* pattern as the agent library; its build instructions can be found [here](#).

If using CMake, the *mqttAgentFilePaths.cmake* file contains the above information of the source files and the header include path from this repository. The same information is found for coreMQTT from *mqttFilePaths.cmake* in the *coreMQTT submodule*.

For a CMake example of building the MQTT Agent library with the *mqttAgentFilePaths.cmake* file, refer to the *coverity_analysis* library target in *test/CMakeLists.txt* file.

Building Unit Tests

Checkout CMock Submodule To build unit tests, the submodule dependency of CMock is required. Use the following command to clone the submodule:

```
git submodule update --checkout --init --recursive test/unit-test/CMock
```

Unit Test Platform Prerequisites

- For running unit tests
 - **C90 compiler** like gcc
 - **CMake 3.13.0 or later**
 - **Ruby 2.0.0 or later** is additionally required for the CMock test framework (that we use).
- For running the coverage target, **gcov** and **lcov** are additionally required.

Steps to build Unit Tests

1. Go to the root directory of this repository. (Make sure that the **CMock** submodule is cloned as described [above](#))
2. Run the *cmake* command: `cmake -S test -B build`
3. Run this command to build the library and unit tests: `make -C build all`
4. The generated test executables will be present in `build/bin/tests` folder.
5. Run `cd build && ctest` to execute all tests and view the test run summary.

CBMC To learn more about CBMC and proofs specifically, review the training material [here](#).

The `test/cbmc/proofs` directory contains CBMC proofs.

In order to run these proofs you will need to install CBMC and other tools by following the instructions [here](#).

Reference examples Please refer to the demos of the MQTT Agent library in the following locations for reference examples on FreeRTOS platforms:

Location
coreMQTT Agent Demos
FreeRTOS/FreeRTOS

Documentation The MQTT Agent API documentation can be found [here](#).

Generating documentation The Doxygen references were created using Doxygen version 1.9.2. To generate the Doxygen pages yourself, please run the following command from the root of this repository:

```
doxygen docs/doxygen/config.doxyfile
```

Getting help You can use your Github login to get support from both the FreeRTOS community and directly from the primary FreeRTOS developers on our [active support forum](#). You can find a list of [frequently asked questions](#) [here](#).

Contributing See *CONTRIBUTING.md* for information on contributing.

License This library is licensed under the MIT License. See the *LICENSE* file.

4.1.8 corepkcs11

PKCS #11 key management library.

Readme

MCUXpresso SDK: corePKCS11 Library This repository is a fork of PKCS #11 key management library (<https://github.com/FreeRTOS/corePKCS11/tree/v3.5.0>)(v3.5.0). Modifications have been made to adapt to NXP MCUXpresso SDK. CMakeLists.txt and Kconfig added to enable corepkcs11 repo sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(<https://github.com/nxp-mcuxpresso/mcuxsdk-manifests>) for the complete delivery of MCUXpresso SDK.

corePKCS11 Library PKCS #11 is a standardized and widely used API for manipulating common cryptographic objects. It is important because the functions it specifies allow application software to use, create, modify, and delete cryptographic objects, without ever exposing those objects to the application's memory. For example, FreeRTOS AWS reference integrations use a small subset of the PKCS #11 API to, among other things, access the secret (private) key necessary to create a network connection that is authenticated and secured by the [Transport Layer Security \(TLS\)](#) protocol – without the application ever ‘seeing’ the key.

The Cryptoki or PKCS #11 standard defines a platform-independent API to manage and use cryptographic tokens. The name, “PKCS #11”, is used interchangeably to refer to the API itself and the standard which defines it.

This repository contains a software based mock implementation of the PKCS #11 interface (API) that uses the cryptographic functionality provided by Mbed TLS. Using a software mock enables rapid development and flexibility, but it is expected that the mock be replaced by an implementation specific to your chosen secure key storage in production devices.

Only a subset of the PKCS #11 standard is implemented, with a focus on operations involving asymmetric keys, random number generation, and hashing.

The targeted use cases include certificate and key management for TLS authentication and code-sign signature verification, on small embedded devices.

corePKCS11 is implemented on PKCS #11 v2.4.0, the full PKCS #11 standard can be found on the [oasis website](#).

This library has gone through code quality checks including verification that no function has a [GNU Complexity](#) score over 8, and checks against deviations from mandatory rules in the [MISRA coding standard](#). Deviations from the MISRA C:2012 guidelines are documented under *MISRA Deviations*. This library has also undergone both static code analysis from [Coverity static analysis](#) and validation of memory safety through the [CBMC automated reasoning tool](#).

See memory requirements for this library [here](#).

corePKCS11 v3.5.0 source code is part of the FreeRTOS 202210.00 LTS release.

corePKCS11 v3.0.0 source code is part of the FreeRTOS 202012.00 LTS release.

Purpose Generally vendors for secure cryptoprocessors such as Trusted Platform Module (TPM), Hardware Security Module (HSM), Secure Element, or any other type of secure hardware enclave, distribute a PKCS #11 implementation with the hardware. The purpose of the corePKCS11 software only mock library is therefore to provide a non hardware specific PKCS #11 implementation that allows for rapid prototyping and development before switching to a cryptoprocessor specific PKCS #11 implementation in production devices.

Since the PKCS #11 interface is defined as part of the PKCS #11 [specification](#) replacing this library with another implementation should require little porting effort, as the interface will not change. The system tests distributed in this repository can be leveraged to verify the behavior of a different implementation is similar to corePKCS11.

corePKCS11 Configuration The corePKCS11 library exposes preprocessor macros which must be defined prior to building the library. A list of all the configurations and their default values are defined in the doxygen documentation for this library.

Build Prerequisites

Library Usage For building the library the following are required:

- **A C99 compiler**
- **mbedcrypto** library from [mbedtls](#) version 2.x or 3.x.
- **pkcs11 API header(s)** available from [OASIS](#) or [OpenSC](#)

Optionally, variables from the pkcsFilePaths.cmake file may be referenced if your project uses cmake.

Integration and Unit Tests In order to run the integration and unit test suites the following are dependencies are necessary:

- **C Compiler**
- **CMake 3.13.0 or later**
- **Ruby 2.0.0 or later** required by CMock.
- **Python 3** required for configuring mbedtls.
- **git** required for fetching dependencies.
- **GNU Make** or **Ninja**

The *mbedtls*, *CMock*, and *Unity* libraries are downloaded and built automatically using the cmake FetchContent feature.

Coverage Measurement and Instrumentation The following software is required to run the coverage target:

- Linux, MacOS, or another POSIX-like environment.
- A recent version of **GCC** or **Clang** with support for gcov-like coverage instrumentation.
- **gcov** binary corresponding to your chosen compiler
- **lcov** from the [Linux Test Project](#)
- **perl** needed to run the lcov utility.

Coverage builds are validated on recent versions of Ubuntu Linux.

Running the Integration and Unit Tests

1. Navigate to the root directory of this repository in your shell.
2. Run **cmake** to construct a build tree: `cmake -S test -B build`
 - You may specify your preferred build tool by appending `-G'Unix Makefiles'` or `-GNinja` to the command above.
 - You may append `-DUNIT_TESTS=0` or `-DSYSTEM_TESTS=0` to disable Unit Tests or Integration Tests respectively.
3. Build the test binaries: `cmake --build ./build --target all`
4. Run `ctest --test-dir ./build` or `cmake --build ./build --target test` to run the tests without capturing coverage.
5. Run `cmake --build ./build --target coverage` to run the tests and capture coverage data.

CBMC To learn more about CBMC and proofs specifically, review the training material [here](#).

The `test/cbmc/proofs` directory contains CBMC proofs.

In order to run these proofs you will need to install CBMC and other tools by following the instructions [here](#).

Reference examples The FreeRTOS-Labs repository contains demos using the PKCS #11 library [here](#) using FreeRTOS on the Windows simulator platform. These can be used as reference examples for the library API.

Porting Guide Documentation for porting corePKCS11 to a new platform can be found on the AWS [docs](#) web page.

corePKCS11 is not meant to be ported to projects that have a TPM, HSM, or other hardware for offloading crypto-processing. This library is specifically meant to be used for development and prototyping.

Related Example Implementations These projects implement the PKCS #11 interface on real hardware and have similar behavior to corePKCS11. It is preferred to use these, over corePKCS11, as they allow for offloading Cryptography to separate hardware.

- ARM's [Platform Security Architecture](#).
- Microchip's [cryptoauthlib](#).
- Infineon's [Optiga Trust X](#).

Documentation

Existing Documentation For pre-generated documentation, please see the documentation linked in the locations below:

Location
AWS IoT Device SDK for Embedded C FreeRTOS.org

Note that the latest included version of corePKCS11 may differ across repositories.

Generating Documentation The Doxygen references were created using Doxygen version 1.9.2. To generate the Doxygen pages, please run the following command from the root of this repository:

```
doxygen docs/doxygen/config.doxyfile
```

Security See *CONTRIBUTING* for more information.

License This library is licensed under the MIT-0 License. See the LICENSE file.

4.1.9 freertos-plus-tcp

Open source RTOS FreeRTOS Plus TCP.

Readme

MCUXpresso SDK: FreeRTOS-Plus-TCP Library This repository is a fork of FreeRTOS-Plus-TCP library (<https://github.com/FreeRTOS/freertos-plus-tcp>)(4.0.0). Modifications have been made to adapt to NXP MCUXpresso SDK. CMakeLists.txt and Kconfig added to enable FreeRTOS-Plus-TCP repo sources build in MCUXpresso SDK. It is part of the MCUXpresso SDK overall delivery which is composed of several sub-repositories/projects. Navigate to the top/parent repository mcuxsdk-manifests(<https://github.com/nxp-mcuxpresso/mcuxsdk-manifests>) for the complete delivery of MCUXpresso SDK.

Introduction This branch contains unified IPv4 and IPv6 functionalities. Refer to the Getting started Guide (found [here](#)) for more details.

FreeRTOS-Plus-TCP Library FreeRTOS-Plus-TCP is a lightweight TCP/IP stack for FreeRTOS. It provides a familiar Berkeley sockets interface, making it as simple to use and learn as possible. FreeRTOS-Plus-TCP's features and RAM footprint are fully scalable, making FreeRTOS-Plus-TCP equally applicable to smaller lower throughput microcontrollers as well as larger higher throughput microprocessors.

This library has undergone static code analysis and checks for compliance with the [MISRA coding standard](#). Any deviations from the MISRA C:2012 guidelines are documented under [MISRA Deviations](#). The library is validated for memory safety and data structure invariance through the [CBMC automated reasoning tool](#) for the functions that parse data originating from the network. The library is also protocol tested using Maxwell protocol tester for both IPv4 and IPv6.

Getting started The easiest way to use the 4.0.0 version of FreeRTOS-Plus-TCP is to refer the Getting started Guide (found [here](#)) Another way is to start with the pre-configured demo application project (found in [this directory](#)). That way you will have the correct FreeRTOS source files included, and the correct include paths configured. Once a demo application is building and executing you can remove the demo application files, and start to add in your own application source files. See the [FreeRTOS Kernel Quick Start Guide](#) for detailed instructions and other useful links.

Additionally, for FreeRTOS-Plus-TCP source code organization refer to the [Documentation](#), and [API Reference](#).

Getting help If you have any questions or need assistance troubleshooting your FreeRTOS project, we have an active community that can help on the [FreeRTOS Community Support Forum](#). Please also refer to [FAQ](#) for frequently asked questions.

Also see the [Submitting a bug/feature request](#) section of CONTRIBUTING.md for more details.

Note: All the remaining sections are generic and applies to all the versions from V3.0.0 onwards.

Upgrading to V3.0.0 and V3.1.0 In version 3.0.0 or 3.1.0, the folder structure of FreeRTOS-Plus-TCP has changed and the files have been broken down into smaller logically separated modules. This change makes the code more modular and conducive to unit-tests. FreeRTOS-Plus-TCP V3.0.0 improves the robustness, security, and modularity of the library. Version 3.0.0 adds comprehensive unit test coverage for all lines and branches of code and has undergone protocol testing, and penetration testing by AWS Security to reduce the exposure to security vulnerabilities. Additionally, the source files have been moved to a `source` directory. This change requires modification of any existing project(s) to include the modified source files and directories. There are examples on how to use the new files and directory structure. For an example based on the Xilinx Zynq-7000, use the code in this [branch](#) and follow these [instructions](#) to build and run the demo.

FreeRTOS-Plus-TCP V3.1.0 source code(.c .h) is part of the FreeRTOS 202210.00 LTS release.

Generating pre V3.0.0 folder structure for backward compatibility: If you wish to continue using a version earlier than V3.0.0 i.e. continue to use your existing source code organization, a script is provided to generate the folder structure similar to [this](#).

Note: After running the script, while the `.c` files will have same names as the pre V3.0.0 source, the files in the `include` directory will have different names and the number of files will differ as well. This should, however, not pose any problems to most projects as projects generally include all files in a given directory.

Running the script to generate pre V3.0.0 folder structure: For running the script, you will need Python version > 3.7. You can download/install it from [here](#).

Once python is downloaded and installed, you can verify the version from your terminal/command window by typing `python --version`.

To run the script, you should switch to the FreeRTOS-Plus-TCP directory that was created using the *Cloning this repository* step above. And then run `python <Path/to/the/script>/GenerateOriginalFiles.py`.

To consume FreeRTOS+TCP

Consume with CMake If using CMake, it is recommended to use this repository using FetchContent. Add the following into your project's main or a subdirectory's CMakeLists.txt:

- Define the source and version/tag you want to use:

```
FetchContent_Declare( freertos_plus_tcp
  GIT_REPOSITORY https://github.com/FreeRTOS/FreeRTOS-Plus-TCP.git
  GIT_TAG        master #Note: Best practice to use specific git-hash or tagged version
  GIT_SUBMODULES "" # Don't grab any submodules since not latest
)
```

- Configure the FreeRTOS-Kernel and make it available
 - this particular example supports a native and cross-compiled build option.

```

set( FREERTOS_PLUS_FAT_DEV_SUPPORT OFF CACHE BOOL "" FORCE)
# Select the native compile PORT
set( FREERTOS_PLUS_FAT_PORT "POSIX" CACHE STRING "" FORCE)
# Select the cross-compile PORT
if (CMAKE_CROSSCOMPILING)
  # Eg. Zynq 2019_3 version of port
  set(FREERTOS_PLUS_FAT_PORT "ZYNQ_2019_3" CACHE STRING "" FORCE)
endif()

FetchContent_MakeAvailable(freertos_plus_tcp)

```

Consuming stand-alone This repository uses [Git Submodules](#) to bring in dependent components.

Note: If you download the ZIP file provided by GitHub UI, you will not get the contents of the submodules. (The ZIP file is also not a valid Git repository)

To clone using HTTPS:

```

git clone https://github.com/FreeRTOS/FreeRTOS-Plus-TCP.git ./FreeRTOS-Plus-TCP
cd ./FreeRTOS-Plus-TCP
git submodule update --checkout --init --recursive tools/CMock test/FreeRTOS-Kernel

```

Using SSH:

```

git clone git@github.com:FreeRTOS/FreeRTOS-Plus-TCP.git ./FreeRTOS-Plus-TCP
cd ./FreeRTOS-Plus-TCP
git submodule update --checkout --init --recursive tools/CMock test/FreeRTOS-Kernel

```

Porting The porting guide is available on [this page](#).

Repository structure This repository contains the FreeRTOS-Plus-TCP repository and a number of supplementary libraries for testing/PR Checks. Below is the breakdown of what each directory contains:

- tools
 - This directory contains the tools and related files (CMock/uncrustify) required to run tests/checks on the TCP source code.
- tests
 - This directory contains all the tests (unit tests and CBMC) and the dependencies ([FreeRTOS-Kernel/Litani-port](#)) the tests require.
- source/portable
 - This directory contains the portable files required to compile the FreeRTOS-Plus-TCP source code for different hardware/compilers.
- source/include
 - The include directory has all the ‘core’ header files of FreeRTOS-Plus-TCP source.
- source
 - This directory contains all the [.c] source files.

Note At this time it is recommended to use `BufferAllocation_2.c` in which case it is essential to use the `heap_4.c` memory allocation scheme. See [memory management](#).

Kernel sources The FreeRTOS Kernel Source is in [FreeRTOS/FreeRTOS-Kernel repository](#), and it is consumed by testing/PR checks as a submodule in this repository.

The version of the FreeRTOS Kernel Source in use could be accessed at `./test/FreeRTOS-Kernel` directory.

CBMC The `test/cbmc/proofs` directory contains CBMC proofs.

To learn more about CBMC and proofs specifically, review the training material [here](#).

In order to run these proofs you will need to install CBMC and other tools by following the instructions [here](#).