



# MCUXpresso SDK Documentation

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NXP  
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This documentation contains information specific to the imx943evk board.



# Chapter 1

## IMX943EVK

### Note:

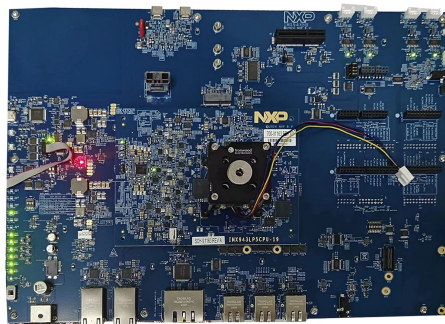
IMX943EVK includes IMX943-19X19-LPDDR5-EVK, IMX943-19X19-LPDDR4-EVK, IMX943-15X15-LPDDR4-EVK

IMX943 19x19 LPDDR5 EVK(IMX943LP5EVK-19) = IMX943LP5CPU-19 SOM + X-IMX943BB

IMX943 19x19 LPDDR4 EVK(IMX943LP4EVK-19) = IMX943LP4CPU-19 SOM + X-IMX943BB

IMX943 15x15 LPDDR4 EVK(IMX943LP4EVK-15) = IMX943LP4CPU-15 SOM + X-IMX943BB

### 1.1 Overview



MCU device and part on board is shown below:

- Device: MIMX94398
- PartNumber: MIMX94398AVKM, MIMX94398AVMM
- Note: - IMX943LP5CPU-19 SOM and IMX943LP4CPU-19 SOM boards are using the Part-Number MIMX94398AVKM - IMX943LP4CPU-15 SOM board is using the PartNumber MIMX94398AVMM

### 1.2 Getting Started with MCUXpresso SDK Package

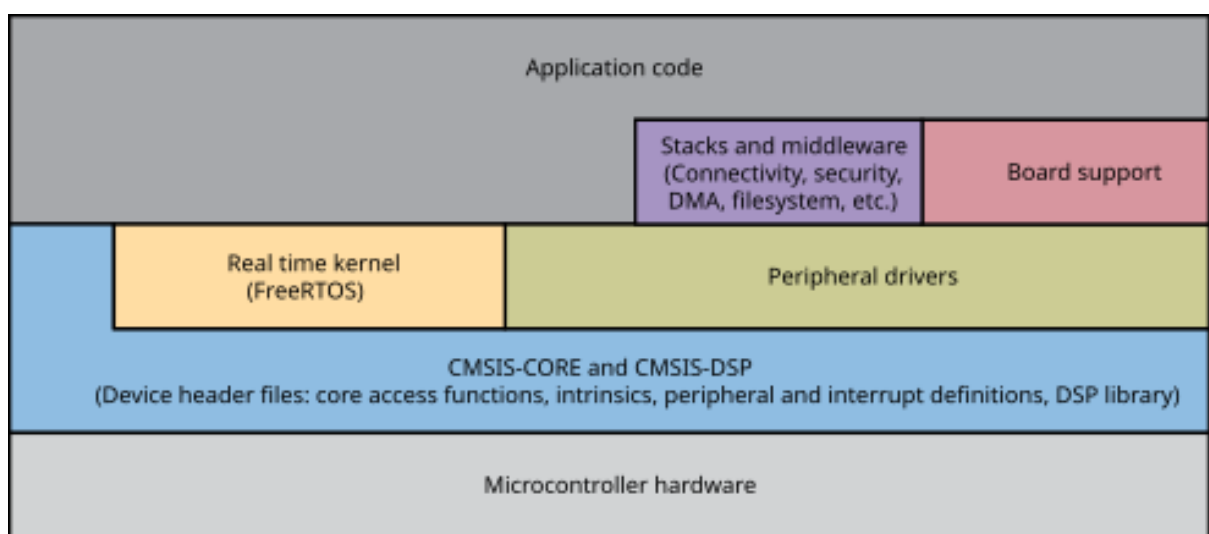
#### 1.2.1 Getting Started with Package

## 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 demo applications. The MCUXpresso SDK also contains optional RTOS integrations such as FreeRTOS and Azure RTOS, and device stack to support rapid development on devices.

For supported toolchain versions, see *MCUXpresso SDK Release Notes for IMX943-EVK (document MCUXSDKIMX943EVKRN)*.

For the latest version of this and other MCUXpresso SDK documents, see the MCUXpresso SDK homepage [MCUXpresso-SDK: Software Development Kit for MCUXpresso](#).



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## MCUXpresso SDK board support folders

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

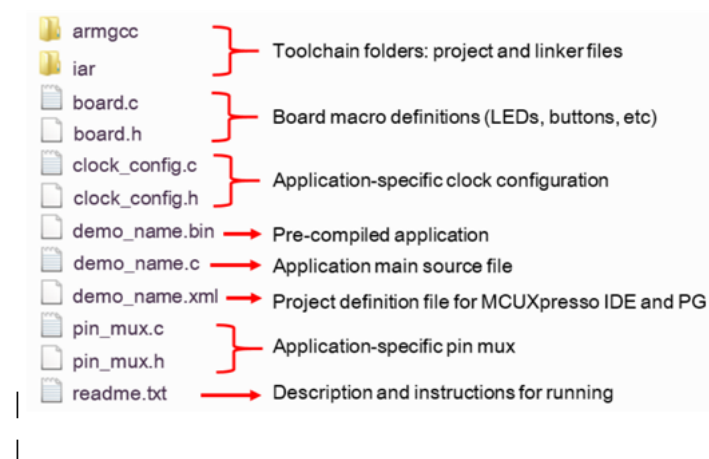
- `cmsis_driver_examples`: Simple applications intended to concisely illustrate how to use CMSIS drivers.
- `demo_apps`: Full-featured applications intended to highlight key functionality and use cases of the target MCU. These applications typically use multiple MCU peripherals and may leverage stacks and middleware.
- `driver_examples`: Simple applications intended to concisely illustrate how to use the MCUXpresso SDK's peripheral drivers for a single use case.
- `rtos_examples`: Basic FreeRTOS OS examples showcasing the use of various RTOS objects (semaphores, queues, and so on) and interfacing with the MCUXpresso SDK's RTOS drivers
- `multicore_examples`: Simple applications intended to concisely illustrate how to use middleware/multicore 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_sm` 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_sm` 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.

**Parent topic:** [MCUXpresso SDK board support folders](#)

**Locating example application source files** When opening an example application in any of the supported IDEs, a variety of source files are referenced. The MCUXpresso SDK devices folder is the central component to all example applications. It means 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_template`: Project template used in CMSIS PACK new project creation

For examples containing an RTOS, there are references to the appropriate source code. 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.

**Parent topic:** [MCUXpresso SDK board support folders](#)

## Toolchain introduction

The MCUXpresso SDK release for i.MX 943 includes the build system to be used with some toolchains. In this chapter, the toolchain support is presented and detailed.

### Build a demo application using Arm GCC

This section describes the steps to configure the command-line Arm GCC tools to build, run, and debug demo applications. Additionally, this section lists the necessary driver libraries provided in the MCUXpresso SDK. The `hello_world_sm` demo application targeted for the IMX943 series hardware platform is used as an example, though these steps can be applied to any board, demo, or example application in the MCUXpresso SDK.

**Linux OS host** The following sections provide steps to run a demo compiled with Arm GCC on Linux host.

**Set up toolchain** This section contains the steps to install the necessary components required to build and run a MCUXpresso SDK demo application with the Arm GCC toolchain, as supported by the MCUXpresso SDK.

**Install GCC Arm embedded toolchain** Download and run the installer from the GNU Arm Embedded Toolchain Downloads page. The GNU Arm embedded toolchain contains the GCC compiler, libraries, and other tools required for bare-metal software development. The GCC toolchain should correspond to the latest supported version, as described in the MCUXpresso SDK Release Notes for IMX943 Series (document MCUXSDKIMX943SERIESRN).

**Parent topic:**Set up toolchain

**Add a new system environment variable for ARMGCC\_DIR** Create a new system environment variable and name it `ARMGCC_DIR`. The value of this variable should point to the Arm GCC embedded toolchain installation path. For this example, the path is: `$ export ARMGCC_DIR=<path_to_GNUARM_GCC_installation_dir>`.

**Parent topic:**Set up toolchain

**Parent topic:**Linux OS host

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

1. 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 example, the exact path is: `<install_dir>/boards/imx943evk/demo_apps/hello_world/armgcc`.
2. Run the `build_debug.sh` script at the command-line to perform the build. The output is shown as below:

```
$ ./build_debug.sh
-- TOOLCHAIN_DIR:
-- BUILD_TYPE: debug
-- TOOLCHAIN_DIR:
-- BUILD_TYPE: debug
-- The ASM compiler identification is GNU
-- Found assembler:
-- Configuring done
```

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```
-- Generating done
-- Build files have been written to:
Scanning dependencies of target hello_world.elf
< -- skipping lines -- >
[100%] Linking C executable debug/hello_world.elf
[100%] Built target hello_world.elf
```

**Note:** build\_debug/release.sh are ram target.

**Parent topic:**Linux OS host

**Parent topic:**[Build a demo application using Arm GCC](#)

**Windows OS host** The following sections provide steps to run a demo compiled with Arm GCC on Windows OS host.

**Set up toolchain** This section contains the steps to install the necessary components required to build and run a MCUXpresso SDK demo application with the Arm GCC toolchain on Windows OS, as supported by the MCUXpresso SDK.

**Install GCC Arm embedded toolchain** Download and run the installer from the GNU Arm Embedded Toolchain Downloads page. The GNU Arm embedded toolchain contains the GCC compiler, libraries, and other tools required for bare-metal software development. The GCC toolchain should correspond to the latest supported version, as described in MCUXpresso SDK Release Notes for IMX943 Series(document MCUXSDKIMX943SERIESRN).

**Parent topic:**Set up toolchain

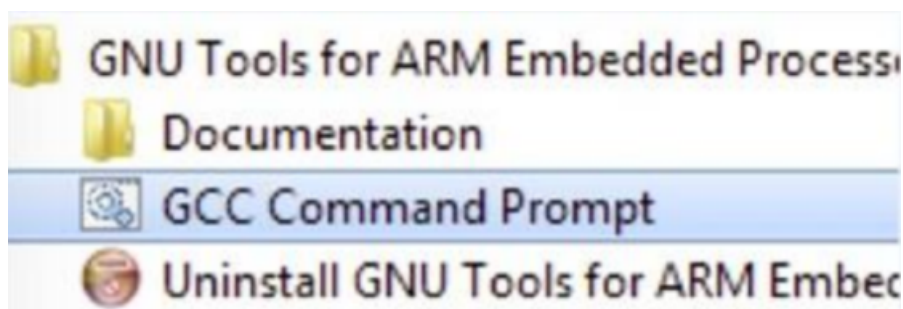
**Add a new system environment variable for ARMGCC\_DIR** Create a new system environment variable and name it ARMGCC\_DIR. The value of this variable should point to the Arm GCC embedded toolchain installation path. For this example, the path is: C:\Program Files (x86)\GNU Arm Embedded Toolchain\9 2020-q2-update. Reference the installation folder of the GNU Arm GCC embedded tools for the exact path.

**Parent topic:**Set up toolchain

**Parent topic:**Windows OS host

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

1. Open the GCC Arm embedded toolchain command window. To launch the window on the Windows operating system, select **Start-> Programs-> GNU Tools ARM Embedded <version>-> 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: `<install_dir>/boards/imx943evk/demo_apps/hello_world/armgcc`.
3. Type `build_debug.bat` at the command-line or double-click the `build_debug.bat` file in Windows Explorer to perform the build. The output is as shown in *Figure 2*.

```
[100%] Linking C executable debug\hello_world_cm33_core1.elf
Memory region      Used Size  Region Size  %age Used
  m_interrupts:      3228 B        8 KB      39.40%
    m_text:         21380 B       248 KB       8.42%
    m_data:          2624 B       172 KB       1.49%
    m_ncache:           0 B        44 KB       0.00%
m_rpmsg_shmem_m70_m33s:      0 B         6 KB       0.00%
m_rpmsg_shmem_m71_m33s:      0 B         6 KB       0.00%
    m_rsc_tbl:           0 B        16 KB       0.00%
m_rsc_tbl_share_with_mpu:      0 B         4 KB       0.00%
[100%] Built target hello_world_cm33_core1.elf
```

Parent topic: Windows OS host

Parent topic: [Build a demo application using Arm GCC](#)

## Build a demo application with IAR

This section describes the steps to run the example applications provided in the MCUXpresso SDK. The demo application targeted for the i.MX 943 hardware platform is used as an example, although these steps can be applied to any example application in the MCUXpresso SDK.

**Build an example application** The following steps guide you through opening the `hello_world` example application. These steps may change slightly for other example applications, as some of these applications may have additional layers of folders in their paths.

1. If not already done, 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
```

Using the i.MX 943 EVK board as an example, the workspace is located in:

```
<install_dir>/boards/imx943evk/demo_apps/hello_world/iar/hello_world.eww
```

2. Select the desired build target from the drop-down. For this example, select **hello\_world - debug**.
3. To build the demo application, click **Make**.
4. The build completes without errors.
5. Rename the generated `hello_world.bin` to `m70_image.bin`/`m71_image.bin`/`m33s_image.bin`, then copy it to the uuu tool directory.

Parent topic: [Generate flash.bin](#)

## Generate a flash.bin

1. Get basic images and the `imx-mkimage` source repository from corresponding Linux BSP release. These below basic images can be put into `imx-mkimage/iMX94`:

- oei-m33-ddr.bin
- m33\_image.bin (m33\_image-mx94alt.bin: the image is generated by the command - make config=mx94alt all;m33\_image-mx94evk.bin: the image is generated by the command - make config=mx94evk all)
- m70\_image.bin (demo binary name for cortex-m7 core0 in M70 MIX)
- m71\_image.bin (demo binary name for cortex-m7 core1 in M71 MIX)
- m33s\_image.bin (demo binary name for cortex-m33 core1 in NETC MIX)
- <lpddr type name>\_dmem\_qb\_v202409.bin(lpddr type name: lpddr5 or lpddr4x)
- <lpddr type name>\_dmem\_v202409.bin
- <lpddr type name>\_imem\_qb\_v202409.bin
- <lpddr type name>\_imem\_v202409.bin
- u-boot.bin
- u-boot-spl.bin
- bl31.bin
- tee.bin
- mx943a0-ahab-container.img

**Note:**

- mx943evk for m33\_image.bin is used for rpmsg str echo, rpmsg ping pong and power\_mode\_switch\_rtos.
- mx943alt for m33\_image.bin is used for almost other examples.

2. Copy binary built by ARMGCC/IAR into imx-mkimage/iMX94, and rename them to m70\_image.bin/m71\_image.bin/m33s\_image.bin.

3. Generate flash.bin.

- make SOC=iMX94 OEI=YES flash\_all LPDDR\_TYPE=lpddr5 (Boot up Cortex-A cores and Cortex-M cores[cortex-m33 core1, cortex-m7 core0, cortex-m7 core1])

or

- make SOC=iMX94 OEI=YES flash\_m33s\_m70\_m71 LPDDR\_TYPE=lpddr5 (Boot up Cortex-M cores[cortex-m33 core1, cortex-m7 core0, cortex-m7 core1])

**Note:**

- For LPDDR5, LPDDR\_TYPE=lpddr5; For LPDDR4, LPDDR\_TYPE=lpddr4x.
- For IMX943-19X19-LPDDR5-EVK, use the following command,
  - make SOC=iMX94 OEI=YES flash\_m33s\_m70\_m71 LPDDR\_TYPE=lpddr5
- or
  - make SOC=iMX94 OEI=YES flash\_all LPDDR\_TYPE=lpddr5
- For IMX943-19X19-LPDDR4-EVK or IMX943-15X15-LPDDR4-EVK, use the following command,
  - make SOC=iMX94 OEI=YES flash\_m33s\_m70\_m71 LPDDR\_TYPE=lpddr4x
- or
  - make SOC=iMX94 OEI=YES flash\_all LPDDR\_TYPE=lpddr4x
- Valid combination demos to avoid resource conflict.
  - Any demo on cm33\_core1, hello\_world demo on cm7 core0 and cm7 core1

- Any demo on cm7\_core0, hello\_world demo on cm33 core1 and cm7 core1
  - Any demo on cm7\_core1, hello\_world demo on cm33 core1 and cm7 core0
4. Burn flash.bin to MicroSD/eMMC at 32 K(0x8000) offset with dd or HxD or UUU and then plug the MicroSD card to the board.

For example:

- Burn flash.bin into Micro SD card with dd

```
dd if=flash.bin of=/dev/sdh bs=1k seek=32 && sync
```

- Burn flash.bin into SD/eMMC with UUU

1. Connect USB Type-C port to PC through the USB cable. It is used for downloading firmware of the board.
2. Switch to serial downloader mode; boot core is cortex-m33. `sd: uuu -b sd imx-boot-imx943-19x19-lpddr5-evk-sd.bin-flash_all new-flash.bin`
3. Burn flash.bin with uuu.

```
emmc: uuu -b emmc imx-boot-imx943-19x19-lpddr5-evk-sd.bin-flash_all flash.bin
```

```
sd: uuu -b sd imx-boot-imx943-19x19-lpddr5-evk-sd.bin-flash_all flash.bin
```

**Note:**

- imx-boot-imx943-19x19-lpddr5-evk-sd.bin-flash\_all (imx-boot-imx943-19x19-lpddr4x-evk-sd.bin-flash\_all for IMX943LP4CPU-19 SOM + X-IMX943BB; imx-boot-imx943-15x15-lpddr4x-evk-sd.bin-flash\_all for IMX943LP4CPU-15 SOM + X-IMX943BB). Get them from linux bsp.
  - flash.bin. The flash.bin is generated by yourself.
5. Change the boot mode to SW4[1:4] = x011 for sd boot, SW4[1:4] = x010 for emmc boot.
6. Power on the board .

**Parent topic:**[Run a demo application](#)

## Enable MCU UARTs

1. Connect usb typec cable from pc to typec port J15 of board.(It will emulate four serial ports[e.g. COM0 - LPUART8, COM1, COM2 - LPUART1, COM3 - LPUART2] in pc)
  - COM0(LPUART8 - use as uart of cortex-m33 core1), please perform the following steps,
    - a. Enable BCU,
      - Change SW7-1 from OFF.(For imx943evk proto2 board, base board version: REV B1)
      - Change SW7-1 from ON.(For imx943evk proto1 board)
    - b. Enable the serial port via bcu command,
      - `bcu set_gpio fta_jtag_host_en 0 -board=imx943evk19b1 or bcu set_gpio fta_jtag_host_en 0 -board=imx943evk19a0`
      - `bcu set_gpio fta_jtag_uart_sel 1 -board=imx943evk19b1 or bcu set_gpio fta_jtag_uart_sel 1 -board=imx943evk19a0`
  - COM2(LPUART1 - use as uart of Cortex-A)
  - COM3(LPUART2 - use as uart of Cortex-m33 core0)
2. Connect two usb2uart converter from pc to arduino interface of board.(It will emulate two serial ports[e.g. COM4 - LPUART11, COM5 - LPUART12] in pc)

- COM4(LPUART11 - use as uart of cortex-m7 core0)  
J48-2(M2\_UART11\_RXD) – TX of usb2uart converter – pc  
J48-4(M2\_UART11\_TXD) – RX of usb2uart converter – pc  
GND ————— GND of usb2uart converter – pc
- COM5(LPUART12 - use as uart of cortex-m7 core1)  
J44-4(M1\_UART12\_RXD) – TX of usb2uart converter – pc  
J44-2(M1\_UART12\_TXD) – RX of usb2uart converter – pc  
GND ————— GND of usb2uart converter – pc

**Note:**

- mx943evk for m33\_image.bin is used for rpmsg str echo, rpmsg ping pong and power\_mode\_switch\_rtos.
  - mx943alt for m33\_image.bin is used for almost other examples.
  - JTAG cannot be used when LPUART8 is used.
  - Pls change uart from LPUART8 to LPUART1 and generate m33\_image.bin with command `make config=mx94alt all` when debugging with jtag.
- For MCUXpresso SDK

```
_boards/imx943evk/board.h
#define BOARD_DEBUG_UART_INSTANCE 8 -> #define BOARD_DEBUG_UART_
↪INSTANCE 1
```

**Parent topic:** [Run a demo application](#)

## Run a demo application

This section describes the steps to download the flash.bin to sd and emmc, run the example applications provided in the MCUXpresso SDK. The `hello_world_sm` demo application targeted for the i.MX 943 hardware platform is used as an example, although these steps can be applied to any example application in the MCUXpresso SDK.

## Generate a flash.bin

1. Get basic images and the imx-mkimage source repository from corresponding Linux BSP release. These below basic images can to be put into imx-mkimage/iMX94:

- oei-m33-ddr.bin
- m33\_image.bin (m33\_image-mx94alt.bin: the image is generated by the command `- make config=mx94alt all`; m33\_image-mx94evk.bin: the image is generated by the command `- make config=mx94evk all`)
- m70\_image.bin (demo binary name for cortex-m7 core0 in M70 MIX)
- m71\_image.bin (demo binary name for cortex-m7 core1 in M71 MIX)
- m33s\_image.bin (demo binary name for cortex-m33 core1 in NETC MIX)
- <lpddr type name>\_dmem\_qb\_v202409.bin (lpddr type name: lpddr5 or lpddr4x)
- <lpddr type name>\_dmem\_v202409.bin
- <lpddr type name>\_imem\_qb\_v202409.bin
- <lpddr type name>\_imem\_v202409.bin
- u-boot.bin



- u-boot-spl.bin
- bl31.bin
- tee.bin
- mx943a0-ahab-container.img

**Note:**

- mx943evk for m33\_image.bin is used for rpmsg str echo, rpmsg ping pong and power\_mode\_switch\_rtos.
  - mx943alt for m33\_image.bin is used for almost other examples.
2. Copy binary built by ARMGCC/IAR into imx-mkimage/iMX94, and rename them to m70\_image.bin/m71\_image.bin/m33s\_image.bin.
  3. Generate flash.bin.
    - make SOC=iMX94 OEI=YES flash\_all LPDDR\_TYPE=lpddr5 (Boot up Cortex-A cores and Cortex-M cores[cortex-m33 core1, cortex-m7 core0, cortex-m7 core1])

or

- make SOC=iMX94 OEI=YES flash\_m33s\_m70\_m71 LPDDR\_TYPE=lpddr5 (Boot up Cortex-M cores[cortex-m33 core1, cortex-m7 core0, cortex-m7 core1])

**Note:**

- For LPDDR5, LPDDR\_TYPE=lpddr5; For LPDDR4, LPDDR\_TYPE=lpddr4x.
  - For IMX943-19X19-LPDDR5-EVK, use the following command,
    - make SOC=iMX94 OEI=YES flash\_m33s\_m70\_m71 LPDDR\_TYPE=lpddr5
  - or
    - make SOC=iMX94 OEI=YES flash\_all LPDDR\_TYPE=lpddr5
  - For IMX943-19X19-LPDDR4-EVK or IMX943-15X15-LPDDR4-EVK, use the following command,
    - make SOC=iMX94 OEI=YES flash\_m33s\_m70\_m71 LPDDR\_TYPE=lpddr4x
  - or
    - make SOC=iMX94 OEI=YES flash\_all LPDDR\_TYPE=lpddr4x
  - Valid combination demos to avoid resource conflict.
    - Any demo on cm33\_core1, hello\_world demo on cm7 core0 and cm7 core1
    - Any demo on cm7\_core0, hello\_world demo on cm33 core1 and cm7 core1
    - Any demo on cm7\_core1, hello\_world demo on cm33 core1 and cm7 core0
4. Burn flash.bin to MicroSD/eMMC at 32 K(0x8000) offset with dd or HxD or UUU and then plug the MicroSD card to the board.

For example:

- Burn flash.bin into Micro SD card with dd
  - dd if=flash.bin of=/dev/sdh bs=1k seek=32 && sync
- Burn flash.bin into SD/eMMC with UUU
  1. Connect USB Type-C port to PC through the USB cable. It is used for downloading firmware of the board.
  2. Switch to serial downloader mode; boot core is cortex-m33. sd: uuu -b sd imx-boot-imx943-19x19-lpddr5-evk-sd.bin-flash\_all new-flash.bin



### 3. Burn flash.bin with uuu.

```
emmc: uuu -b emmc imx-boot-imx943-19x19-lpddr5-evk-sd.bin-flash_all flash.bin
```

```
sd: uuu -b sd imx-boot-imx943-19x19-lpddr5-evk-sd.bin-flash_all flash.bin
```

**Note:**

- imx-boot-imx943-19x19-lpddr5-evk-sd.bin-flash\_all (imx-boot-imx943-19x19-lpddr4x-evk-sd.bin-flash\_all for IMX943LP4CPU-19 SOM + X-IMX943BB; imx-boot-imx943-15x15-lpddr4x-evk-sd.bin-flash\_all for IMX943LP4CPU-15 SOM + X-IMX943BB). Get them from linux bsp.
- flash.bin. The flash.bin is generated by yourself.

5. Change the boot mode to SW4[1:4] = x011 for sd boot, SW4[1:4] = x010 for emmc boot.

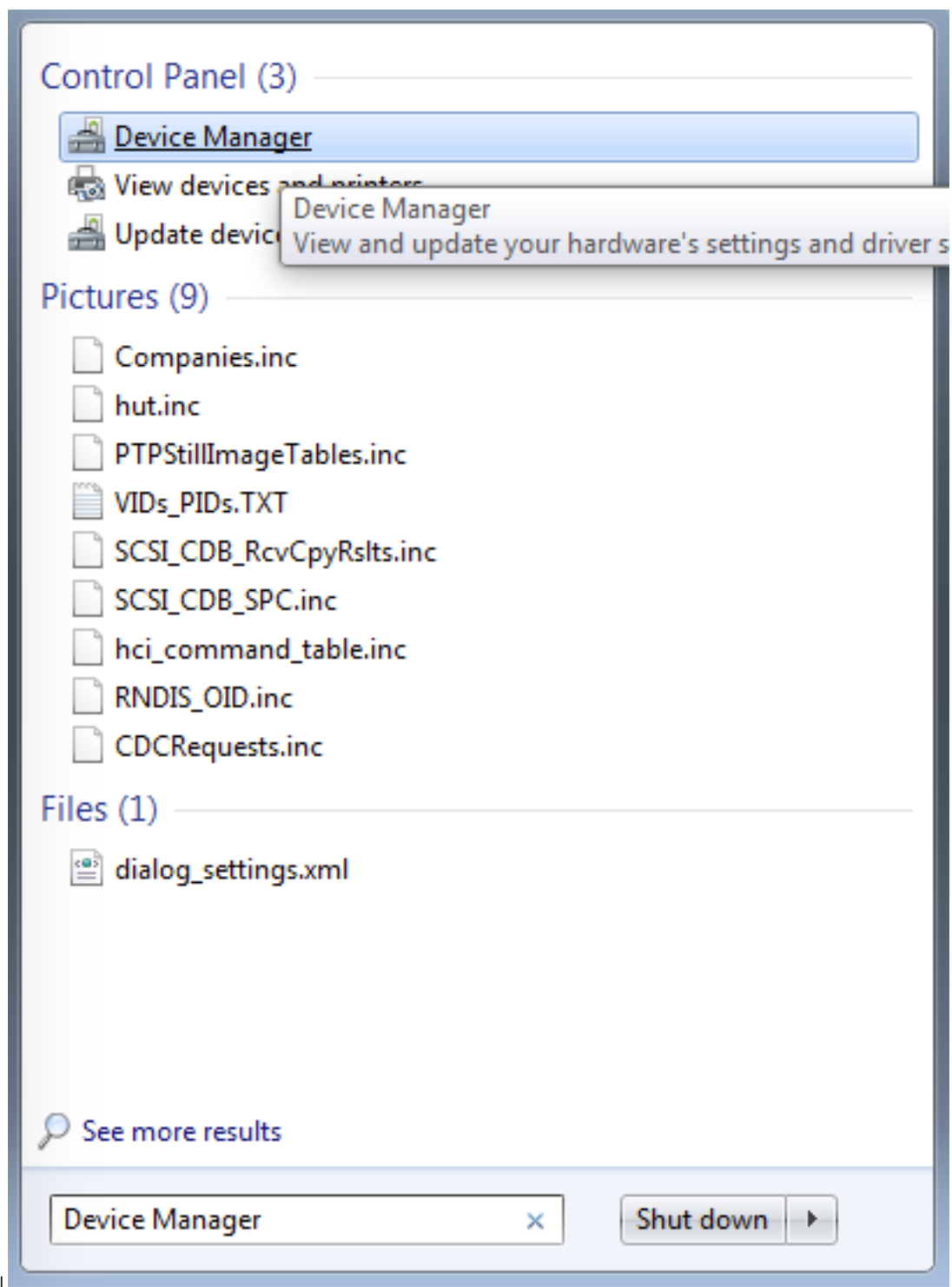
6. Power on the board .

**Parent topic:**[Run a demo application](#)

## How to determine COM port

This section describes the steps necessary to determine the debug COM port number of your NXP hardware development platform.

1. To determine the COM port, open the Windows operating system Device Manager. This can be achieved by going to the Windows operating system Start menu and typing **Device Manager** in the search bar, as shown in *Figure 1*.



2. In the **Device Manager**, expand the **Ports (COM & LPT)** section to view the available ports. Depending on the NXP board you're using, the COM port can be named differently.

1. **USB-UART interface**



## Host setup

An MCUXpresso SDK build requires that some packages are installed on the Host. Depending on the used Host operating system, the following tools should be installed.

### Linux:

- Cmake

```
$ sudo apt-get install cmake
$ # Check the version >= 3.0.x
$ cmake --version
```

### Windows:

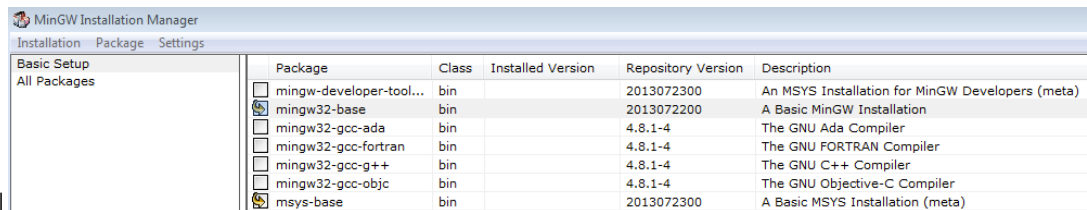
- MinGW

The Minimalist GNU for Windows OS (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 SDK does not utilize 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 [sourceforge.net/projects/mingw/files/Installer/](https://sourceforge.net/projects/mingw/files/Installer/).
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 **mingw32-base** and **msys-base** are selected under **Basic Setup**.



4. Click **Apply Changes** in the **Installation** menu 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``.

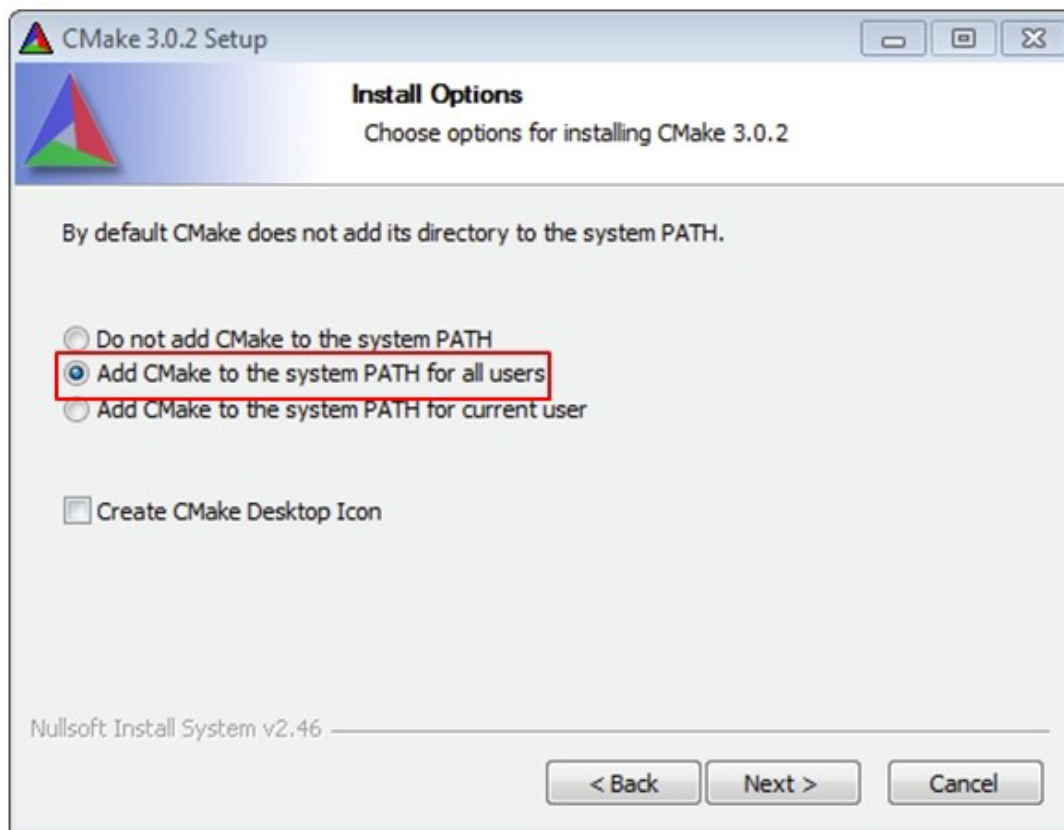
Assuming the default installation path, `C:\MinGW``, an example is as shown in [Figure 3](host\_setup.md #ADDINGPATH). If the path is not set correctly, the toolchain does not work.

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



- Cmake

1. Download CMake 3.0.x from [www.cmake.org/cmake/resources/software.html](http://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.

## 1.3 Getting Started with MCUXpresso SDK GitHub

### 1.3.1 Getting Started with MCUXpresso SDK Repository

Welcome to the **GitHub Repository SDK Guide**. This documentation provides instructions for setting up and working with the MCUXpresso SDK distributed in a **multi-repository model**. The SDK is distributed across multiple GitHub repositories and managed using the **Zephyr West** tool, enabling modular development and streamlined workflows.

#### Overview

The GitHub Repository SDK approach offers:

- **Modular Structure:** Multiple repositories for flexibility and scalability.
- **Zephyr West Integration:** Simplified repository management and synchronization.

- **Cross-Platform Support:** Designed for MCUXpresso SDK development environments.

### Benefits of the Multi-Repository Approach

- **Scalability:** Easily add or update components without impacting the entire SDK.
- **Collaboration:** Enables distributed development across teams and repositories.
- **Version Control:** Independent versioning for components ensures better stability.
- **Automation:** Zephyr West simplifies dependency handling and repository synchronization.

### Setup and Configuration

Follow these steps to prepare your development environment:

**Development Tools Installation** This guide explains how to install the essential tools for development with the MCUXpresso SDK.

**Quick Start: Automated Installation (Recommended)** The **MCUXpresso Installer** is the fastest way to get started. It automatically installs all the basic tools you need.

1. **Download the MCUXpresso Installer** from: [Dependency-Installation](#)
2. **Run the installer** and select “**MCUXpresso SDK Developer**” from the menu
3. **Click Install** and let it handle everything automatically

**Manual Installation** If you prefer to install tools manually or need specific versions, follow these steps:

### Essential Tools

**Git - Version Control** **What it does:** Manages code versions and downloads SDK repositories from GitHub.

#### Installation:

- Visit [git-scm.com](https://git-scm.com)
- Download for your operating system
- Run installer with default settings
- **Important:** Make sure “Add Git to PATH” is selected during installation

#### Setup:

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

**Python - Scripting Environment** **What it does:** Runs build scripts and SDK tools.

**Installation:**

- Install Python **3.10 or newer** from [python.org](https://python.org)
- **Important:** Check “Add Python to PATH” during installation

**West - SDK Management Tool** **What it does:** Manages SDK repositories and provides build commands. The west tool is developed by the Zephyr project for managing multiple repositories.

**Installation:**

```
pip install -U west
```

**Minimum version:** 1.2.0 or newer

## Build System Tools

**CMake - Build Configuration** **What it does:** Configures how your projects are built.

**Recommended version:** 3.30.0 or newer

**Installation:**

- **Windows:** Download .msi installer from [cmake.org/download](https://cmake.org/download)
- **Linux:** Use package manager or download from [cmake.org](https://cmake.org)
- **macOS:** Use Homebrew (brew install cmake) or download from [cmake.org](https://cmake.org)

**Ninja - Fast Build System** **What it does:** Compiles your code quickly.

**Minimum version:** 1.12.1 or newer

**Installation:**

- **Windows:** Usually included, or download from [ninja-build.org](https://ninja-build.org)
- **Linux:** sudo apt install ninja-build or download binary
- **macOS:** brew install ninja or download binary

**Ruby - IDE Project Generation (Optional)** **What it does:** Generates project files for IDEs like IAR and Keil.

**When needed:** Only if you want to use traditional IDEs instead of VS Code.

**Installation:** Follow the Ruby environment setup guide

**Compiler Toolchains** Choose and install the compiler toolchain you want to use:

Toolchain			Best For	Download Link		Environment Variable
<b>ARM GCC</b> (Recommended)	Most users, free		Professional development	<a href="#">ARM Toolchain</a>	<a href="#">GNU</a>	ARMGCC_DIR
	<b>IAR EWARM</b>			<a href="#">IAR Systems</a>		IAR_DIR
	<b>Keil MDK</b>			<a href="#">ARM Developer</a>		MDK_DIR
	<b>ARM Compiler</b>			<a href="#">ARM Developer</a>		ARMCLANG_DIR

**Setting Up Environment Variables** After toolchain installation, set an environment variable so the build system locates it:

**Windows:**

```
# Example for ARM GCC installed in C:\armgcc
setx ARMGCC_DIR "C:\armgcc"
```

**Linux/macOS:**

```
# Add to ~/.bashrc or ~/.zshrc
export ARMGCC_DIR="/usr" # or your installation path
```

**Verify Your Installation** After installation, verify everything works by opening a terminal/command prompt and running these commands:

```
# Check each tool - you should see version numbers
git --version
python --version
west --version
cmake --version
ninja --version
arm-none-eabi-gcc --version # (if using ARM GCC)
```

**Troubleshooting Installation Issues** “Command not found” errors:

- The tool isn’t in your system PATH
- **Solution:** Add the installation directory to your PATH environment variable

**Python/pip issues:**

- Try using python3 and pip3 instead of python and pip
- On Windows, run the Command Prompt as an Administrator

**Slow downloads:**

- Add timeout option: `pip install -U west --default-timeout=1000`
- Use alternative mirror: `pip install -U west -i https://pypi.tuna.tsinghua.edu.cn/simple`

**GitHub Repository Setup** This guide explains how to initialize your MCUXpresso SDK workspace from GitHub repositories using the west tool. The GitHub Repository SDK uses multiple repositories hosted on GitHub to provide modular, flexible development.

**Prerequisites** Verify the requirements:

**System Requirements:**

- Python 3.8 or later
- Git 2.25 or later
- CMake 3.20 or later
- Build tools for your target platform

**Verification Commands:**

```
python --version  # Should show 3.8+
git --version     # Should show 2.25+
cmake --version   # Should show 3.20+
west --version    # Should show west tool installation
```

**Workspace Initialization** The GitHub Repository SDK uses the Zephyr west tool to manage multiple repositories containing different SDK components.

**Step 1: Initialize Workspace** Create and initialize your SDK workspace from GitHub:

**Get the latest SDK from main branch:**

```
west init -m https://github.com/nxp-mcuxpresso/mcuxsdk-manifests.git mcuxpresso-sdk
```

**Get SDK at specific revision:**

```
west init -m https://github.com/nxp-mcuxpresso/mcuxsdk-manifests.git mcuxpresso-sdk --mr {revision}
```

*Note: Replace {revision} with the desired release tag, such as v25.09.00*

**Step 2: Choose Your Repository Update Strategy** Navigate to the SDK workspace:

```
cd mcuxpresso-sdk
```

The west tool manages multiple GitHub repositories containing different SDK components. You have two options for downloading:

**Option A: Download All Repositories (Complete SDK)** Download all SDK repositories for comprehensive development:

```
west update
```

This command downloads all the repositories defined in the manifest from GitHub. Initial download takes several minutes and requires ~7 GB of disk space.

**Best for:**

- Exploring the complete SDK
- Multi-board development projects
- Comprehensive middleware evaluation

**Option B: Targeted Repository Download (Recommended)** Download only repositories needed for your specific board or device to save time and disk space:

```
# For specific board development
west update_board --set board your_board_name

# For specific device family development
west update_board --set device your_device_name

# List available repositories before downloading
west update_board --set board your_board_name --list-repo
```

**Best for:**

- Single board development



- Faster setup and reduced disk usage
- Focused development workflows

**Examples:**

```
# Update only repositories for FRDM-MCXW23 board
west update_board --set board frdm-mcxw23

# Update only repositories for MCXW23 device family
west update_board --set device mcxw23
```

**Step 3: Verify Installation** Confirm successful setup:

```
# Verify workspace structure
ls -la
# Should show: manifests/ and mcuxsdk/ directories

# Test build system
west list_project -p examples/demo_apps/hello_world
# Should display available build configurations
```

**Advanced Repository Management** The west extension command `update_board` provides advanced repository management capabilities for optimized workspace setup with GitHub repositories.

**Board-Specific Setup** Update only repositories required for a specific board:

```
# Update only repositories for specific board, e.g., frdm-mcxw23
west update_board --set board frdm-mcxw23

# List available repositories for the board before updating
west update_board --set board frdm-mcxw23 --list-repo
```

**Device-Specific Setup** Update only repositories required for a specific device family:

```
# Update only repositories for specific device, e.g., MCXW235
west update_board --set device mcxw23

# List available repositories for the device family
west update_board --set device mcxw23 --list-repo
```

**Custom Configuration** For advanced users who want to create custom repository combinations:

```
# Use custom configuration file
west update_board --set custom path/to/custom-config.yml

# Generate custom configuration template
cp manifests/boards/custom.yml.template my-custom-config.yml
```

**Benefits of Targeted Setup** **Reduced Download Size**

- Download only components needed for your target board or device
- Significantly faster initial setup for focused development

- Typical reduction from 7 GB to 2GB

### Optimized Workspace

- Cleaner workspace with relevant components only
- Reduced disk space usage
- Faster repository operations

### Flexible Development

- Switch between different board configurations easily
- Maintain separate workspaces for different projects
- Include optional components as needed

**Repository Information** Before setting up your workspace, you can explore what repositories are available:

```
# Display repository information in console
west update_board --set board frdm-mcxw23 --list-repo

# Export repository information to YAML file for reference
west update_board --set board frdm-mcxw23 --list-repo -o board-repos.yml
```

This command lists all the available repositories with descriptions and outlines the included components in the workspace.

**Package Generation (Optional)** The `update_board` command can also generate ZIP packages for offline distribution:

```
# Generate board-specific SDK package
west update_board --set board frdm-mcxw23 -o frdm-mcxw23-sdk.zip
```

**Note:** Package generation is primarily intended for creating custom SDK distributions. For regular development, use the workspace update commands without the `-o` option.

## Workspace Management

**Updating Your Workspace** Keep your SDK current with latest updates from GitHub:

### For Complete SDK Workspace:

```
# Update manifest repository
cd manifests
git pull

# Update all component repositories
cd ..
west update
```

### For Targeted Workspace:

```
# Update manifest repository
cd manifests
git pull

# Update board-specific repositories
cd ..
west update_board --set board your_board_name
```

**Workspace Status** Check workspace synchronization status:

```
# Show status of all repositories
west status
```

```
# Show detailed information about repositories
west list
```

### Troubleshooting Network Issues:

- Use `west update --keep-descendants` for partial failures
- Configure Git credentials for private repositories
- Check firewall settings for Git protocol access

### Permission Issues:

- Ensure write permissions in workspace directory
- Run commands without `sudo`/administrator privileges
- Verify Git SSH key configuration for authenticated access

### Disk Space:

- Full SDK workspace requires approximately 7-8 GB
- Targeted workspace typically requires 1-2 GB
- Use board-specific setup to reduce workspace size

### Repository Management Issues:

- Verify board/device names match available configurations
- Check that custom YAML files follow the correct template format
- Use `--list-repo` to verify available repositories before setup

**Next Steps** With your workspace initialized:

1. Review [Workspace Structure](#) to understand the layout
2. Build your first project with [First Build Guide](#)
3. Explore [Development Workflows MCUXpresso VSCode](#) or [Development Workflows Command Line](#) for the details on project setup and execution

For advanced repository management, see the [west tool documentation](#).

## Explore SDK Structure and Content

Learn about the organization of the SDK and its components:

**SDK Architecture Overview** The MCUXpresso SDK uses a modular architecture where software components are distributed across multiple repositories hosted on GitHub and managed through the west tool. This approach provides flexibility, maintainability, and enables selective component inclusion.

**Repository Organization** Based on the manifest structure, the SDK consists of four main repository categories:

**Manifest Repository** The manifest repo (mcuxsdk-manifests) contains the west.yml manifest file that tracks all other repositories in the SDK.

**Base Repositories** Recorded in submanifests/base.yml and loaded in the root west.yml manifest file. These are the foundational repositories that build the SDK:

- **Devices:** MCU-specific support packages
- **Examples:** Demonstration applications and code samples
- **Boards:** Board support packages

**Middleware Repositories** Recorded in the submanifests/middleware subdirectory, categorized according to functionality:

- **Connectivity:** Networking stacks, USB, and communication protocols
- **Security:** Cryptographic libraries and secure boot components
- **Wireless:** Bluetooth, IEEE 802.15.4, and other wireless protocols
- **Graphics:** Display drivers and UI frameworks
- **Audio:** Audio processing and voice recognition libraries
- **Machine Learning:** AI inference engines and neural network libraries
- **Safety:** IEC60730B safety libraries
- **Motor Control:** Motor control and real-time control libraries

**Internal Repositories** Recorded in submanifests/internal.yml and grouped into the “bifrost” group. These are only visible to NXP internal developers and hosted on NXP internal git servers.

**Repository Hosting** Public repositories are hosted on GitHub under these organizations:

- [nxp-mcuxpresso](#)
- [NXP](#)
- [nxp-zephyr](#)

Internal repositories are hosted on NXP's private Git infrastructure.

**Benefits of This Architecture** **Selective Integration:** Projects include only required components, reducing memory footprint and build complexity.

**Independent Versioning:** Each component maintains its own release cycle and version control.

**Community Collaboration:** Public repositories accept community contributions through standard Git workflows.

**Scalable Maintenance:** Component owners can update their repositories without affecting the entire SDK.

**Workspace Management** The west tool manages repository synchronization, version tracking, and workspace updates. All repositories are checked out under the mcuxsdk/ directory with their designated paths defined in the manifest files.

**Workspace Structure** After you initialize your SDK workspace, it creates a specific directory structure that organizes all SDK components. This structure is identical for both GitHub Repository SDK and Repository-Layout SDK Package.

### Top-Level Organization

```
your-sdk-workspace/
  manifests/      # West manifest repository
  mcuxsdk/        # Main SDK content
```

The `mcuxsdk/` directory serves as your primary working directory and contains all the SDK components.

**SDK Component Layout** Based on the actual SDK structure, the main directories include:

Directory	Contents	Purpose
<code>arch/</code>	Architecture-specific files	ARM CMSIS, build configurations
<code>cmake</code>	Build system modules	CMake configuration and build rules
<code>compo</code>	Software components	Reusable software libraries and utilities
<code>device</code>	Device support packages	MCU-specific headers, startup code, linker scripts
<code>drivers</code>	Peripheral drivers	Hardware abstraction layer for MCU peripherals
<code>examp</code>	Sample applications	Demonstration code and reference implementations
<code>middle</code>	Optional software stacks	Networking, graphics, security, and other libraries
<code>rtos/</code>	Operating system support	FreeRTOS integration
<code>scripts</code>	Build and utility scripts	West extensions and development tools
<code>svd</code>	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.	

**Example Organization** Examples follow a two-tier structure separating common code from board-specific implementations:

### Common Example Files

```
examples/demo_apps/hello_world/
  CMakeLists.txt      # Build configuration
  example.yml         # Example metadata
  hello_world.c       # Application source code
  Kconfig             # Configuration options
  readme.md           # General documentation
```

## Board-Specific Files

```
examples/_boards/your_board/demo_apps/hello_world/  
  app.h           # Board specific application header  
  example_board_readme.md # Board specific documentation  
  hardware_init.c # Board specific hardware initialization  
  pin_mux.c       # Pin multiplexing configuration  
  pin_mux.h       # Pin multiplexing header definitions  
  hello_world.bin  # Pre-built binary for quick testing  
  hello_world.mex  # MCUXpresso Config Tools project file  
  prj.conf        # Board specific Kconfig configuration  
  reconfig.cmake  # Board specific cmake configuration overrides
```

**Device Support Structure** Device support is organized hierarchically by MCU family:

```
devices/  
  MCX/           # MCU portfolio  
    MCXW/        # MCU family  
      MCXW235/    # Specific device  
        MCXW235.h # Device register definitions  
        drivers/  # Device-specific drivers  
        gcc/      # GNU toolchain files  
        iar/      # IAR toolchain files  
        mcuxpresso/ # MCUXpresso IDE files  
        startup_MCXW235.c # Startup and vector table  
        system_MCXW235.c # System initialization
```

**Middleware Organization** Middleware components are categorized by functionality and maintained in separate repositories. Based on the manifest files, common middleware categories include:

- **Connectivity:** USB, TCP/IP, industrial protocols
- **Security:** Cryptographic libraries, secure boot
- **Wireless:** Bluetooth, IEEE 802.15.4, Wi-Fi
- **Graphics:** Display drivers, UI frameworks
- **Audio:** Processing libraries, voice recognition
- **Machine Learning:** Inference engines, neural networks
- **Safety:** IEC60730B safety libraries
- **Motor Control:** Motor control and real-time control libraries

**Documentation Structure** SDK documentation is distributed across multiple locations:

- docs/ - Core SDK documentation and build infrastructure
- Component repositories - API documentation and integration guides
- Board directories - Hardware-specific setup instructions

For complete documentation, refer to the [online documentation](#).

**Understanding Example Structure** Each example has **two README files**:

**1. General README:** `examples/demo_apps/hello_world/readme.md`

- What the example does
- General functionality description
- Common usage information

**2. Board-Specific README:** `examples/_boards/{board_name}/demo_apps/hello_world/example_board_readme.md`

- Board-specific setup instructions
- Hardware connections required
- Board-specific behavior notes

**Tip:** Always check both readme files - start with the general one, then read the board-specific one for detailed setup.

## Development Workflows

Get started with building and running projects:

**Building Your First Project** This guide explains how to build and run your first SDK example project using the west build system. This applies to both GitHub Repository SDK and Repository-Layout SDK Package.

### Prerequisites

- GitHub Repository SDK workspace initialized OR Repository-Layout SDK Package extracted
- Development board connected via USB
- Build tools installed per [Installation Guide](#)

**Understanding Board Support** Use the west extension to discover available examples for your board:

```
west list _project -p examples/demo_apps/hello_world
```

This shows all supported build configurations. You can filter by toolchain:

```
west list _project -p examples/demo_apps/hello_world -t armgcc
```

## Basic Build Process

**Simple Build** Build the hello\_world example with default settings:

```
west build -b your_board examples/demo_apps/hello_world
```

The default toolchain is armgcc, and the build system will select the first debug target as default if no config is specified.

## Specifying Configuration

```
# Release build
west build -b your_board examples/demo_apps/hello_world --config release

# Debug build (default)
west build -b your_board examples/demo_apps/hello_world --config debug
```

## Alternative Toolchains

```
# IAR toolchain
west build -b your_board examples/demo_apps/hello_world --toolchain iar

# Other toolchains as supported by the example
```

## Multicore Applications

 For multicore devices, specify the core ID:

```
west build -b evkbmimxrt1170 examples/demo_apps/hello_world --toolchain iar -Dcore_id=cm7 --config ↵
↵ flexspi_nor_debug
```

For multicore projects using sysbuild:

```
west build -b evkbmimxrt1170 --sysbuild ./examples/multicore_examples/hello_world/primary -Dcore_ ↵
↵ id=cm7 --config flexspi_nor_debug --toolchain=armgcc -p always
```

## Flash an Application

 Flash the built application to your board:

```
west flash -r linkserver
```

## Debug

 Start a debug session:

```
west debug -r linkserver
```

## Common Build Options

### Clean Build

 Force a complete rebuild:

```
west build -b your_board examples/demo_apps/hello_world -p always
```

### Dry Run

 See the commands that get executed without running them:

```
west build -b your_board examples/demo_apps/hello_world --dry-run
```

### Device Variants

 For boards supporting multiple device variants:

```
west build -b your_board examples/demo_apps/hello_world --device DEVICE_PART_NUMBER --config ↵
↵ release
```

## Project Configuration



**CMake Configuration Only** Run configuration without building:

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

**Interactive Configuration** Launch the configuration GUI:

```
west build -t guiconfig
```

## Troubleshooting

**Build Failures** Use pristine builds to resolve dependency issues:

```
west build -b your_board examples/demo_apps/hello_world -p always
```

**Getting Help** View the help information for west build:

```
west build -h
```

**Check Supported Configurations** To see available configuration options and board targets for an example, refer to the below command:

```
west list_project -p examples/demo_apps/hello_world
```

## Next Steps

- Explore other examples in the SDK
- Learn about [Command Line Development](#) for advanced options
- Try [VS Code Development](#) for integrated development
- Refer [Workspace Structure](#) to understand the SDK layout

**MCUXpresso for VS Code Development** This guide covers using MCUXpresso for VS Code extension to build, debug, and develop SDK applications with an integrated development environment.

## Prerequisites

- SDK workspace initialized (GitHub Repository SDK or Repository-Layout SDK Package)
- Development tools installed per [Installation Guide](#)
- Visual Studio Code installed
- MCUXpresso for VS Code extension installed

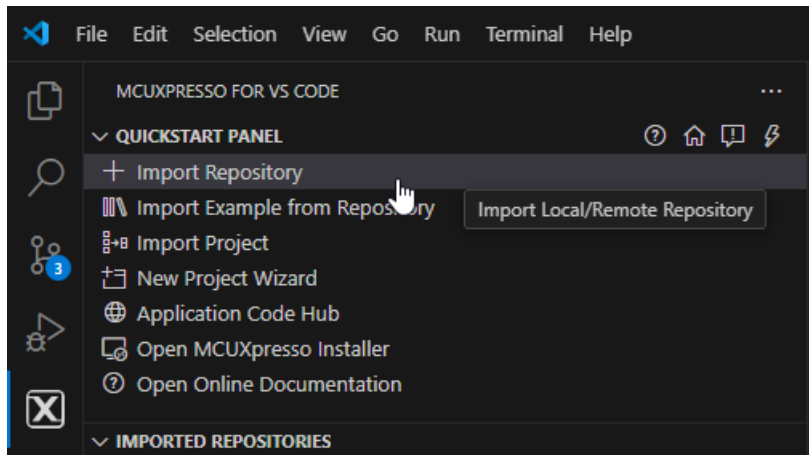
## Extension Installation

**Install MCUXpresso for VS Code** The MCUXpresso for VS Code extension provides integrated development capabilities for MCUXpresso SDK projects. Refer to the [MCUXpresso for VS Code Wiki](#) for detailed installation and setup instructions.

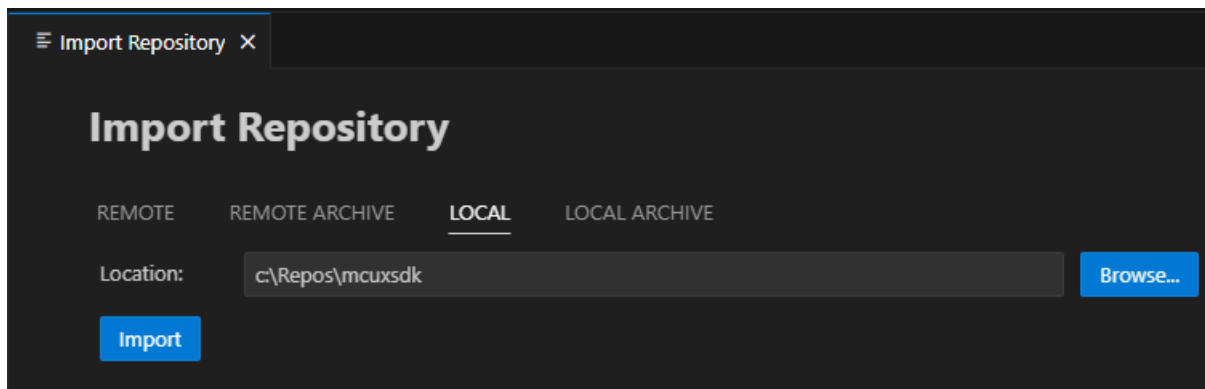
## SDK Import and Setup

**Import Methods** The SDK can be imported in several ways. The MCUXpresso for VS Code extension supports both GitHub Repository SDK and Repository-Layout SDK Package distributions.

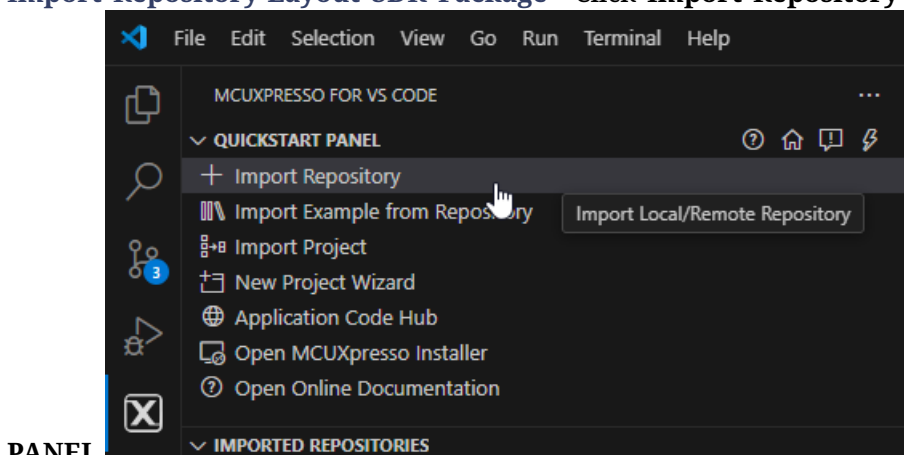
**Import GitHub Repository SDK** Click **Import Repository** from the **QUICKSTART PANEL**



**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 according to [setting up the repo](#). Select your location and click **Import**.

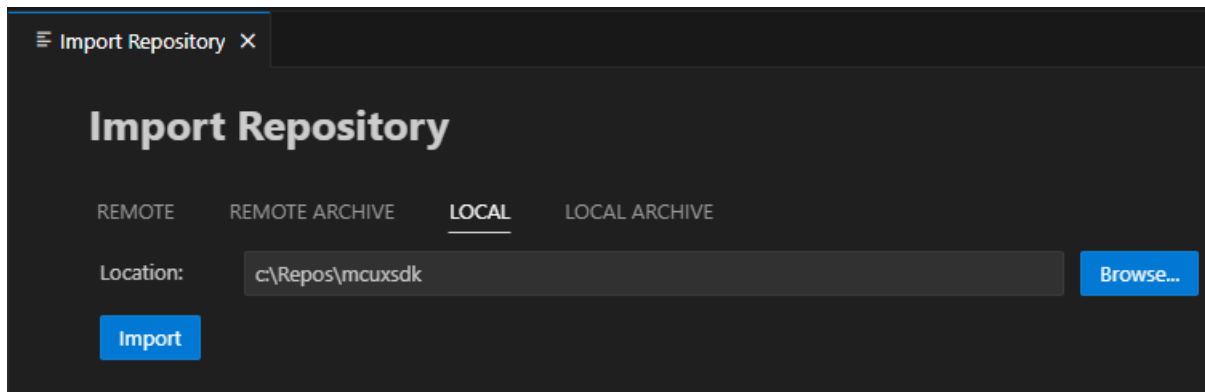


**Import Repository-Layout SDK Package** Click **Import Repository** from the **QUICKSTART**

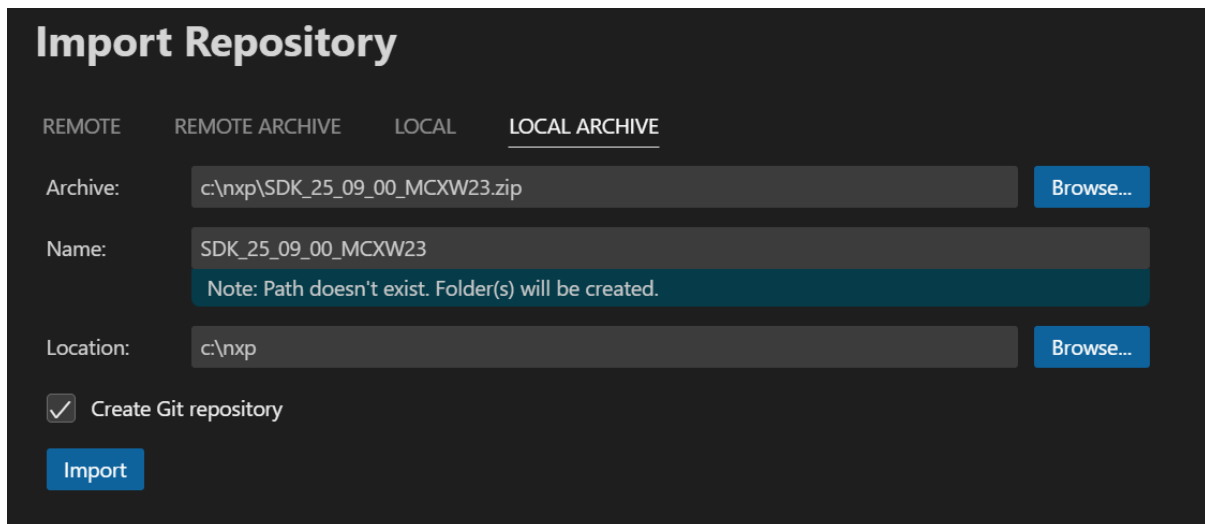


PANEL

Select **Local** if you've already unzipped the Repository-Layout SDK Package. Select your location and click **Import**.



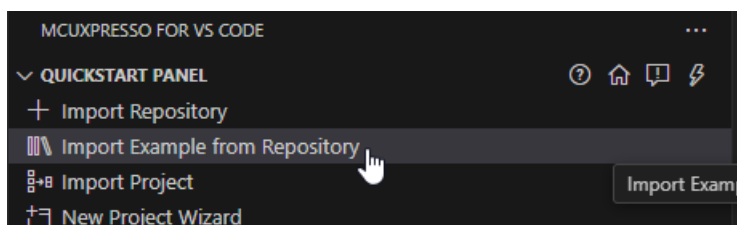
Else if the SDK is ZIP archive, select **Local Archive**, browse to the downloaded SDK ZIP file, fill the link of expect location, then click **Import**.



## Building Example Applications

### Import Example Project

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



2. Configure project settings:
  - **MCUXpresso SDK:** Select your imported SDK
  - **Arm GNU Toolchain:** Choose toolchain
  - **Board:** Select your target development board
  - **Template:** Choose example category

- **Application:** Select specific example (e.g., hello\_world)
- **App type:** Choose between Repository applications or Freestanding applications

### 3. Click **Import**


Import Example from Repository

## Import Example from Repository

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

Toolchain: (Arm GNU Toolchain 13.2.rel1 (Build arm-13.7)) 13.2.1 20231009 (C:\NXP\MCUXpressoIDE\_24.

Board: FRDM-MCXC444


FRDM-MCXC444

Template: demo\_apps/hello\_world

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

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

### Application Types    **Repository Applications:**

- Located inside the MCUXpresso SDK
- Integrated with SDK workspace

### **Freestanding Applications:**

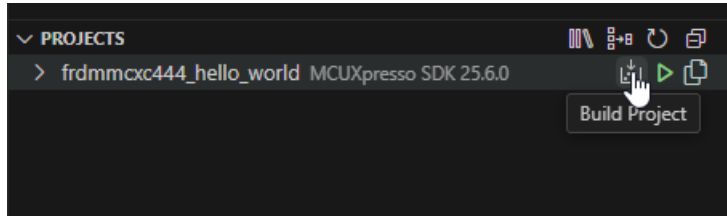
- Imported to user-defined location
- Independent of SDK location

**Trust Confirmation** VS Code will prompt you to confirm if the imported files are trusted. Click **Yes** to proceed.

### Building Projects

## Build Process

1. Navigate to **PROJECTS** view
2. Find your project
3. Click the **Build Project** icon

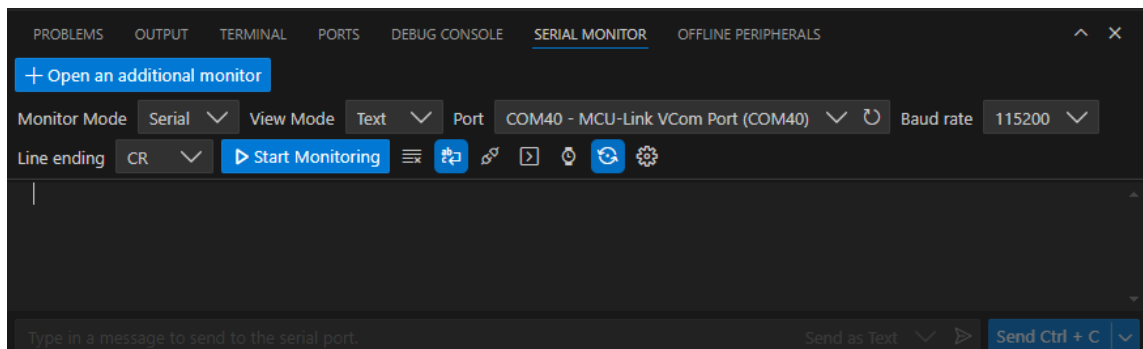


The integrated terminal will display build output at the bottom of the VS Code window.

## Running and Debugging

### Serial Monitor Setup

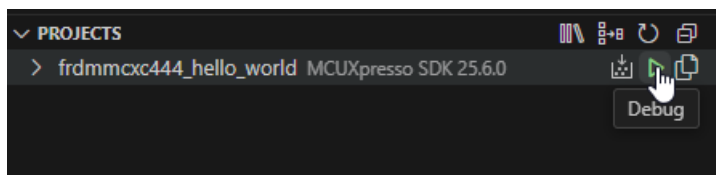
1. Open **Serial Monitor** from VS Code's integrated terminal



2. Configure serial settings:
  - **VCom Port:** Select port for your device
  - **Baud Rate:** Set to 115200

### Debug Session

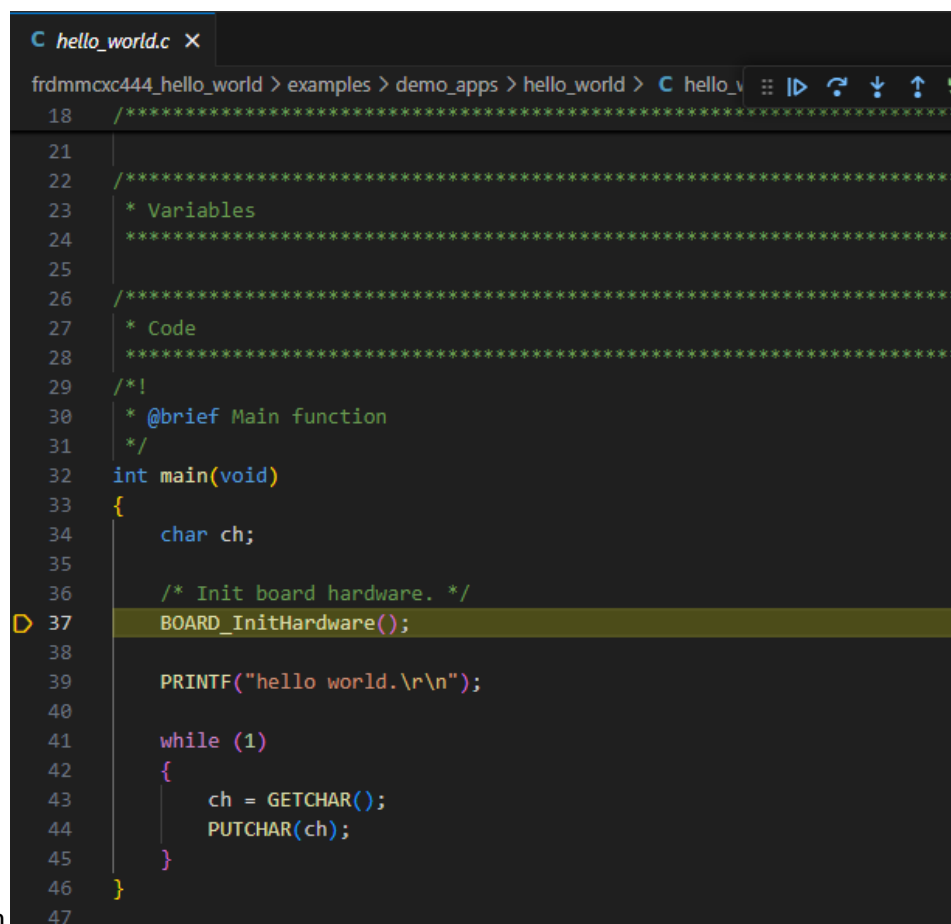
1. Navigate to **PROJECTS** view
2. Click the play button to initiate a debug session



The debug session will begin with debug controls initially at the top of the interface.

**Debug Controls** Use the debug controls to manage execution:

- **Continue:** Resume code execution
- **Step controls:** Navigate through code



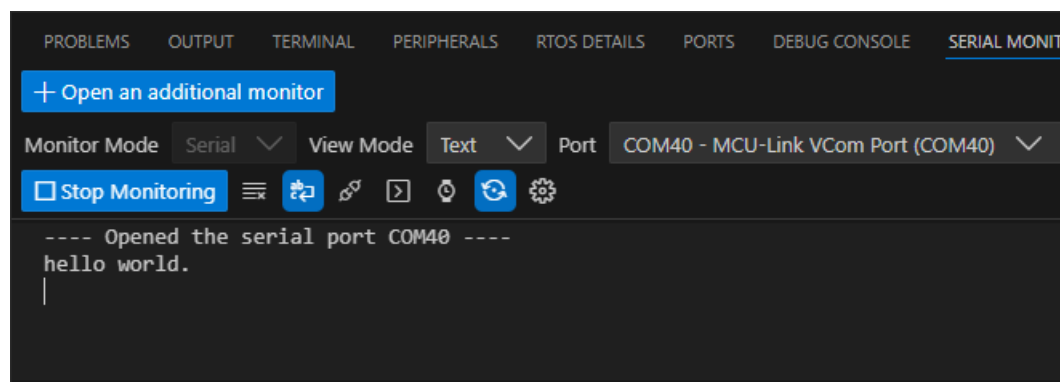
```

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

```

- **Stop:** Terminate debug session

**Monitor Output** Observe application output in the **Serial Monitor** to verify correct operation.



**Debug Probe Support** For comprehensive information on debug probe support and configuration, refer to the [MCUXpresso for VS Code Wiki DebugK](#) section.

## Project Configuration

**Workspace Management** The extension integrates with the MCUXpresso SDK workspace structure, providing access to:

- Example applications
- Board configurations

- Middleware components
- Build system integration

**Multi-Project Support** The PROJECTS view allows management of multiple imported projects within the same workspace.

## Troubleshooting

### Import Issues SDK not detected:

- Verify SDK workspace is properly initialized
- Ensure all required repositories are updated
- Check SDK manifest files are present

### Project import failures:

- Confirm board support exists for selected example
- Verify toolchain installation
- Check example compatibility with selected board

### Build Problems Build failures:

- Check integrated terminal for error messages
- Verify all dependencies are installed
- Ensure toolchain is properly configured

### Debug Issues Debug session fails:

- Verify board connection via USB
- Check debug probe drivers are installed
- Confirm build completed successfully

### Serial monitor problems:

- Verify correct VCom port selection
- Check baud rate configuration (115200)
- Ensure board drivers are installed

**Integration with Command Line** MCUXpresso for VS Code integrates with the underlying west build system, allowing seamless integration with command line workflows described in [Command Line Development](#).

## Advanced Features

**Project Types** The extension supports both repository-based and freestanding project types, providing flexibility in project organization and SDK integration.

**Build System Integration** The extension leverages the MCUXpresso SDK build system, providing access to all build configurations and options available through command line tools.

### Next Steps

- Explore additional examples in the SDK
- Review [Command Line Development](#) for advanced build options
- Refer [MCUXpresso for VS Code Wiki](#) for detailed documentation
- Learn about [SDK Architecture](#) for better understanding of the development environment

**Command Line Development** This guide covers developing with the MCUXpresso SDK using command line tools and the west build system. This workflow applies to both GitHub Repository SDK and Repository-Layout SDK Package distributions.

### Prerequisites

- GitHub Repository SDK workspace initialized OR Repository-Layout SDK Package extracted
- Development tools installed per [Installation Guide](#)
- Target board connected via USB

**Understanding Board Support** Use the west extension to discover available examples for your board:

```
west list _project -p examples/demo_apps/hello_world
```

This shows all supported build configurations. You can filter by toolchain:

```
west list _project -p examples/demo_apps/hello_world -t armgcc
```

### Basic Build Commands

**Standard Build Process** Build with default settings (armgcc toolchain, first debug config):

```
west build -b your_board examples/demo_apps/hello_world
```

### Specifying Build Configuration

```
# Release build
west build -b your_board examples/demo_apps/hello_world --config release

# Debug build with specific toolchain
west build -b your_board examples/demo_apps/hello_world --toolchain iar --config debug
```

**Multicore Applications** For multicore devices, specify the core ID:

```
west build -b evkbmimxrt1170 examples/demo_apps/hello_world --toolchain iar -Dcore_id=cm7 --config ↵
↵ flexspi_nor_debug
```

For multicore projects using sysbuild:



```
west build -b evkbmimxrt1170 --sysbuild ./examples/multicore_examples/hello_world/primary -Dcore_
↪id=cm7 --config flexspi_nor_debug --toolchain=armgcc -p always
```

**Shield Support** For boards with shields:

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

## Advanced Build Options

**Clean Builds** Force a complete rebuild:

```
west build -b your_board examples/demo_apps/hello_world -p always
```

**Dry Run** See what commands would be executed:

```
west build -b your_board examples/demo_apps/hello_world --dry-run
```

**Device Variants** For boards supporting multiple device variants:

```
west build -b your_board examples/demo_apps/hello_world --device MK22F12810 --config release
```

## Project Configuration

**CMake Configuration Only** Run configuration without building:

```
west build -b evkbmimxrt1170 examples/demo_apps/hello_world -Dcore_id=cm7 --cmake-only -p
```

**Interactive Configuration** Launch the configuration GUI:

```
west build -t guiconfig
```

## Flashing and Debugging

**Flash Application** Flash the built application to your board:

```
west flash -r linkserver
```

**Debug Session** Start a debugging session:

```
west debug -r linkserver
```

**IDE Project Generation** Generate IDE project files for traditional IDEs:

```
# Generate IAR project
west build -b evkbmimxrt1170 examples/demo_apps/hello_world --toolchain iar -Dcore_id=cm7 --config_
↪ flexspi_nor_debug -p always -t guiproject
```

IDE project files are generated in `mcuxsdk/build/<toolchain>` folder.

**Note:** Ruby installation is required for IDE project generation. See [Installation Guide](#) for setup instructions.

## Troubleshooting

**Build Failures** Use pristine builds to resolve dependency issues:

```
west build -b your_board examples/demo_apps/hello_world -p always
```

**Toolchain Issues** Verify environment variables are set correctly:

```
# Check ARM GCC
echo $ARMGCC_DIR
arm-none-eabi-gcc --version

# Check IAR (if using)
echo $IAR_DIR
```

**Getting Help** Display help information:

```
west build -h
west flash -h
west debug -h
```

**Check Supported Configurations** If unsure about supported options for an example:

```
west list_project -p examples/demo_apps/hello_world
```

## Best Practices

### Project Organization

- Keep custom projects outside the SDK tree
- Use version control for your application code
- Document any SDK modifications

### Build Efficiency

- Use `-p always` for clean builds when troubleshooting
- Leverage `--dry-run` to understand build processes
- Use specific configs and toolchains to reduce build time

## Development Workflow

1. Start with existing examples closest to your requirements
2. Copy and modify rather than building from scratch
3. Test with hello\_world before moving to complex examples
4. Use configuration tools for pin muxing and clock setup

## Next Steps

- Explore [VS Code Development](#) for integrated development experience
- Review [Workspace Structure](#) to understand SDK organization
- Refer build system documentation for advanced configurations

**Using MCUXpresso Config Tools** MCUXpresso Config tools provide a user-friendly way to configure hardware initialization of your projects. This guide explains the basic workflow with the MCUXpresso SDK west build system and the Config Tools.

## Prerequisites

- GitHub Repository SDK workspace initialized OR Repository-Layout SDK Package extracted
- MCUXpresso Config Tools standalone installed (version 25.09 or above)
- MCUXpresso SDK Project that can be successfully built

**Board Files** MCUXpresso Config Tools generate source files for the board. These files include pin\_mux.c/h and clock\_config.c/h. The files contain initialization code functions that reflect the hardware configuration in the Config Tools. Within the SDK codebase, these files are specific for the board and either shared by multiple example projects or specific for one example. Open or import the configuration from the SDK project in the Config Tools and customize the settings to match the custom board or specific project use case and regenerate the code. See *User Guide for MCUXpresso Config Tools (Desktop)* (document [GSMCUXCTUG](#)) for details.

**Note:** When opening the configuration for SDK example projects, the board files may be shared across multiple examples. To ensure a separate copy of the board configuration files exists, create a freestanding project with copied board files.

**Visual Studio Code** To open the configuration in Visual Studio Code, use the context menu for the project to access Config Tools. See [MCUXpresso Extension Documentation](#) for details. Otherwise, use the manual workflow described in detail in the following section.

**Manual Workflow** Use the following steps:

1. Before using Config Tools, run the west command to get the project information for Config Tools from the SDK project files, for example:

```
west cfg_project_info -b lpcxpresso55s69 ...mcuxsdk/examples/demo_apps/hello_world/ -Dcore_
↪ id=cm33_core0
```

This results in the creation of the project information json file that is searched by the config tools when the configuration is created. The parameters of the command should match the build parameters that will be used for the project.

2. Launch the MCUXpresso Config Tools and in the **Start development** wizard, select **Create a new configuration based on the existing IDE/Toolchain project**. Select the created “cfg\_tools” subfolder as a project folder (for example: ...mcuxsdk/examples/demo\_apps/hello\_world/cfg\_tools/).

**Updating the SDK West project** **Note:** Updating project is supported with Config Tools V25.12 or newer only.

Changes in the Config tools generated source code modules may require adjustments to the toolchain project to ensure a successful build. These changes may mean, for example, adding the newly generated files, adding include paths, required drivers, or other SDK components. This section describes how to manually resolve the changes needed in the project within the toolchain projects based on the SDK project managed by the West tool.

After the configuration in the Config Tools is finished, write updated files to the disk using the ‘Update Code’ command. The written files include a json file with the required changes for the toolchain project.

To resolve the changes in the project in the terminal, launch the west command that updates the project. For example:

```
west cfg_resolve -b lpcxpresso55s69 ...mcuxsdk/examples/demo_apps/hello_world/ -Dcore_id=cm33_core0
```

This command updates the appropriate cmake and kconfig files to address the changes. After this, the application can be built.

**Note:** The `cfg_resolve` command supports additional arguments. Launch the `west cfg_resolve -h` command to get the list and description.

## 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.

- IAR Embedded Workbench for Arm, version is 9.60.4
- MCUXpresso for VS Code v25.09
- 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
<b>IMX943-EVK</b>	<b>MIMX94398AVKM</b> , MIMX94398AVMM, MIMX94398CVKM, MIMX94398CVMM, MIMX94398DVKM, MIMX94398DVMM, MIMX94398XVKM, MIMX94398XVMM

## 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.

**USB Type-C PD Stack** See the *MCUXpresso SDK USB Type-C PD Stack User's Guide* (document MCUXSDKUSBPDUG) for more information

**USB Host, Device, OTG Stack** See the *MCUXpresso SDK USB Stack User's Guide* (document MCUXSDKUSBSUG) for more information.

**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”.

**FreeModbus** FreeModbus Library

**Simple Open EtherCAT Master** Simple Open EtherCAT Master (SOEM) is an open source EtherCAT master stack that is used to write custom EtherCAT Master applications. For more information on how to use SOEM, see the *Getting Started with MCUXpresso SDK for SOEM* document.

**Motor Control Software (ACIM, BLDC, PMSM)** Motor control examples.

**Multicore** Multicore Software Development Kit

**lwIP** The lwIP TCP/IP stack is pre-integrated with MCUXpresso SDK and runs on top of the MCUXpresso SDK Ethernet driver with Ethernet-capable devices/boards.

For details, see the *lwIP TCP/IP Stack and MCUXpresso SDK Integration User's Guide* (document MCUXSDKLWIPUG).

lwIP is a small independent implementation of the TCP/IP protocol suite.

**llhttp** HTTP parser llhttp

**FreeMASTER** FreeMASTER communication driver for 32-bit platforms.

## 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.

### SEGGER J-Link debugger usage problem

When an M core software is already running, it is possible to get HardFault or data verification issue during loading image into TCM by debugger.

The following steps are recommended to use the J-Link debugger.

1. Configure switch SW1301 to M core boot; low-power boot. Ensure that there is no image on the boot source.
2. Power the board and start the debugger for use.
3. To restart the debugger, stop the debugger, power off the board, and repeat step 2.

### Failed to get temperature from temp\_ana

**Issue Description** Failed to get data from sensor after selecting temp\_ana (index 0) sensor when the demo temperature\_measurement is running.

### Reference

Ticket	Description	Version
MCUX-80597	Failed to get data from sensor after selecting temp_ana (index 0) sensor	25.06.00

#### Sar\_adc trigger not enabled

**Issue Description** Sar\_adc cannot be triggered due to FSL\_FEATURE\_ADC\_HAS\_EXTERNAL\_TRIGGER not enabled in i.mx943.

### Reference

Ticket	Description	Version
MCUX-80565	[adc_polling_trigger] the app will block after press any key	25.06.00

#### LPUART trigger no output

**Issue Description** There is no output after LPUART being triggered due to wrong pin mux configuration for lpuart12 on i.mx943.

### Reference

Ticket	Description	Version
MCUX-80622	[lpuart_polling_trigger] no logs after flashing	25.06.00

## 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
- 

### AOI

#### [2.0.2]

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

#### [2.0.1]

- Bug Fixes
  - MISRA C-2012 issue fixed: rule 10.8, 2.2.

#### [2.0.0]

- Initial version.
- 

### BBNSM

#### [2.0.0]

- Initial version.
- 

### BiSS

#### [1.0.2]

- Bug Fixes
  - Fixed freqMADiv and freqAGSDiv setting

#### [1.0.1]

- Bug Fixes
  - Fixed coverity issues

#### [1.0.0]

- Initial version.
-

## CACHE ARMv7-M7

### [2.0.5]

- Bug Fixes
  - Fixed cache operations to handle zero size and overflow in invalidate/clean functions

### [2.0.4]

- Bug Fixes
  - Fixed doxygen issue.

### [2.0.3]

- Improvements
  - Deleted redundancy code about calculating cache clean/invalidate size and address aligns.

### [2.0.2]

- Bug Fixes
  - Fixed violation of MISRA C-2012 Rule 10.1, 10.3 and 10.4.

### [2.0.1]

- Bug Fixes
  - Fixed cache size issue in L2CACHE\_GetDefaultConfig API.

### [2.0.0]

- Initial version.
- 

## CACHE XCACHE

### [2.0.4]

- Improvements
  - Add memory barrier when enabling/disabling cache.

### [2.0.3]

- Bug Fixes
  - Fixed CERT INT30-C violations.

### [2.0.2]

- Bug Fixes
  - Updated `XCACHE_InvalidateCacheByRange()`, `XCACHE_CleanCacheByRange()`, `XCACHE_CleanInvalidateCacheByRange()` in case of startAddr equal to endAddr.

**[2.0.1]**

- Improvements
  - Check input parameter “size\_byte” must be larger than 0.

**[2.0.0]**

- Initial version.
- 
- 

**COMMON****[2.6.3]**

- Bug Fixes
  - Fixed build issue of CMSIS PACK BSP example caused by CMSIS 6.1 issue.

**[2.6.2]**

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule for implicit conversions in boolean contexts

**[2.6.1]**

- Improvements
  - Support Cortex M23.

**[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 irq's 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 stddef.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.
- 

## DCIF

### [2.1.0]

- Improvements
  - Support background layer 0.

**[2.0.0]**

- Initial version.
- 

**ECAT****[2.0.1]**

- Fix Coverity warning
  - CID: 41891133
  - CID: 41897853

**[2.0.0]**

- Initial version.
- 

**EDMA****[2.10.9]**

- Bug Fixes
  - Add new api EDMA\_TcdInit to avoid destroying code logic by reordering blocks in the toolchain.

**[2.10.8]**

- Bug Fixes
  - Fixed coverity issues with CERT INT30-C, CERT INT31-C compliance.
  - Fixed incorrect enabling of preemption capability issue.

**[2.10.7]**

- Improvements
  - Add condition to fix build warnings(array subscript 4 is above array bounds of 'edma\_handle\_t \*[4][64]')
- Bug Fixes
  - Fixed the EDMA header index retrieval error caused by done bit calculation mistake issue.

**[2.10.6]**

- Improvements
  - Add macro FSL\_FEATURE\_EDMA\_HAS\_EDMA\_TCD\_CLOCK\_ENABLE to enable tcd clocks in EDMA\_Init function.

#### [2.10.5]

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

#### [2.10.4]

- Improvements
  - Add new MP register macros to ensure compatibility with different devices.
  - Add macro DMA\_CHANNEL\_ARRAY\_STEPn to adapt to complex addressing of edma tcd registers.

#### [2.10.3]

- Bug Fixes
  - Clear interrupt status flags in EDMA\_CreateHandle to avoid triggering interrupt by mistake.

#### [2.10.2]

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

#### [2.10.1]

- Bug Fixes
  - Fixed EDMA\_GetRemainingMajorLoopCount may return wrong value issue.
  - Fixed violations of the MISRA C-2012 rules 13.5, 10.4.

#### [2.10.0]

- Improvements
  - Modify the structures edma\_core\_mp\_t, edma\_core\_channel\_t, edma\_core\_tcd\_t to adapt to edma5.
  - Add TCD register macro to facilitate confirmation of tcd type.
  - Modify the mask macro to a fixed value.
  - Add EDMA\_TCD\_TYPE macro to determine edma tcd type.
  - Add extension API to the following API to determine edma tcd type.
    - \* EDMA\_ConfigChannelSoftwareTCD -> EDMA\_ConfigChannelSoftwareTCDExt
    - \* EDMA\_TcdReset -> EDMA\_TcdResetExt
    - \* EDMA\_TcdSetTransferConfig -> EDMA\_TcdSetTransferConfigExt
    - \* EDMA\_TcdSetMinorOffsetConfig -> EDMA\_TcdSetMinorOffsetConfigExt
    - \* EDMA\_TcdSetChannelLink -> EDMA\_TcdSetChannelLinkExt
    - \* EDMA\_TcdSetBandWidth -> EDMA\_TcdSetBandWidthExt
    - \* EDMA\_TcdSetModulo -> EDMA\_TcdSetModuloExt
    - \* EDMA\_TcdEnableAutoStopRequest -> EDMA\_TcdEnableAutoStopRequestExt



- \* `EDMA_TcdEnableInterrupts` -> `EDMA_TcdEnableInterruptsExt`
- \* `EDMA_TcdDisableInterrupts` -> `EDMA_TcdDisableInterruptsExt`
- \* `EDMA_TcdSetMajorOffsetConfig` -> `EDMA_TcdSetMajorOffsetConfigExt`

#### [2.9.2]

- Improvements
  - Remove tcd alignment check in API that is low level and does not necessarily use scatter/gather mode.

#### [2.9.1]

- Bug Fixes
  - Deinit channel request source before set channel mux.

#### [2.9.0]

- Improvements
  - Release peripheral from reset if necessary in init function.
- Bug Fixes
  - Fixed the variable type definition error issue.
  - Fixed doxygen warning.
  - Fixed violations of MISRA C-2012 rule 18.1.

#### [2.8.1]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.3

#### [2.8.0]

- Improvements
  - Added feature `FSL_FEATURE_EDMA_HAS_NO_CH_SBR_SEC` to separate DMA without SEC bitfield.

#### [2.7.1]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.3, 10.4, 11.6, 11.8, 14.3,.

#### [2.7.0]

- Improvements
  - Use more accurate DMA instance based feature macros.
- New Features
  - Add new APIs `EDMA_PrepareTransferTCD` and `EDMA_SubmitTransferTCD`, which support EDMA transfer using TCD.

#### [2.6.0]

- Improvements
  - Modify the type of parameter channelRequestSource from dma\_request\_source\_t to int32\_t in the EDMA\_SetChannelMux.

#### [2.5.3]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.3, 10.4, 11.6, 20.7, 12.2, 20.9, 5.3, 10.8, 8.4, 9.3.

#### [2.5.2]

- Improvements
  - Applied ERRATA 51327.

#### [2.5.1]

- Bug Fixes
  - Fixed the EDMA\_ResetChannel function cannot reset channel DONE/ERROR status.

#### [2.5.0]

- Improvements
  - Added feature FSL\_FEATURE\_EDMA\_HAS\_NO\_SBR\_ATTR\_BIT to separate DMA without ATTR bitfield.
  - Added api EDMA\_GetChannelSystemBusInformation to gets the channel identification and attribute information on the system bus interface.
- Bug Fixes
  - Fixed the ESG bit not set in scatter gather mode issue.
  - Fixed the DREQ bit configuration missed in single transfer issue.
  - Cleared the interrupt status before invoke callback to avoid miss interrupt issue.
  - Removed disableRequestAfterMajorLoopComplete from edma\_transfer\_config\_t structure as driver will handle it.
  - Fixed the channel mux configuration not compatible issue.
  - Fixed the out of bound access in function EDMA\_DriverIRQHandler.

#### [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.

#### [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.
- 

### EnDat2.2

#### [1.0.1]

- Bug Fixes
  - Fixed coverity issues

#### [1.0.0]

- Initial version.
-

## ENDAT3

### [2.0.0]

- Initial version.

### [2.0.1]

- Add Daisy Chain support.
- 

## EQDC

### [2.3.1]

- Bug Fix
- Fixed CTRL2[CMODE] field overwritten in API EQDC\_Init.

### [2.3.0]

- Improvements
- Add feature macro to support platforms which do not have compare interrupt.

### [2.2.3]

- Bug Fix
- Clear Revolution Counter Register(REV) in init function to prevent its value not equal to zero after reset.

### [2.2.2]

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

### [2.2.1]

- Bug Fix
- Fixed violations of the MISRA C-2012 rules 20.9.

### [2.2.0]

- New features
- Supported the feature that the position counter to be initialized by Index Event Edge Mark.

#### [2.1.0]

- Bug Fix
- Fixed typo in interrupt enumeration values.
  - Improvements
- Supported Count Direct Change interrupt.
- Removed unused parameter in user configuration.
- Supported ERRATA\_051383 check, the CTRL[DMAEN] can't be cleared.

#### [2.0.1]

- Bug Fix
- Fixed violations of the MISRA C-2012 rules 10.3, 10.6, 10.8, 14.4, 16.4.

#### [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.
-



## FLEXCAN

### [2.14.5]

- Improvements
  - Make API FLEXCAN\_GetFDMailboxOffset **public**.
  - Add API FLEXCAN\_SetMbID and FLEXCAN\_SetFDMbID to configure Message Buffer ID individually.
- Bug Fixes
  - Fixed violations of the CERT INT30-C INT31-C.
  - Fixed violations of the CERT ARR30-C.

### [2.14.4]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 8.4, 10.1, 10.4, 18.1.

### [2.14.3]

- Improvements
  - Add unhandled interrupt events check for following API:
    - \* FLEXCAN\_MbHandleIRQ
    - \* FLEXCAN\_EhancedRxFifoHandleIRQ
- Bug Fixes
  - Remove FLEXCAN\_MemoryErrorHandleIRQ on some platform without memory error interrupt.
  - Add conditional compile for CTRL2[ISOCANFDEN] because some platform do not have this bit.

### [2.14.2]

- Improvements
  - Add Coverage Justification for uncovered code.
  - Adjust API FLEXCAN\_TransferAbortReceive **order**.
  - Update FLEXCAN\_Enable to enter Freeze Mode first when enter Disable mode on some platform.
  - Added while loop timeout for following API:
    - \* FLEXCAN\_EnterFreezeMode
    - \* FLEXCAN\_ExitFreezeMode
    - \* FLEXCAN\_Enable
    - \* FLEXCAN\_Reset
    - \* FLEXCAN\_TransferSendBlocking
    - \* FLEXCAN\_TransferReceiveBlocking
    - \* FLEXCAN\_TransferFDSendBlocking
    - \* FLEXCAN\_TransferFDReceiveBlocking

- \* FLEXCAN\_TransferReceiveFifoBlocking
- \* FLEXCAN\_TransferReceiveEnhancedFifoBlocking
- Bug Fixes
  - Remove remote frame feature in CANFD mode because there is no remote frame in the CANFD format.
  - Remove legacy Rx FIFO disabled branch in FLEXCAN\_SubHandlerForLegacyRxFIFO and FLEXCAN\_SubHandlerForDataTransferred.

#### [2.14.1]

- Bug Fixes
  - Fixed register IMASK2-4 IFLAG2-4 HR\_TIME\_STAMP<sub>n</sub> access issue on FlexCAN instances with different number of MBs.
  - Fixed bit field MBDSR1-3 access issue on FlexCAN instances with different number of MBs.
- Improvements
  - Unified following API as same parameter and return value type:
    - \* FLEXCAN\_GetMbStatusFlags
    - \* FLEXCAN\_ClearMbStatusFlags
    - \* FLEXCAN\_EnableMbInterrupts
    - \* FLEXCAN\_DisableMbInterrupts
  - Add workaround for ERR050443 and ERR052403.
  - Update message buffer read process in API FLEXCAN\_ReadRxMb and FLEXCAN\_ReadFDRxMb to make critical section as short as possible.
  - Simplify API FLEXCAN\_DriverDataIRQHandler implementation by remove parameter type.

#### [2.14.0]

- Improvements
  - Support external time tick feature.
  - Support high resolution timestamp feature.
  - Enter Freeze Mode first when enter Disable Mode on some platform.
  - Add feature macro for Pretended Networking because some FlexCAN instance do not have this feature.
  - Add feature macro for enhanced Rx FIFO because some FlexCAN instance do not have this feature.
  - Add new FlexCAN IRQ Handler FLEXCAN\_DriverDataIRQHandler and FLEXCAN\_DriverEventIRQHandler. These IRQ Handlers are used on soc which FlexCAN interrupts are grouped by specific function and assigned to different vector.
  - Update macro FLEXCAN\_WAKE\_UP\_FLAG and FLEXCAN\_PNWAKE\_UP\_FLAG to simplify code.
  - Replace macro FSL\_FEATURE\_FLEXCAN\_HAS\_NO\_WAKMSK\_SUPPORT with FSL\_FEATURE\_FLEXCAN\_HAS\_NO\_SLFWAK\_SUPPORT.

- Replace macro `FSL_FEATURE_FLEXCAN_HAS_NO_WAKSRC_SUPPORT` with `FSL_FEATURE_FLEXCAN_HAS_GLITCH_FILTER`.
- Bug Fixes
  - Fixed wrong interrupt and status flag helper macro in enumeration `_flexcan_flags` and API `FLEXCAN_DisableInterrupts`.
  - Fixed interrupt flag helper macro typo issue.
  - Remove flags which will be unassociated with interrupt in macro `FLEXCAN_MEMORY_ERROR_INT_FLAG`.
  - Remove flags which will be unassociated with interrupt in macro `FLEXCAN_ERROR_AND_STATUS_INT_FLAG`.
  - Fixed array out-of-bounds access when read enhanced Rx FIFO.

#### [2.13.1]

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

#### [2.13.0]

- Improvements
  - Support payload endianness selection feature.

#### [2.12.0]

- Improvements
  - Support automatic Remote Response feature.
  - Add API `FLEXCAN_SetRemoteResponseMbConfig()` to configure automatic Remote Response mailbox.

#### [2.11.8]

- Improvements
  - Synchronize flexcan driver update on s32z platform.

#### [2.11.7]

- Bug Fixes
  - Fixed `FLEXCAN_TransferReceiveEnhancedFifoEDMA()` compatibility with edma5.

#### [2.11.6]

- Bug Fixes
  - Fixed ERRATA\_9595 `FLEXCAN_EnterFreezeMode()` may result to bus fault on some platform.

#### [2.11.5]

- Bug Fixes
  - Fixed flexcan\_memset() crash under high optimization compilation.

#### [2.11.4]

- Improvements
  - Update CANFD max bitrate to 10Mbps on MCXNx3x and MCXNx4x.
  - Release peripheral from reset if necessary in init function.

#### [2.11.3]

- Bug Fixes
  - Fixed FLEXCAN\_TransferReceiveEnhancedFifoEDMA() compile error with DMA3.

#### [2.11.2]

- Bug Fixes
  - Fixed bug that timestamp in flexcan\_handle\_t not updated when RX overflow happens.

#### [2.11.1]

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

#### [2.11.0]

- Bug Fixes
  - Fixed wrong base address argument in FLEXCAN2 IRQ Handler.
- Improvements
  - Add API to determine if the instance supports CAN FD mode at run time.

#### [2.10.1]

- Bug Fixes
  - Fixed HIS CCM issue.
  - Fixed RTOS issue by adding protection to read-modify-write operations on interrupt enable/disable API.

#### [2.10.0]

- Improvements
  - Update driver to make it able to support devices which has more than 64 8bytes MBs.
  - Update CAN FD transfer APIs to make them set/get edl bit according to frame content, which can make them compatible with classic CAN.

### [2.9.2]

- Bug Fixes
  - Fixed the issue that FLEXCAN\_CheckUnhandleInterruptEvents() can't detecting the exist enhanced RX FIFO interrupt status.
  - Fixed the issue that FLEXCAN\_ReadPNWakeUpMB() does not return fail even no existing valid wake-up frame.
  - Fixed the issue that FLEXCAN\_ReadEnhancedRxFifo() may clear bits other than the data available bit.
  - Fixed violations of the MISRA C-2012 rules 10.4, 10.8.
- Improvements
  - Return kStatus\_FLEXCAN\_RxFifoDisabled instead of kStatus\_Fail when read FIFO fail during IRQ handler.
  - Remove unreachable code from timing calculates APIs.
  - Update Enhanced Rx FIFO handler to make it deal with underflow/overflow status first.

### [2.9.1]

- Bug Fixes
  - Fixed the issue that FLEXCAN\_TransferReceiveEnhancedFifoBlocking() API clearing Fifo data available flag more than once.
  - Fixed the issue that entering FLEXCAN\_SubHandlerForEnhancedRxFifo() even if Enhanced Rx fifo interrupts are not enabled.
  - Fixed the issue that FLEXCAN\_TransferReceiveEnhancedFifoEDMA() update handle even if previous Rx FIFO receive not finished.
  - Fixed the issue that FLEXCAN\_SetEnhancedRxFifoConfig() not configure the ERFCR[NFE] bits to the correct value.
  - Fixed the issue that FLEXCAN\_ReceiveFifoEDMACallback() can't differentiate between Rx fifo and enhanced rx fifo.
  - Fixed the issue that FLEXCAN\_TransferHandleIRQ() can't report Legacy Rx FIFO warning status.

### [2.9.0]

- Improvements
  - Add public set bit rate API to make driver easier to use.
  - Update Legacy Rx FIFO transfer APIs to make it support received multiple frames during one API call.
  - Optimized FLEXCAN\_SubHandlerForDataTransferred() API in interrupt handling to reduce the probability of packet loss.

### [2.8.7]

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

#### [2.8.6]

- Bug Fixes
  - Fix Coverity overrun issues in fsl\_flexcan\_edma driver.

#### [2.8.5]

- Improvements
  - Make driver aarch64 compatible.

#### [2.8.4]

- Bug Fixes
  - Fixed FlexCan\_Errata\_6032 to disable all interrupts.

#### [2.8.3]

- Bug Fixes
  - Fixed an issue with the FLEXCAN\_EnableInterrupts and FLEXCAN\_DisableInterrupts interrupt enable bits in the CTRL1 register.

#### [2.8.2]

- Bug Fixes
  - Fixed errors in timing calculations and simplify the calculation process.
  - Fixed issue of CBT and FDCBT register may write failure.

#### [2.8.1]

- Bug Fixes
  - Fixed the issue of CAN FD three sampling points.
  - Added macro to support the devices that no MCR[SUPV] bit.
  - Remove unnecessary clear WMB operations.

#### [2.8.0]

- Improvements
  - Update config configuration.
    - \* Added enableSupervisorMode member to support enable/disable Supervisor mode.
  - Simplified the algorithm in CAN FD improved timing APIs.

#### [2.7.1]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.3, 10.7.

### [2.7.0]

- Improvements
  - Update config configuration.
    - \* Added enablePretendedNetworking member to support enable/disable Pretended Networking feature.
    - \* Added enableTransceiverDelayMeasure member to support enable/disable Transceiver Delay MeasurementPretended feature.
    - \* Added bitRate/bitRateFD member to work as baudRate/baudRateFD member union.
  - Rename all “baud” in code or comments to “bit” to align with the CAN spec.
  - Added Pretended Networking mode related APIs.
    - \* FLEXCAN\_SetPNConfig
    - \* FLEXCAN\_GetPNMatchCount
    - \* FLEXCAN\_ReadPNWakeUpMB
  - Added support for Enhanced Rx FIFO.
  - Removed independent memory error interrupt/status APIs and put all interrupt/status control operation into FLEXCAN\_EnableInterrupts/FLEXCAN\_DisableInterrupts and FLEXCAN\_GetStatusFlags/FLEXCAN\_ClearStatusFlags APIs.
  - Update improved timing APIs to make it calculate improved timing according to CiA doc recommended.
    - \* FLEXCAN\_CalculateImprovedTimingValues.
    - \* FLEXCAN\_FDCalculateImprovedTimingValues.
  - Update FLEXCAN\_SetBitRate/FLEXCAN\_SetFDBitRate to added the use of enhanced timing registers.

### [2.6.2]

- Improvements
  - Add CANFD frame data length enumeration.

### [2.6.1]

- Bug Fixes
  - Fixed the issue of not fully initializing memory in FLEXCAN\_Reset() API.

### [2.6.0]

- Improvements
  - Enable CANFD ISO mode in FLEXCAN\_FDInit API.
  - Enable the transceiver delay compensation feature when enable FD operation and set bitrate switch.
  - Implementation memory error control in FLEXCAN\_Init API.
  - Improve FLEXCAN\_FDCalculateImprovedTimingValues API to get same value for FPRESDIV and PRES DIV.
  - Added memory error configuration for user.

- \* enableMemoryErrorControl
- \* enableNonCorrectableErrorEnterFreeze
- Added memory error related APIs.
  - \* FLEXCAN\_GetMemoryErrorReportStatus
  - \* FLEXCAN\_GetMemoryErrorStatusFlags
  - \* FLEXCAN\_ClearMemoryErrorStatusFlags
  - \* FLEXCAN\_EnableMemoryErrorInterrupts
  - \* FLEXCAN\_DisableMemoryErrorInterrupts
- Bug Fixes
  - Fixed the issue of sent duff CAN frame after call FLEXCAN\_FDInit() API.

### [2.5.2]

- Bug Fixes
  - Fixed the code error issue and simplified the algorithm in improved timing APIs.
    - \* The bit field in CTRL1 register couldn't calculate higher ideal SP, we set it as the lowest one(75%)
      - FLEXCAN\_CalculateImprovedTimingValues
      - FLEXCAN\_FDCalculateImprovedTimingValues
  - Fixed MISRA-C 2012 Rule 17.7 and 14.4.
- Improvements
  - Pass EsrStatus to callback function when kStatus\_FLEXCAN\_ErrorStatus is coming.

### [2.5.1]

- Bug Fixes
  - Fixed the non-divisible case in improved timing APIs.
    - \* FLEXCAN\_CalculateImprovedTimingValues
    - \* FLEXCAN\_FDCalculateImprovedTimingValues

### [2.5.0]

- Bug Fixes
  - MISRA C-2012 issue check.
    - \* Fixed rules, containing: rule-10.1, rule-10.3, rule-10.4, rule-10.7, rule-10.8, rule-11.8, rule-12.2, rule-13.4, rule-14.4, rule-15.5, rule-15.6, rule-15.7, rule-16.4, rule-17.3, rule-5.8, rule-8.3, rule-8.5.
  - Fixed the issue that API FLEXCAN\_SetFDRxMbConfig lacks inactive message buff.
  - Fixed the issue of Pa082 warning.
  - Fixed the issue of dead lock in the function of interruption handler.
  - Fixed the issue of Legacy Rx Fifo EDMA transfer data fail in evkmimxrt1060 and evk-mimxrt1064.
  - Fixed the issue of setting CANFD Bit Rate Switch.



- Fixed the issue of operating unknown pointer risk.
  - \* when used the pointer “handle->mbFrameBuf[mbIdx]” to update the timestamp in a short-live TX frame, the frame pointer became as unknown, the action of operating it would result in program stack destroyed.
- Added assert to check current CAN clock source affected by other clock gates in current device.
  - \* In some chips, CAN clock sources could be selected by CCM. But for some clock sources affected by other clock gates, if user insisted on using that clock source, they had to open these gates at the same time. However, they should take into consideration the power consumption issue at system level. In RT10xx chips, CAN clock source 2 was affected by the clock gate of lpuart1. ERRATA ID: (ERR050235 in CCM).
- Improvements
  - Implementation for new FLEXCAN with ECC feature able to exit Freeze mode.
  - Optimized the function of interruption handler.
  - Added two APIs for FLEXCAN EDMA driver.
    - \* FLEXCAN\_PrepareTransfConfiguration
    - \* FLEXCAN\_StartTransferDatafromRxFIFO
  - Added new API for FLEXCAN driver.
    - \* FLEXCAN\_GetTimeStamp
      - For TX non-blocking API, we wrote the frame into mailbox only, so no need to register TX frame address to the pointer, and the timestamp could be updated into the new global variable handle->timestamp[mbIdx], the FLEXCAN driver provided a new API for user to get it by handle and index number after TX DONE Success.
    - \* FLEXCAN\_EnterFreezeMode
    - \* FLEXCAN\_ExitFreezeMode
  - Added new configuration for user.
    - \* disableSelfReception
    - \* enableListenOnlyMode
  - Renamed the two clock source enum macros based on CLKSRC bit field value directly.
    - \* The CLKSRC bit value had no property about Oscillator or Peripheral type in lots of devices, it acted as two different clock input source only, but the legacy enum macros name contained such property, that misled user to select incorrect CAN clock source.
  - Created two new enum macros for the FLEXCAN driver.
    - \* kFLEXCAN\_ClkSrc0
    - \* kFLEXCAN\_ClkSrc1
  - Deprecated two legacy enum macros for the FLEXCAN driver.
    - \* kFLEXCAN\_ClkSrcOsc
    - \* kFLEXCAN\_ClkSrcPeri
  - Changed the process flow for Remote request frame response..
    - \* Created a new enum macro for the FLEXCAN driver.
      - kStatus\_FLEXCAN\_RxRemote

- Changed the process flow for kFLEXCAN\_StateRxRemote state in the interrupt handler.
  - \* Should the TX frame not register to the pointer of frame handle, interrupt handler would not be able to read the remote response frame from the mail box to ram, so user should read the frame by manual from mail box after a complete remote frame transfer.

#### [2.4.0]

- Bug Fixes
  - MISRA C-2012 issue check.
    - \* Fixed rules, containing: rule-12.1, rule-17.7, rule-16.4, rule-11.9, rule-8.4, rule-14.4, rule-10.8, rule-10.4, rule-10.3, rule-10.7, rule-10.1, rule-11.6, rule-13.5, rule-11.3, rule-8.3, rule-12.2 and rule-16.1.
  - Fixed the issue that CANFD transfer data fail when bus baudrate is 30Khz.
  - Fixed the issue that ERR009595 does not follow the ERRATA document.
  - Fixed code error for ERR006032 work around solution.
  - Fixed the Coverity issue of BAD\_SHIFT in FLEXCAN.
  - Fixed the Repo build warning issue for variable without initial.
- Improvements
  - Fixed the run fail issue of FlexCAN RemoteRequest UT Case.
  - Implementation all TX and RX transferring Timestamp used in FlexCAN demos.
  - Fixed the issue of UT Test Fail for CANFD payload size changed from 64BperMB to 8PerMB.
  - Implementation for improved timing API by baud rate.

#### [2.3.2]

- Improvements
  - Implementation for ERR005959.
  - Implementation for ERR005829.
  - Implementation for ERR006032.

#### [2.3.1]

- Bug Fixes
  - Added correct handle when kStatus\_FLEXCAN\_TxSwitchToRx is coming.

#### [2.3.0]

- Improvements
  - Added self-wakeup support for STOP mode in the interrupt handling.

#### [2.2.3]

- Bug Fixes
  - Fixed the issue of CANFD data phase's bit rate not set as expected.

**[2.2.2]**

- Improvements
  - Added a time stamp feature and enable it in the interrupt\_transfer example.

**[2.2.1]**

- Improvements
  - Separated CANFD initialization API.
  - In the interrupt handling, fix the issue that the user cannot use the normal CAN API when with an FD.

**[2.2.0]**

- Improvements
  - Added FSL\_FEATURE\_FLEXCAN\_HAS\_SUPPORT\_ENGINE\_CLK\_SEL\_REMOVE feature to support SoCs without CAN Engine Clock selection in FlexCAN module.
  - Added FlexCAN Serial Clock Operation to support i.MX SoCs.

**[2.1.0]**

- Bug Fixes
  - Corrected the spelling error in the function name FLEXCAN\_XXX().
  - Moved Freeze Enable/Disable setting from FLEXCAN\_Enter/ExitFreezeMode() to FLEXCAN\_Init().
  - Corrected wrong helper macro values.
- Improvements
  - Hid FLEXCAN\_Reset() from user.
  - Used NDEBUG macro to wrap FLEXCAN\_IsMbOccupied() function instead of DEBUG macro.

**[2.0.0]**

- Initial version.
- 

**FLEXCAN\_EDMA****[2.12.1]**

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 18.1.

#### [2.12.0]

- Improvements
  - Support high resolution timestamp feature in enhanced Rx FIFO EDMA.
  - Add feature macro for enhanced Rx FIFO because some FlexCAN instance do not have this feature.
- Bug Fixes
  - Fixed array out-of-bounds access when read enhanced Rx FIFO in EDMA.

#### [2.11.7]

- Refer FLEXCAN driver change log 2.7.0 to 2.11.7
- 

### 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\_A-FORMAT****[1.0.0]**

- New Features
    - The polling mode was added to read or configure encoder data
    - The interrupt mode was added to read or configure encoder data
- 

**FLEXIO\_I2C****[2.6.2]**

- Improvements
  - Added timeout for while loop in FLEXIO\_I2C\_MasterTransferBlocking().
- Bug Fixes
  - Fixed build issues related to I2C\_RETRY\_TIMES.

#### [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

#### [2.4.3]

- Improvements
  - Make SPI\_RETRY\_TIMES configurable by CONFIG\_SPI\_RETRY\_TIMES.

#### [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\_T-FORMAT

#### [1.0.0]

- New Features
    - The polling mode was added to read or configure encoder data
    - The interrupt mode was added to read or configure encoder data
- 

### FLEXIO\_UART

#### [2.6.4]

- Improvements
  - Make UART\_RETRY\_TIMES configurable by CONFIG\_UART\_RETRY\_TIMES.

**[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
- 

**FRACT\_PLL****[2.0.0]**

- Initial version.
- 

**GPT****[2.0.6]**

- Bug Fixes
  - Fix CERT INT30-C issues.

**[2.0.5]**

- Improvements
  - Support workaround for ERR003777. This workaround helps switching the clock sources.

#### [2.0.4]

- Bug Fixes
  - Fixed compiler warning when built with FSL\_SDK\_DISABLE\_DRIVER\_CLOCK\_CONTROL flag enabled.

#### [2.0.3]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 5.3 by customizing function parameter.

#### [2.0.2]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 17.7.

#### [2.0.1]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.1, 10.3, 10.4, 10.6, 10.8, 17.7.

#### [2.0.0]

- Initial version.
- 

### HIPERFACE

#### [1.0.0]

- Initial version.
- 

### IGF

#### [2.0.0]

- Initial version.
- 
- 

### IRQSTEER

#### [2.0.1]

- Improvement
  - Initialize irqsteer defaultly, so users don't need to call api IRQSTEER\_Init to intialize irqsteer.



**[2.0.0]**

- Initial version.
- 

**LPI2C****[2.6.3]**

- Bug Fixes
  - Fixed static analysis identified issues.

**[2.6.2]**

- Improvements
  - Added timeout for while loop in LPI2C\_TransferStateMachineSendCommand().

**[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

### [2.4.6]

- Bug Fixes
  - Fixed static analysis identified issues.

**[2.4.5]**

- Improvements
  - Added condition to IRQ handler to check whether the interrupt is enabled - kLPI2C\_MasterTxReadyFlag.

**[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****[2.1.3]**

- Bug Fixes
  - Fixed doxygen generation warnings.

**[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.
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### LPSPPI

#### [2.7.4]

- Bug Fixes
  - Clear WIDTH bits from the TCR register before writing a new value in LPSPPI\_MasterTransferBlocking().

#### [2.7.3]

- Improvements
  - Added timeout for while loop in LPSPPI\_MasterTransferWriteAllTxData().
  - Make SPI\_RETRY\_TIMES configurable by CONFIG\_SPI\_RETRY\_TIMES.

#### [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\_LPSPI\_HAS\_NO\_PCSCFG and FSL\_FEATURE\_LPSPI\_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 LPSPIn\_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****[2.4.9]**

- Improvements
  - Removed unused code from LPSPI\_SeparateEdmaReadData().

**[2.4.8]**

- Improvements
  - Added timeout for while loop in EDMA\_LpspiMasterCallback() and EDMA\_LpspiSlaveCallback().

**[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 LP-SPI\_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 LP-SPI\_MasterTransferPrepareEDMA and LPSPI\_MasterTransferEDMALite to optimize the process of transfer.
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## 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****[2.10.0]**

- New Feature
  - Added support to configure RTS watermark.

**[2.9.4]**

- Improvements
  - Merged duplicate code.

### [2.9.3]

- Improvements
  - Added timeout for while loops in LPUART\_Deinit().

### [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.
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**LPUART\_EDMA****[2.4.0]**

- Refer LPUART driver change log 2.1.0 to 2.4.0
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**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.
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## MSGINTR

### [2.0.2]

- Improvements
  - Conditional compile IRQ handlers.

### [2.0.1]

- Bug Fixes
  - Fixed MISRA issue rule 8.4, 11.9, 17.7.

### [2.0.0]

- Initial version.
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## MU

### [2.8.1]

- Bug Fixes
  - Avoid incorrect MU\_BUSY\_POLL\_COUNT macro use.

### [2.8.0]

- New Features
  - Added MU1\_BUSY\_POLL\_COUNT parameter to prevent infinite polling loops in MU operations.
  - Added timeout mechanism to all polling loops in MU driver code.
- Improvements
  - Updated function signatures to return status codes for better error handling:
    - \* Changed MU\_ResetBothSides to return status\_t instead of void
    - \* Updated MU\_SendMsg to return status\_t for timeout indication
    - \* Added new function MU\_ReceiveMsgTimeout() to include timeout mechanism.
  - Enhanced documentation across all functions to clarify timeout behavior and return values.

### [2.7.0]

- New Features
  - Added API MU\_GetRxStatusFlags.

### [2.6.0]

- New Features
  - Added API MU\_GetInterruptsPending.

**[2.5.1]**

- Bug Fixes
  - Fixed the bug that MU\_TriggerGeneralPurposeInterrupts and MU\_TriggerInterrupts may trigger previous triggered general purpose interrupts again by mistake.

**[2.5.0]**

- New Features
  - Supported more than 4 general purpose interrupts.
  - Added separate APIs for general purpose interrupts.

**[2.4.0]**

- Improvements
  - Supported the case that some features only available with specific instances. These features include Hardware Reset, Boot Peer Core, Hold Reset. When using the features with instances which don't support them, driver will report error.

**[2.3.3]**

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

**[2.3.2]**

- Improvements
  - Supported platforms which don't have CCR0[RSTH], CCR0[CLKE], CCR0[HR], CCR0[HRM].

**[2.3.1]**

- Bug Fixes
  - Fixed build error for platforms which have CCR0[RSTH], but no CCR0[NMI].

**[2.3.0]**

- New features
  - Added support for i.MX RT7xx.

**[2.2.1]**

- Bug Fixes
  - Fixed issue that MU\_GetInstance() is defined but never used.

#### [2.2.0]

- New features
  - Added support for i.MX RT118x.
- Bug Fixes
  - Fixed general purpose interrupt bug.
- Other Changes
  - Change `_mu_interrupt_trigger` item value.

#### [2.1.2]

- Bug Fixes
  - Fixed bug that general purpose interrupt can't be configured.

#### [2.1.1]

- Bug Fixes
  - Fixed MISRA C-2012 issues.

#### [2.1.0]

- Improvements
  - Added new enum `mu_msg_reg_index_t`.

#### [2.0.0]

- Initial version.
- 

## NETC

#### [2.10.3]

- New Features
  - Supported `rrt` member in `netc_tb_ipf_cfge_t`.
  - Moved timer reference clock definition to soc to support i.MX95/i.MX943.
- Bug Fixes
  - Got right size of TX timestamp response frame.

#### [2.10.2]

- Bug Fixes
  - Correct transmit start time bit width of transmit buffer descriptor format.



### [2.10.1]

- New Features
  - Supported IP version class commands in VSI-PSI message driver.
  - Added VSI3 definition.

### [2.10.0]

- Bug Fixes
  - Fixed structures used for time gate control list and stream gate request commands memset.
- New Features
  - Added public API to query table entry in Frame Modification Table.
- Improvements
  - Optimized NETC Transmit functions: cached configuration in driver handle instead of accessing directly device registers at each packet transmit, and removed calls to memset/memcpy in the transmit path.

### [2.9.1]

- Improvements
  - NETC\_TimerInit() will always ignore user config->atomicMode and set it to 1 internally. This guarantees that period updates, that change both the integer and fractional part are always done atomically.

### [2.9.0]

- Bug Fixes
  - Fixed padding in netc\_tb\_sgi\_rsp\_data\_t union structure for query operations on OEXEN and IRXEN parameters.
  - Fixed structure use for rate policer and stream gate request commands memset.
  - Updated ERRATA 052134 to 052206.
  - Fixed MII mode setting.
  - Fixed i.MX943 getting function instance.
- New Features
  - Added API to Reset IRX and OEX flags in stream gate instance entry.
  - Added API to configure the priority to traffic class map.
  - Added APIs to query table entry and get maximum entry number for Frame Modification Table.
  - Added APIs to configure Frame preemption.
  - Added APIs to configure PSRCR and PGCR registers to implement HSR feature.
  - Moved PHY WRAPPER init sequence (NETC\_PHYInit) implementation to SoC. And Added i.MX943 support.
- Improvements
  - keep netc\_tb\_sgi\_rsp\_data\_t local to the low level driver functions for SGI table entry query.

- Converted to use preinitVsi callback for VSI pre-init.
- Added note for ERRATA 052167 to remind that actual MAC Tx IPG is longer than configured when transmitting back-to-back packets in MII half duplex. When using MII protocol, using full-duplex mode is recommended instead of half-duplex. If using MII half-duplex mode, additional bandwidth loss should be expected and accounted for due to extended IPG.

#### [2.8.2]

- Bug Fixes
  - Fixed ingress port filter table frame attribute flags mask field issue.

#### [2.8.1]

- Bug Fixes
  - Fixed MAC/VLAN filter operations through VSI-PSI message.
  - Fixed NETC\_PortConfigTxIpgPreamble compile.
- Improvements
  - Enabled standard VLAN EtherTypes for i.MX95 VSIs for VLAN support.
  - Added netc\_timer\_exttrig\_index\_t definition for i.MX95.
  - Updated default BPCR[STAMVD] value setting to align the register reset value.

#### [2.8.0]

- Bug Fixes
  - Fixed ERRATA 052024.
  - Fixed ERRATA 052129.
  - Fixed ERRATA 052134.
  - Fixed ERRATA 052031.
  - Fixed ERRATA 051994.
  - Fixed ERRATA 051936.
- New Features
  - Added interface to reset the mark frame red parameter.
  - Added support for FRER sequence generation reset.
  - Added NETC Switch Tag support.
  - Added the Tx offload feature support.
- Improvements
  - Simplify NETC\_TimerGetFreeRunningTime. Hardware synchronizes reads from high/low registers for the free running time. No need to do it in software.

#### [2.7.2]

- Bug Fixes
  - Fixed MISRA issue rule 4.10, 10.1, 10.3, 10.4, 10.7, 10.8, 11.3, 16.1, 16.4, 17.7.

**[2.7.1]**

- Bug Fixes
  - Fixed Coverity issue with array out of bounds access.

**[2.7.0]**

- New Features
  - Added VSI-PSI messaging driver.
- Bug Fixes
  - Fixed the issue that EP/SWT\_ReceiveFrame don't return error status when some errors occur.

**[2.6.1]**

- Bug Fixes
  - Updated the MAC loopback configuration as Reference Manual.

**[2.6.0]**

- New Features
  - Added API to get transmit max SDU for specified port Traffic Class.
  - Added API to query entry from the Rate Policing table.
  - Added API to retrieve maximum rate policer entries.
  - Added API to set switch port default VID separately.
  - Added API to set max frame size separately.
  - Added API to query FRER resource.
- Bug Fixes
  - Fixed the issue that stream gate query functions don't check return status.
  - Fixed the ISF table query function operation issue.
  - Fixed the wrong configuration of Tx max SDU check.
  - Fixed ERRATA 051524.
  - Fixed ERRATA 051649.
  - Fixed ERRATA 051707.
  - Fixed ERRATA 051710.
  - Fixed ERRATA 051711.
- Improvements
  - Factorized qbv basetime workaround code, and stop using synchronized time for the workaround code. Synchronized time functionality should be reserved for gPTP operation.

**[2.5.1]**

- Improvements
  - Conditional compile NETC\_ETH\_LINK\_PM0\_COMMAND\_CONFIG\_HD\_FCEN register.

### [2.5.0]

- New Features
  - Added PHY WRAPPER driver.
  - Added C45 support for internal MDIO.
  - Added 10G support.
- Bug Fixes
  - Fixed ERRATA 051130.
  - Fixed master bus and memory access.
- Improvements
  - Moved platform specific code to soc driver.
  - Split switch code.

### [2.4.0]

- New Features
  - Added the interrupt control functions for port MAC module.
  - Added setting parameters including half-duplex back pressure, port timestamp capture point, RGMII Tx clock stop state during low power idle, ports default traffic class gating states and timer atomic writing setting.
  - Added NETC\_TimerInitHandle() to initialize a timer handle without modifying hardware state. Required to be able to read timer from another CPU.
  - Added NETC\_TimerGetFreeRunningTime() to be able to read free running timer.
  - Added support for ingress stream gate query.
- Improvements
  - Added necessary default settings in the GetDefaultConfig functions in case some features can't work after initialization.
  - Updated loopback function according to new bit field in CRR.
  - Deleted the useless error check for ERRATA051243.
  - Updated NETC\_TimerGetCurrentTime() to avoid using synchronized time and be able to read the time from different threads/cpus without locking.
  - Deleted the useless priority check in NETC\_PortConfigTcCBS().
- Bug Fixes
  - Fixed typo in NETC\_PortConfig.

### [2.3.2]

- Bug Fixes
  - Added workaround for ERRATA051587.

### [2.3.1]

- Bug Fixes
  - Fixed MISRA issue rule 10.3, 10.4, 10.8, 11.6, 11.7.

### [2.3.0]

- Bug Fixes
  - Added SWT\_PortStop() API for ERRATA051398.
  - Fixed the build error by add feature macro for port FCS Error Action feature.
  - Removed duplicate code from NETC\_PortEthMacGracefulStop() API.
  - Fixed MISRA issue rule 8.6, 10.4, 11.9, 14.4.

### [2.2.2]

- Bug Fixes
  - Fixed the issue that NETC\_PortSetSpeed() would overwrite the full PCR register.

### [2.2.1]

- Improvements
  - Fixed cpp build warning.

### [2.2.0]

- Bug Fixes
  - Fixed the issue that NETC\_ConfigTGSAdminList() doesn't clear the previous command response data status filed.
  - Fixed the issue that EP\_ReceiveFrameCopy(&handle, 0, NULL, 0, NULL) can't drop error frame.
  - Fixed the issue that SWT\_GetTimestampRefResp can't get Switch Tx TS Resp with no MgmtRxBdRing.
  - Fixed the issue that RGMII Half Duplex mode misconfigured.
  - Fixed the issue that missing workaround for ERR050679, ERR051246 and ERR051254.
  - Fixed the issue that missing feature macro for ERR051130, ERR051202, ERR051260.
  - Fixed the issue that ep/swt\_tx\_opt struct use wrong vlan tag tpid value.
  - Fixed MISRA issue rule 5.8, 8.3, 8.12, 10.1, 10.3, 10.4, 10.6, 10.7, 10.8, 11.6, 11.8, 12.2, 14.4, 15.5, 15.6, 16.1, 16.3, 16.4, 17.7.
  - Fixed the issue that internal MDIO read function uses wrong register.
  - Fixed the issue that SWT\_TxPortTGSEnable()/EP\_TxPortTGSEnable() still uses the default timer after enabling the 1588 timer.
  - Remove the resetCount parameter from get port discard statistic APIs because the registers required by this function have been removed from hardware design.
  - Fixed the issue that SWT/EP\_ReclaimTxDesc() can't call reclaim callback for each full frame.
  - Fixed the issue in NETC\_TimerAdjustFreq().
- New Features
  - Added the support for 1588 One-Step timestamp when chip doesn't have ERR051255.
  - Added APIs to get dynamic table remaining available entry numbers.
  - Added APIs to get static table number of entries.

- Improvements
  - Return detail error status instead of `kStatus_Fail` in NTMP APIs.
  - Rename feature macros and move them into the feature file.
  - Optimize the implementation of the `NETC_TimerAddOffset()` function to avoid change the `TMR_CNT_L/H` registers, and add required procedure for call `NETC_TimerAddOffset()` API in the comments.
  - Update the `SWT_FMDUpdateTableEntry()/SWT_FMDQueryTableEntry()` APIs to make them use internal table buffer.
  - Update `SWT_TxPortTGSEnable()/EP_TxPortTGSEnable()` to make it can config the default administration gate control list gates' state.
  - Use `TMR_SRT_L/H` instead of `TMR_CUR_TIMER` when want to get current 1588 timer value.

## [2.1.0]

- Bug Fixes
  - Fixed the issue that `EP_RxL2MFINit` doesn't set the multicast promiscuous correctly.
  - Fixed the timer add offset issue.
  - Fixed the issue that all ENETC/Switch PCIe functions must be enabled firstly before triggering EP/SWT NTMP access and MSIX messages.
  - Fixed RT1180 NETC errata 051202: Configure Tx MAC to wait until 32 bytes of data are built up in the transmit FIFO before beginning transmission on the link.
  - Added workaround for RT1180 NETC errata 051130: C Egress time gate scheduling can get corrupted when functional level reset is applied or when time gating is disabled.
  - Fixed bugs in statistic APIs.
- New Features
  - Added the support for EP VSI transmission and PSI-VSI message exchanging.
  - Added EP receive regular frame zero-copy support.
  - Integrated EMDIO support in NETC MDIO driver for accessing PHY when EP/Switch function isn't enabled.
  - Added Timer and Switch MSIX table configuration support.
  - Added update entry APIs for IPF/VF/FDB/L2MCF/IS/ISF/SGI/RP/FM/ET/ISEQG tables, and search entry APIs for FDB/L2MCF table.
  - Added Ingress buffer pool table config APIs.
  - Added MAC Tx padding and Rx min/max frame size configuration to support Tx/Rx frames smaller than 64 bytes.
  - Added API to do graceful Stop for ETH MAC.
- Improvements
  - Used Rx buffer address array provided by application instead of buffer start address with contiguous memory to make the Rx buffer setup more flexible.
  - Added ring and userData parameter in the Tx reclaim callback.
  - Updated NETC hardware layer folder name from 'hw' to 'netc\_hw'.
  - Stored necessary EP and SWT configurations constant in handle structure instead of storing pointer which forces application to keep static configuration structure data.

- Updated NETC\_MsixXxx to EP\_MsixXxx to differentiate with corresponding SWT/Timer MSIX configuration APIs.
- Aligned TGSL/SGCL API with enet\_qos high-level driver.
- Updated EP/Switch config structure to include all port related config.
- Updated Switch transfer API only send management frame (Direct enqueue and Switch Port Masquerading) and only receive Host Reason no-zero frames.
- Updated EP transfer API only send/receive regular frames.
- Updated Switch/EP handle to make them use independent cache maintain, alloc/free memory and reclaimCallback functions.

#### [2.0.0]

- Initial version.
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### PDM

#### [2.9.3]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.1, 10.3, 10.4, 10.5, 10.6, 10.7, 10.8, 12.4.

#### [2.9.2]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.1, 10.3, 10.4, 10.5, 10.6, 10.7, 10.8, 12.4.

#### [2.9.1]

- Bug Fixes
  - Fixed the issue that the driver still enters the interrupt after disabling clock.

#### [2.9.0]

- Improvements
- Added feature FSL\_FEATURE\_PDM\_HAS\_DECIMATION\_FILTER\_BYPASS to config CTRL\_2[DEC\_BYPASS] field.
- Modify code to make the OSR value is not limited to 16.

#### [2.8.1]

- Improvements
- Added feature FSL\_FEATURE\_PDM\_HAS\_NO\_DOZEN to handle nonexistent CTRL\_1[DOZEN] field.

#### [2.8.0]

- Improvements
- Added feature FSL\_FEATURE\_PDM\_HAS\_NO\_HWVAD to remove the support of hardware voice activity detector.
- Added feature FSL\_FEATURE\_PDM\_HAS\_NO\_FILTER\_BUFFER to remove the support of FIR\_RDY bitfield in STAT register.

#### [2.7.4]

- Bug Fixes
  - Fixed driver can not determine the specific float number of clock divider.
  - Fixed PDM\_ValidateSrcClockRate calculates PDM channel in wrong method issue.

#### [2.7.3]

- Improvements
- Added feature FSL\_FEATURE\_PDM\_HAS\_NO\_VADEF to remove the support of VADEF bitfield in VADO\_STAT register.

#### [2.7.2]

- Improvements
- Added feature FSL\_FEATURE\_PDM\_HAS\_NO\_MINIMUM\_CLKDIV to decide whether the minimum clock frequency division is required.

#### [2.7.1]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 8.4, 10.3, 10.1, 10.4, 14.4

#### [2.7.0]

- Improvements
  - Added api PDM\_EnableHwvadInterruptCallback to support handle hwvad IRQ in PDM driver.
  - Corrected the sample rate configuration for non high quality mode.
  - Added api PDM\_SetChannelGain to support adjust the channel gain.

#### [2.6.0]

- Improvements
  - Added new features FSL\_FEATURE\_PDM\_HAS\_STATUS\_LOW\_FREQ/FSL\_FEATURE\_PDM\_HAS\_DC\_OUT

#### [2.5.0]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 8.4, 16.5, 10.4, 10.3, 10.1, 11.9, 17.7, 10.6, 14.4, 11.8, 11.6.



#### [2.4.1]

- Bug Fixes
  - Fixed MDK 66-D warning in pdm driver.

#### [2.4.0]

- Improvements
  - Added api `PDM_TransferSetChannelConfig/PDM_ReadFifo` to support read different width data.
  - Added feature `FSL_FEATURE_PDM_HAS_RANGE_CTRL` and api `PDM_ClearRangeStatus/PDM_GetRangeStatus` for range register.
- Bug Fixes
  - Fixed violation of MISRA C-2012 Rule 14.4, 10.3, 10.4.

#### [2.3.0]

- Improvements
  - Enabled envelope/energy voice detect mode by adding apis `PDM_SetHwvadInEnvelopeBasedMode/PDM_SetHwvadInEnergyBasedMode`.
  - Added feature `FSL_FEATURE_PDM_CHANNEL_NUM` for different SOC.

#### [2.2.1]

- Bug Fixes
  - Fixed violation of MISRA C-2012 Rule 10.1, 10.3, 10.4, 10.6, 10.7, 11.3, 11.8, 14.4, 17.7, 18.4.
  - Added medium quality mode support in function `PDM_SetSampleRateConfig`.

#### [2.2.0]

- Improvements
  - Added api `PDM_SetSampleRateConfig` to improve user experience and marked api `PDM_SetSampleRate` as deprecated.

#### [2.1.1]

- Improvements
  - Used new SDMA API `SDMA_SetDoneConfig` instead of `SDMA_EnableSwDone` for PDM SDMA driver.

#### [2.1.0]

- Improvements
  - Added software buffer queue for transactional API.

#### [2.0.1]

- Improvements
  - Improved HWVAD feature.

#### [2.0.0]

- Initial version.
- 

### PDM\_EDMA

#### [2.6.5]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.1, 10.3, 10.4, 10.5, 10.6, 10.7, 10.8.

#### [2.6.4]

- Improvements
  - Add handling for runtime change of number of linked transfers

#### [2.6.3]

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

#### [2.6.2]

- Improvements
  - Add macro `MCUX_SDK_PDM_EDMA_PDM_ENABLE_INTERNAL` to let the user decide whether to enable it when calling `PDM_TransferReceiveEDMA`.

#### [2.6.1]

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

#### [2.6.0]

- Improvements
  - Updated api `PDM_TransferReceiveEDMA` to support channel block interleave transfer.
  - Added new api `PDM_TransferSetMultiChannelInterleaveType` to support channel interleave type configurations.

#### [2.5.0]

- Refer PDM driver change log 2.1.0 to 2.5.0
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## PWM

### [2.9.1]

- Improvements
  - Add new API `PWM_SetupFaultsExt` and `PWM_SetupFaultInputFilterExt` to support Flex-PWM which has more than one fault input channels.
  - Support fault 4-7 interrupt and its flag.
- Bug Fixes
  - Fixed violations of the CERT INT31-C.

### [2.9.0]

- Improvements
  - Support PWMX channel output for edge aligned PWM.
  - Forbid submodule 0 counter initialize with master sync and master reload mode.
  - Clarify `kPWM_BusClock` meaning.
  - Verify `pulseCnt` within 65535 when update period register.

### [2.8.4]

- Improvements
  - Support workaround for ERR051989. This function helps realize no phase delay between submodule 0 and other submodule.

### [2.8.3]

- Bug Fixes
  - Fixed MISRA C-2012 Rule 15.7

### [2.8.2]

- Bug Fixes
  - Fixed warning conversion from 'int' to 'uint16\_t' on API `PWM_Init`.
  - Fixed warning unused variable 'reg' on API `PWM_SetPwmForceOutputToZero`.

### [2.8.1]

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

### [2.8.0]

- Improvements
  - Added API `PWM_UpdatePwmPeriodAndDutycycle` to update the PWM signal's period and dutycycle for a PWM submodule.

- Added API PWM\_SetPeriodRegister and PWM\_SetDutycycleRegister to merge duplicate code in API PWM\_SetupPwm, PWM\_UpdatePwmDutycycleHighAccuracy and PWM\_UpdatePwmPeriodAndDutycycle

#### [2.7.1]

- Improvements
  - Supported UPDATE\_MASK bit in MASK register.

#### [2.7.0]

- Improvements
  - Supported platforms which don't have Capture feature with channel A and B.
  - Supported platforms which don't have Submodule 3.
  - Added assert function in API PWM\_SetPhaseDelay to prevent wrong argument.

#### [2.6.1]

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

#### [2.6.0]

- Improvements
  - Added API PWM\_SetPhaseDelay to set the phase delay from the master sync signal of submodule 0.
  - Added API PWM\_SetFilterSampleCount to set number of consecutive samples that must agree prior to the input filter.
  - Added API PWM\_SetFilterSamplePeriod to set the sampling period of the fault pin input filter.

#### [2.5.1]

- Bug Fixes
  - Fixed MISRA C-2012 rules: 10.1, 10.3, 10.4 , 10.6 and 10.8.
  - Fixed the issue that PWM\_UpdatePwmDutycycle() can't update duty cycle status value correct.

#### [2.5.0]

- Improvements
  - Added API PWM\_SetOutputToIdle to set pwm channel output to idle.
  - Added API PWM\_GetPwmChannelState to get the pwm channel output duty cycle value.
  - Added API PWM\_SetPwmForceOutputToZero to set the pwm channel output to zero logic.
  - Added API PWM\_SetChannelOutput to set the pwm channel output state.
  - Added API PWM\_SetClockMode to set the value of the clock prescaler.

- Added API PWM\_SetupPwmPhaseShift to set PWM which a special phase shift and 50% duty cycle.
- Added API PWM\_SetVALxValue/PWM\_GetVALxValue to set/get PWM VALs registers values directly.

#### [2.4.0]

- Improvements
  - Supported the PWM which can't work in wait mode.

#### [2.3.0]

- Improvements
  - Add PWM output enable&disbale API for SDK.
- Bug Fixes
  - Fixed changing channel B configuration when parameter is kPWM\_PWMX and PWMX configuration is not supported yet.

#### [2.2.1]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rules: 10.3, 10.4.
- Bug Fixes
  - Fixed the issue that PWM drivers computed VAL1 improperly.
- Improvements
  - Updated calculation accuracy of reloadValue in dutyCycleToReloadValue function.

#### [2.2.0]

- Improvements
  - Added new enumeration and two APIs to support enabling and disabling one or more PWM output triggers.
  - Added a new function to make the most of 16-bit resolution PWM.
  - Added one API to support updating fault status of PWM output.
  - Added one API to support PWM DMA write request.
  - Added three APIs to support PWM DMA capture read request.
  - Added one API to support get default fault config of PWM.
  - Added one API to support setting PWM fault disable mapping.

#### [2.1.0]

- Improvements
  - Moved the configuration of fault input filter into a new API to avoid be initialized multiple times.
- Bug Fixes
  - MISRA C-2012 issue fixed.

- \* Fix rules, containing: rule-10.2, rule-10.3, rule-10.4, rule-10.7, rule-10.8, rule-14.4, rule-16.4.

#### [2.0.1]

- Bug Fixes
  - Fixed the issue that PWM submodule may be initialized twice in function PWM\_SetupPwm().

#### [2.0.0]

- Initial version.
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### PXP

#### [2.7.0]

- New Features
  - Added the PS\_LRC setting for V4.
  - Added the PXP\_SetPath setting for V4.
  - Fixed the code logic, V4 do not support DATA\_PATH\_CTRL1.

#### [2.6.1]

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

#### [2.6.0]

- Bug Fixes
  - Added missing configuration option for fetch engine background value.
  - Fixed bug in PXP\_SetStoreEngineConfig that the address increment for store mask is not linear.
  - Added channel arbitration configuration for fetch engine, channel combine for store engine.
  - Fixed wrong method of obtaining the store mask address.
  - Fixed wrong method of configuring flag shift mask/width which can only be written in word boundary.
  - Fixed wrong configurations of block store and pitch in PXP\_SetStoreEngineConfig.
  - Fixed wrong method of obtaining cfaValue address and calculating word count.
  - Fixed the channel word order cannot be updated when configuring the second channel.
  - Fixed bugs in PXP\_SetHistogramConfig of wrong method to obtain the store mask address and wrong access of 32-bit registers.

### [2.5.0]

- New Features
  - Added new API PXP\_GetPorterDuffConfigExt for flexible Porter-Duff configuration.
  - Added enumerations for new AS/PS pixel formats for certain SoCs.

### [2.4.1]

- New Features
  - Added API PXP\_ResetControl to reset the PXP and the control register to initialized state.

### [2.4.0]

- New Features
  - Added the API PXP\_BuildRect of building a solid rectangle of given pixel value.
  - Added the interrupt enable/disable and status mask for V3.
  - Added API PXP\_EnableProcessEngine to enable/disable process engines for V3.
  - Added API PXP\_SetHistogramSize to re-configure the histogram size for each update.
  - Updated PXP\_WfeaInit and PXP\_SetWfeaConfig according to header file's update of WFE related registers.
  - Updated PXP\_WfeaInit to support handshake with upstream dither store engine and added API PXP\_WfeaEnableDitherHandshake to enable/disable the feature.
  - Added API PXP\_GetLutUsage to get the occupied LUT list.
  - Updated APIs to support alpha blending engine1.
  - Added the API PXP\_MemCopy to support all memory size copy.
- Bug Fixes
  - Fixed wrong naming for mux16.
  - Fixed wrong naming for enumerations in pxp\_scanline\_burst\_t.
  - Fixed bug in PXP\_GetHistogramMatchResult since there are 2 histograms engines rather than 1.
  - Fixed bug in PXP\_SetFetchEngineConfig that the fetch size should not be minus one coding.

### [2.3.0]

- New Features
  - Added the configuration of fetch engine, store engine, pre-dither engine and histogram block.

### [2.2.2]

- Improvements
  - Disable alpha surface (AS) in PXP\_Init.

### [2.2.1]

- Improvements
  - Added memory address conversion to support buffers which could only be accessed using alias address by non-core masters.

### [2.2.0]

- Bug Fixes
  - Fixed Porter Duff configuration error.

### [2.1.0]

- New Features
  - Added Porter Duff support.
  - Added APIs PXP\_StartMemCopy and PXP\_StartPictureCopy.
  - Added API PXP\_SetProcessSurfaceYUVFormat.

### [2.0.2]

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 3.1, 10.8, 11.6, 12.2.

### [2.0.1]

- Bug Fixes
  - Fixed the rotate function issue for i.MX 6ULL.

### [2.0.0]

- Initial version.
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## QTMR

### [2.3.0]

- Improvements
  - Support for platforms which QTMR registers are 32-bit.

### [2.2.2]

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

### [2.2.1]

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



**[2.2.0]**

- Improvements
  - Added API QTMR\_SetPwmOutputToIdle to set the generated pwm signal to the configured idle value.
  - Added API QTMR\_GetPwmOutputStatus to return the output status of the generated pwm signal.
  - Added API QTMR\_GetPwmChannelStatus to return the channel dutycycle value.
  - Added API QTMR\_SetPwmClockMode to set clock mode change peripheral clock frequency.
- Bug Fixes
  - Fixed the issue that pwm duty cycle could not be 0 and 100.

**[2.1.0]**

- Bug Fixes
  - Fixed the issue QTMR\_SetTimerPeriod needs to decrement down count by 1, and added new APIs to configure the LOAD register, COMP register.

**[2.0.2]**

- Bug Fixes
  - Fixed the issue introduced by previous code correction for improving the output signal accuracy.

**[2.0.1]**

- Bug Fixes
  - Fixed violations of MISRA C-2012 rules: 10.1, 10.3, 11.5, 11.9.
- Improvements
  - Improved the output signal accuracy.

**[2.0.0]**

- Initial version.
- 

**RGPIO****[2.2.0]**

- Added RGPIO\_GetPinDirection() API to get the current direction of a RGPIO pin.
- Added FGPIO\_GetPinDirection() API to get the current direction of a FGPIO pin.

#### [2.1.0]

- New feature:
  - Added API RGPIO\_EnablePortInput()
  - Added API RGPIO\_SetPinInterruptConfig()
  - Added API RGPIO\_GetPinsInterruptFlags()
  - Added API RGPIO\_ClearPinsInterruptFlags()

#### [2.0.3]

- Improvements:
  - Enhanced FGPIO\_PinInit to enable clock internally.

#### [2.0.2]

- Bug fix
  - MISRA C-2012 issue fixed.
    - \* Fix rules, containing: rule-10.3, rule-14.4, rule-15.5.

#### [2.0.1]

- API Interface Change:
  - Refined naming of API while keep all original APIs with marking them as deprecated. The original API will be removed in the next release. The main change is to update API with prefix of \_PinXXX() and \_PortXXX().

#### [2.0.0]

- Initial version.
- 

### S3MU

- 2.0.2 Fix macro BIT redefined warning when compiling with Zephyr.
  - 2.0.1 Update kStatusGroup\_SNT to kStatusGroup\_ELEMU.
  - 2.0.0 Initial version of S3MU driver.
- 

### SAI

#### [2.4.10]

- Improvements
  - Allow enabling/disabling implicit channel configuration.
  - Allow NULL FIFO watermark.
- Bug Fixes
  - Fix compilation warnings when asserts are disabled

**[2.4.9]**

- Added Errata ERR051421 workaround.

**[2.4.8]**

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.1, 10.3, 10.4, 10.5, 10.6, 10.7, 10.8, 12.4.

**[2.4.7]**

- Added conditional support for bit clock swap feature
- Added common IRQ handler entry SAI\_DriverIRQHandler.

**[2.4.6]**

- Bug Fixes
  - Fixed the IAR build warning.

**[2.4.5]**

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.1, 10.3, 10.4, 10.5, 10.6, 10.7, 10.8, 12.4.

**[2.4.4]**

- Bug Fixes
  - Fixed enumeration sai\_fifo\_combine\_t - add RX configuration.

**[2.4.3]**

- Bug Fixes
  - Fixed enumeration sai\_fifo\_combine\_t value configuration issue.

**[2.4.2]**

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

**[2.4.1]**

- Bug Fixes
  - Fixed bitWidth incorrectly assigned issue.

**[2.4.0]**

- Improvements
  - Removed deprecated APIs.

#### [2.3.8]

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

#### [2.3.7]

- Improvements
  - Change feature “FSL\_FEATURE\_SAI\_FIFO\_COUNT” to “FSL\_FEATURE\_SAI\_HAS\_FIFO”.
  - Added feature “FSL\_FEATURE\_SAI\_FIFO\_COUNTn(x)” to align SAI fifo count function with IP in function

#### [2.3.6]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 5.6.

#### [2.3.5]

- Improvements
  - Make driver to be aarch64 compatible.

#### [2.3.4]

- Bug Fixes
  - Corrected the fifo combine feature macro used in driver.

#### [2.3.3]

- Bug Fixes
  - Added bit clock polarity configuration when sai act as slave.
  - Fixed out of bound access coverity issue.
  - Fixed violations of MISRA C-2012 rule 10.3, 10.4.

#### [2.3.2]

- Bug Fixes
  - Corrected the frame sync configuration when sai act as slave.

#### [2.3.1]

- Bug Fixes
  - Corrected the peripheral name in function SAI0\_DriverIRQHandler.
  - Fixed violations of MISRA C-2012 rule 17.7.

#### [2.3.0]

- Bug Fixes
  - Fixed the build error caused by the SOC has no fifo feature.

### [2.2.3]

- Bug Fixes
  - Corrected the peripheral name in function SAI0\_DriverIRQHandler.

### [2.2.2]

- Bug Fixes
  - Fixed the issue of MISRA 2004 rule 9.3.
  - Fixed sign-compare warning.
  - Fixed the PA082 build warning.
  - Fixed sign-compare warning.
  - Fixed violations of MISRA C-2012 rule 10.3,17.7,10.4,8.4,10.7,10.8,14.4,17.7,11.6,10.1,10.6,8.4,14.3,16.4,18.2
  - Allow to reset Rx or Tx FIFO pointers only when Rx or Tx is disabled.
- Improvements
  - Added 24bit raw audio data width support in sai sdma driver.
  - Disabled the interrupt/DMA request in the SAI\_Init to avoid generates unexpected sai FIFO requests.

### [2.2.1]

- Improvements
  - Added mclk post divider support in function SAI\_SetMasterClockDivider.
  - Removed useless configuration code in SAI\_RxSetSerialDataConfig.
- Bug Fixes
  - Fixed the SAI SDMA driver build issue caused by the wrong structure member name used in the function SAI\_TransferRxSetConfigSDMA/SAI\_TransferTxSetConfigSDMA.
  - Fixed BAD BIT SHIFT OPERATION issue caused by the FSL\_FEATURE\_SAI\_CHANNEL\_COUNTn.
  - Applied ERR05144: not set FCONT = 1 when TMR > 0, otherwise the TX may not work.

### [2.2.0]

- Improvements
  - Added new APIs for parameters collection and simplified user interfaces:
    - \* SAI\_Init
    - \* SAI\_SetMasterClockConfig
    - \* SAI\_TxSetBitClockRate
    - \* SAI\_TxSetSerialDataConfig
    - \* SAI\_TxSetFrameSyncConfig
    - \* SAI\_TxSetFifoConfig
    - \* SAI\_TxSetBitclockConfig
    - \* SAI\_TxSetConfig
    - \* SAI\_TxSetTransferConfig

- \* SAI\_RxSetBitClockRate
- \* SAI\_RxSetSerialDataConfig
- \* SAI\_RxSetFrameSyncConfig
- \* SAI\_RxSetFifoConfig
- \* SAI\_RxSetBitclockConfig
- \* SAI\_RXSetConfig
- \* SAI\_RxSetTransferConfig
- \* SAI\_GetClassicI2SConfig
- \* SAI\_GetLeftJustifiedConfig
- \* SAI\_GetRightJustifiedConfig
- \* SAI\_GetTDMConfig

#### [2.1.9]

- Improvements
  - Improved SAI driver comment for clock polarity.
  - Added enumeration for SAI for sample inputs on different edges.
  - Changed FSL\_FEATURE\_SAI\_CHANNEL\_COUNT to FSL\_FEATURE\_SAI\_CHANNEL\_COUNTn(base) for the difference between the different SAI instances.
- Added new APIs:
  - SAI\_TxSetBitClockDirection
  - SAI\_RxSetBitClockDirection
  - SAI\_RxSetFrameSyncDirection
  - SAI\_TxSetFrameSyncDirection

#### [2.1.8]

- Improvements
  - Added feature macro test for the sync mode2 and mode 3.
  - Added feature macro test for masterClockHz in sai\_transfer\_format\_t.

#### [2.1.7]

- Improvements
  - Added feature macro test for the mclkSource member in sai\_config\_t.
  - Changed “FSL\_FEATURE\_SAI5\_SAI6\_SHARE\_IRQ” to “FSL\_FEATURE\_SAI\_SAI5\_SAI6\_SHARE\_IRQ”.
  - Added #ifndef #endif check for SAI\_XFER\_QUEUE\_SIZE to allow redefinition.
- Bug Fixes
  - Fixed build error caused by feature macro test for mclkSource.

**[2.1.6]**

- Improvements
  - Added feature macro test for mclkSourceClockHz check.
  - Added bit clock source name for general devices.
- Bug Fixes
  - Fixed incorrect channel numbers setting while calling RX/TX set format together.

**[2.1.5]**

- Bug Fixes
  - Corrected SAI3 driver IRQ handler name.
  - Added I2S4/5/6 IRQ handler.
  - Added base in handler structure to support different instances sharing one IRQ number.
- New Features
  - Updated SAI driver for MCR bit MICS.
  - Added 192 KHZ/384 KHZ in the sample rate enumeration.
  - Added multi FIFO interrupt/SDMA transfer support for TX/RX.
  - Added an API to read/write multi FIFO data in a blocking method.
  - Added bclk bypass support when bclk is same with mclk.

**[2.1.4]**

- New Features
  - Added an API to enable/disable auto FIFO error recovery in platforms that support this feature.
  - Added an API to set data packing feature in platforms which support this feature.

**[2.1.3]**

- New Features
  - Added feature to make I2S frame sync length configurable according to bitWidth.

**[2.1.2]**

- Bug Fixes
  - Added 24-bit support for SAI eDMA transfer. All data shall be 32 bits for send/receive, as eDMA cannot directly handle 3-Byte transfer.

**[2.1.1]**

- Improvements
  - Reduced code size while not using transactional API.

### [2.1.0]

- Improvements
  - API name changes:
    - \* SAI\_GetSendRemainingBytes -> SAI\_GetSentCount.
    - \* SAI\_GetReceiveRemainingBytes -> SAI\_GetReceivedCount.
    - \* All names of transactional APIs were added with “Transfer” prefix.
    - \* All transactional APIs use base and handle as input parameter.
    - \* Unified the parameter names.
- Bug Fixes
  - Fixed WLC bug while reading TCSR/RCSR registers.
  - Fixed MOE enable flow issue. Moved MOE enable after MICS settings in SAI\_TxInit/SAI\_RxInit.

### [2.0.0]

- Initial version.
- 

## SAI\_EDMA

### [2.7.3]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.1, 10.3, 10.4, 10.5, 10.6, 10.7, 10.8, 12.4.

### [2.7.2]

- Improvements
  - Add macros `MCUX_SDK_SAI_EDMA_TX_ENABLE_INTERNAL` and `MCUX_SDK_SAI_EDMA_RX_ENABLE_INTERNAL` to let the user decide whether to enable SAI when calling `SAI_TransferSendEDMA/SAI_TransferReceiveEDMA`.

### [2.7.1]

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

### [2.7.0]

- Improvements
  - Updated api `SAI_TransferReceiveEDMA` to support voice channel block interleave transfer.
  - Updated api `SAI_TransferSendEDMA` to support voice channel block interleave transfer.
  - Added new api `SAI_TransferSetInterleaveType` to support channel interleave type configurations.



**[2.6.0]**

- Improvements
  - Removed deprecated APIs.

**[2.5.1]**

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 20.7.

**[2.5.0]**

- Improvements
  - Added new api SAI\_TransferSendLoopEDMA/SAI\_TransferReceiveLoopEDMA to support loop transfer.
  - Added multi sai channel transfer support.

**[2.4.0]**

- Improvements
  - Added new api SAI\_TransferGetValidTransferSlotsEDMA which can be used to get valid transfer slot count in the sai edma transfer queue.
  - Deprecated the api SAI\_TransferRxSetFormatEDMA and SAI\_TransferTxSetFormatEDMA.
- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.3,10.4.

**[2.3.2]**

- Refer SAI driver change log 2.1.0 to 2.3.2
- 

**SAR\_ADC****[2.3.0]**

- New Feature
  - Added new feature macro a for compatibility with ADCs on some platforms where some instances do not support group3.

**[2.2.0]**

- New Feature
  - Added new features to compatible with new platforms.

**[2.1.1]**

- Improvement
  - Change ADC sample rate phase duration default value from 0x08 to 0x14.

#### [2.1.0]

- New Feature
  - Added ADC\_StopConvChain function to support stop scan in normal conversion scan operation mode.

#### [2.0.3]

- Bug Fixes
  - Fixed the array name usage error in function ADC\_GetInstance.

#### [2.0.2]

- Bug Fixes
  - Fixed MISRA issues.

#### [2.0.1]

- Bug Fixes
  - Fixed the bug that when calling function ADC\_EnableWdgThresholdInt() in function ADC\_SetAnalogWdgConfig(), the parameter was passed incorrectly.

#### [2.0.0]

- Initial version.
- 

### SEMA42

#### [2.1.1]

- Improvements
  - Updated SEMA42\_TryLock function to avoid unsigned integer operations wrap issue.

#### [2.1.0]

- New Features
  - Added SEMA42\_BUSY\_POLL\_COUNT parameter to prevent infinite polling loops in SEMA42 operations.
  - Added timeout mechanism to all polling loops in SEMA42 driver code.
- Improvements
  - Updated SEMA42\_Lock function to return status\_t instead of void for better error handling.
  - Enhanced documentation to clarify timeout behavior and return values.

#### [2.0.4]

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

**[2.0.3]**

- Improvements
  - Changed to implement SEMA42\_Lock base on SEMA42\_TryLock.

**[2.0.2]**

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 17.7.

**[2.0.1]**

- Bug Fixes
  - Fixed violations of the MISRA C-2012 rules 10.3, 10.4, 14.4, 18.1.

**[2.0.0]**

- Initial version.
- 

**SINC****[2.1.5]**

- Bug Fixes
  - Fixed building warning.

**[2.1.4]**

- Bug Fixes
  - Fixed building issue.

**[2.1.3]**

- Bug Fixes
  - Fixed function 'SINC\_SetChannelProtectionOption' logic operation error.

**[2.1.2]**

- Bug Fixes
  - Fixed the typo issue of missing character 'U' in the feature macro 'FSL\_FEATRE\_SINC\_CACFR\_HAS\_NO\_PTMUX'.

**[2.1.1]**

- Bug Fixes
  - Fixed MISRA C-2012 rule 10.4 and 10.8 issues.

#### [2.1.0]

- Improvements
  - Added support for chips that each instance equipped with 5 channels.

#### [2.0.2]

- Improvements
  - Added comments for over sample ratio.

#### [2.0.1]

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 15.6, 10.4, 10.1, 10.3 and 10.7.

#### [2.0.0]

- Initial version.
- 

### SRAMCTL

#### [3.0.0]

- Initial version.
- 

### TPM

#### [2.4.1]

- Improvements
  - Add Coverage Justification for uncovered code.

#### [2.4.0]

- New Feature
  - Added while loop timeout for MOD CnV CnSC and SC register write sequence.
  - Change the return type from void to status\_t for following API:
    - \* TPM\_DisableChannel
    - \* TPM\_EnableChannel
    - \* TPM\_SetupOutputCompare
    - \* TPM\_SetTimerPeriod
    - \* TPM\_StopTimer

#### [2.3.6]

- Bug Fixes
  - Fixed CERT INT30-C INT31-C issue for TPM\_SetupDualEdgeCapture.

**[2.3.5]**

- New Feature
  - Added IRQ handler entry for TPM2.

**[2.3.4]**

- New Feature
  - Added common IRQ handler entry TPM\_DriverIRQHandler.

**[2.3.3]**

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

**[2.3.2]**

- Bug Fixes
  - Fixed ERR008085 TPM writing the TPMx\_MOD or TPMx\_CnV registers more than once may fail when the timer is disabled.

**[2.3.1]**

- Bug Fixes
  - Fixed compilation error when macro FSL\_SDK\_DISABLE\_DRIVER\_CLOCK\_CONTROL is 1.

**[2.3.0]**

- Improvements
  - Create callback feature for TPM match and timer overflow interrupts.

**[2.2.4]**

- Improvements
  - Add feature macros(FSL\_FEATURE\_TPM\_HAS\_GLOBAL\_TIME\_BASE\_EN, FSL\_FEATURE\_TPM\_HAS\_GLOBAL\_TIME\_BASE\_SYNC).

**[2.2.3]**

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

**[2.2.2]**

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

### [2.2.1]

- Bug Fixes
  - Fixed CCM issue by splitting function from TPM\_SetupPwm() function to reduce function complexity.
  - Fixed violations of MISRA C-2012 rule 17.7.

### [2.2.0]

- Improvements
  - Added TPM\_SetChannelPolarity to support select channel input/output polarity.
  - Added TPM\_EnableChannelExtTrigger to support enable external trigger input to be used by channel.
  - Added TPM\_CalculateCounterClkDiv to help calculates the counter clock prescaler.
  - Added TPM\_GetChannelValue to support get TPM channel value.
  - Added new TPM configuration.
    - \* syncGlobalTimeBase
    - \* extTriggerPolarity
    - \* chnlPolarity
  - Added new PWM signal configuration.
    - \* secPauseLevel
- Bug Fixes
  - Fixed TPM\_SetupPwm can't configure 0% combined PWM issues.

### [2.1.1]

- Improvements
  - Add feature macro for PWM pause level select feature.

### [2.1.0]

- Improvements
  - Added TPM\_EnableChannel and TPM\_DisableChannel APIs.
  - Added new PWM signal configuration.
    - \* pauseLevel - Support select output level when counter first enabled or paused.
    - \* enableComplementary - Support enable/disable generate complementary PWM signal.
    - \* deadTimeValue - Support deadtime insertion for each pair of channels in combined PWM mode.
- Bug Fixes
  - Fixed issues about channel MSnB:MSnA and ELSnB:ELSnA bit fields and CnV register change request acknowledgement. Writes to these bits are ignored when the interval between successive writes is less than the TPM clock period.

**[2.0.8]**

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.1, 10.4 ,10.7 and 14.4.

**[2.0.7]**

- Bug Fixes
  - Fixed violations of MISRA C-2012 rule 10.4 and 17.7.

**[2.0.6]**

- Bug Fixes
  - Fixed Out-of-bounds issue.

**[2.0.5]**

- Bug Fixes
  - Fixed MISRA-2012 rules.
    - \* Rule 10.6, 10.7

**[2.0.4]**

- Bug Fixes
  - Fixed ERR050050 in functions TPM\_SetupPwm/TPM\_UpdatePwmDutycycle. When TPM was configured in EPWM mode as PS = 0, the compare event was missed on the first reload/overflow after writing 1 to the CnV register.

**[2.0.3]**

- Bug Fixes
  - MISRA-2012 issue fixed.
    - \* Fixed rules: rule-12.1, rule-17.7, rule-16.3, rule-14.4, rule-1.3, rule-10.4, rule-10.3, rule-10.7, rule-10.1, rule-10.6, and rule-18.1.

**[2.0.2]**

- Bug Fixes
  - Fixed issues in functions TPM\_SetupPwm/TPM\_UpdateChnEdgeLevelSelect/TPM\_SetupInputCapture/TPM\_SetupOutputCompare/TPM\_SetupDualEdgeCapture, wait acknowledgement when the channel is disabled.

**[2.0.1]**

- Bug Fixes
  - Fixed TPM\_UpdateChnEdgeLevelSelect ACK wait issue.
  - Fixed the issue that TPM\_SetupDualEdgeCapture could not set FILTER register.
  - Fixed TPM\_UpdateChnEdgeLevelSelect ACK wait issue.

## [2.0.0]

- Initial version.
- 

## TSTMR

### [2.1.0]

- New Features
  - Support configured clock frequency.
  - Add TSTMR\_Init and TSTMR\_init APIs.
- Improvements
  - Change TSTMR\_DelayUs from static inline function to normal function.

### [2.0.4]

- Bugfix
  - Fix MISRA C-2012 Rule 10.4 and 14.4 issues.

### [2.0.3]

- Bugfix
  - Fix CERT INT30-C that Unsigned integer operation TSTMR\_ReadTimeStamp(base) - startTime may wrap.

### [2.0.2]

- Improvements
  - Support 24MHz clock source.
- Bugfix
  - Fix MISRA C-2012 Rule 10.4 issue.
  - Read of TSTMR HIGH must follow TSTMR LOW atomically: require masking interrupt around 2 LSB / MSB accesses.

### [2.0.1]

- Bugfix
  - Restrict to read with 32-bit accesses only.
  - Restrict that TSTMR LOW read occurs first, followed by the TSTMR HIGH read.

### [2.0.0]

- Initial version.
-



## XBAR

### [2.2.0]

- New Features
  - Support register write protection.

### [2.1.2]

- Correct bits of SEL registers

### [2.1.1]

- Fix wrong offset of ctrl registers

### [2.1.0]

- unify bit fields width for xbar instance index and xbar input/output signal index.

### [2.0.4]

- Improvements
  - Rename feature macro name.

### [2.0.3]

- Improvements
  - Improved to support 32-bit width peripheral.

### [2.0.2]

- Bug Fixes
  - Fixed MISRA C-2012 violations.

### [2.0.1]

- Bug Fixes
  - Fixed the xbar instance base offset error.

### [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.

MIMX94398\_drivers

## 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 Multicore

*[Multicore SDK](#)*

### 1.7.2 FreeMASTER

*[freemaster](#)*

### 1.7.3 FreeRTOS

*[FreeRTOS](#)*

### 1.7.4 lwIP

*[lwIP](#)*

## Chapter 2

# Drivers

The following is a list of the Driver API Reference Manuals categorized by device series.

### 2.1 DSC

### 2.2 i.MX

### 2.3 i.MX RT

### 2.4 Kinetis

### 2.5 LPC

### 2.6 MCX

### 2.7 Wireless



# Chapter 3

## Middleware

### 3.1 Connectivity

#### 3.1.1 lwIP

**This is the NXP fork of the [lwIP networking stack](#).**

- For details about changes and additions made by NXP, see CHANGELOG.
- For details about the NXP porting layer, see [The NXP lwIP Port](#).
- For usage and API of lwIP, use official documentation at <http://www.nongnu.org/lwip/>.

#### The NXP lwIP Port

Below is description of possible settings of the port layer and an overview of a few helper functions.

The best place for redefinition of any mentioned macro is `lwipopts.h`.

The declaration of every mentioned function is in `ethernetif.h`. Please check the doxygen comments of those functions before.

**Link state** Physical link state (up/down) and its speed and duplex must be read out from PHY over MDIO bus. Especially link information is useful for lwIP stack so it can for example send DHCP discovery immediately when a link becomes up.

To simplify this port layer offers a function `ethernetif_probe_link()` which reads those data from PHY and forwards them into lwIP stack.

In almost all examples this function is called every `ETH_LINK_POLLING_INTERVAL_MS` (1500ms) by a function `probe_link_cyclic()`.

By setting `ETH_LINK_POLLING_INTERVAL_MS` to 0 polling will be disabled. On FreeRTOS, `probe_link_cyclic()` will be then called on an interrupt generated by PHY. GPIO port and pin for the interrupt line must be set in the `ethernetifConfig` struct passed to `ethernetif_init()`. On bare metal interrupts are not supported right now.

**Rx task** To improve the reaction time of the app, reception of packets is done in a dedicated task. The rx task stack size can be set by `ETH_RX_TASK_STACK_SIZE` macro, its priority by `ETH_RX_TASK_PRIO`.

If you want to save memory you can set reception to be done in an interrupt by setting `ETH_DO_RX_IN_SEPARATE_TASK` macro to 0.

**Disabling Rx interrupt when out of buffers** If `ETH_DISABLE_RX_INT_WHEN_OUT_OF_BUFFERS` is set to 1, then when the port gets out of Rx buffers, Rx enet interrupt will be disabled for a particular controller. Everytime Rx buffer is freed, Rx interrupt will be enabled.

This prevents your app from never getting out of Rx interrupt when the network is flooded with traffic.

`ETH_DISABLE_RX_INT_WHEN_OUT_OF_BUFFERS` is by default turned on, on FreeRTOS and off on bare metal.

**Limit the number of packets read out from the driver at once on bare metal.** You may define macro `ETH_MAX_RX_PKTS_AT_ONCE` to limit the number of received packets read out from the driver at once.

In case of heavy Rx traffic, lowering this number improves the realtime behaviour of an app. Increasing improves Rx throughput.

Setting it to value  $< 1$  or not defining means “no limit”.

**Helper functions** If your application needs to wait for the link to become up you can use one of the following functions:

- `ethernetif_wait_linkup()` - Blocks until the link on the passed netif is not up.
- `ethernetif_wait_linkup_array()` - Blocks until the link on at least one netif from the passed list of netifs becomes up.

If your app needs to wait for the IPv4 address on a particular netif to become different than “ANY” address (255.255.255.255) function `ethernetif_wait_ipv4_valid()` does this.

## 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\_pdbdm** 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\_QUEUE\_SIZE

```
#define FMSTR_COMM_QUEUE_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:

$N * T_{char}$

where:

- *N* is equal to the length of the receive FIFO queue (configured by the *FMSTR\_COMM\_QUEUE\_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 */
```

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```

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 *fmstr:* 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 */

/* 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 <a href="#">FM-STR_PipeOpen</a> 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>FM-STR_U16</i>	Unsigned 16-bit integer.
<i>FM-STR_U32</i>	Unsigned 32-bit integer.
<i>FMSTR_S8</i>	Signed 8-bit integer.
<i>FM-STR_S16</i>	Signed 16-bit integer.
<i>FM-STR_S32</i>	Signed 32-bit integer.
<i>FM-STR_FLOAT</i>	4-byte standard IEEE floating-point type.
<i>FM-STR_FLAGS</i>	Data type forming a union with a structure of flag bit-fields.
<i>FM-STR_SIZE8</i>	Data type holding a general size value, at least 8 bits wide.
<i>FM-STR_INDEX</i>	General for-loop index. Must be signed, at least 16 bits wide.
<i>FM-STR_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>FM-STR_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](http://www.nxp.com/freemaster)
- FreeMASTER community area: [community.nxp.com/community/freemaster](http://community.nxp.com/community/freemaster)
- FreeMASTER GitHub code repo: <https://github.com/nxp-mcuxpresso/mcux-freemaster>
- MCUXpresso SDK home: [www.nxp.com/mcuxpresso](http://www.nxp.com/mcuxpresso)
- MCUXpresso SDK builder: [mcuxpresso.nxp.com/en](http://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.

## 3.3 MultiCore

### 3.3.1 Multicore SDK

Multicore Software Development Kit (MCSDK) is a Software Development Kit that provides comprehensive software support for NXP dual/multicore devices. The MCSDK is combined with the MCUXpresso SDK to make the software framework for easy development of multicore applications.

## Multicore SDK (MCSDK) Release Notes

**Overview** These are the release notes for the NXP Multicore Software Development Kit (MCSDK) version 25.12.00.

This software package contains components for efficient work with multicore devices as well as for the multiprocessor communication.

### What is new

- eRPC [CHANGELOG](#)
- RMPMsg-Lite [CHANGELOG](#)
- MCMgr [CHANGELOG](#)
- Supported evaluation boards (multicore examples):
  - LPCXpresso55S69
  - FRDM-K32L3A6
  - MIMXRT1170-EVKB
  - MIMXRT1160-EVK
  - MIMXRT1180-EVK
  - MCX-N5XX-EVK
  - MCX-N9XX-EVK
  - FRDM-MCXN947
  - MIMXRT700-EVK
  - KW47-EVK
  - KW47-LOC
  - FRDM-MCXW72
  - MCX-W72-EVK
  - FRDM-IMXRT1186
- Supported evaluation boards (multiprocessor examples):
  - LPCXpresso55S36
  - FRDM-K22F
  - FRDM-K32L2B
  - MIMXRT685-EVK
  - MIMXRT1170-EVKB
  - MIMXRT1180
  - FRDM-MCXN236
  - FRDM-MCXC242
  - FRDM-MCXC444
  - MCX-N9XX-EVK
  - FRDM-MCXN947
  - MIMXRT700-EVK
  - FRDM-IMXRT1186

**Development tools** The Multicore SDK (MCSDK) was compiled and tested with development tools referred in: [Development tools](#)

**Release contents** This table describes the release contents. Not all MCUXpresso SDK packages contain the whole set of these components.

Deliverable	Location
Multicore SDK location	<MCUXpressoSDK_install_dir>/middleware/multicore/
Documentation	<MCSDK_dir>/mcuxsdk-doc/
Embedded Remote Procedure Call component	<MCSDK_dir>/erpc/
Multicore Manager component	<MCSDK_dir>/mcmgr/
RPMsg-Lite	<MCSDK_dir>/rpmsg_lite/
Multicore demo applications	<MCUXpressoSDK_install_dir>/examples/multicore_examples/
Multiprocessor demo applications	<MCUXpressoSDK_install_dir>/examples/multiprocessor_examples/

**Multicore SDK release overview** Together, the Multicore SDK (MCSDK) and the MCUXpresso SDK (SDK) form a framework for the development of software for NXP multicore devices. The MCSDK release consists of the following elementary software components for multicore:

- Embedded Remote Procedure Call (eRPC)
- Multicore Manager (MCMGR) - included just in SDK for multicore devices
- Remote Processor Messaging - Lite (RPMsg-Lite) - included just in SDK for multicore devices

The MCSDK is also accompanied with documentation and several multicore and multiprocessor demo applications.

**Demo applications** The multicore demo applications demonstrate the usage of the MCSDK software components on supported multicore development boards.

The following multicore demo applications are located together with other MCUXpresso SDK examples in the <MCUXpressoSDK\_install\_dir>/examples/multicore\_examples subdirectories.

- erpc\_matrix\_multiply\_mu
- erpc\_matrix\_multiply\_mu\_rtos
- erpc\_matrix\_multiply\_rpmsg
- erpc\_matrix\_multiply\_rpmsg\_rtos
- erpc\_two\_way\_rpc\_rpmsg\_rtos
- freertos\_message\_buffers
- hello\_world
- multicore\_manager
- rpmsg\_lite\_pingpong
- rpmsg\_lite\_pingpong\_rtos
- rpmsg\_lite\_pingpong\_dsp
- rpmsg\_lite\_pingpong\_tzm

The eRPC multicore component can be leveraged for inter-processor communication and remote procedure calls between SoCs / development boards.

The following multiprocessor demo applications are located together with other MCUXpresso SDK examples in

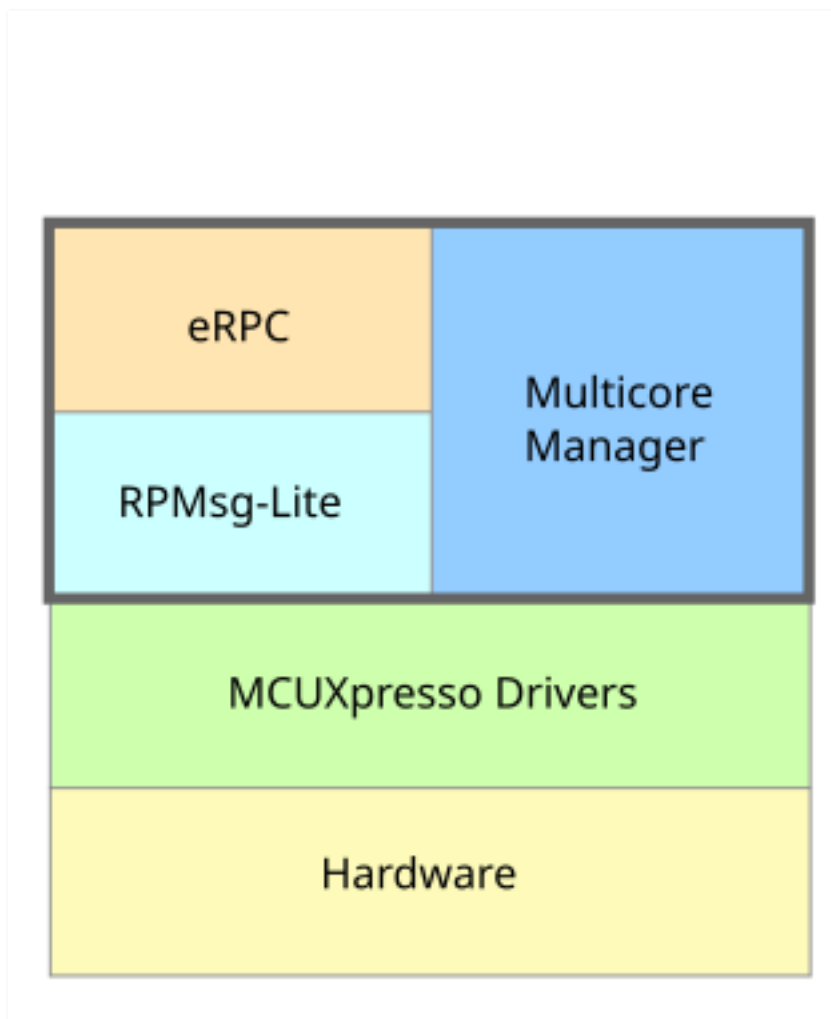
the <MCUXpressoSDK\_install\_dir>/examples/multiprocessor\_examples subdirectories.

- erpc\_client\_matrix\_multiply\_spi
- erpc\_server\_matrix\_multiply\_spi
- erpc\_client\_matrix\_multiply\_uart
- erpc\_server\_matrix\_multiply\_uart
- erpc\_server\_dac\_adc
- erpc\_remote\_control

### Getting Started with Multicore SDK (MCSDK)

**Overview** Multicore Software Development Kit (MCSDK) is a Software Development Kit that provides comprehensive software support for NXP dual/multicore devices. The MCSDK is combined with the MCUXpresso SDK to make the software framework for easy development of multicore applications.

The following figure highlights the layers and main software components of the MCSDK.

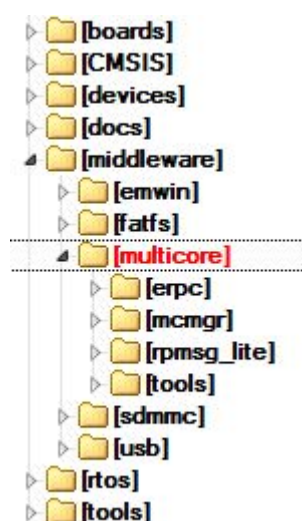


All the MCSDK-related files are located in `<MCUXpressoSDK_install_dir>/middleware/multicore` folder.

For supported toolchain versions, see the *Multicore SDK v25.12.00 Release Notes* (document MCS-DKRN). For the latest version of this and other MCSDK documents, visit [www.nxp.com](http://www.nxp.com).

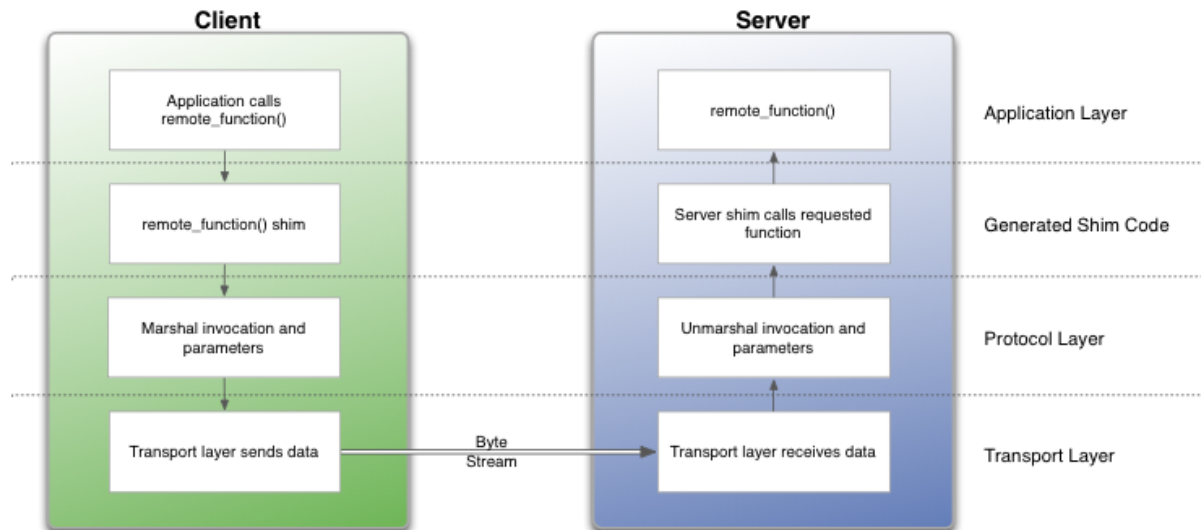
**Multicore SDK (MCSDK) components** The MCSDK consists of the following software components:

- **Embedded Remote Procedure Call (eRPC):** This component is a combination of a library and code generator tool that implements a transparent function call interface to remote services (running on a different core).
- **Multicore Manager (MCMGR):** This library maintains information about all cores and starts up secondary/auxiliary cores.
- **Remote Processor Messaging - Lite (RPMsg-Lite):** Inter-Processor Communication library.



**Embedded Remote Procedure Call (eRPC)** The Embedded Remote Procedure Call (eRPC) is the RPC system created by NXP. The RPC is a mechanism used to invoke a software routine on a remote system via a simple local function call.

When a remote function is called by the client, the function's parameters and an identifier for the called routine are marshaled (or serialized) into a stream of bytes. This byte stream is transported to the server through a communications channel (IPC, TPC/IP, UART, and so on). The server unmarshals the parameters, determines which function was invoked, and calls it. If the function returns a value, it is marshaled and sent back to the client.



RPC implementations typically use a combination of a tool (erpcgen) and IDL (interface definition language) file to generate source code to handle the details of marshaling a function's parameters and building the data stream.

#### Main eRPC features:

- Scalable from BareMetal to Linux OS - configurable memory and threading policies.
- Focus on embedded systems - intrinsic support for C, modular, and lightweight implementation.
- Abstracted transport interface - RPMsg is the primary transport for multicore, UART, or SPI-based solutions can be used for multichip.

The eRPC library is located in the `<MCUXpressoSDK_install_dir>/middleware/multicore/erpc` folder. For detailed information about the eRPC, see the documentation available in the `<MCUXpressoSDK_install_dir>/middleware/multicore/erpc/doc` folder.

**Multicore Manager (MCMGR)** The Multicore Manager (MCMGR) software library provides a number of services for multicore systems.

The main MCMGR features:

- Maintains information about all cores in system.
- Secondary/auxiliary cores startup and shutdown.
- Remote core monitoring and event handling.

The MCMGR library is located in the `<MCUXpressoSDK_install_dir>/middleware/multicore/mcmgr` folder. For detailed information about the MCMGR library, see the documentation available in the `<MCUXpressoSDK_install_dir>/middleware/multicore/mcmgr/doc` folder.

**Remote Processor Messaging Lite (RPMsg-Lite)** RPMsg-Lite is a lightweight implementation of the RPMsg protocol. The RPMsg protocol defines a standardized binary interface used to communicate between multiple cores in a heterogeneous multicore system. Compared to the legacy OpenAMP implementation, RPMsg-Lite offers a code size reduction, API simplification, and improved modularity.

The main RPMsg protocol features:

- Shared memory interprocessor communication.
- Virtio-based messaging bus.
- Application-defined messages sent between endpoints.



- Portable to different environments/platforms.
- Available in upstream Linux OS.

The RPMsg-Lite library is located in the `<MCUXpressoSDK_install_dir>/middleware/multicore/rpmsg-lite` folder. For detailed information about the RPMsg-Lite, see the RPMsg-Lite User's Guide located in the `<MCUXpressoSDK_install_dir>/middleware/multicore/rpmsg_lite/doc` folder.

**MCSDK demo applications** Multicore and multiprocessor example applications are stored together with other MCUXpresso SDK examples, in the dedicated multicore subfolder.

Location	Folder
Multicore example projects	<code>&lt;MCUXpressoSDK_install_dir&gt;/examples/multicore_examples/&lt;application_name&gt;/</code>
Multiprocessor example projects	<code>&lt;MCUXpressoSDK_install_dir&gt;/examples/multiprocessor_examples/&lt;application_name&gt;/</code>

See the *Getting Started with MCUXpresso SDK* (document MCUXSDKGSUG) and *Getting Started with MCUXpresso SDK for XXX Derivatives* documents for more information about the MCUXpresso SDK example folder structure and the location of individual files that form the example application projects. These documents also contain information about building, running, and debugging multicore demo applications in individual supported IDEs. Each example application also contains a readme file that describes the operation of the example and required setup steps.

**Inter-Processor Communication (IPC) levels** The MCSDK provides several mechanisms for Inter-Processor Communication (IPC). Particular ways and levels of IPC are described in this chapter.

### IPC using low-level drivers

The NXP multicore SoCs are equipped with peripheral modules dedicated for data exchange between individual cores. They deal with the Mailbox peripheral for LPC parts and the Messaging Unit (MU) peripheral for Kinetis and i.MX parts. The common attribute of both modules is the ability to provide a means of IPC, allowing multiple CPUs to share resources and communicate with each other in a simple manner.

The most lightweight method of IPC uses the MCUXpresso SDK low-level drivers for these peripherals. Using the Mailbox/MU driver API functions, it is possible to pass a value from core to core via the dedicated registers (could be a scalar or a pointer to shared memory) and also to trigger inter-core interrupts for notifications.

For details about individual driver API functions, see the MCUXpresso SDK API Reference Manual of the specific multicore device. The MCUXpresso SDK is accompanied with the RPMsg-Lite documentation that shows how to use this API in multicore applications.

### Messaging mechanism

On top of Mailbox/MU drivers, a messaging system can be implemented, allowing messages to send between multiple endpoints created on each of the CPUs. The RPMsg-Lite library of the MCSDK provides this ability and serves as the preferred MCUXpresso SDK messaging library. It implements ring buffers in shared memory for messages exchange without the need of a locking mechanism.

The RPMsg-Lite provides the abstraction layer and can be easily ported to different multicore platforms and environments (Operating Systems). The advantages of such a messaging system are ease of use (there is no need to study behavior of the used underlying hardware) and smooth application code portability between platforms due to unified messaging API.

However, this costs several kB of code and data memory. The MCUXpresso SDK is accompanied by the RPMsg-Lite documentation and several multicore examples. You can also obtain the latest RPMsg-Lite code from the GitHub account [github.com/nxp-mcuxpresso/rpmsg-lite](https://github.com/nxp-mcuxpresso/rpmsg-lite).

### **Remote procedure calls**

To facilitate the IPC even more and to allow the remote functions invocation, the remote procedure call mechanism can be implemented. The eRPC of the MCSDK serves for these purposes and allows the ability to invoke a software routine on a remote system via a simple local function call. Utilizing different transport layers, it is possible to communicate between individual cores of multicore SoCs (via RPMsg-Lite) or between separate processors (via SPI, UART, or TCP/IP). The eRPC is mostly applicable to the MPU parts with enough of memory resources like i.MX parts.

The eRPC library allows you to export existing C functions without having to change their prototypes (in most cases). It is accompanied by the code generator tool that generates the shim code for serialization and invocation based on the IDL file with definitions of data types and remote interfaces (API).

If the communicating peer is running as a Linux OS user-space application, the generated code can be either in C/C++ or Python.

Using the eRPC simplifies the access to services implemented on individual cores. This way, the following types of applications running on dedicated cores can be easily interfaced:

- Communication stacks (USB, Thread, Bluetooth Low Energy, Zigbee)
- Sensor aggregation/fusion applications
- Encryption algorithms
- Virtual peripherals

The eRPC is publicly available from the following GitHub account: [github.com/EmbeddedRPC/erpc](https://github.com/EmbeddedRPC/erpc). Also, the MCUXpresso SDK is accompanied by the eRPC code and several multicore and multiprocessor eRPC examples.

The mentioned IPC levels demonstrate the scalability of the Multicore SDK library. Based on application needs, different IPC techniques can be used. It depends on the complexity, required speed, memory resources, system design, and so on. The MCSDK brings users the possibility for quick and easy development of multicore and multiprocessor applications.

### **Changelog Multicore 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](#).

#### **[25.12.00]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.14.0
  - eRPC generator (erpcgen) v1.14.0
  - Multicore Manager (MCMgr) v5.0.2
  - RPMsg-Lite v5.3.0

#### **[25.09.00]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.14.0

- eRPC generator (erpcgen) v1.14.0
- Multicore Manager (MCMgr) v5.0.1
- RPSMsg-Lite v5.2.1

#### [25.06.00]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.14.0
  - eRPC generator (erpcgen) v1.14.0
  - Multicore Manager (MCMgr) v5.0.0
  - RPSMsg-Lite v5.2.0

#### [25.03.00]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.13.0
  - eRPC generator (erpcgen) v1.13.0
  - Multicore Manager (MCMgr) v4.1.7
  - RPSMsg-Lite v5.1.4

#### [24.12.00]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.13.0
  - eRPC generator (erpcgen) v1.13.0
  - Multicore Manager (MCMgr) v4.1.6
  - RPSMsg-Lite v5.1.3

#### [2.16.0]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.13.0
  - eRPC generator (erpcgen) v1.13.0
  - Multicore Manager (MCMgr) v4.1.5
  - RPSMsg-Lite v5.1.2

#### [2.15.0]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.12.0
  - eRPC generator (erpcgen) v1.12.0
  - Multicore Manager (MCMgr) v4.1.5
  - RPSMsg-Lite v5.1.1

#### [2.14.0]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.11.0
  - eRPC generator (erpcgen) v1.11.0
  - Multicore Manager (MCMgr) v4.1.4
  - RPSMsg-Lite v5.1.0

#### [2.13.0\_imxrt1180a0]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.10.0
  - eRPC generator (erpcgen) v1.10.0
  - Multicore Manager (MCMgr) v4.1.3
  - RPSMsg-Lite v5.0.0

#### [2.13.0]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.10.0
  - eRPC generator (erpcgen) v1.10.0
  - Multicore Manager (MCMgr) v4.1.3
  - RPSMsg-Lite v5.0.0

#### [2.12.0\_imx93]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.9.1
  - eRPC generator (erpcgen) v1.9.1
  - Multicore Manager (MCMgr) v4.1.2
  - RPSMsg-Lite v4.0.1

#### [2.12.0]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.9.1
  - eRPC generator (erpcgen) v1.9.1
  - Multicore Manager (MCMgr) v4.1.2
  - RPSMsg-Lite v4.0.0

**[2.11.1]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.9.0
  - eRPC generator (erpcgen) v1.9.0
  - Multicore Manager (MCMgr) v4.1.1
  - RPSMsg-Lite v3.2.1

**[2.11.0]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.9.0
  - eRPC generator (erpcgen) v1.9.0
  - Multicore Manager (MCMgr) v4.1.1
  - RPSMsg-Lite v3.2.0

**[2.10.0]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.8.1
  - eRPC generator (erpcgen) v1.8.1
  - Multicore Manager (MCMgr) v4.1.1
  - RPSMsg-Lite v3.1.2

**[2.9.0]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.8.0
  - eRPC generator (erpcgen) v1.8.0
  - Multicore Manager (MCMgr) v4.1.1
  - RPSMsg-Lite v3.1.1

**[2.8.0]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.7.4
  - eRPC generator (erpcgen) v1.7.4
  - Multicore Manager (MCMgr) v4.1.0
  - RPSMsg-Lite v3.1.0

#### [2.7.0]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.7.3
  - eRPC generator (erpcgen) v1.7.3
  - Multicore Manager (MCMgr) v4.1.0
  - RPSMsg-Lite v3.0.0

#### [2.6.0]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.7.2
  - eRPC generator (erpcgen) v1.7.2
  - Multicore Manager (MCMgr) v4.0.3
  - RPSMsg-Lite v2.2.0

#### [2.5.0]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.7.1
  - eRPC generator (erpcgen) v1.7.1
  - Multicore Manager (MCMgr) v4.0.2
  - RPSMsg-Lite v2.0.2

#### [2.4.0]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.7.0
  - eRPC generator (erpcgen) v1.7.0
  - Multicore Manager (MCMgr) v4.0.1
  - RPSMsg-Lite v2.0.1

#### [2.3.1]

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.6.0
  - eRPC generator (erpcgen) v1.6.0
  - Multicore Manager (MCMgr) v4.0.0
  - RPSMsg-Lite v1.2.0

**[2.3.0]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.5.0
  - eRPC generator (erpcgen) v1.5.0
  - Multicore Manager (MCMgr) v3.0.0
  - RPMMsg-Lite v1.2.0

**[2.2.0]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.4.0
  - eRPC generator (erpcgen) v1.4.0
  - Multicore Manager (MCMgr) v2.0.1
  - RPMMsg-Lite v1.1.0

**[2.1.0]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.3.0
  - eRPC generator (erpcgen) v1.3.0

**[2.0.0]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.2.0
  - eRPC generator (erpcgen) v1.2.0
  - Multicore Manager (MCMgr) v2.0.0
  - RPMMsg-Lite v1.0.0

**[1.1.0]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.1.0
  - Multicore Manager (MCMgr) v1.1.0
  - Open-AMP / RPMMsg based on SHA1 ID 44b5f3c0a6458f3cf80 rev01

**[1.0.0]**

- Multicore SDK component versions:
  - embedded Remote Procedure Call (eRPC) v1.0.0
  - Multicore Manager (MCMgr) v1.0.0
  - Open-AMP / RPMMsg based on SHA1 ID 44b5f3c0a6458f3cf80 rev00

## Multicore SDK Components

### RPMSG-Lite

#### MCUXpresso SDK : mcuxsdk-middleware-rpmsg-lite

**Overview** This repository is for MCUXpresso SDK RPMSG-Lite middleware delivery and it contains RPMSG-Lite component 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](#) for the complete delivery of MCUXpresso SDK to be able to build and run RPMSG-Lite examples that are based on mcux-sdk-middleware-rpmsg-lite component.

**Documentation** Overall details can be reviewed here: [MCUXpresso SDK Online Documentation](#)

Visit [RPMSG-Lite - Documentation](#) to review details on the contents in this sub-repo.

For Further API documentation, please look at [doxygen documentation](#)

**Setup** Instructions on how to install the MCUXpresso SDK provided from GitHub via west manifest [Getting Started with SDK - Detailed Installation Instructions](#)

**Contribution** We welcome and encourage the community to submit patches directly to the rpmsg-lite project placed on github. Contributing can be managed via pull-requests. Before a pull-request is created the code should be tested and properly formatted.

---

**RPMSG-Lite** This documentation describes the RPMsg-Lite component, which is a lightweight implementation of the Remote Processor Messaging (RPMsg) protocol. The RPMsg protocol defines a standardized binary interface used to communicate between multiple cores in a heterogeneous multicore system.

Compared to the RPMsg implementation of the Open Asymmetric Multi Processing (OpenAMP) framework (<https://github.com/OpenAMP/open-amp>), the RPMsg-Lite offers a code size reduction, API simplification, and improved modularity. On smaller Cortex-M0+ based systems, it is recommended to use RPMsg-Lite.

The RPMsg-Lite is an open-source component developed by NXP Semiconductors and released under the BSD-compatible license.

For overview please read RPMSG-Lite VirtIO Overview.

For RPMSG-Lite Design Considerations please read RPMSG-Lite Design Considerations.

**Motivation to create RPMsg-Lite** There are multiple reasons why RPMsg-Lite was developed. One reason is the need for the small footprint of the RPMsg protocol-compatible communication component, another reason is the simplification of extensive API of OpenAMP RPMsg implementation.

RPMsg protocol was not documented, and its only definition was given by the Linux Kernel and legacy OpenAMP implementations. This has changed with [1] which is a standardization protocol allowing multiple different implementations to coexist and still be mutually compatible.



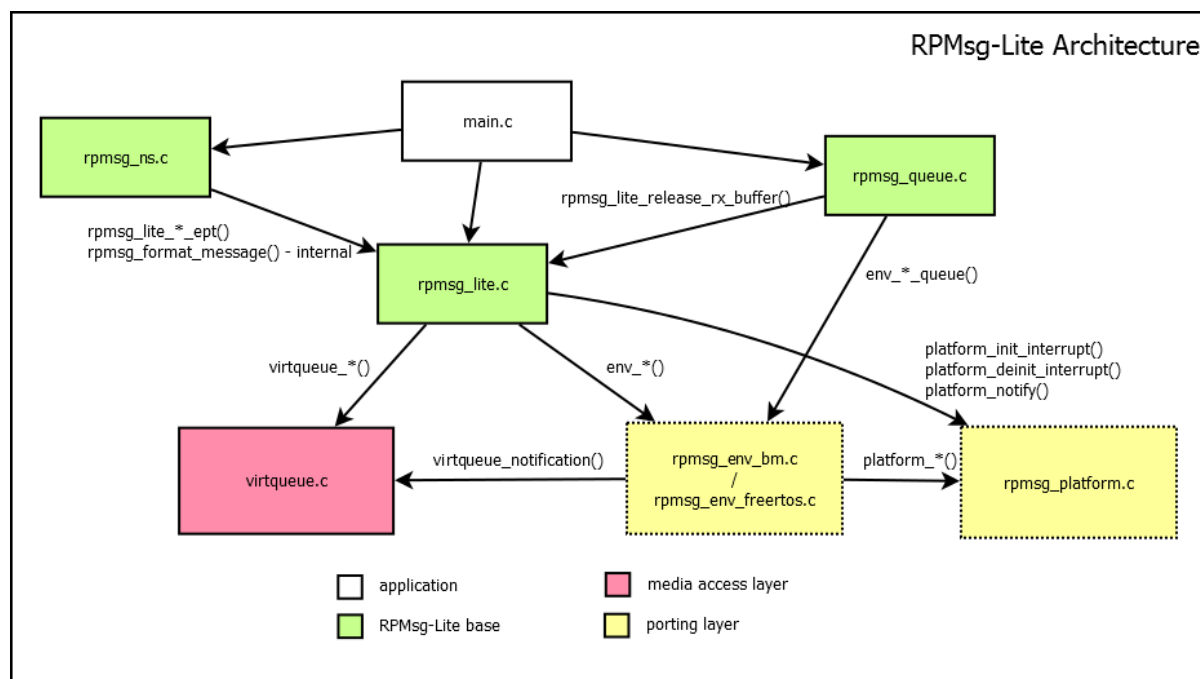
Small MCU-based systems often do not implement dynamic memory allocation. The creation of static API in RPMsg-Lite enables another reduction of resource usage. Not only does the dynamic allocation adds another 5 KB of code size, but also communication is slower and less deterministic, which is a property introduced by dynamic memory. The following table shows some rough comparison data between the OpenAMP RPMsg implementation and new RPMsg-Lite implementation:

Component / Configuration	Flash [B]	RAM [B]
OpenAMP RPMsg / Release (reference)	5547	456 + dynamic
RPMsg-Lite / Dynamic API, Release	3462	56 + dynamic
Relative Difference [%]	~62.4%	~12.3%
RPMsg-Lite / Static API (no malloc), Release	2926	352
Relative Difference [%]	~52.7%	~77.2%

**Implementation** The implementation of RPMsg-Lite can be divided into three sub-components, from which two are optional. The core component is situated in `rpmsg_lite.c`. Two optional components are used to implement a blocking receive API (in `rpmsg_queue.c`) and dynamic “named” endpoint creation and deletion announcement service (in `rpmsg_ns.c`).

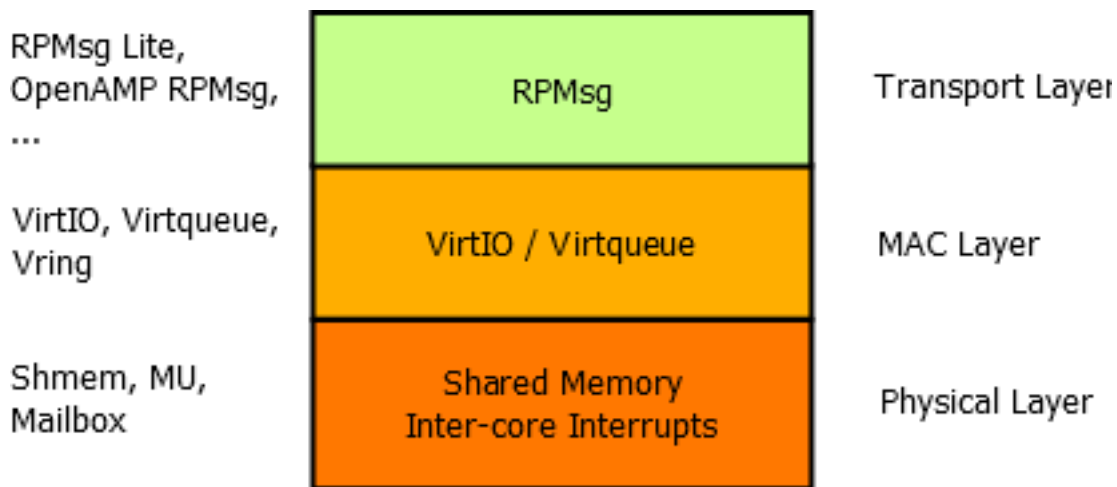
The actual “media access” layer is implemented in `virtqueue.c`, which is one of the few files shared with the OpenAMP implementation. This layer mainly defines the shared memory model, and internally defines used components such as `vring` or `virtqueue`.

The porting layer is split into two sub-layers: the environment layer and the platform layer. The first sublayer is to be implemented separately for each environment. (The bare metal environment already exists and is implemented in `rpmsg_env_bm.c`, and the FreeRTOS environment is implemented in `rpmsg_env_freertos.c` etc.) Only the source file, which matches the used environment, is included in the target application project. The second sublayer is implemented in `rpmsg_platform.c` and defines low-level functions for interrupt enabling, disabling, and triggering mainly. The situation is described in the following figure:



**RPMsg-Lite core sub-component** This subcomponent implements a blocking send API and callback-based receive API. The RPMsg protocol is part of the transport layer. This is realized by using so-called endpoints. Each endpoint can be assigned a different receive callback function.

However, it is important to notice that the callback is executed in an interrupt environment in current design. Therefore, certain actions like memory allocation are discouraged to execute in the callback. The following figure shows the role of RPMsg in an ISO/OSI-like layered model:



**Queue sub-component (optional)** This subcomponent is optional and requires implementation of the `env_*_queue()` functions in the environment porting layer. It uses a blocking receive API, which is common in RTOS-environments. It supports both copy and nocopy blocking receive functions.

**Name Service sub-component (optional)** This subcomponent is a minimum implementation of the name service which is present in the Linux Kernel implementation of RPMsg. It allows the communicating node both to send announcements about “named” endpoint (in other words, channel) creation or deletion and to receive these announcement taking any user-defined action in an application callback. The endpoint address used to receive name service announcements is arbitrarily fixed to be 53 (0x35).

**Usage** The application should put the `/rpmmsg_lite/lib/include` directory to the include path and in the application, include either the `rpmmsg_lite.h` header file, or optionally also include the `rpmmsg_queue.h` and/or `rpmmsg_ns.h` files. Both porting sublayers should be provided for you by NXP, but if you plan to use your own RTOS, all you need to do is to implement your own environment layer (in other words, `rpmmsg_env_myrtos.c`) and to include it in the project build.

The initialization of the stack is done by calling the `rpmmsg_lite_master_init()` on the master side and the `rpmmsg_lite_remote_init()` on the remote side. This initialization function must be called prior to any RPMsg-Lite API call. After the init, it is wise to create a communication endpoint, otherwise communication is not possible. This can be done by calling the `rpmmsg_lite_create_ept()` function. It optionally accepts a last argument, where an internal context of the endpoint is created, just in case the `RL_USE_STATIC_API` option is set to 1. If not, the stack internally calls `env_alloc()` to allocate dynamic memory for it. In case a callback-based receiving is to be used, an ISR-callback is registered to each new endpoint with user-defined callback data pointer. If a blocking receive is desired (in case of RTOS environment), the `rpmmsg_queue_create()` function must be called before calling `rpmmsg_lite_create_ept()`. The queue handle is passed to the endpoint creation function as a callback data argument and the callback function is set to `rpmmsg_queue_rx_cb()`. Then, it is possible to use `rpmmsg_queue_receive()` function to listen on a queue object for incoming messages. The `rpmmsg_lite_send()` function is used to send messages to the other side.

The RPMsg-Lite also implements no-copy mechanisms for both sending and receiving operations. These methods require specifics that have to be considered when used in an application.

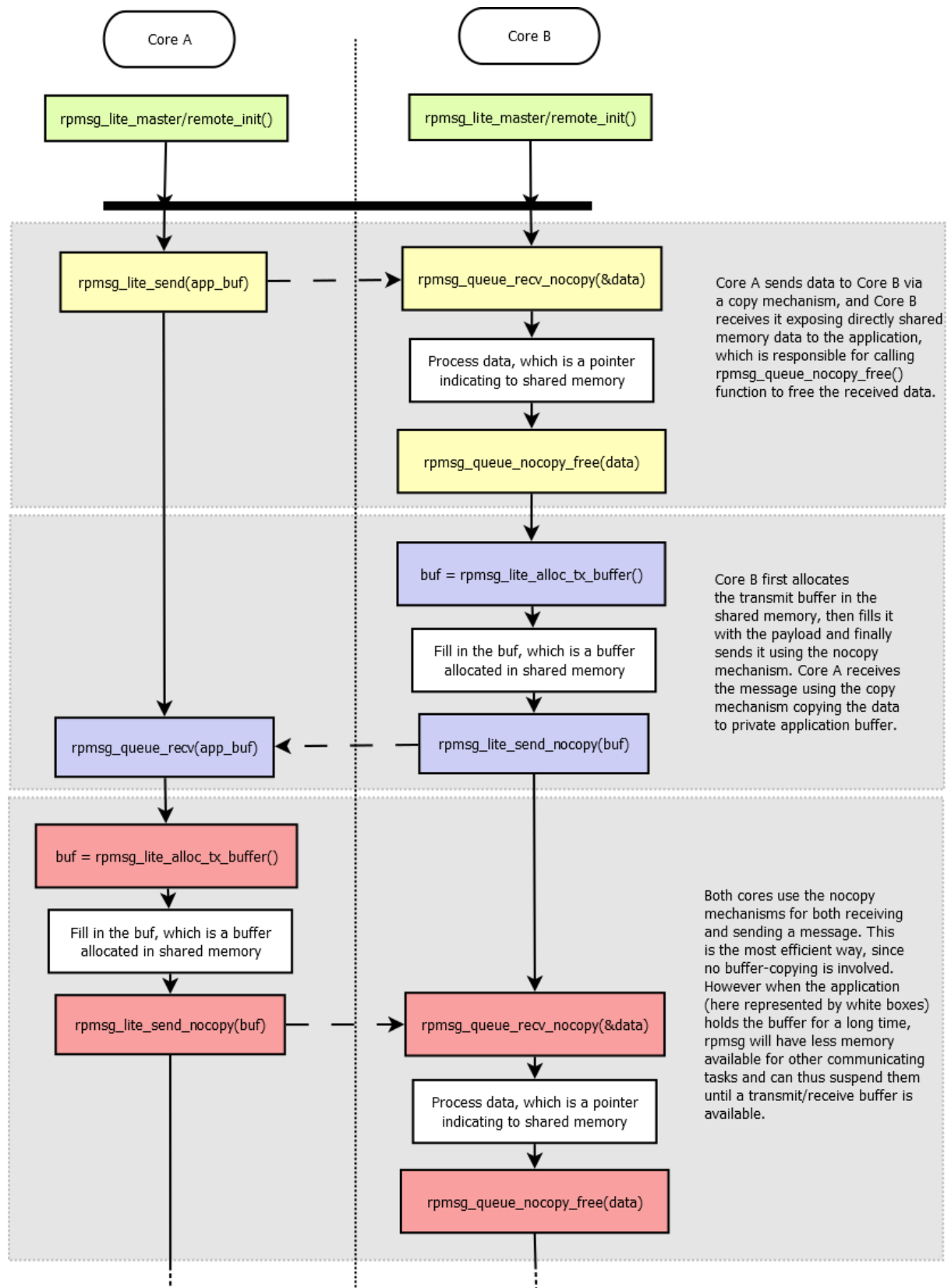
no-copy-send mechanism: This mechanism allows sending messages without the cost for copying data from the application buffer to the RPMsg/virtio buffer in the shared memory. The sequence of no-copy sending steps to be performed is as follows:

- Call the `rpmmsg_lite_alloc_tx_buffer()` function to get the virtio buffer and provide the buffer pointer to the application.
- Fill the data to be sent into the pre-allocated virtio buffer. Ensure that the filled data does not exceed the buffer size (provided as the `rpmmsg_lite_alloc_tx_buffer()` size output parameter).
- Call the `rpmmsg_lite_send_nocopy()` function to send the message to the destination endpoint. Consider the cache functionality and the virtio buffer alignment. See the `rpmmsg_lite_send_nocopy()` function description below.

no-copy-receive mechanism: This mechanism allows reading messages without the cost for copying data from the virtio buffer in the shared memory to the application buffer. The sequence of no-copy receiving steps to be performed is as follows:

- Call the `rpmmsg_queue_rcv_nocopy()` function to get the virtio buffer pointer to the received data.
- Read received data directly from the shared memory.
- Call the `rpmmsg_queue_nocopy_free()` function to release the virtio buffer and to make it available for the next data transfer.

The user is responsible for destroying any RPMsg-Lite objects he has created in case of deinitialization. In order to do this, the function `rpmmsg_queue_destroy()` is used to destroy a queue, `rpmmsg_lite_destroy_ept()` is used to destroy an endpoint and finally, `rpmmsg_lite_deinit()` is used to deinitialize the RPMsg-Lite intercore communication stack. Deinitialize all endpoints using a queue before deinitializing the queue. Otherwise, you are actively invalidating the used queue handle, which is not allowed. RPMsg-Lite does not check this internally, since its main aim is to be lightweight.



**Examples** RPMsg\_Lite multicore examples are part of NXP MCUXpressoSDK packages. Visit <https://mcuxpresso.nxp.com> to configure, build and download these packages. To get the board list with multicore support (RPMsg\_Lite included) use filtering based on Middleware and search for 'multicore' string. Once the selected package with the multicore middleware is downloaded,

see

<MCUXpressoSDK\_install\_dir>/boards/<board\_name>/multicore\_examples for RPMsg\_Lite multicore examples with 'rpmsg\_lite\_' name prefix.

Another way of getting NXP MCUXpressoSDK RPMsg\_Lite multicore examples is using the [mcuxsdk-manifests](#) Github repo. Follow the description how to use the West tool to clone and update the mcuxsdk-manifests repo in [readme section](#). Once done the armgcc rpmsg\_lite examples can be found in

mcuxsdk/examples/\_<board\_name>/multicore\_examples

You can use the evkmimxrt1170 as the board\_name for instance. Similar to MCUXpressoSDK packages the RPMsg\_Lite examples use the 'rpmsg\_lite\_' name prefix.

## Notes

**Environment layers implementation** Several environment layers are provided in lib/rpmsg\_lite/porting/environment folder. Not all of them are fully tested however. Here is the list of environment layers that passed testing:

- rpmsg\_env\_bm.c
- rpmsg\_env\_freertos.c
- rpmsg\_env\_xos.c
- rpmsg\_env\_threadx.c

The rest of environment layers has been created and used in some experimental projects, it has been running well at the time of creation but due to the lack of unit testing there is no guarantee it is still fully functional.

**Shared memory configuration** It is important to correctly initialize/configure the shared memory for data exchange in the application. The shared memory must be accessible from both the master and the remote core and it needs to be configured as Non-Cacheable memory. Dedicated shared memory section in linker file is also a good practise, it is recommended to use linker files from MCUXpressoSDK packages for NXP devices based applications. It needs to be ensured no other application part/component is unintentionally accessing this part of memory.

**Configuration options** The RPMsg-Lite can be configured at the compile time. The default configuration is defined in the rpmsg\_default\_config.h header file. This configuration can be customized by the user by including rpmsg\_config.h file with custom settings. The following table summarizes all possible RPMsg-Lite configuration options.

Config- uration option	De- fault value	Usage
RL_MS_PE (1)		Delay in milliseconds used in non-blocking API functions for polling.
RL_BUFEE (496)		Size of the buffer payload, it must be more than 1 byte, and has to be word align (including rpmsg header size 16 bytes), if not it will be aligned up
RL_BUFEE (2)		Number of the buffers, it must be power of two (2, 4, ...)
RL_API_H (1)		Zero-copy API functions enabled/disabled.
RL_USE_S' (0)		Static API functions (no dynamic allocation) enabled/disabled.
RL_USE_D (0)		Memory cache management of shared memory. Use in case of data cache is enabled for shared memory.
RL_CLEAF (0)		Clearing used buffers before returning back to the pool of free buffers enabled/disabled.
RL_USE_M (0)		When enabled IPC interrupts are managed by the Multicore Manager (IPC interrupts router), when disabled RPMsg-Lite manages IPC interrupts by itself.
RL_USE_E (0)		When enabled the environment layer uses its own context. Required for some environments (QNX). The default value is 0 (no context, saves some RAM).
RL_DEBU (0)		When enabled buffer pointers passed to <code>rpmsg_lite_send_nocopy()</code> and <code>rpmsg_lite_release_rx_buffer()</code> functions (enabled by <code>RL_API_HAS_ZEROCOPY</code> config) are checked to avoid passing invalid buffer pointer. The default value is 0 (disabled). Do not use in RPMsg-Lite to Linux configuration.
RL_ALLOV (0)		When enabled the opposite side is notified each time received buffers are consumed and put into the queue of available buffers. Enable this option in RPMsg-Lite to Linux configuration to allow unblocking of the Linux blocking send. The default value is 0 (RPMsg-Lite to RPMsg-Lite communication).
RL_ALLOV (0)		It allows to define custom shared memory configuration and replacing the shared memory related global settings from <code>rpmsg_config.h</code> . This is useful when multiple instances are running in parallel but different shared memory arrangement (vring size & alignment, buffers size & count) is required. The default value is 0 (all RPMsg_Lite instances use the same shared memory arrangement as defined by common config macros).
RL_ASSER	see rpmsg	Assert implementation.

**How to format rpmsg-lite code** To format code, use the application developed by Google, named *clang-format*. This tool is part of the [llvm](#) project. Currently, the clang-format 10.0.0 version is used for rpmsg-lite. The set of style settings used for clang-format is defined in the `.clang-format` file, placed in a root of the rpmsg-lite directory where Python script `run_clang_format.py` can be executed. This script executes the application named *clang-format.exe*. You need to have the path of this application in the OS's environment path, or you need to change the script.

## References

[1] M. Novak, M. Cingel, **Lockless Shared Memory Based Multicore Communication Protocol**  
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**Changelog RPMMSG-Lite** 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](#).

**[v5.3.0]****Added**

- RT700 porting layer added support to send rpmsg messages between CM33\_0 <-> Hifi1 and CM33\_1 <-> Hifi4 cores.
- Add new platform macro `RL_PLATFORM_MAX_ISR_COUNT` this will set number of IRQ count per platform. This macro is then used in environment layers to set `isr_table` size where irq handles are registered. It size should match the bit length of `VQ_ID` so all combinations can fit into table.
- Unit tests updated to improve code coverage, new unit tests added covering static allocations in rtos environment layers.

**Fixed**

- `virtio.h` removed `typedef uint8_t boolean` and in its place use standard C99 `bool` type to avoid potential type conflicts.
- `env_acquire_sync_lock()` and `env_release_sync_lock()` synchronization primitives removed
- Kconfig consolidation, when `RL_ALLOW_CUSTOM_SHMEM_CONFIG` enabled the `platform_get_custom_shmem_config()` function needs to be implemented in platform layer to provide custom shared memory configuration for RPMsg-Lite instance.

**v5.2.1****Added**

- Doc added RPMSG-Lite VirtIO Overview
- Doc added RPMSG-Lite Design Considerations
- Added `frdmimxrt1186` unit testing

**Changed**

- Remove limitation that `RL_BUFFER_SIZE` needs to be power of 2. It just has to be more than 16 bytes, e.g. 16 bytes of rpmsg header and payload size at least 1 byte and word aligned, if not it will be aligned up.

**Fixed**

- Fixed CERT-C INT31-C violation in `platform_notify` function in `rpmsg_platform.c` for `imxrt700_m33`, `imxrt700_hifi4`, `imxrt700_hifi1` platforms

**v5.2.0****Added**

- Add MCXL20 porting layer and unit testing
- New utility macro `RL_CALCULATE_BUFFER_COUNT_DOWN_SAFE` to safely determine maximum buffer count within shared memory while preventing integer underflow.
- RT700 platform add support for MCMGR in DSPs



## Changed

- Change `rpmsg_platform.c` to support new MCMGR API
- Improved input validation in initialization functions to properly handle insufficient memory size conditions.
- Refactored repeated buffer count calculation pattern for better code maintainability.
- To make sure that remote has already registered IRQ there is required App level IPC mechanism to notify master about it

## Fixed

- Fixed `env_wait_for_link_up` function to handle timeout in link state checks for baremetal and qnx environment, `RL_BLOCK` mode can be used to wait indefinitely.
- Fixed CERT-C INT31-C violation by adding compile-time check to ensure `RL_PLATFORM_HIGHEST_LINK_ID` remains within safe range for 16-bit casting in virtqueue ID creation.
- Fixed CERT-C INT30-C violations by adding protection against unsigned integer underflow in shared memory calculations, specifically in `shmem_length - (uint32_t)RL_VRING_OVERHEAD` and `shmem_length - 2U * shmem_config.vring_size` expressions.
- Fixed CERT INT31-C violation in `platform_interrupt_disable()` and similar functions by replacing unsafe cast from `uint32_t` to `int32_t` with a return of 0 constant.
- Fixed unsigned integer underflow in `rpmsg_lite_alloc_tx_buffer()` where subtracting header size from buffer size could wrap around if buffer was too small, potentially leading to incorrect buffer sizing.
- Fixed CERT-C INT31-C violation in `rpmsg_lite.c` where `size` parameter was cast from `uint32_t` to `uint16_t` without proper validation.
  - Applied consistent masking approach to both `size` and `flags` parameters: `(uint16_t)(value & 0xFFFFU)`.
  - This fix prevents potential data loss when `size` values exceed 65535.
- Fixed CERT INT31-C violation in `env_memset` functions by explicitly converting `int32_t` values to unsigned char using bit masking. This prevents potential data loss or misinterpretation when passing values outside the unsigned char range (0-255) to the standard `memset()` function.
- Fixed CERT-C INT31-C violations in RPMsg-Lite environment porting: Added validation checks for signed-to-unsigned integer conversions to prevent data loss and misinterpretation.
  - `rpmsg_env_freertos.c`: Added validation before converting `int32_t` to `UBaseType_t`.
  - `rpmsg_env_qnx.c`: Fixed format string and added validation before assigning to `mqstat` fields.
  - `rpmsg_env_threadx.c`: Added validation to prevent integer overflow and negative values.
  - `rpmsg_env_xos.c`: Added range checking before casting to `uint16_t`.
  - `rpmsg_env_zephyr.c`: Added validation before passing values to `k_msgq_init`.
- Fixed a CERT INT31-C compliance issue in `env_get_current_queue_size()` function where an unsigned queue count was cast to a signed `int32_t` without proper validation, which could lead to lost or misinterpreted data if queue size exceeded `INT32_MAX`.
- Fixed CERT INT31-C violation in `rpmsg_platform.c` where `memcmp()` return value (signed int) was compared with unsigned constant without proper type handling.



- Fixed CERT INT31-C violation in `rpmsg_platform.c` where casting from `uint32_t` to `uint16_t` could potentially result in data loss. Changed length variable type from `uint16_t` to `uint32_t` to properly handle memory address differences without truncation.
- Fixed potential integer overflow in `env_sleep_msec()` function in ThreadX environment implementation by rearranging calculation order in the sleep duration formula.
- Fixed CERT-C INT31-C violation in RPMsg-Lite where bitwise NOT operations on integer constants were performed in signed integer context before being cast to unsigned. This could potentially lead to misinterpreted data on `imx943` platform.
- Added `RL_MAX_BUFFER_COUNT` (32768U) and `RL_MAX_VRING_ALIGN` (65536U) limit to ensure alignment values cannot contribute to integer overflow
- Fixed CERT INT31-C violation in `vring_need_event()`, added cast to `uint16_t` for each operand.

#### v5.1.4 - 27-Mar-2025

##### Added

- Add KW43B43 porting layer

##### Changed

- Doxygen bump to version 1.9.6

#### v5.1.3 - 13-Jan-2025

##### Added

- Memory cache management of shared memory. Enable with `#define RL_USE_DCACHE (1)` in `rpmsg_config.h` in case of data cache is used.
- Cmake/Kconfig support added.
- Porting layers for `imx95`, `imxrt700`, `mcmxw71x`, `mcmxw72x`, `kw47b42` added.

#### v5.1.2 - 08-Jul-2024

##### Changed

- Zephyr-related changes.
- Minor Misra corrections.

#### v5.1.1 - 19-Jan-2024

##### Added

- Test suite provided.
- Zephyr support added.

### Changed

- Minor changes in platform and env. layers, minor test code updates.

### v5.1.0 - 02-Aug-2023

#### Added

- RPMMsg-Lite: Added aarch64 support.

#### Changed

- RPMMsg-Lite: Increased the queue size to (2 \* RL\_BUFFER\_COUNT) to cover zero copy cases.
- Code formatting using LLVM16.

#### Fixed

- Resolved issues in ThreadX env. layer implementation.

### v5.0.0 - 19-Jan-2023

#### Added

- Timeout parameter added to `rpmmsg_lite_wait_for_link_up` API function.

#### Changed

- Improved debug check buffers implementation - instead of checking the pointer fits into shared memory check the presence in the VirtIO ring descriptors list.
- VRING\_SIZE is set based on number of used buffers now (as calculated in `vring_init`) - updated for all platforms that are not communicating to Linux rpmmsg counterpart.

#### Fixed

- Fixed wrong RL\_VRING\_OVERHEAD macro comment in platform.h files
- Misra corrections.

### v4.0.0 - 20-Jun-2022

#### Added

- Added support for custom shared memory arrangement per the RPMMsg\_Lite instance.
- Introduced new `rpmmsg_lite_wait_for_link_up()` API function - this allows to avoid using busy loops in rtos environments, GitHub PR [#21](#).

#### Changed

- Adjusted `rpmmsg_lite_is_link_up()` to return RL\_TRUE/RL\_FALSE.

**v3.2.0 - 17-Jan-2022****Added**

- Added support for i.MX8 MP multicore platform.

**Changed**

- Improved static allocations - allow OS-specific objects being allocated statically, GitHub PR [#14](#).
- Aligned rpmsg\_env\_xos.c and some platform layers to latest static allocation support.

**Fixed**

- Minor Misra and typo corrections, GitHub PR [#19](#), [#20](#).

**v3.1.2 - 16-Jul-2021****Added**

- Addressed MISRA 21.6 rule violation in rpmsg\_env.h (use SDK's PRINTF in MCUXpressoSDK examples, otherwise stdio printf is used).
- Added environment layers for XOS.
- Added support for i.MX RT500, i.MX RT1160 and i.MX RT1170 multicore platforms.

**Fixed**

- Fixed incorrect description of the rpmsg\_lite\_get\_endpoint\_from\_addr function.

**Changed**

- Updated RL\_BUFFER\_COUNT documentation (issue [#10](#)).
- Updated imxrt600\_hifi4 platform layer.

**v3.1.1 - 15-Jan-2021****Added**

- Introduced RL\_ALLOW\_CONSUMED\_BUFFERS\_NOTIFICATION config option to allow opposite side notification sending each time received buffers are consumed and put into the queue of available buffers.
- Added environment layers for Threadx.
- Added support for i.MX8QM multicore platform.

**Changed**

- Several MISRA C-2012 violations addressed.

**v3.1.0 - 22-Jul-2020**

### Added

- Added support for several new multicore platforms.

### Fixed

- MISRA C-2012 violations fixed (7.4).
- Fixed missing lock in `rpmsg_lite_rx_callback()` for QNX env.
- Correction of `rpmsg_lite_instance` structure members description.
- Address -Waddress-of-packed-member warnings in GCC9.

### Changed

- Clang update to v10.0.0, code re-formatted.

## v3.0.0 - 20-Dec-2019

### Added

- Added support for several new multicore platforms.

### Fixed

- MISRA C-2012 violations fixed, incl. data types consolidation.
- Code formatted.

## v2.2.0 - 20-Mar-2019

### Added

- Added configuration macro `RL_DEBUG_CHECK_BUFFERS`.
- Several MISRA violations fixed.
- Added environment layers for QNX and Zephyr.
- Allow environment context required for some environment (controlled by the `RL_USE_ENVIRONMENT_CONTEXT` configuration macro).
- Data types consolidation.

## v1.1.0 - 28-Apr-2017

### Added

- Supporting i.MX6SX and i.MX7D MPU platforms.
- Supporting LPC5411x MCU platform.
- Baremetal and FreeRTOS support.
- Support of copy and zero-copy transfer.
- Support of static API (without dynamic allocations).

## Multicore Manager

### MCUXpresso SDK : mcuxsdk-middleware-mcmgr (Multicore Manager)

**Overview** This repository is for MCUXpresso SDK Multicore Manager middleware delivery and it contains Multicore Manager component 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](#) for the complete delivery of MCUXpresso SDK to be able to build and run Multicore Manager examples that are based on mcux-sdk-middleware-mcmgr component.

**Documentation** Overall details can be reviewed here: [MCUXpresso SDK Online Documentation](#)

Visit [Multicore Manager - Documentation](#) to review details on the contents in this sub-repo.

For Further API documentation, please look at [doxygen documentation](#)

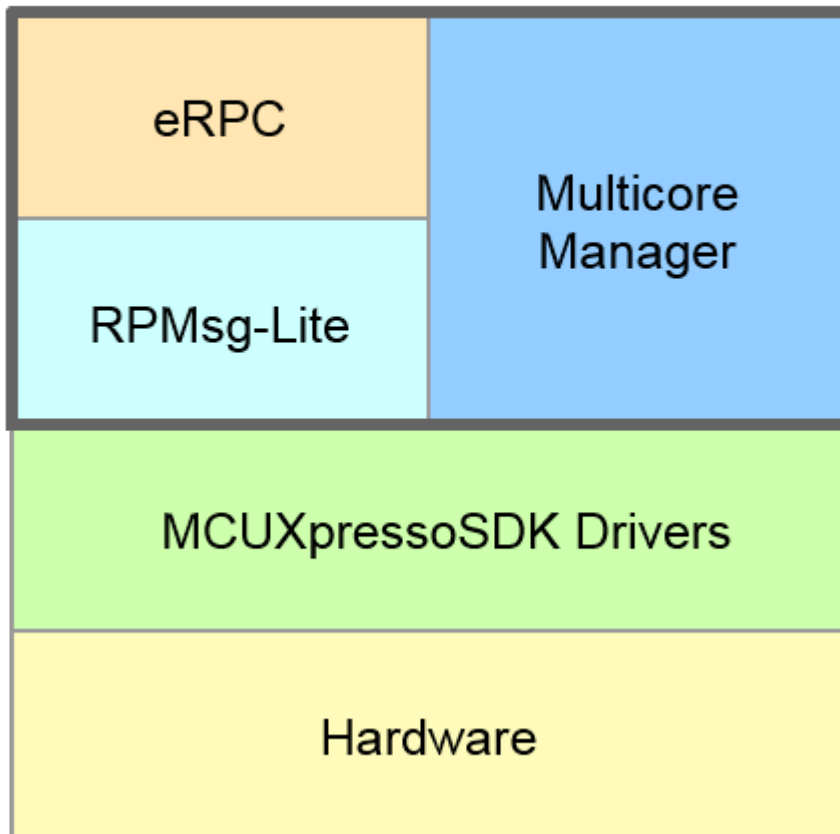
**Setup** Instructions on how to install the MCUXpresso SDK provided from GitHub via west manifest [Getting Started with SDK - Detailed Installation Instructions](#)

**Contribution** We welcome and encourage the community to submit patches directly to the mcmgr project placed on github. Contributing can be managed via pull-requests. Before a pull-request is created the code should be tested and properly formatted.

---

**Multicore Manager (MCMGR)** The Multicore Manager (MCMGR) software library provides a number of services for multicore systems. This library is distributed as a part of the Multicore SDK (MCSDK). Together, the MCSDK and the MCUXpresso SDK (SDK) form a framework for development of software for NXP multicore devices.

The MCMGR component is located in the <MCUXpressoSDK\_install\_dir>/middleware/multicore/mcmgr directory.



The Multicore Manager provides the following major functions:

- Maintains information about all cores in system.
- Secondary/auxiliary core(s) startup and shutdown.
- Remote core monitoring and event handling.

**Usage of the MCMGR software component** The main use case of MCMGR is the secondary/auxiliary core start. This functionality is performed by the public API function.

Example of MCMGR usage to start secondary core:

```
#include "mcmgr.h"

void main()
{
    /* Initialize MCMGR - low level multicore management library.
       Call this function as close to the reset entry as possible,
       (into the startup sequence) to allow CoreUp event triggering. */
    MCMGR_EarlyInit();

    /* Initialize MCMGR, install generic event handlers */
    MCMGR_Init();
}
```

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```

/* Boot secondary core application from the CORE1_BOOT_ADDRESS, pass "1" as startup data,
↳ starting synchronously. */
MCMGR_StartCore(kMCMGR_Core1, CORE1_BOOT_ADDRESS, 1, kMCMGR_Start_Synchronous);
.
.
.
/* Stop secondary core execution. */
MCMGR_StopCore(kMCMGR_Core1);
}

```

Some platforms allow stopping and re-starting the secondary core application again, using the MCMGR\_StopCore / MCMGR\_StartCore API calls. It is necessary to ensure the initially loaded image is not corrupted before re-starting, especially if it deals with the RAM target. Cache coherence has to be considered/ensured as well.

It could also happen that the secondary core application stops running correctly and the primary core application does not know about that situation. Therefore, it is beneficial to implement a mechanism for core health monitoring. The *test\_heartbeat* unit test can serve as an example how to ensure that: secondary core could periodically send heartbeat signals to the primary core using MCMGR\_TriggerEvent() API to indicate that it is alive and functioning properly.

Another important MCMGR feature is the ability for remote core monitoring and handling of events such as reset, exception, and application events. Application-specific callback functions for events are registered by the MCMGR\_RegisterEvent() API. Triggering these events is done using the MCMGR\_TriggerEvent() API. mcmgr\_event\_type\_t enums all possible event types.

An example of MCMGR usage for remote core monitoring and event handling. Code for the primary side:

```

#include "mcmgr.h"

#define APP_RPMSG_READY_EVENT_DATA (1)
#define APP_NUMBER_OF_CORES (2)
#define APP_SECONDARY_CORE kMCMGR_Core1

/* Callback function registered via the MCMGR_RegisterEvent() and triggered by MCMGR_TriggerEvent()
↳ called on the secondary core side */
void RPSMsgRemoteReadyEventHandler(mcmgr_core_t coreNum, uint16_t eventData, void *context)
{
    uint16_t *data = &((uint16_t *)context)[coreNum];

    *data = eventData;
}

void main()
{
    uint16_t RPSMsgRemoteReadyEventData[NUMBER_OF_CORES] = {0};

    /* Initialize MCMGR - low level multicore management library.
       Call this function as close to the reset entry as possible,
       (into the startup sequence) to allow CoreUp event triggering. */
    MCMGR_EarlyInit();

    /* Initialize MCMGR, install generic event handlers */
    MCMGR_Init();

    /* Register the application event before starting the secondary core */
    MCMGR_RegisterEvent(kMCMGR_RemoteApplicationEvent, RPSMsgRemoteReadyEventHandler, (void
↳ *)RPSMsgRemoteReadyEventData);

```

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```
/* Boot secondary core application from the CORE1_BOOT_ADDRESS, pass rpmsg_lite_base address,
↳as startup data, starting synchronously. */
MCMGR_StartCore(APP_SECONDARY_CORE, CORE1_BOOT_ADDRESS, (uint32_t)rpmsg_lite_
↳base, kMCMGR_Start_Synchronous);

/* Wait until the secondary core application signals the rpmsg remote has been initialized and is ready to
↳communicate. */
while(APP_RPMSG_READY_EVENT_DATA != RPSMsgRemoteReadyEventData[APP_SECONDARY_
↳CORE]) {}
.
.
.
}
```

Code for the secondary side:

```
#include "mcmgr.h"

#define APP_RPMSG_READY_EVENT_DATA (1)

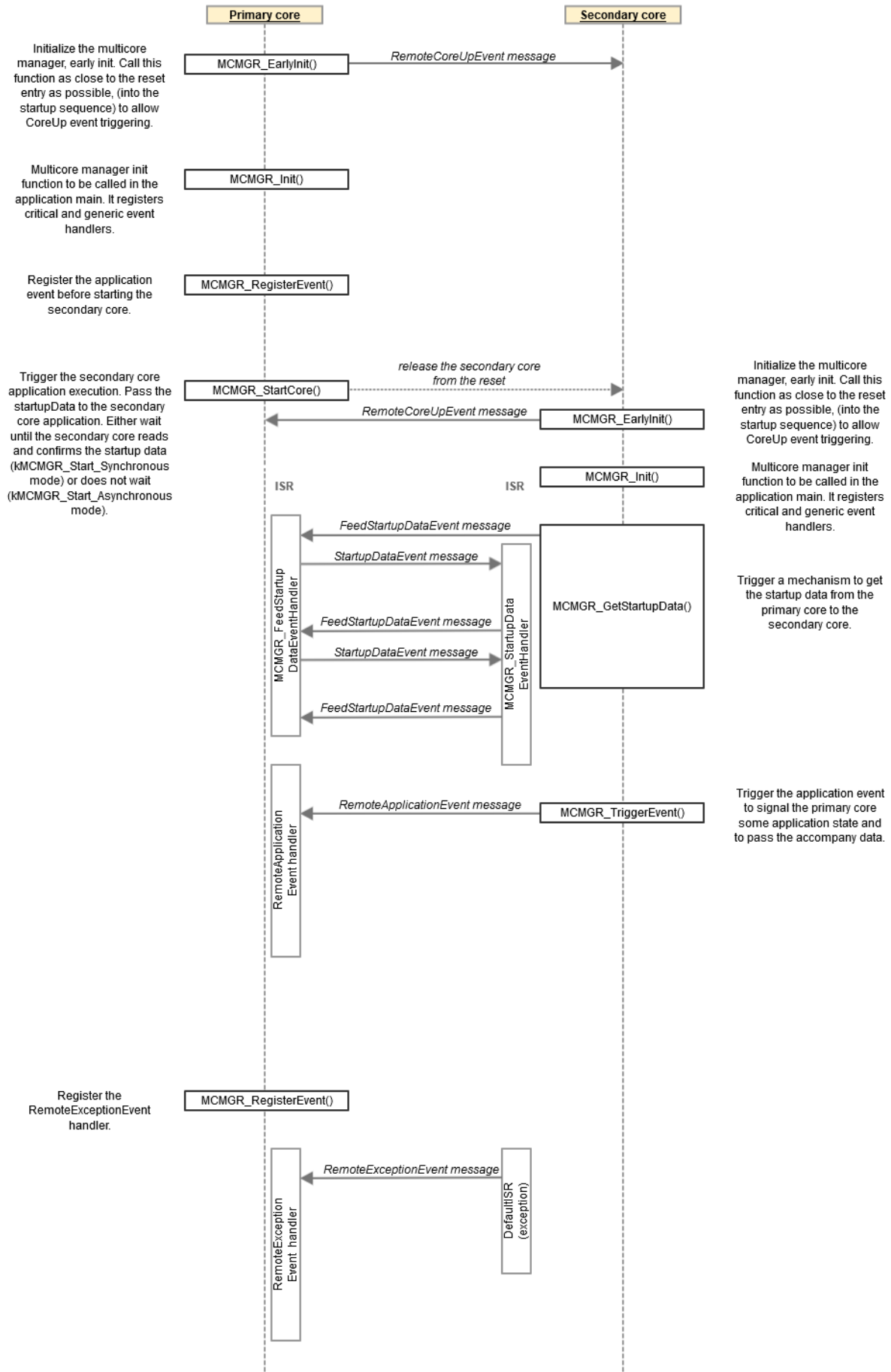
void main()
{
    /* Initialize MCMGR - low level multicore management library.
       Call this function as close to the reset entry as possible,
       (into the startup sequence) to allow CoreUp event triggering. */
    MCMGR_EarlyInit();

    /* Initialize MCMGR, install generic event handlers */
    MCMGR_Init();
    .
    .
    .

    /* Signal the to other core that we are ready by triggering the event and passing the APP_RPMSG_
    ↳READY_EVENT_DATA */
    MCMGR_TriggerEvent(kMCMGR_Core0, kMCMGR_RemoteApplicationEvent, APP_RPMSG_
    ↳READY_EVENT_DATA);
    .
    .
    .
}
```

**MCMGR Data Exchange Diagram** The following picture shows how the handshakes are supposed to work between the two cores in the MCMGR software.





**Changelog Multicore Manager** 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](#).

## [v5.0.2]

### Added

- Added gcov options and configs to support mcmgr code coverage
- Added new test\_weak\_mu\_isr testcase for devices with MU peripheral
- Added new test\_heartbeat testcase showing heartbeat mechanism between primary and secondary cores using the MCMGR

## v5.0.1

### Added

- Added frdmimxrt1186 unit testing

### Changed

- [KW43] Rename core#1 reset control register

### Fixed

- Added CX flag into CMakeLists.txt to allow c++ build compatibility.
- Fix path to mcmgr headers directory in doxyfile

## v5.0.0

### Added

- Added MCMGR\_BUSY\_POLL\_COUNT macro to prevent infinite polling loops in MCMGR operations.
- Implemented timeout mechanism for all polling loops in MCMGR code.
- Added support to handle more then two cores. Breaking API change by adding parameter coreNum specifying core number in functions bellow.
  - MCMGR\_GetStartupData(uint32\_t \*startupData, mcmgr\_core\_t coreNum)
  - MCMGR\_TriggerEvent(mcmgr\_event\_type\_t type, uint16\_t eventData, mcmgr\_core\_t coreNum)
  - MCMGR\_TriggerEventForce(mcmgr\_event\_type\_t type, uint16\_t eventData, mcmgr\_core\_t coreNum)
  - typedef void (\*mcmgr\_event\_callback\_t)(uint16\_t data, void \*context, mcmgr\_core\_t coreNum);

When registering the event with function `MCMGR_RegisterEvent()` user now needs to provide `callbackData` pointer to array of elements per every core in system (see README.md for example). In case of systems with only two cores the `coreNum` in callback can be ignored as events can arrive only from one core. Please see Porting guide for more details: `Porting-GuideTo_v5.md`

- Updated all porting files to support new MCMGR API.
- Added new platform specific include file `mcmgr_platform.h`. It will contain common platform specific macros that can be then used in `mcmgr` and application. e.g. platform core count `MCMGR_CORECOUNT` 4.
- Move all header files to new `inc` directory.
- Added new platform-specific include files `inc/platform/<platform_name>/mcmgr_platform.h`.

#### Added

- Add MCXL20 porting layer and unit testing

#### v4.1.7

#### Fixed

- `mcmgr_stop_core_internal()` function now returns `kStatus_MCMGR_NotImplemented` status code instead of `kStatus_MCMGR_Success` when device does not support stop of secondary core. Ports affected: `kw32w1`, `kw45b41`, `kw45b42`, `mcxw716`, `mcxw727`.

#### [v4.1.6]

#### Added

- Multicore Manager moved to standalone repository.
- Add porting layers for `imxrt700`, `mcmxw727`, `kw47b42`.
- New `MCMGR_ProcessDeferredRxIsr()` API added.

#### [v4.1.5]

#### Added

- Add notification into `MCMGR_EarlyInit` and `mcmgr_early_init_internal` functions to avoid using uninitialized data in their implementations.

#### [v4.1.4]

#### Fixed

- Avoid calling tx isr callbacks when respective Messaging Unit Transmit Interrupt Enable flag is not set in the CR/TCR register.
- Messaging Unit RX and status registers are cleared after the initialization.

#### [v4.1.3]

##### Added

- Add porting layers for imxrt1180.

##### Fixed

- mu\_isr() updated to avoid calling tx isr callbacks when respective Transmit Interrupt Enable flag is not set in the CR/TCR register.
- mcmgr\_mu\_internal.c code adaptation to new supported SoCs.

#### [v4.1.2]

##### Fixed

- Update mcmgr\_stop\_core\_internal() implementations to set core state to kMCMGR\_ResetCoreState.

#### [v4.1.0]

##### Fixed

- Code adjustments to address MISRA C-2012 Rules

#### [v4.0.3]

##### Fixed

- Documentation updated to describe handshaking in a graphic form.
- Minor code adjustments based on static analysis tool findings

#### [v4.0.2]

##### Fixed

- Align porting layers to the updated MCUXpressoSDK feature files.

#### [v4.0.1]

##### Fixed

- Code formatting, removed unused code

#### [v4.0.0]

#### Added

- Add new MCMGR\_TriggerEventForce() API.

#### [v3.0.0]

#### Removed

- Removed MCMGR\_LoadApp(), MCMGR\_MapAddress() and MCMGR\_SignalReady()

#### Modified

- Modified MCMGR\_GetStartupData()

#### Added

- Added MCMGR\_EarlyInit(), MCMGR\_RegisterEvent() and MCMGR\_TriggerEvent()
- Added the ability for remote core monitoring and event handling

#### [v2.0.1]

#### Fixed

- Updated to be Misra compliant.

#### [v2.0.0]

#### Added

- Support for lpcxpresso54114 board.

#### [v1.1.0]

#### Fixed

- Ported to KSDK 2.0.0.

#### [v1.0.0]

#### Added

- Initial release.

#### eRPC

#### MCUXpresso SDK : mcuxsdk-middleware-erpc

**Overview** This repository is for MCUXpresso SDK eRPC middleware delivery and it contains eRPC component 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](#) for the complete delivery of MCUXpresso SDK to be able to build and run eRPC examples that are based on mcux-sdk-middleware-erpc component.

**Documentation** Overall details can be reviewed here: [MCUXpresso SDK Online Documentation](#)

Visit [eRPC - 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** We welcome and encourage the community to submit patches directly to the eRPC project placed on github. Contributing can be managed via pull-requests. Before a pull-request is created the code should be tested and properly formatted.

---

### eRPC

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*\* Installing for Python*

- *Known issues and limitations*
- *Code providing*

## About

eRPC (Embedded RPC) is an open source Remote Procedure Call (RPC) system for multichip embedded systems and heterogeneous multicore SoCs.

Unlike other modern RPC systems, such as the excellent [Apache Thrift](#), eRPC distinguishes itself by being designed for tightly coupled systems, using plain C for remote functions, and having a small code size (<5kB). It is not intended for high performance distributed systems over a network.

eRPC does not force upon you any particular API style. It allows you to export existing C functions, without having to change their prototypes. (There are limits, of course.) And although the internal infrastructure is written in C++, most users will be able to use only the simple C setup APIs shown in the examples below.

A code generator tool called `erpcgen` is included. It accepts input IDL files, having an `.erpc` extension, that have definitions of your data types and remote interfaces, and generates the shim code that handles serialization and invocation. `erpcgen` can generate either C/C++ or Python code.

Example `.erpc` file:

```
// Define a data type.
enum LEDName { kRed, kGreen, kBlue }

// An interface is a logical grouping of functions.
interface IO {
    // Simple function declaration with an empty reply.
    set_led(LEDName whichLed, bool onOrOff) -> void
}
```

Client side usage:

```
void example_client(void) {
    erpc_transport_t transport;
    erpc_mbf_t message_buffer_factory;
    erpc_client_t client_manager;

    /* Init eRPC client infrastructure */
    transport = erpc_transport_cmsis_uart_init(Driver_USART0);
    message_buffer_factory = erpc_mbf_dynamic_init();
    client_manager = erpc_client_init(transport, message_buffer_factory);

    /* init eRPC client IO service */
    initIO_client(client_manager);

    // Now we can call the remote function to turn on the green LED.
    set_led(kGreen, true);

    /* deinit objects */
    deinitIO_client();
    erpc_client_deinit(client_manager);
    erpc_mbf_dynamic_deinit(message_buffer_factory);
}
```

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```

    erpc_transport_tcp_deinit(transport);
}

void example_client(void) {
    erpc_transport_t transport;
    erpc_mbf_t message_buffer_factory;
    erpc_client_t client_manager;

    /* Init eRPC client infrastructure */
    transport = erpc_transport_cmsis_uart_init(Driver_USART0);
    message_buffer_factory = erpc_mbf_dynamic_init();
    client_manager = erpc_client_init(transport, message_buffer_factory);

    /* scope for client service */
    {
        /* init eRPC client IO service */
        IO_client client(client_manager);

        // Now we can call the remote function to turn on the green LED.
        client.set_led(kGreen, true);
    }

    /* deinit objects */
    erpc_client_deinit(client_manager);
    erpc_mbf_dynamic_deinit(message_buffer_factory);
    erpc_transport_tcp_deinit(transport);
}

```

**Server side usage:**

```

// Implement the remote function.
void set_led(LEDName whichLed, bool onOrOff) {
    // implementation goes here
}

void example_server(void) {
    erpc_transport_t transport;
    erpc_mbf_t message_buffer_factory;
    erpc_server_t server;
    erpc_service_t service = create_IO_service();

    /* Init eRPC server infrastructure */
    transport = erpc_transport_cmsis_uart_init(Driver_USART0);
    message_buffer_factory = erpc_mbf_dynamic_init();
    server = erpc_server_init(transport, message_buffer_factory);

    /* add custom service implementation to the server */
    erpc_add_service_to_server(server, service);

    // Run the server.
    erpc_server_run();

    /* deinit objects */
    destroy_IO_service(service);
    erpc_server_deinit(server);
    erpc_mbf_dynamic_deinit(message_buffer_factory);
    erpc_transport_tcp_deinit(transport);
}

```

```

// Implement the remote function.
class IO : public IO_interface

```

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```

{
    /* eRPC call definition */
    void set_led(LEDName whichLed, bool onOrOff) override {
        // implementation goes here
    }
}

void example_server(void) {
    erpc_transport_t transport;
    erpc_mbf_t message_buffer_factory;
    erpc_server_t server;
    IO IOImpl;
    IO_service io(&IOImpl);

    /* Init eRPC server infrastructure */
    transport = erpc_transport_cmsis_uart_init(Driver_USART0);
    message_buffer_factory = erpc_mbf_dynamic_init();
    server = erpc_server_init(transport, message_buffer_factory);

    /* add custom service implementation to the server */
    erpc_add_service_to_server(server, &io);

    /* poll for requests */
    erpc_status_t err = server.run();

    /* deinit objects */
    erpc_server_deinit(server);
    erpc_mbf_dynamic_deinit(message_buffer_factory);
    erpc_transport_tcp_deinit(transport);
}

```

A number of transports are supported, and new transport classes are easy to write.

Supported transports can be found in *erpc/erpc\_c/transport* folder. E.g:

- CMSIS UART
- NXP Kinetis SPI and DSPI
- POSIX and Windows serial port
- TCP/IP (mostly for testing)
- NXP RPMsg-Lite / RPMsg TTY
- SPIdev Linux
- USB CDC
- NXP Messaging Unit

eRPC is available with an unrestrictive BSD 3-clause license. See the [LICENSE file](#) for the full license text.

## Releases [eRPC releases](#)

**Edge releases** Edge releases can be found on [eRPC CircleCI](#) webpage. Choose build of interest, then platform target and choose ARTIFACTS tab. Here you can find binary application from chosen build.

**Documentation** Documentation is in the wiki section.

eRPC Infrastructure documentation

**Examples** Example IDL is available in the *examples/* folder.

Plenty of eRPC multicore and multiprocessor examples can be also found in NXP MCUXpressoSDK packages. Visit <https://mcuxpresso.nxp.com> to configure, build and download these packages.

To get the board list with multicore support (eRPC included) use filtering based on Middleware and search for 'multicore' string. Once the selected package with the multicore middleware is downloaded, see

<MCUXpressoSDK\_install\_dir>/boards/<board\_name>/multicore\_examples for eRPC multicore examples (RPMsg\_Lite or Messaging Unit transports used) or

<MCUXpressoSDK\_install\_dir>/boards/<board\_name>/multiprocessor\_examples for eRPC multiprocessor examples (UART or SPI transports used).

eRPC examples use the 'erpc\_' name prefix.

Another way of getting NXP MCUXpressoSDK eRPC multicore and multiprocessor examples is using the [mcux-sdk](#) Github repo. Follow the description how to use the West tool to clone and update the mcuxsdk repo in [readme Overview section](#). Once done the armgcc eRPC examples can be found in

mcuxsdk/examples/<board\_name>/multicore\_examples or in

mcuxsdk/examples/<board\_name>/multiprocessor\_examples folders.

You can use the evkmimxrt1170 as the board\_name for instance. Similar to MCUXpressoSDK packages the eRPC examples use the 'erpc\_' name prefix.

**References** This section provides links to interesting erpc-based projects, articles, blogs or guides:

- [erpc \(EmbeddedRPC\) getting started notes](#)
- [ERPC Linux Local Environment Construction and Use](#)
- [The New Wio Terminal eRPC Firmware](#)

**Directories** *doc* - Documentation.

*doxygen* - Configuration and support files for running Doxygen over the eRPC C++ infrastructure and erpcgen code.

*erpc\_c* - Holds C/C++ infrastructure for eRPC. This is the code you will include in your application.

*erpc\_python* - Holds Python version of the eRPC infrastructure.

*erpcgen* - Holds source code for erpcgen and makefiles or project files to build erpcgen on Windows, Linux, and OS X.

*erpcsniffer* - Holds source code for erpcsniffer application.

*examples* - Several example IDL files.

*mk* - Contains common makefiles for building eRPC components.

*test* - Client/server tests. These tests verify the entire communications path from client to server and back.

*utilities* - Holds utilities which bring additional benefit to eRPC apps developers.

**Building and installing** These build instructions apply to host PCs and embedded Linux. For bare metal or RTOS embedded environments, you should copy the *erpc\_c* directory into your application sources.

### CMake and KConfig build:

It builds a static library of the eRPC C/C++ infrastructure, the `erpcgen` executable, and optionally the unit tests and examples.

CMake is compatible with gcc and clang. On Windows local MingGW downloaded by *script* can be used.

## Make build:

It builds a static library of the eRPC C/C++ infrastructure, the `erpcgen` executable, and optionally the unit tests.

The makefiles are compatible with gcc or clang on Linux, OS X, and Cygwin. A Windows build of erpcgen using Visual Studio is also available in the *erpcgen/VisualStudio\_v14* directory. There is also an Xcode project file in the *erpcgen* directory, which can be used to build erpcgen for OS X.

**Requirements** erPC now support building **erpcgen**, **erpc\_lib**, **tests** and **C examples** using CMake.

### Requirements when using CMake:

- **CMake** (minimal version 3.20.0)
- Generator - **Make**, **Ninja**, ...
- **C/C++ compiler** - **GCC**, **CLANG**, ...
- **Binson** - <https://www.gnu.org/software/bison/>
- **Flex** - <https://github.com/westes/flex/>

### Requirements when using Make:

- **Make**
- **C/C++ compiler - GCC, CLANG, ...**
- **Binson** - <https://www.gnu.org/software/bison/>
- **Flex** - <https://github.com/westes/flex/>

**Windows** Related steps to build **erpcgen** using **Visual Studio** are described in `erpcgen/VisualStudio v14/readme erpcgen.txt`.

To install MinGW, Bison, Flex locally on Windows:

```
./install_dependencies.ps1
*   \ \ \

#### Linux

\ \ \ bash
./install_dependencies.sh
```

Mandatory for case, when build for different architecture is needed

- gcc-multilib, g++-multilib

## Mac OS X

```
./install_dependencies.sh
```

## Building

**CMake and KConfig** eRPC use CMake and KConfig to configure and build eRPC related targets. KConfig can be edited by *prj.conf* or *menuconfig* when building.

Generate project, config and build. In *erpc/* execute:

```
cmake -B ./build # in erpc/build generate cmake project
cmake --build ./build --target menuconfig # Build menuconfig and configure erpcgen, erpc_lib, tests and
↳examples
cmake --build ./build # Build all selected target from prj.conf/menuconfig
```

**\*\*CMake will use the system's default compilers and generator**

If you want to use Windows and locally installed MinGW, use *CMake preset* :

```
cmake --preset mingw64 # Generate project in ./build using mingw64's make and compilers
cmake --build ./build --target menuconfig # Build menuconfig and configure erpcgen, erpc_lib, tests and
↳examples
cmake --build ./build # Build all selected target from prj.conf/menuconfig
```

**Make** To build the library and erpcgen, run from the repo root directory:

```
make
```

To install the library, erpcgen, and include files, run:

```
make install
```

You may need to `sudo` the `make install`.

By default this will install into `/usr/local`. If you want to install elsewhere, set the `PREFIX` environment variable. Example for installing into `/opt`:

```
make install PREFIX=/opt
```

List of top level Makefile targets:

- `erpc`: build the `liberpc.a` static library
- `erpcgen`: build the `erpcgen` tool
- `erpcsniffer`: build the sniffer tool
- `test`: build the unit tests under the *test* directory
- `all`: build all of the above
- `install`: install `liberpc.a`, `erpcgen`, and include files

eRPC code is validated with respect to the C++ 11 standard.

**Installing for Python** To install the Python infrastructure for eRPC see instructions in the *erpc python readme*.

### Known issues and limitations

- Static allocations controlled by the `ERPC_ALLOCATION_POLICY` config macro are not fully supported yet, i.e. not all erpc objects can be allocated statically now. It deals with the ongoing process and the full static allocations support will be added in the future.

**Code providing** Repository on Github contains two main branches: **main** and **develop**. Code is developed on **develop** branch. Release version is created via merging **develop** branch into **main** branch.

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### eRPC Getting Started

**Overview** This *Getting Started User Guide* shows software developers how to use Remote Procedure Calls (RPC) in embedded multicore microcontrollers (eRPC).

The eRPC documentation is located in the `<MCUXpressoSDK_install_dir>/middleware/multicore/erpc/doc` folder.

**Create an eRPC application** This section describes a generic way to create a client/server eRPC application:

1. **Design the eRPC application:** Decide which data types are sent between applications, and define functions that send/receive this data.
2. **Create the IDL file:** The IDL file contains information about data types and functions used in an eRPC application, and is written in the IDL language.
3. **Use the eRPC generator tool:** This tool takes an IDL file and generates the shim code for the client and the server-side applications.
4. **Create an eRPC application:**
  1. Create two projects, where one project is for the client side (primary core) and the other project is for the server side (secondary core).
  2. Add generated files for the client application to the client project, and add generated files for the server application to the server project.
  3. Add infrastructure files.
  4. Add user code for client and server applications.
  5. Set the client and server project options.
5. **Run the eRPC application:** Run both the server and the client applications. Make sure that the server has been run before the client request was sent.

A specific example follows in the next section.

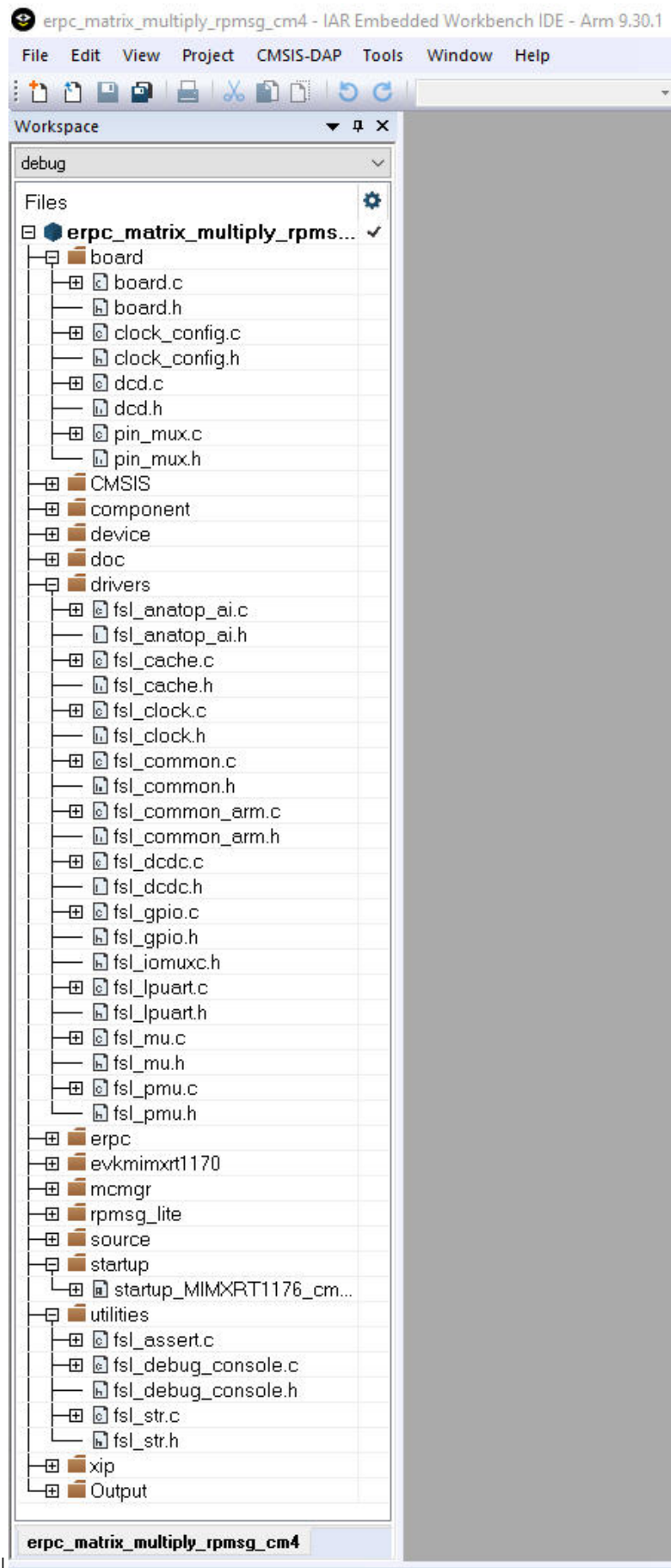
**Multicore server application** The “Matrix multiply” eRPC server project is located in the following folder:

`<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_matrix_multiply_rpmsg/cm4/iar`

The project files for the eRPC server have the `_cm4` suffix.

**Server project basic source files** The startup files, board-related settings, peripheral drivers, and utilities belong to the basic project source files and form the skeleton of all MCUXpresso SDK applications. These source files are located in:

- `<MCUXpressoSDK_install_dir>/devices/<device>`
- `<MCUXpressoSDK_install_dir>/boards/<board_name>/multicore_examples/<example_name>/`



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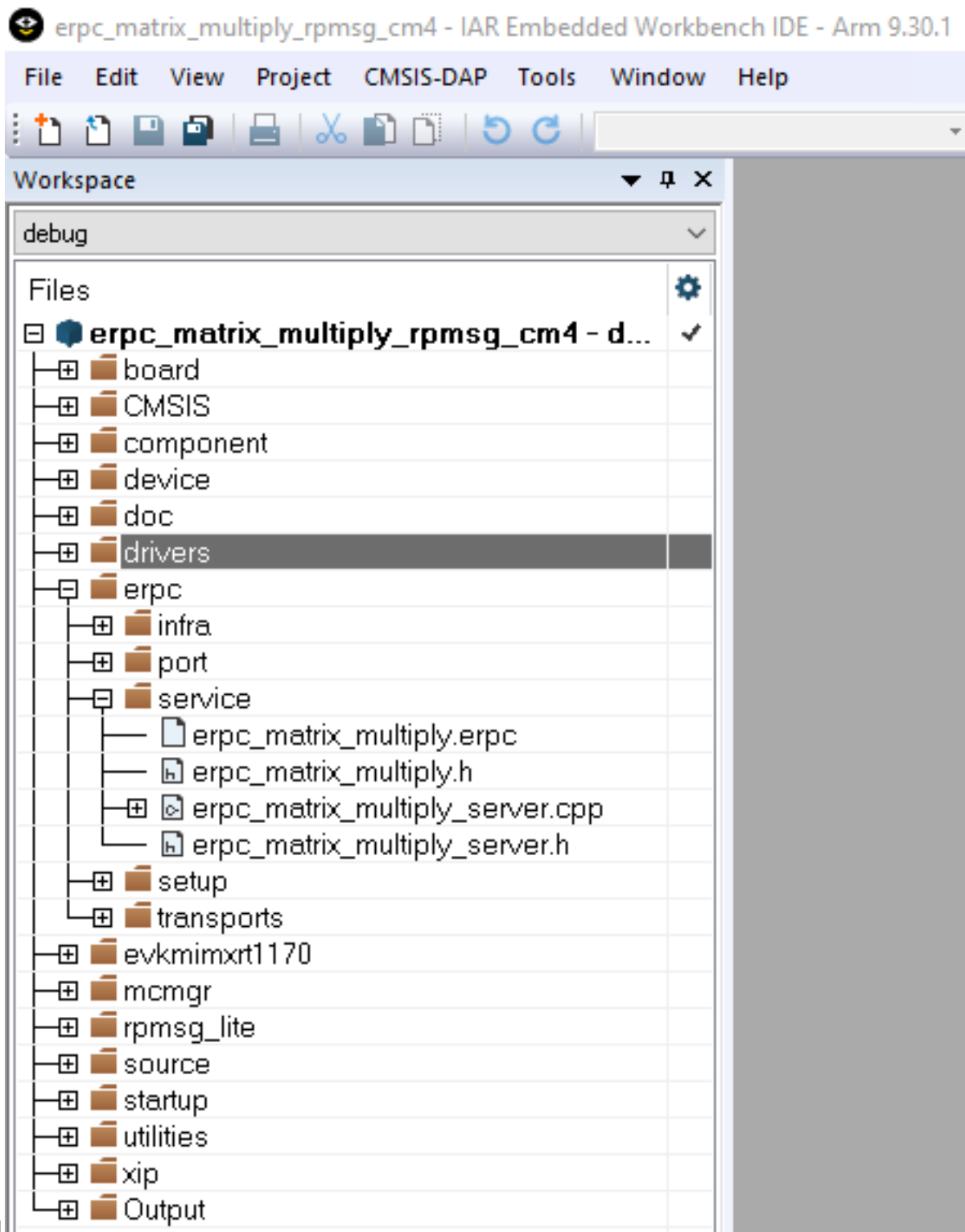
**Parent topic:** Multicore server application**Server related generated files** The server-related generated files are:

- erpc\_\_matric\_\_multiply.h
- erpc\_\_matrix\_\_multiply\_\_server.h
- erpc\_\_matrix\_\_multiply\_\_server.cpp

The server-related generated files contain the shim code for functions and data types declared in the IDL file. These files also contain functions for the identification of client requested functions, data deserialization, calling requested function's implementations, and data serialization and return, if requested by the client. These shim code files can be found in the following folder:

<MCUXpressoSDK\_install\_dir>/boards/evkmimxrt1170/multicore\_examples/erpc\_common/erpc\_matrix\_multiply/





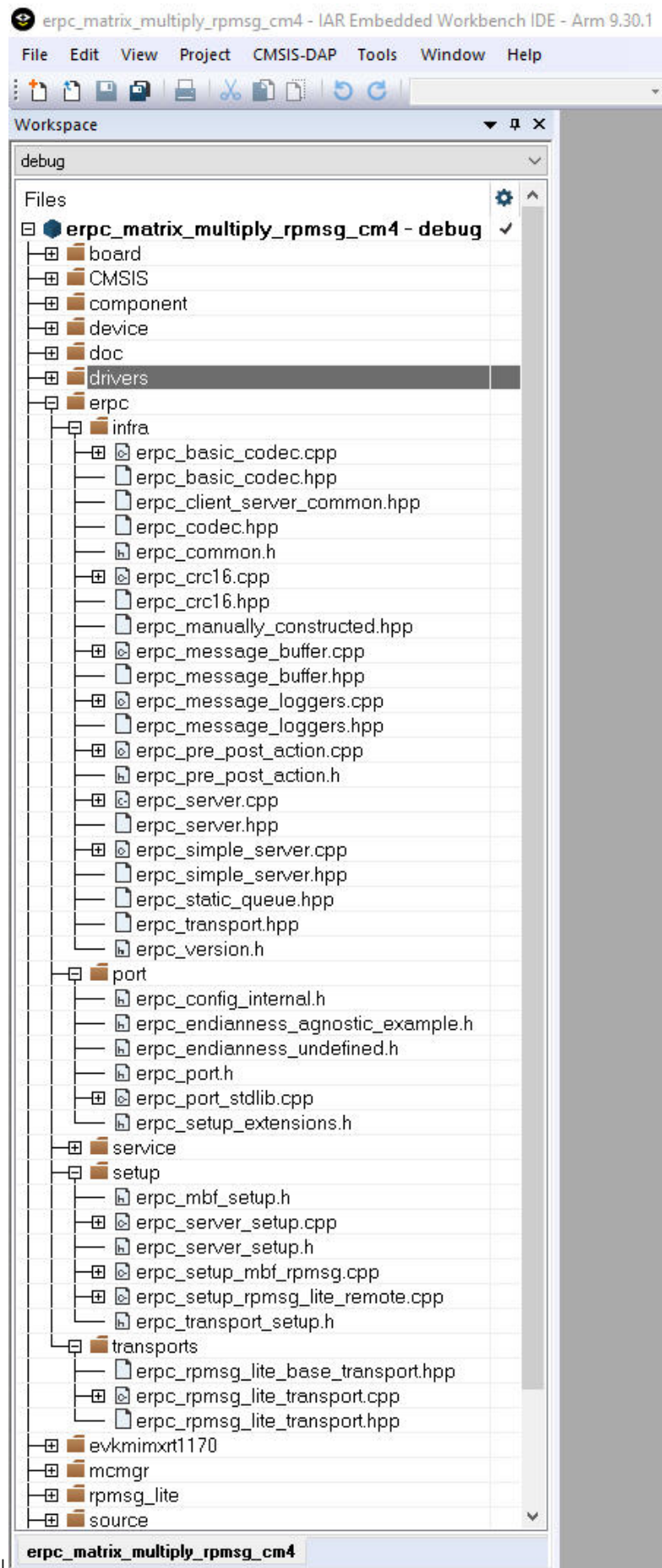
**Parent topic:** Multicore server application

**Server infrastructure files** The eRPC infrastructure files are located in the following folder:

`<MCUXpressoSDK_install_dir>/middleware/multicore/erpc/erpc_c`

The **erpc\_c** folder contains files for creating eRPC client and server applications in the C/C++ language. These files are distributed into subfolders.

- The **infra** subfolder contains C++ infrastructure code used to build server and client applications.
  - Four files, `erpc_server.hpp`, `erpc_server.cpp`, `erpc_simple_server.hpp`, and `erpc_simple_server.cpp`, are used for running the eRPC server on the server-side applications. The simple server is currently the only implementation of the server, and its role is to catch client requests, identify and call requested functions, and send data back when requested.
  - Three files (`erpc_codec.hpp`, `erpc_basic_codec.hpp`, and `erpc_basic_codec.cpp`) are used for codecs. Currently, the basic codec is the initial and only implementation of the codecs.
  - The `erpc_common.hpp` file is used for common eRPC definitions, typedefs, and enums.
  - The `erpc_manually_constructed.hpp` file is used for allocating static storage for the used objects.
  - Message buffer files are used for storing serialized data: `erpc_message_buffer.h` and `erpc_message_buffer.cpp`.
  - The `erpc_transport.h` file defines the abstract interface for transport layer.
- The **port** subfolder contains the eRPC porting layer to adapt to different environments.
  - `erpc_port.h` file contains definition of `erpc_malloc()` and `erpc_free()` functions.
  - `erpc_port_stdlib.cpp` file ensures adaptation to `stdlib`.
  - `erpc_config_internal.h` internal erpc configuration file.
- The **setup** subfolder contains a set of plain C APIs that wrap the C++ infrastructure, providing client and server init and deinit routines that greatly simplify eRPC usage in C-based projects. No knowledge of C++ is required to use these APIs.
  - The `erpc_server_setup.h` and `erpc_server_setup.cpp` files need to be added into the “Matrix multiply” example project to demonstrate the use of C-wrapped functions in this example.
  - The `erpc_transport_setup.h` and `erpc_setup_rpmsg_lite_remote.cpp` files need to be added into the project in order to allow the C-wrapped function for transport layer setup.
  - The `erpc_mbf_setup.h` and `erpc_setup_mbf_rpmsg.cpp` files need to be added into the project in order to allow message buffer factory usage.
- The **transports** subfolder contains transport classes for the different methods of communication supported by eRPC. Some transports are applicable only to host PCs, while others are applicable only to embedded or multicore systems. Most transports have corresponding client and server setup functions in the setup folder.
  - RPMsg-Lite is used as the transport layer for the communication between cores, `erpc_rpmsg_lite_base_transport.hpp`, `erpc_rpmsg_lite_transport.hpp`, and `erpc_rpmsg_lite_transport.cpp` files need to be added into the server project.



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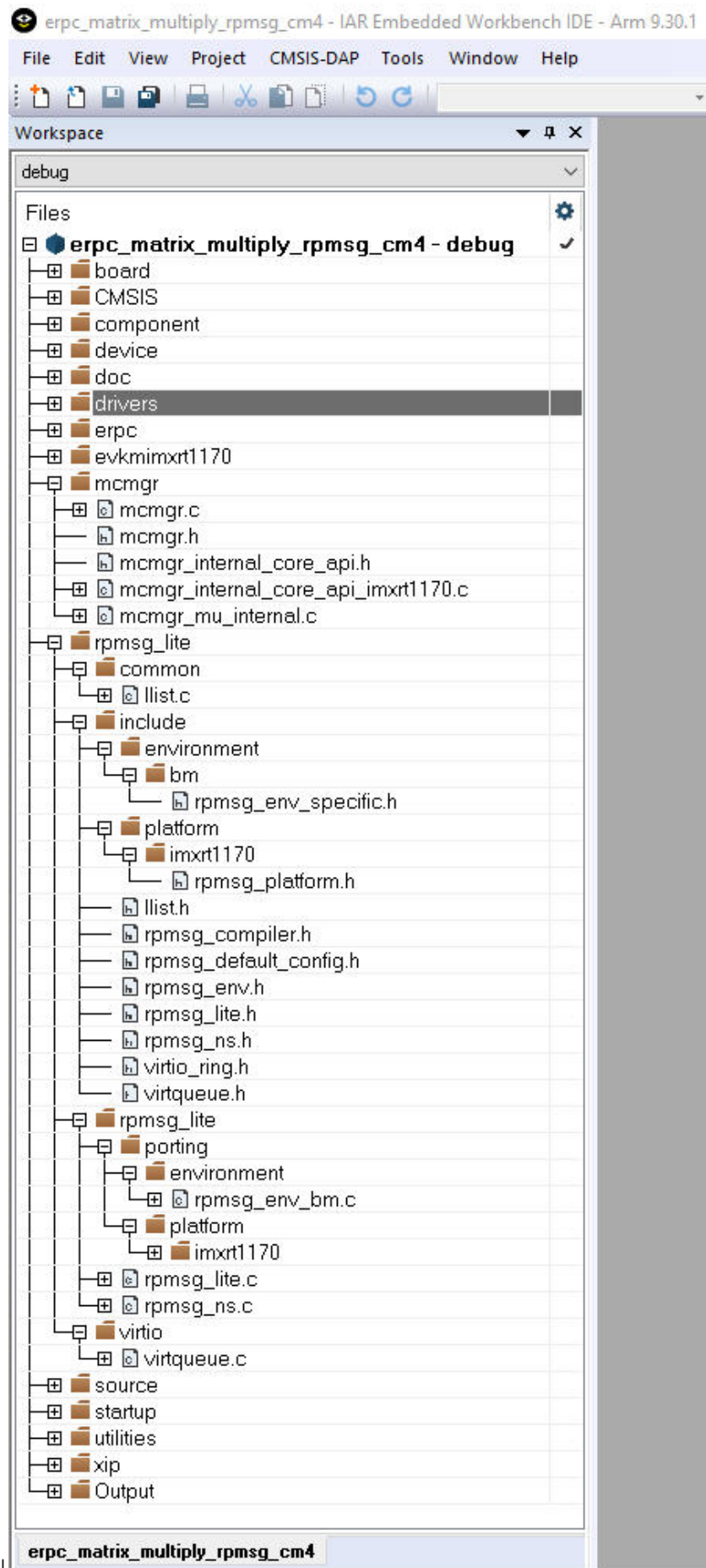
**Parent topic:** Multicore server application

**Server multicore infrastructure files** Because of the RPMsg-Lite (transport layer), it is also necessary to include RPMsg-Lite related files, which are in the following folder:

`<MCUXpressoSDK_install_dir>/middleware/multicore/rpmsg_lite/`

The multicore example applications also use the Multicore Manager software library to control the secondary core startup and shutdown. These source files are located in the following folder:

`<MCUXpressoSDK_install_dir>/middleware/multicore/mcmgr/`



|

**Parent topic:** Multicore server application

**Server user code** The server's user code is stored in the `main_core1.c` file, located in the following folder:

`<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_matrix_multiply_rpmsg/cm4`

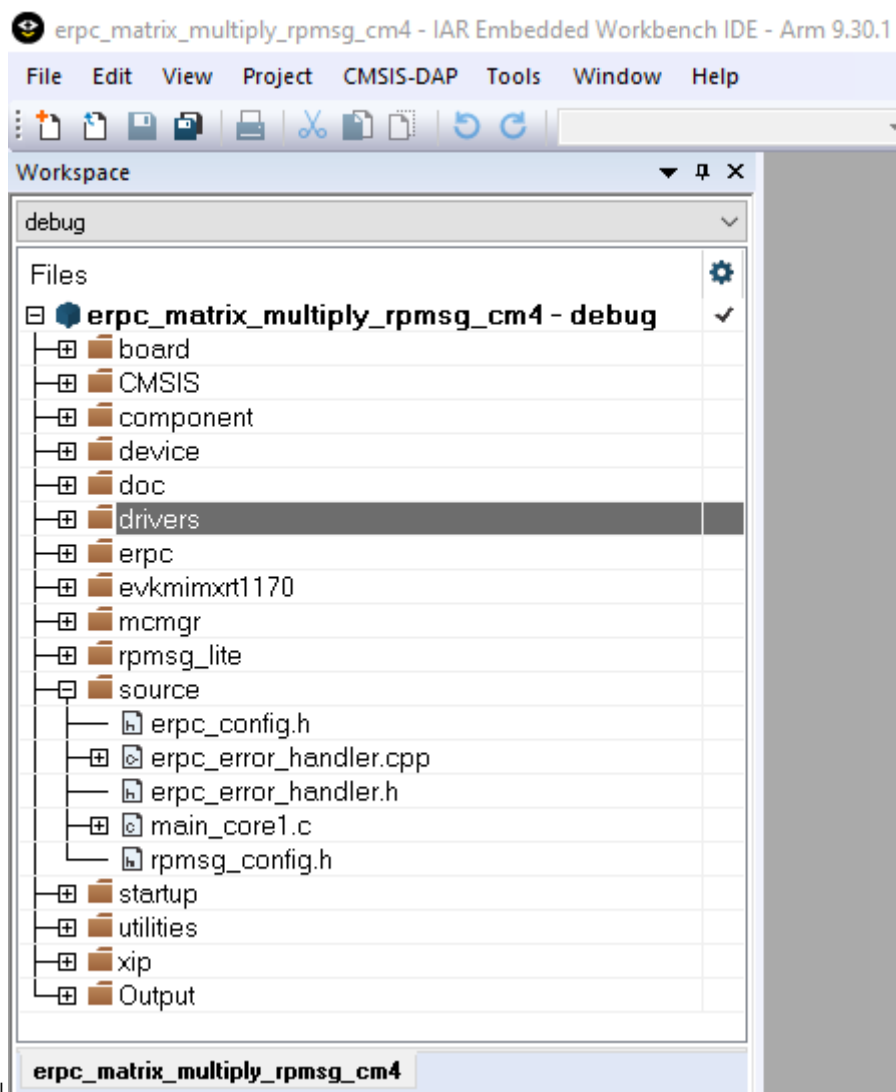
The `main_core1.c` file contains two functions:

- The **main()** function contains the code for the target board and eRPC server initialization. After the initialization, the matrix multiply service is added and the eRPC server waits for client's requests in the while loop.
- The **erpcMatrixMultiply()** function is the user implementation of the eRPC function defined in the IDL file.
- There is the possibility to write the application-specific eRPC error handler. The eRPC error handler of the matrix multiply application is implemented in the `erpc_error_handler.h` and `erpc_error_handler.cpp` files.

The eRPC-relevant code is captured in the following code snippet:

```
/* erpcMatrixMultiply function user implementation */
void erpcMatrixMultiply(const Matrix *matrix1, const Matrix *matrix2, Matrix *result_matrix)
{
    ...
}
int main()
{
    ...
    /* RPSMsg-Lite transport layer initialization */
    erpc_transport_t transport;
    transport = erpc_transport_rpmsg_lite_remote_init(src, dst, (void*)startupData,
    ERPC_TRANSPORT_RPMSG_LITE_LINK_ID, SignalReady, NULL);
    ...
    /* MessageBufferFactory initialization */
    erpc_mbf_t message_buffer_factory;
    message_buffer_factory = erpc_mbf_rpmsg_init(transport);
    ...
    /* eRPC server side initialization */
    erpc_server_t server;
    server = erpc_server_init(transport, message_buffer_factory);
    ...
    /* Adding the service to the server */
    erpc_service_t service = create_MatrixMultiplyService_service();
    erpc_add_service_to_server(server, service);
    ...
    while (1)
    {
        /* Process eRPC requests */
        erpc_status_t status = erpc_server_poll(server);
        /* handle error status */
        if (status != kErpcStatus_Success)
        {
            /* print error description */
            erpc_error_handler(status, 0);
            ...
        }
        ...
    }
}
```

Except for the application main file, there are configuration files for the RPMsg-Lite (rpmsg\_config.h) and eRPC (erpc\_config.h), located in the `<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_matrix_multiply_rpmsg` folder.



**Parent topic:**Multicore server application

**Parent topic:**[Create an eRPC application](#)

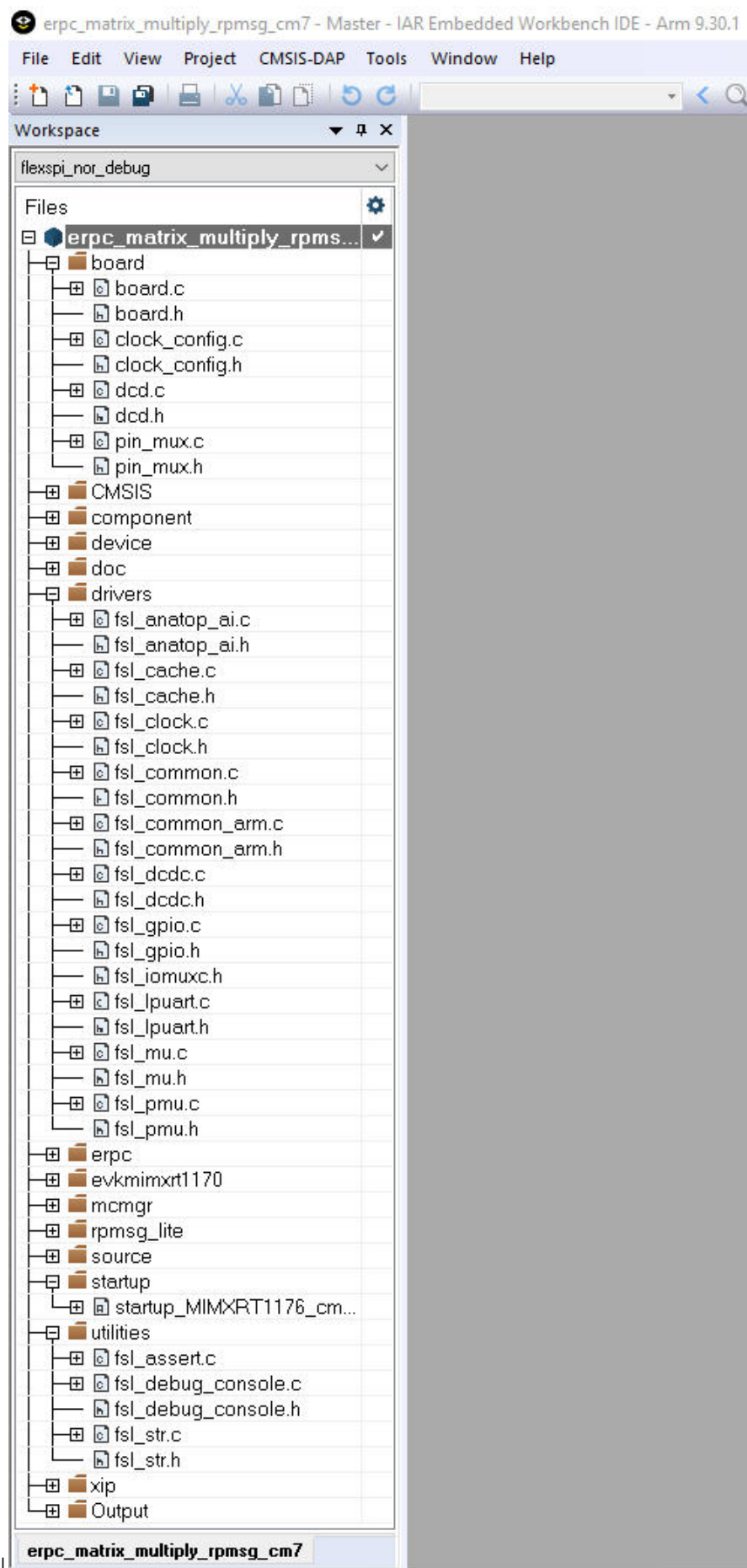
**Multicore client application** The “Matrix multiply” eRPC client project is located in the following folder:

`<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_matrix_multiply_rpmsg/cm7/iar`

Project files for the eRPC client have the `_cm7` suffix.

**Client project basic source files** The startup files, board-related settings, peripheral drivers, and utilities belong to the basic project source files and form the skeleton of all MCUXpresso SDK applications. These source files are located in the following folders:

- `<MCUXpressoSDK_install_dir>/devices/<device>`
- `<MCUXpressoSDK_install_dir>/boards/<board_name>/multicore_examples/<example_name>/`





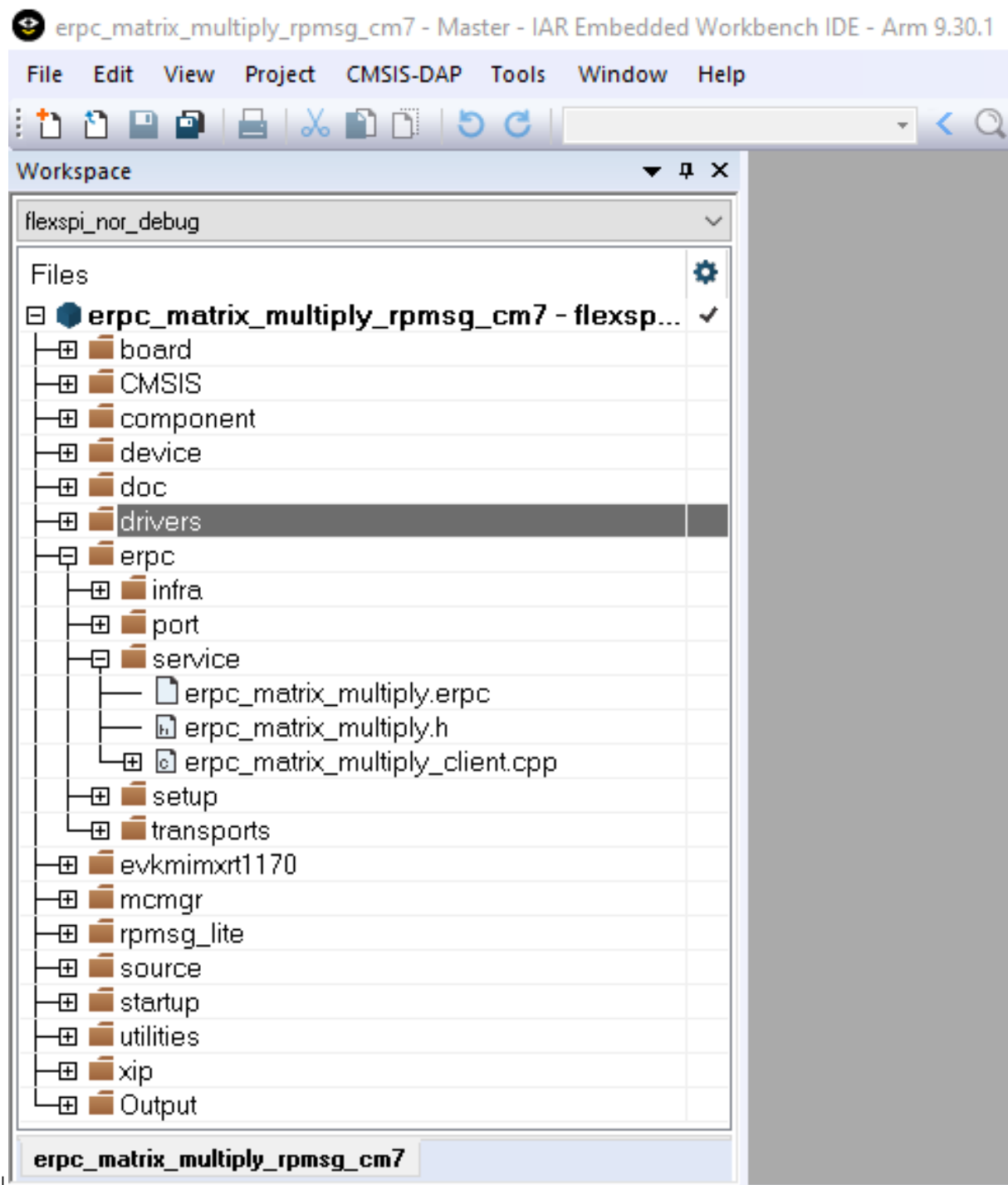
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**Parent topic:**Multicore client application

**Client-related generated files** The client-related generated files are:

- erpc\_\_matric\_\_multiply.h
- erpc\_\_matrix\_\_multiply\_\_client.cpp

These files contain the shim code for the functions and data types declared in the IDL file. These functions also call methods for codec initialization, data serialization, performing eRPC requests, and de-serializing outputs into expected data structures (if return values are expected). These shim code files can be found in the `<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_common/erpc_matrix_multiply/service/` folder.



**Parent topic:** Multicore client application

**Client infrastructure files** The eRPC infrastructure files are located in the following folder:

`<MCUXpressoSDK_install_dir>/middleware/multicore/erpc/erpc_c`

The **erpc\_c** folder contains files for creating eRPC client and server applications in the C/C++ language. These files are distributed into subfolders.

- The **infra** subfolder contains C++ infrastructure code used to build server and client applications.

- Two files, `erpc_client_manager.h` and `erpc_client_manager.cpp`, are used for managing the client-side application. The main purpose of the client files is to create, perform, and release eRPC requests.
- Three files (`erpc_codec.hpp`, `erpc_basic_codec.hpp`, and `erpc_basic_codec.cpp`) are used for codecs. Currently, the basic codec is the initial and only implementation of the codecs.
- `erpc_common.h` file is used for common eRPC definitions, typedefs, and enums.
- `erpc_manually_constructed.hpp` file is used for allocating static storage for the used objects.
- Message buffer files are used for storing serialized data: `erpc_message_buffer.hpp` and `erpc_message_buffer.cpp`.
- `erpc_transport.hpp` file defines the abstract interface for transport layer.

The **port** subfolder contains the eRPC porting layer to adapt to different environments.

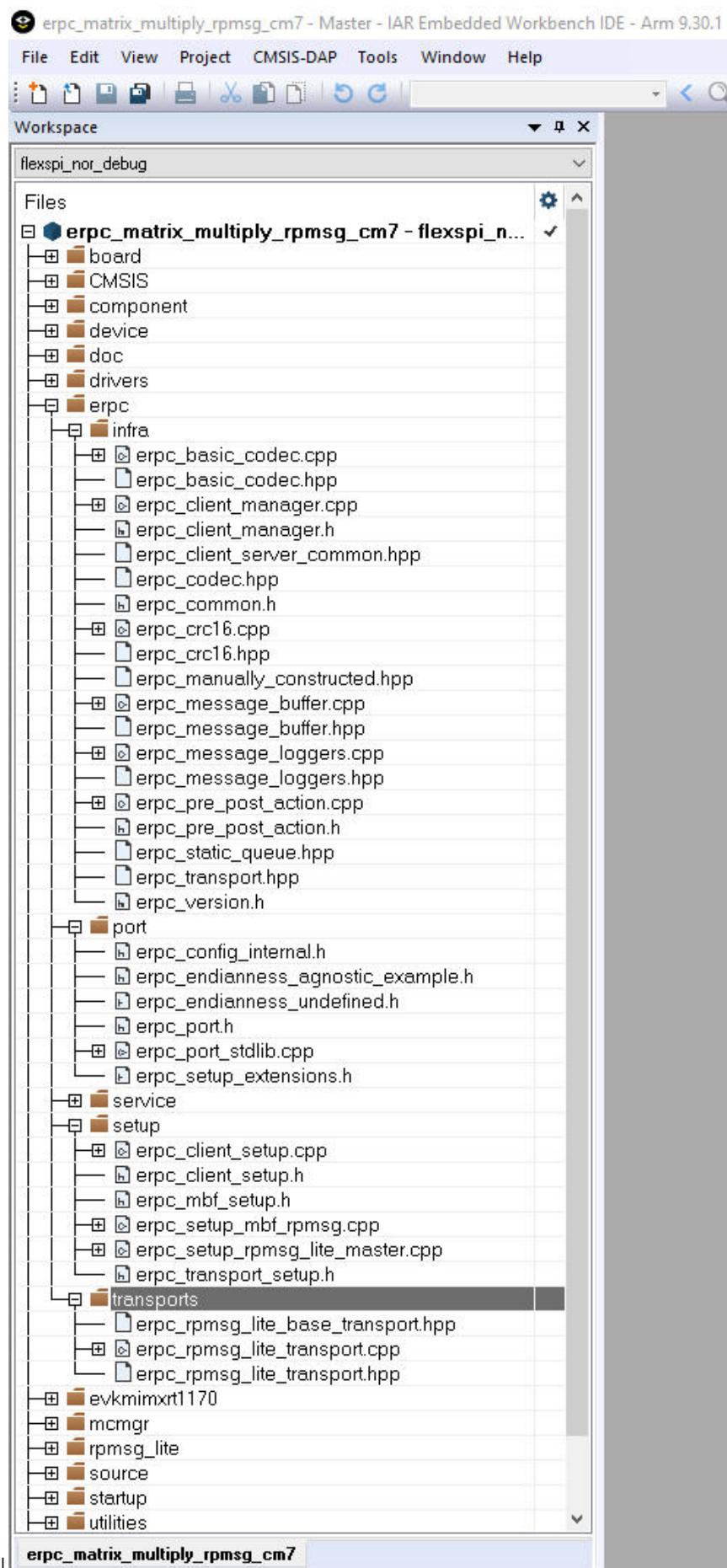
- `erpc_port.h` file contains definition of `erpc_malloc()` and `erpc_free()` functions.
- `erpc_port_stdlib.cpp` file ensures adaptation to `stdlib`.
- `erpc_config_internal.h` internal eRPC configuration file.

The **setup** subfolder contains a set of plain C APIs that wrap the C++ infrastructure, providing client and server init and deinit routines that greatly simplify eRPC usage in C-based projects. No knowledge of C++ is required to use these APIs.

- `erpc_client_setup.h` and `erpc_client_setup.cpp` files needs to be added into the “Matrix multiply” example project to demonstrate the use of C-wrapped functions in this example.
- `erpc_transport_setup.h` and `erpc_setup_rpmsg_lite_master.cpp` files needs to be added into the project in order to allow C-wrapped function for transport layer setup.
- `erpc_mbf_setup.h` and `erpc_setup_mbf_rpmsg.cpp` files needs to be added into the project in order to allow message buffer factory usage.

The **transports** subfolder contains transport classes for the different methods of communication supported by eRPC. Some transports are applicable only to host PCs, while others are applicable only to embedded or multicore systems. Most transports have corresponding client and server setup functions, in the setup folder.

- RPMsg-Lite is used as the transport layer for the communication between cores, `erpc_rpmsg_lite_base_transport.hpp`, `erpc_rpmsg_lite_transport.hpp`, and `erpc_rpmsg_lite_transport.cpp` files needs to be added into the client project.



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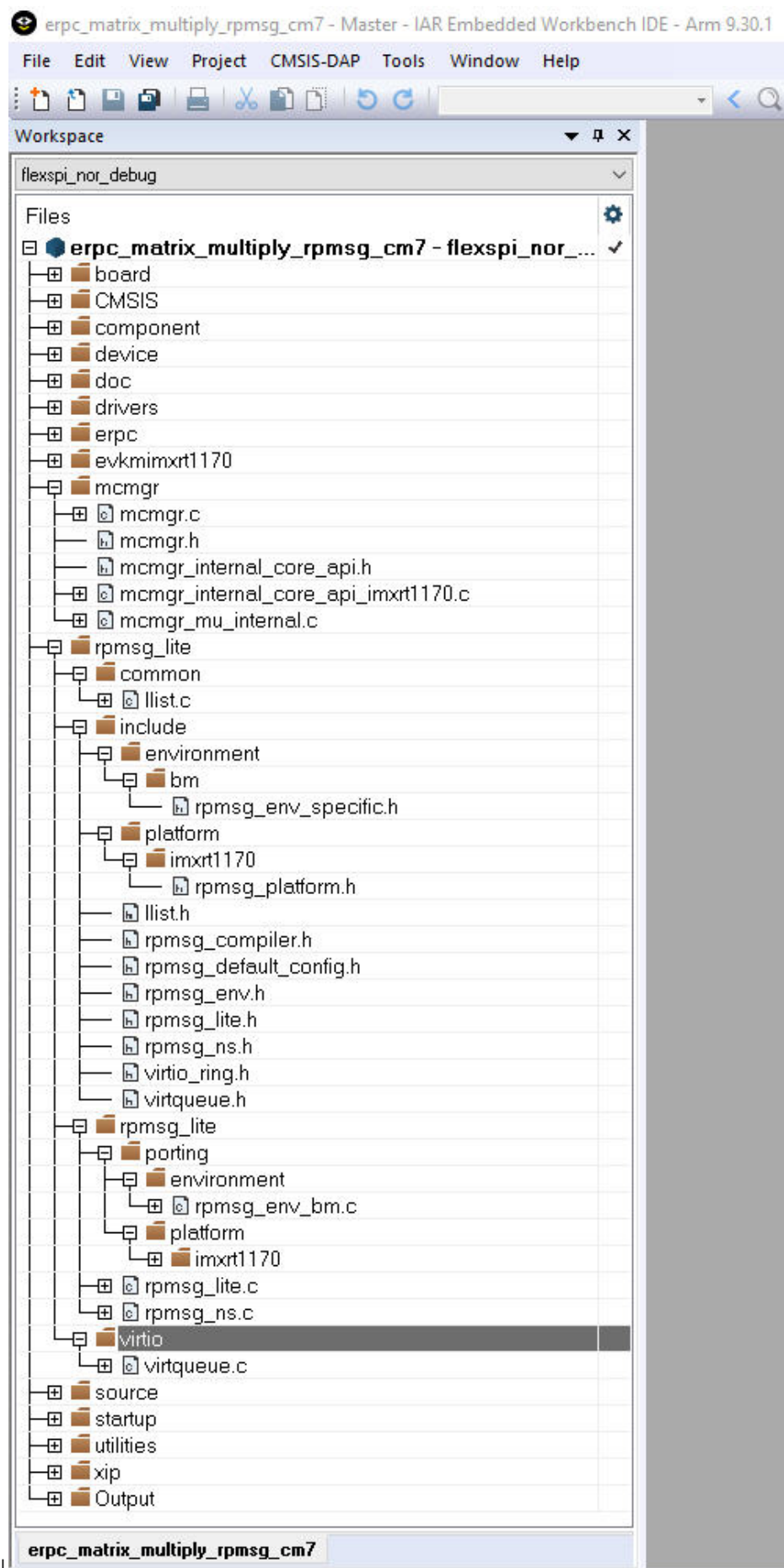
**Parent topic:**Multicore client application

**Client multicore infrastructure files** Because of the RPSMsg-Lite (transport layer), it is also necessary to include RPSMsg-Lite related files, which are in the following folder:

*<MCUXpressoSDK\_install\_dir>/middleware/multicore/rpsmsg\_lite/*

The multicore example applications also use the Multicore Manager software library to control the secondary core startup and shutdown. These source files are located in the following folder:

*<MCUXpressoSDK\_install\_dir>/middleware/multicore/mcmgr/*



**Parent topic:** Multicore client application

**Client user code** The client's user code is stored in the `main_core0.c` file, located in the following folder:

`<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_example/erpc_matrix_multiply_rpmsg/cm7`

The `main_core0.c` file contains the code for target board and eRPC initialization.

- After initialization, the secondary core is released from reset.
- When the secondary core is ready, the primary core initializes two matrix variables.
- The `erpcMatrixMultiply` eRPC function is called to issue the eRPC request and get the result.

It is possible to write the application-specific eRPC error handler. The eRPC error handler of the matrix multiply application is implemented in `erpc_error_handler.h` and `erpc_error_handler.cpp` files.

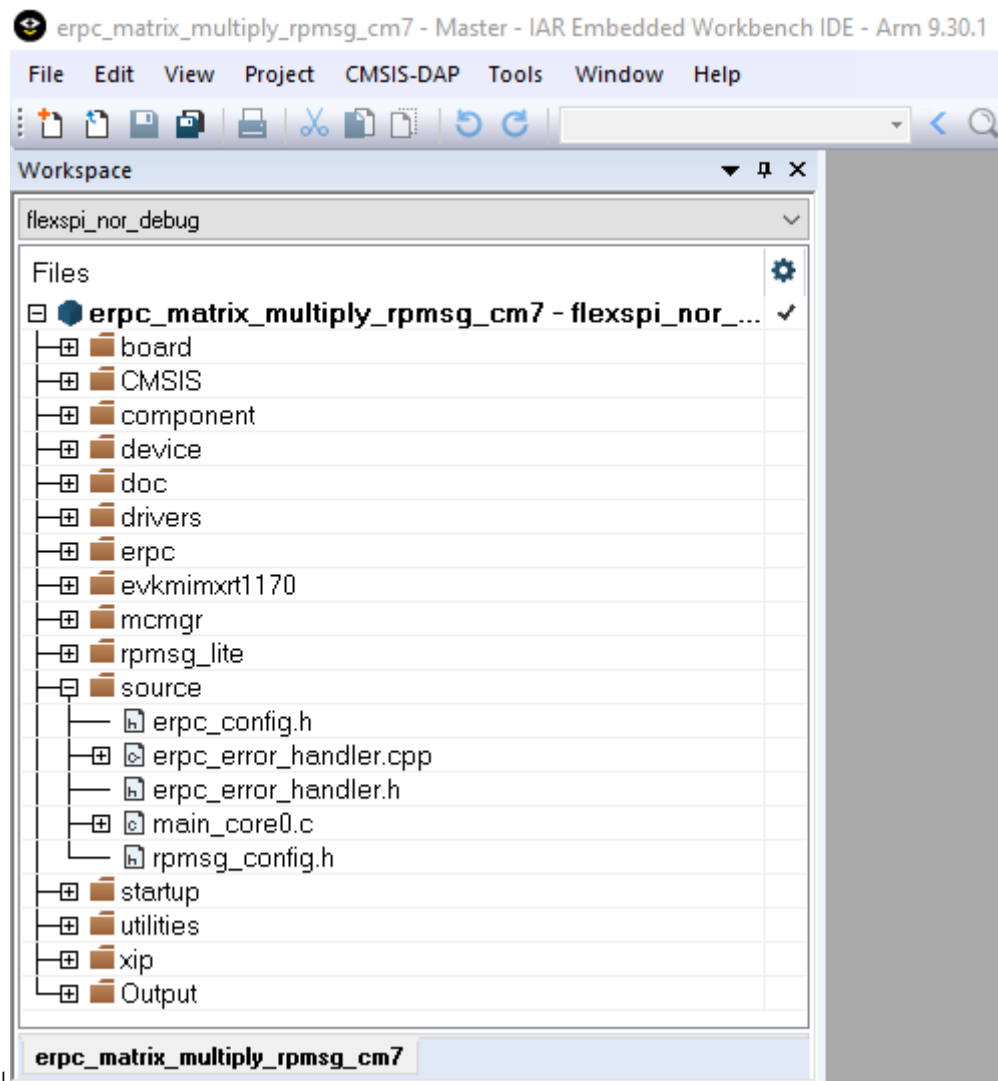
The matrix multiplication can be issued repeatedly, when pressing a software board button.

The eRPC-relevant code is captured in the following code snippet:

```
...
extern bool g_erpc_error_occurred;
...
/* Declare matrix arrays */
Matrix matrix1 = {0}, matrix2 = {0}, result_matrix = {0};
...
/* RPSMsg-Lite transport layer initialization */
erpc_transport_t transport;
transport = erpc_transport_rpmsg_lite_master_init(src, dst,
ERPC_TRANSPORT_RPMSG_LITE_LINK_ID);
...
/* MessageBufferFactory initialization */
erpc_mbf_t message_buffer_factory;
message_buffer_factory = erpc_mbf_rpmsg_init(transport);
...
/* eRPC client side initialization */
erpc_client_t client;
client = erpc_client_init(transport, message_buffer_factory);
...
/* Set default error handler */
erpc_client_set_error_handler(client, erpc_error_handler);
...
while (1)
{
    /* Invoke the erpcMatrixMultiply function */
    erpcMatrixMultiply(matrix1, matrix2, result_matrix);
    ...
    /* Check if some error occurred in eRPC */
    if (g_erpc_error_occurred)
    {
        /* Exit program loop */
        break;
    }
    ...
}
```

Except for the application main file, there are configuration files for the RPSMsg-Lite (`rpmsg_config.h`) and eRPC (`erpc_config.h`), located in the following folder:

`<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_matrix_multiply_rpmsg`



**Parent topic:**Multicore client application

**Parent topic:**[Create an eRPC application](#)

**Multiprocessor server application** The “Matrix multiply” eRPC server project for multiprocessor applications is located in the `<MCUXpressoSDK_install_dir>/boards/<board_name>/multiprocessor_examples/erpc_server_matrix_multiply_<transport_layer>` folder.

Most of the multiprocessor application setup is the same as for the multicore application. The multiprocessor server application requires server-related generated files (server shim code), server infrastructure files, and the server user code. There is no need for server multicore infrastructure files (MCMGR and RPMMsg-Lite). The RPMMsg-Lite transport layer is replaced either by SPI or UART transports. The following table shows the required transport-related files per each transport type.

SPI	<eRPC base directory>/erpc_c/setup/erpc_setup_(d)spi_slave.cpp
	<eRPC base directory>/erpc_c/transports/erpc_(d)spi_slave_transport.hpp
	<eRPC base directory>/erpc_c/transports/erpc_(d)spi_slave_transport.cpp
UART	<eRPC base directory>/erpc_c/setup/erpc_setup_uart_cmsis.cpp



<eRPC base directory>/erpc\_c/transport/erpc\_uart\_cmsis\_transport.hpp

<eRPC base directory>/erpc\_c/transport/erpc\_uart\_cmsis\_transport.cpp

|

**Server user code** The server's user code is stored in the main\_server.c file, located in the <MCUXpressoSDK\_install\_dir>/boards/<board\_name>/multiprocessor\_examples/erpc\_server\_matrix\_multiply\_<transport\_layer>/ folder.

The eRPC-relevant code with UART as a transport is captured in the following code snippet:

```
/* erpcMatrixMultiply function user implementation */
void erpcMatrixMultiply(Matrix matrix1, Matrix matrix2, Matrix result_matrix)
{
    ...
}
int main()
{
    ...
    /* UART transport layer initialization, ERPC_DEMO_UART is the structure of CMSIS UART driver
    ↪operations */
    erpc_transport_t transport;
    transport = erpc_transport_cmsis_uart_init((void *)&ERPC_DEMO_UART);
    ...
    /* MessageBufferFactory initialization */
    erpc_mbf_t message_buffer_factory;
    message_buffer_factory = erpc_mbf_dynamic_init();
    ...
    /* eRPC server side initialization */
    erpc_server_t server;
    server = erpc_server_init(transport, message_buffer_factory);
    ...
    /* Adding the service to the server */
    erpc_service_t service = create_MatrixMultiplyService_service();
    erpc_add_service_to_server(server, service);
    ...
    while (1)
    {
        /* Process eRPC requests */
        erpc_status_t status = erpc_server_poll(server)
        /* handle error status */
        if (status != kErpcStatus_Success)
        {
            /* print error description */
            erpc_error_handler(status, 0);
            ...
        }
        ...
    }
}
```

**Parent topic:**Multiprocessor server application

**Multiprocessor client application** The “Matrix multiply” eRPC client project for multiprocessor applications is located in the <MCUXpressoSDK\_install\_dir>/boards/<board\_name>/multiprocessor\_examples/erpc\_client\_matrix\_multiply\_<transport\_layer>/iar/ folder.

Most of the multiprocessor application setup is the same as for the multicore application. The multiprocessor server application requires client-related generated files (server shim code),

client infrastructure files, and the client user code. There is no need for client multicore infrastructure files (MCMGR and RPSMsg-Lite). The RPSMsg-Lite transport layer is replaced either by SPI or UART transports. The following table shows the required transport-related files per each transport type.

SPI	<eRPC base directory>/erpc_c/setup/erpc_setup_(d)spi_master.cpp
<eRPC base directory>/erpc_c/transports/	erpc_(d)spi_master_transport.hpp
<eRPC base directory>/erpc_c/transports/	erpc_(d)spi_master_transport.cpp
UART	<eRPC base directory>/erpc_c/setup/erpc_setup_uart_cmsis.cpp
<eRPC base directory>/erpc_c/transports/	erpc_uart_cmsis_transport.hpp
<eRPC base directory>/erpc_c/transports/	erpc_uart_cmsis_transport.cpp

**Client user code** The client's user code is stored in the `main_client.c` file, located in the `<MCUXpressoSDK_install_dir>/boards/<board_name>/multiprocessor_examples/erpc_client_matrix_multiply_<transport_layer>/` folder.

The eRPC-relevant code with UART as a transport is captured in the following code snippet:

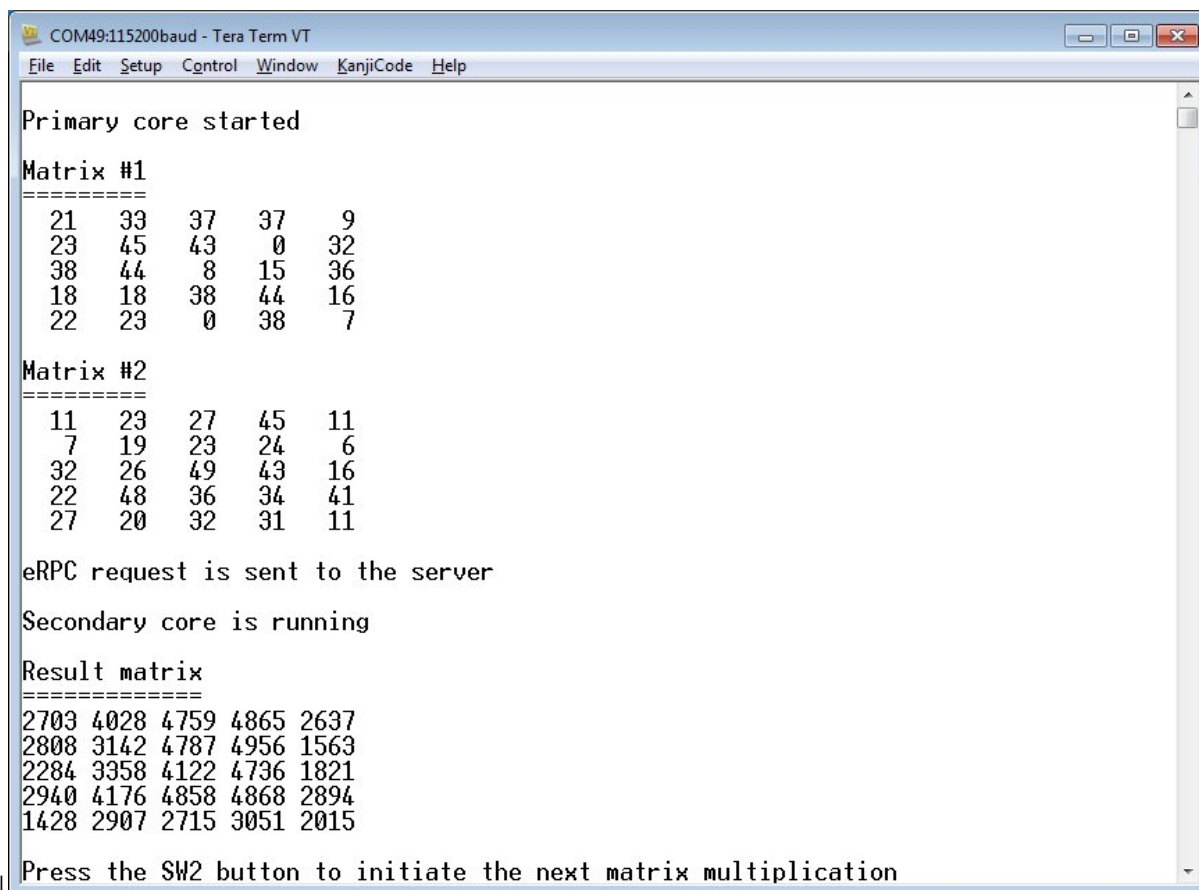
```
...
extern bool g_erpc_error_occurred;
...
/* Declare matrix arrays */
Matrix matrix1 = {0}, matrix2 = {0}, result_matrix = {0};
...
/* UART transport layer initialization, ERPC_DEMO_UART is the structure of CMSIS UART driver
↳operations */
erpc_transport_t transport;
transport = erpc_transport_cmsis_uart_init((void *)&ERPC_DEMO_UART);
...
/* MessageBufferFactory initialization */
erpc_mbf_t message_buffer_factory;
message_buffer_factory = erpc_mbf_dynamic_init();
...
/* eRPC client side initialization */
erpc_client_t client;
client = erpc_client_init(transport,message_buffer_factory);
...
/* Set default error handler */
erpc_client_set_error_handler(client, erpc_error_handler);
...
while (1)
{
    /* Invoke the erpcMatrixMultiply function */
    erpcMatrixMultiply(matrix1, matrix2, result_matrix);
    ...
    /* Check if some error occurred in eRPC */
    if (g_erpc_error_occurred)
    {
        /* Exit program loop */
        break;
    }
    ...
}
```

**Parent topic:**Multiprocessor client application

**Parent topic:**Multiprocessor server application

Parent topic:[Create an eRPC application](#)

**Running the eRPC application** Follow the instructions in *Getting Started with MCUXpresso SDK* (document MCUXSDKGSUG) (located in the <MCUXpressoSDK\_install\_dir>/docs folder), to load both the primary and the secondary core images into the on-chip memory, and then effectively debug the dual-core application. After the application is running, the serial console should look like:



```

COM49:115200baud - Tera Term VT
File Edit Setup Control Window KanjiCode Help

Primary core started

Matrix #1
=====
 21  33  37  37   9
 23  45  43   0  32
 38  44   8  15  36
 18  18  38  44  16
 22  23   0  38   7

Matrix #2
=====
 11  23  27  45  11
  7  19  23  24   6
 32  26  49  43  16
 22  48  36  34  41
 27  20  32  31  11

eRPC request is sent to the server

Secondary core is running

Result matrix
=====
2703 4028 4759 4865 2637
2808 3142 4787 4956 1563
2284 3358 4122 4736 1821
2940 4176 4858 4868 2894
1428 2907 2715 3051 2015

Press the SW2 button to initiate the next matrix multiplication

```

For multiprocessor applications that are running between PC and the target evaluation board or between two boards, follow the instructions in the accompanied example readme files that provide details about the proper board setup and the PC side setup (Python).

Parent topic:[Create an eRPC application](#)

Parent topic:[eRPC example](#)

**eRPC example** This section shows how to create an example eRPC application called “Matrix multiply”, which implements one eRPC function (matrix multiply) with two function parameters (two matrices). The client-side application calls this eRPC function, and the server side performs the multiplication of received matrices. The server side then returns the result.

For example, use the NXP MIMXRT1170-EVK board as the target dual-core platform, and the IAR Embedded Workbench for ARM (EWARM) as the target IDE for developing the eRPC example.

- The primary core (CM7) runs the eRPC client.
- The secondary core (CM4) runs the eRPC server.
- RPMsg-Lite (Remote Processor Messaging Lite) is used as the eRPC transport layer.

The “Matrix multiply” application can be also run in the multi-processor setup. In other words, the eRPC client running on one SoC communicates with the eRPC server that runs on another SoC, utilizing different transport channels. It is possible to run the board-to-PC example (PC as the eRPC server and a board as the eRPC client, and vice versa) and also the board-to-board example. These multiprocessor examples are prepared for selected boards only.

| Multicore application source and project files | `<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore/`  
| Multiprocessor application source and project files | `<MCUXpressoSDK_install_dir>/boards/<board_name>/multi`  
`<MCUXpressoSDK_install_dir>/boards/<board_name>/multiprocessor_examples/erpc_server_matrix_multiply_<tr`  
| | eRPC source files | `<MCUXpressoSDK_install_dir>/middleware/multicore/erpc/` | | RPLite  
source files | `<MCUXpressoSDK_install_dir>/middleware/multicore/rplite/`

**Designing the eRPC application** The matrix multiply application is based on calling single eRPC function that takes 2 two-dimensional arrays as input and returns matrix multiplication results as another 2 two-dimensional array. The IDL file syntax supports arrays with the dimension length set by the number only (in the current eRPC implementation). Because of this, a variable is declared in the IDL dedicated to store information about matrix dimension length, and to allow easy maintenance of the user and server code.

For a simple use of the two-dimensional array, the alias name (new type definition) for this data type has been declared in the IDL. Declaring this alias name ensures that the same data type can be used across the client and server applications.

**Parent topic:** [eRPC example](#)

**Creating the IDL file** The created IDL file is located in the following folder:

`<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_common/erpc_matrix_multiply/`

The created IDL file contains the following code:

```
program erpc_matrix_multiply
/*! This const defines the matrix size. The value has to be the same as the
Matrix array dimension. Do not forget to re-generate the erpc code once the
matrix size is changed in the erpc file */
const int32 matrix_size = 5;
/*! This is the matrix array type. The dimension has to be the same as the
matrix size const. Do not forget to re-generate the erpc code once the
matrix size is changed in the erpc file */
type Matrix = int32[matrix_size][matrix_size];
interface MatrixMultiplyService {
erpcMatrixMultiply(in Matrix matrix1, in Matrix matrix2, out Matrix result_matrix) ->
void
}
```

Details:

- The IDL file starts with the program name (*erpc\_matrix\_multiply*), and this program name is used in the naming of all generated outputs.
- The declaration and definition of the constant variable named *matrix\_size* follows next. The *matrix\_size* variable is used for passing information about the length of matrix dimensions to the client/server user code.
- The alias name for the two-dimensional array type (*Matrix*) is declared.
- The interface group *MatrixMultiplyService* is located at the end of the IDL file. This interface group contains only one function declaration *erpcMatrixMultiply*.
- As shown above, the function’s declaration contains three parameters of *Matrix* type: *matrix1* and *matrix2* are input parameters, while *result\_matrix* is the output parameter. Additionally, the returned data type is declared as *void*.

When writing the IDL file, the following order of items is recommended:

1. Program name at the top of the IDL file.
2. New data types and constants declarations.
3. Declarations of interfaces and functions at the end of the IDL file.

**Parent topic:** [eRPC example](#)

**Using the eRPC generator tool** | Windows OS | `<MCUXpressoSDK_install_dir>/middleware/multicore/tools/erpcgen/Linux_x64`  
 | Linux OS | `<MCUXpressoSDK_install_dir>/middleware/multicore/tools/erpcgen/Linux_x86`  
 | Mac OS | `<MCUXpressoSDK_install_dir>/middleware/multicore/tools/erpcgen/Mac`

The files for the “Matrix multiply” example are pre-generated and already a part of the application projects. The following section describes how they have been created.

- The easiest way to create the shim code is to copy the erpcgen application to the same folder where the IDL file (\*.erpc) is located; then run the following command:

```
erpcgen <IDL_file>.erpc
```

- In the “Matrix multiply” example, the command should look like:

```
erpcgen erpc_matrix_multiply.erpc
```

Additionally, another method to create the shim code is to execute the eRPC application using input commands:

- “-?”/”—help” – Shows supported commands.
- “-o <filePath>”/”—output<filePath>” – Sets the output directory.

For example,

```
<path_to_erpcgen>/erpcgen -o <path_to_output>  
<path_to_IDL>/<IDL_file_name>.erpc
```

For the “Matrix multiply” example, when the command is executed from the default erpcgen location, it looks like:

```
erpcgen -o  
../../../../../boards/evkmimxrt1170/multicore_examples/erpc_common/erpc_matrix_multiply/service  
../../../../../boards/evkmimxrt1170/multicore_examples/erpc_common/erpc_matrix_multiply/service/erpc_matrix_mu
```

In both cases, the following four files are generated into the `<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_common/erpc_matrix_multiply/service` folder:

- erpc\_matrix\_multiply.h
- erpc\_matrix\_multiply\_client.cpp
- erpc\_matrix\_multiply\_server.h
- erpc\_matrix\_multiply\_server.cpp

For multiprocessor examples, the eRPC file and pre-generated files can be found in the `<MCUXpressoSDK_install_dir>/boards/<board_name>/multiprocessor_examples/erpc_common/erpc_matrix_multiply/service` folder.

**For Linux OS users:**

- Do not forget to set the permissions for the eRPC generator application.
- Run the application as `./erpcgen...` instead of as `erpcgen ....`

Parent topic: [eRPC example](#)

**Create an eRPC application** This section describes a generic way to create a client/server eRPC application:

1. **Design the eRPC application:** Decide which data types are sent between applications, and define functions that send/receive this data.
2. **Create the IDL file:** The IDL file contains information about data types and functions used in an eRPC application, and is written in the IDL language.
3. **Use the eRPC generator tool:** This tool takes an IDL file and generates the shim code for the client and the server-side applications.
4. **Create an eRPC application:**
  1. Create two projects, where one project is for the client side (primary core) and the other project is for the server side (secondary core).
  2. Add generated files for the client application to the client project, and add generated files for the server application to the server project.
  3. Add infrastructure files.
  4. Add user code for client and server applications.
  5. Set the client and server project options.
5. **Run the eRPC application:** Run both the server and the client applications. Make sure that the server has been run before the client request was sent.

A specific example follows in the next section.

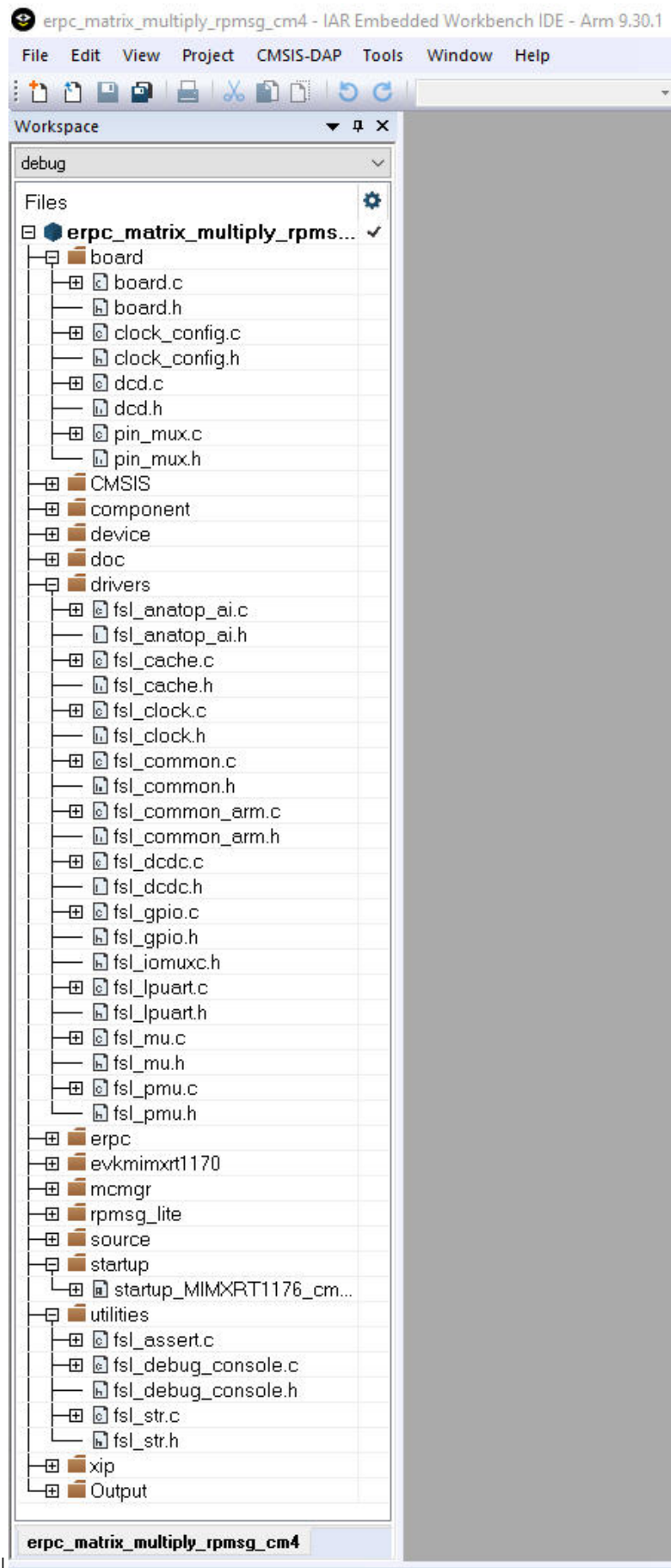
**Multicore server application** The “Matrix multiply” eRPC server project is located in the following folder:

`<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_matrix_multiply_rpmmsg/cm4/iar/`

The project files for the eRPC server have the `_cm4` suffix.

**Server project basic source files** The startup files, board-related settings, peripheral drivers, and utilities belong to the basic project source files and form the skeleton of all MCUXpresso SDK applications. These source files are located in:

- `<MCUXpressoSDK_install_dir>/devices/<device>`
- `<MCUXpressoSDK_install_dir>/boards/<board_name>/multicore_examples/<example_name>/`



|

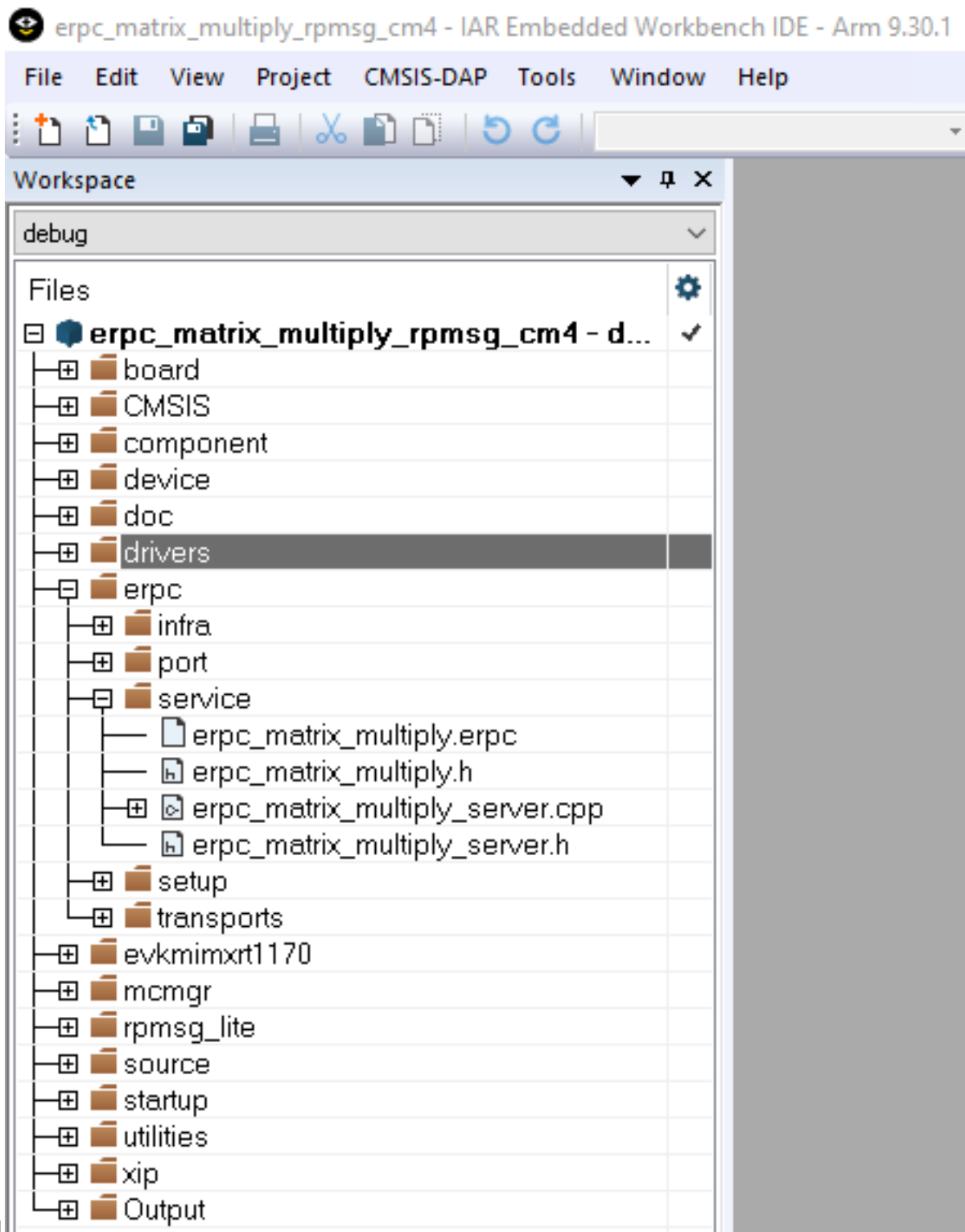
**Parent topic:** Multicore server application**Server related generated files** The server-related generated files are:

- erpc\_\_matric\_\_multiply.h
- erpc\_\_matrix\_\_multiply\_\_server.h
- erpc\_\_matrix\_\_multiply\_\_server.cpp

The server-related generated files contain the shim code for functions and data types declared in the IDL file. These files also contain functions for the identification of client requested functions, data deserialization, calling requested function's implementations, and data serialization and return, if requested by the client. These shim code files can be found in the following folder:

<MCUXpressoSDK\_install\_dir>/boards/evkmimxrt1170/multicore\_examples/erpc\_common/erpc\_matrix\_multiply/





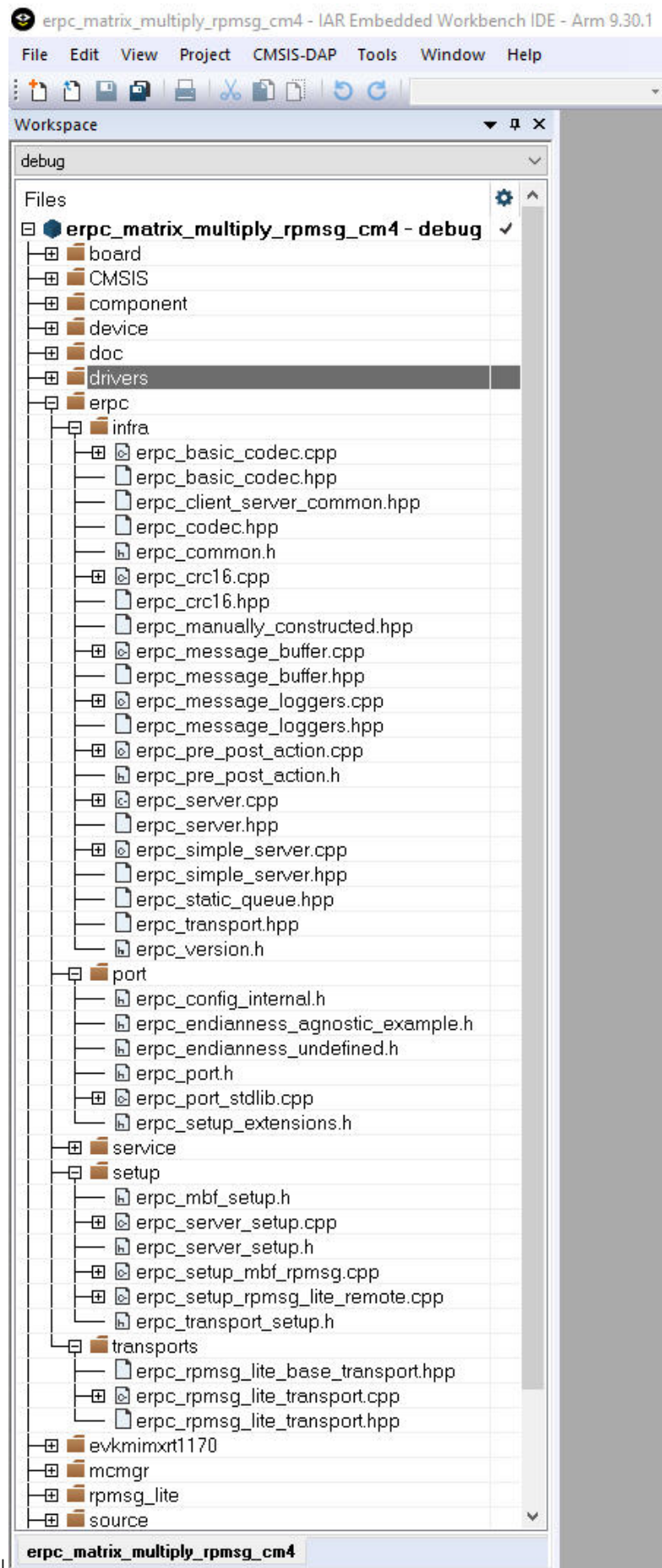
**Parent topic:** Multicore server application

**Server infrastructure files** The eRPC infrastructure files are located in the following folder:

`<MCUXpressoSDK_install_dir>/middleware/multicore/erpc/erpc_c`

The **erpc\_c** folder contains files for creating eRPC client and server applications in the C/C++ language. These files are distributed into subfolders.

- The **infra** subfolder contains C++ infrastructure code used to build server and client applications.
  - Four files, `erpc_server.hpp`, `erpc_server.cpp`, `erpc_simple_server.hpp`, and `erpc_simple_server.cpp`, are used for running the eRPC server on the server-side applications. The simple server is currently the only implementation of the server, and its role is to catch client requests, identify and call requested functions, and send data back when requested.
  - Three files (`erpc_codec.hpp`, `erpc_basic_codec.hpp`, and `erpc_basic_codec.cpp`) are used for codecs. Currently, the basic codec is the initial and only implementation of the codecs.
  - The `erpc_common.hpp` file is used for common eRPC definitions, typedefs, and enums.
  - The `erpc_manually_constructed.hpp` file is used for allocating static storage for the used objects.
  - Message buffer files are used for storing serialized data: `erpc_message_buffer.h` and `erpc_message_buffer.cpp`.
  - The `erpc_transport.h` file defines the abstract interface for transport layer.
- The **port** subfolder contains the eRPC porting layer to adapt to different environments.
  - `erpc_port.h` file contains definition of `erpc_malloc()` and `erpc_free()` functions.
  - `erpc_port_stdlib.cpp` file ensures adaptation to `stdlib`.
  - `erpc_config_internal.h` internal erpc configuration file.
- The **setup** subfolder contains a set of plain C APIs that wrap the C++ infrastructure, providing client and server init and deinit routines that greatly simplify eRPC usage in C-based projects. No knowledge of C++ is required to use these APIs.
  - The `erpc_server_setup.h` and `erpc_server_setup.cpp` files need to be added into the “Matrix multiply” example project to demonstrate the use of C-wrapped functions in this example.
  - The `erpc_transport_setup.h` and `erpc_setup_rpmsg_lite_remote.cpp` files need to be added into the project in order to allow the C-wrapped function for transport layer setup.
  - The `erpc_mbf_setup.h` and `erpc_setup_mbf_rpmsg.cpp` files need to be added into the project in order to allow message buffer factory usage.
- The **transports** subfolder contains transport classes for the different methods of communication supported by eRPC. Some transports are applicable only to host PCs, while others are applicable only to embedded or multicore systems. Most transports have corresponding client and server setup functions in the setup folder.
  - RPMsg-Lite is used as the transport layer for the communication between cores, `erpc_rpmsg_lite_base_transport.hpp`, `erpc_rpmsg_lite_transport.hpp`, and `erpc_rpmsg_lite_transport.cpp` files need to be added into the server project.



|

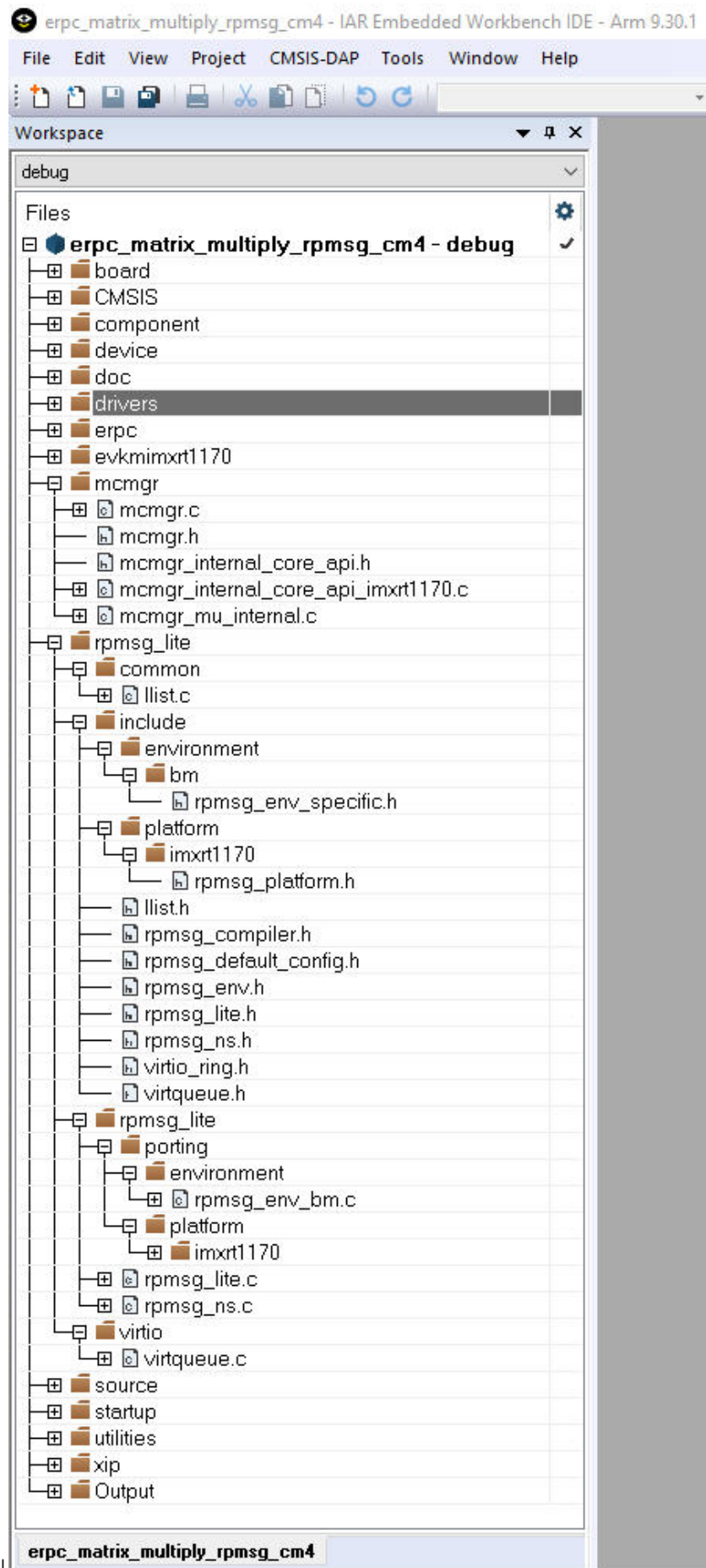
**Parent topic:** Multicore server application

**Server multicore infrastructure files** Because of the RPSMsg-Lite (transport layer), it is also necessary to include RPSMsg-Lite related files, which are in the following folder:

`<MCUXpressoSDK_install_dir>/middleware/multicore/rpsmsg_lite/`

The multicore example applications also use the Multicore Manager software library to control the secondary core startup and shutdown. These source files are located in the following folder:

`<MCUXpressoSDK_install_dir>/middleware/multicore/mcmgr/`



|

**Parent topic:**Multicore server application

**Server user code** The server's user code is stored in the `main_core1.c` file, located in the following folder:

`<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_matrix_multiply_rpmsg/cm4`

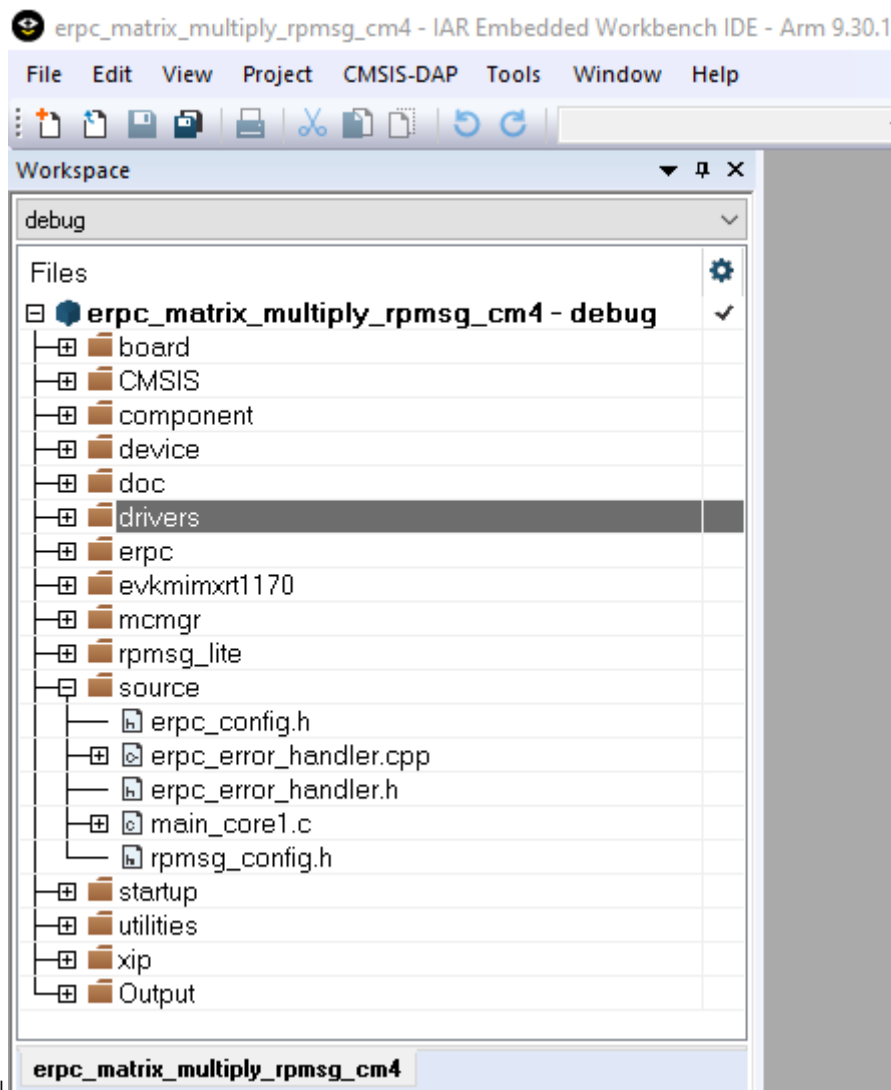
The `main_core1.c` file contains two functions:

- The **main()** function contains the code for the target board and eRPC server initialization. After the initialization, the matrix multiply service is added and the eRPC server waits for client's requests in the while loop.
- The **erpcMatrixMultiply()** function is the user implementation of the eRPC function defined in the IDL file.
- There is the possibility to write the application-specific eRPC error handler. The eRPC error handler of the matrix multiply application is implemented in the `erpc_error_handler.h` and `erpc_error_handler.cpp` files.

The eRPC-relevant code is captured in the following code snippet:

```
/* erpcMatrixMultiply function user implementation */
void erpcMatrixMultiply(const Matrix *matrix1, const Matrix *matrix2, Matrix *result_matrix)
{
    ...
}
int main()
{
    ...
    /* RPSMsg-Lite transport layer initialization */
    erpc_transport_t transport;
    transport = erpc_transport_rpmsg_lite_remote_init(src, dst, (void*)startupData,
    ERPC_TRANSPORT_RPMSG_LITE_LINK_ID, SignalReady, NULL);
    ...
    /* MessageBufferFactory initialization */
    erpc_mbf_t message_buffer_factory;
    message_buffer_factory = erpc_mbf_rpmsg_init(transport);
    ...
    /* eRPC server side initialization */
    erpc_server_t server;
    server = erpc_server_init(transport, message_buffer_factory);
    ...
    /* Adding the service to the server */
    erpc_service_t service = create_MatrixMultiplyService_service();
    erpc_add_service_to_server(server, service);
    ...
    while (1)
    {
        /* Process eRPC requests */
        erpc_status_t status = erpc_server_poll(server);
        /* handle error status */
        if (status != kErpcStatus_Success)
        {
            /* print error description */
            erpc_error_handler(status, 0);
            ...
        }
        ...
    }
}
```

Except for the application main file, there are configuration files for the RPMsg-Lite (rpmsg\_config.h) and eRPC (erpc\_config.h), located in the `<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_matrix_multiply_rpmsg` folder.



**Parent topic:**Multicore server application

**Parent topic:**[Create an eRPC application](#)

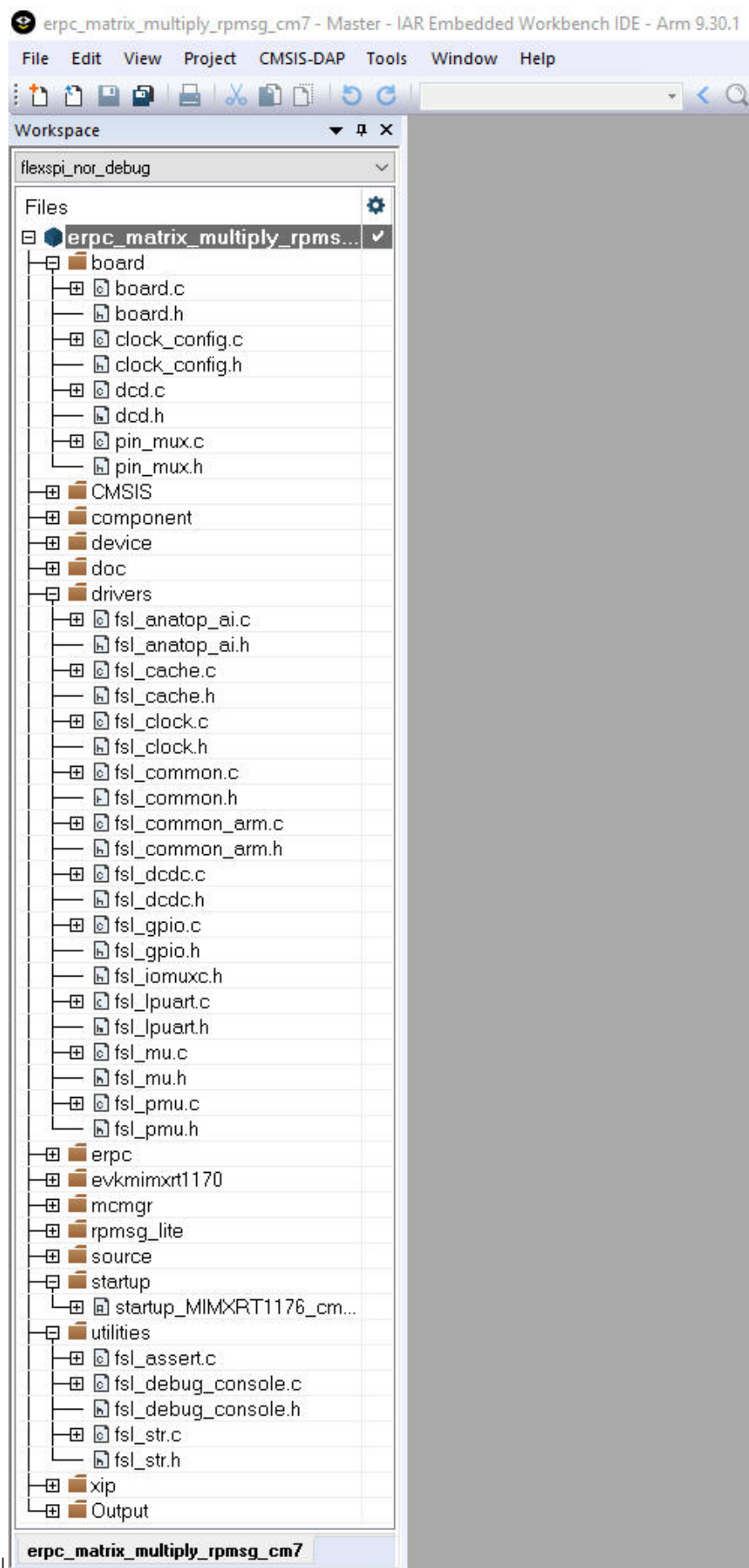
**Multicore client application** The “Matrix multiply” eRPC client project is located in the following folder:

`<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_matrix_multiply_rpmsg/cm7/iar`

Project files for the eRPC client have the `_cm7` suffix.

**Client project basic source files** The startup files, board-related settings, peripheral drivers, and utilities belong to the basic project source files and form the skeleton of all MCUXpresso SDK applications. These source files are located in the following folders:

- `<MCUXpressoSDK_install_dir>/devices/<device>`
- `<MCUXpressoSDK_install_dir>/boards/<board_name>/multicore_examples/<example_name>/`





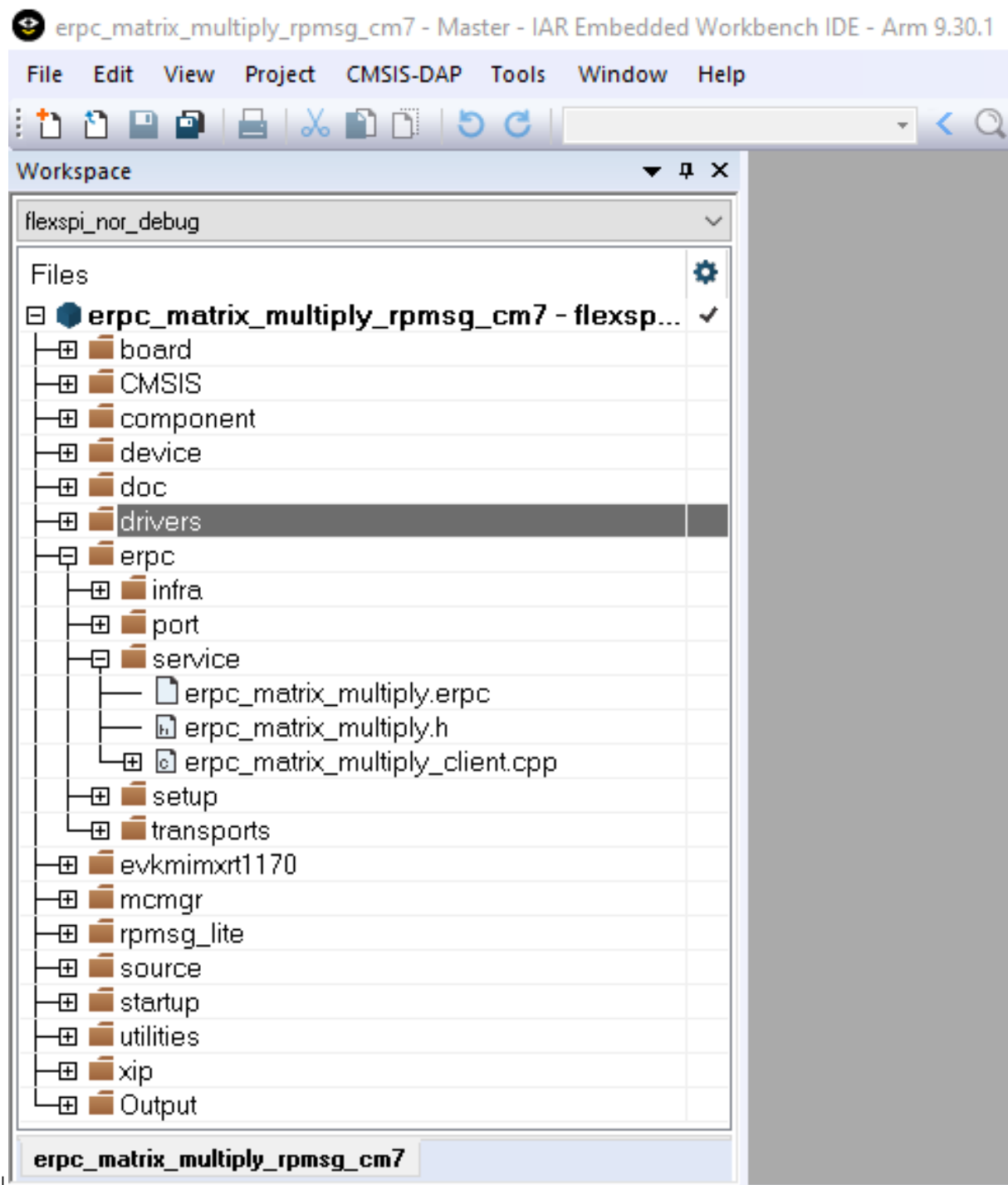
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**Parent topic:** Multicore client application

**Client-related generated files** The client-related generated files are:

- `erpc__matric__multiply.h`
- `erpc__matrix__multiply__client.cpp`

These files contain the shim code for the functions and data types declared in the IDL file. These functions also call methods for codec initialization, data serialization, performing eRPC requests, and de-serializing outputs into expected data structures (if return values are expected). These shim code files can be found in the `<MCUXpressoSDK_install_dir>/boards/evkmimxrt1170/multicore_examples/erpc_common/erpc_matrix_multiply/service/` folder.



**Parent topic:**Multicore client application

**Client infrastructure files** The eRPC infrastructure files are located in the following folder:

`<MCUXpressoSDK_install_dir>/middleware/multicore/erpc/erpc_c`

The **erpc\_c** folder contains files for creating eRPC client and server applications in the C/C++ language. These files are distributed into subfolders.

- The **infra** subfolder contains C++ infrastructure code used to build server and client applications.

- Two files, `erpc_client_manager.h` and `erpc_client_manager.cpp`, are used for managing the client-side application. The main purpose of the client files is to create, perform, and release eRPC requests.
- Three files (`erpc_codec.hpp`, `erpc_basic_codec.hpp`, and `erpc_basic_codec.cpp`) are used for codecs. Currently, the basic codec is the initial and only implementation of the codecs.
- `erpc_common.h` file is used for common eRPC definitions, typedefs, and enums.
- `erpc_manually_constructed.hpp` file is used for allocating static storage for the used objects.
- Message buffer files are used for storing serialized data: `erpc_message_buffer.hpp` and `erpc_message_buffer.cpp`.
- `erpc_transport.hpp` file defines the abstract interface for transport layer.

The **port** subfolder contains the eRPC porting layer to adapt to different environments.

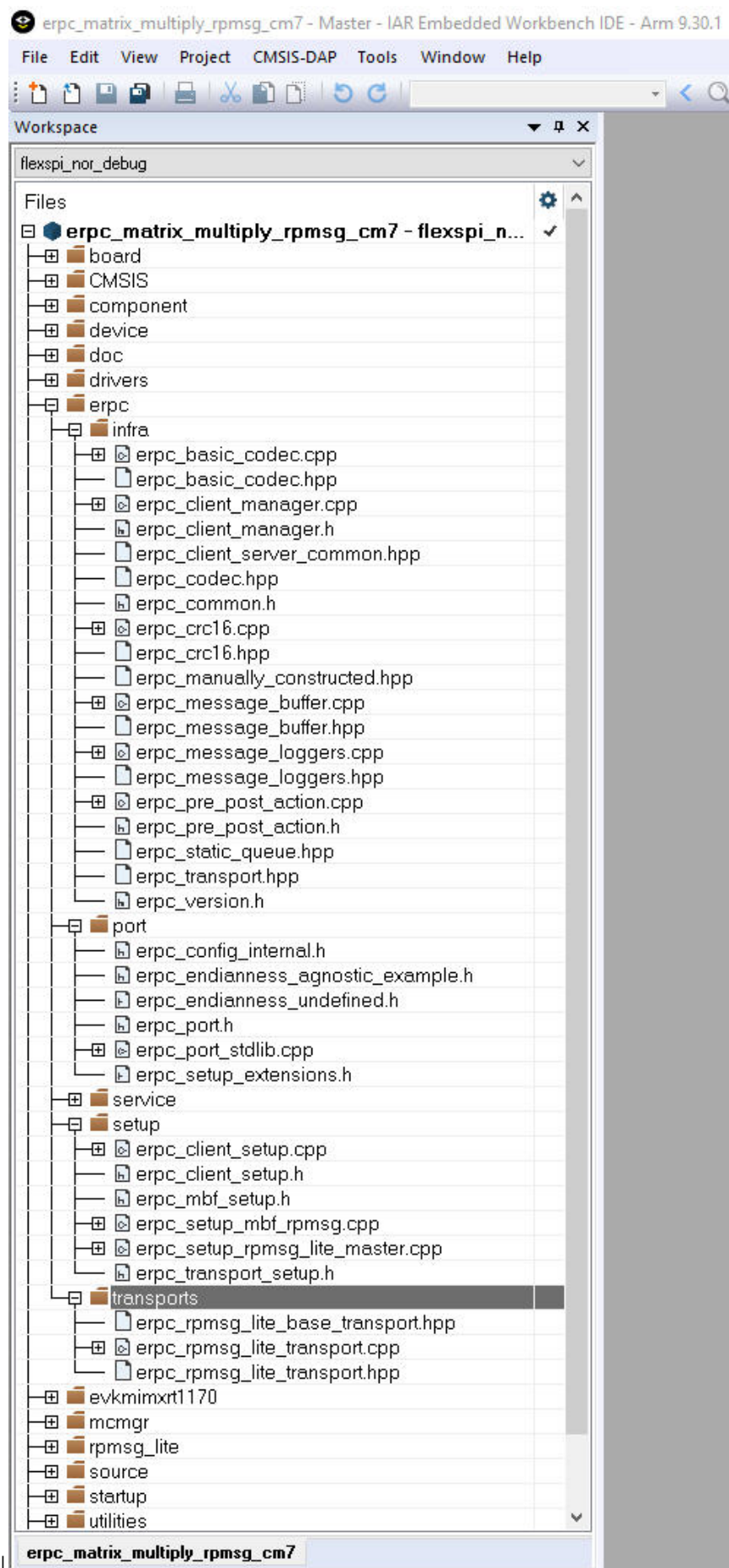
- `erpc_port.h` file contains definition of `erpc_malloc()` and `erpc_free()` functions.
- `erpc_port_stdlib.cpp` file ensures adaptation to `stdlib`.
- `erpc_config_internal.h` internal eRPC configuration file.

The **setup** subfolder contains a set of plain C APIs that wrap the C++ infrastructure, providing client and server init and deinit routines that greatly simplify eRPC usage in C-based projects. No knowledge of C++ is required to use these APIs.

- `erpc_client_setup.h` and `erpc_client_setup.cpp` files needs to be added into the “Matrix multiply” example project to demonstrate the use of C-wrapped functions in this example.
- `erpc_transport_setup.h` and `erpc_setup_rpmsg_lite_master.cpp` files needs to be added into the project in order to allow C-wrapped function for transport layer setup.
- `erpc_mbf_setup.h` and `erpc_setup_mbf_rpmsg.cpp` files needs to be added into the project in order to allow message buffer factory usage.

The **transports** subfolder contains transport classes for the different methods of communication supported by eRPC. Some transports are applicable only to host PCs, while others are applicable only to embedded or multicore systems. Most transports have corresponding client and server setup functions, in the setup folder.

- RPMsg-Lite is used as the transport layer for the communication between cores, `erpc_rpmsg_lite_base_transport.hpp`, `erpc_rpmsg_lite_transport.hpp`, and `erpc_rpmsg_lite_transport.cpp` files needs to be added into the client project.



|

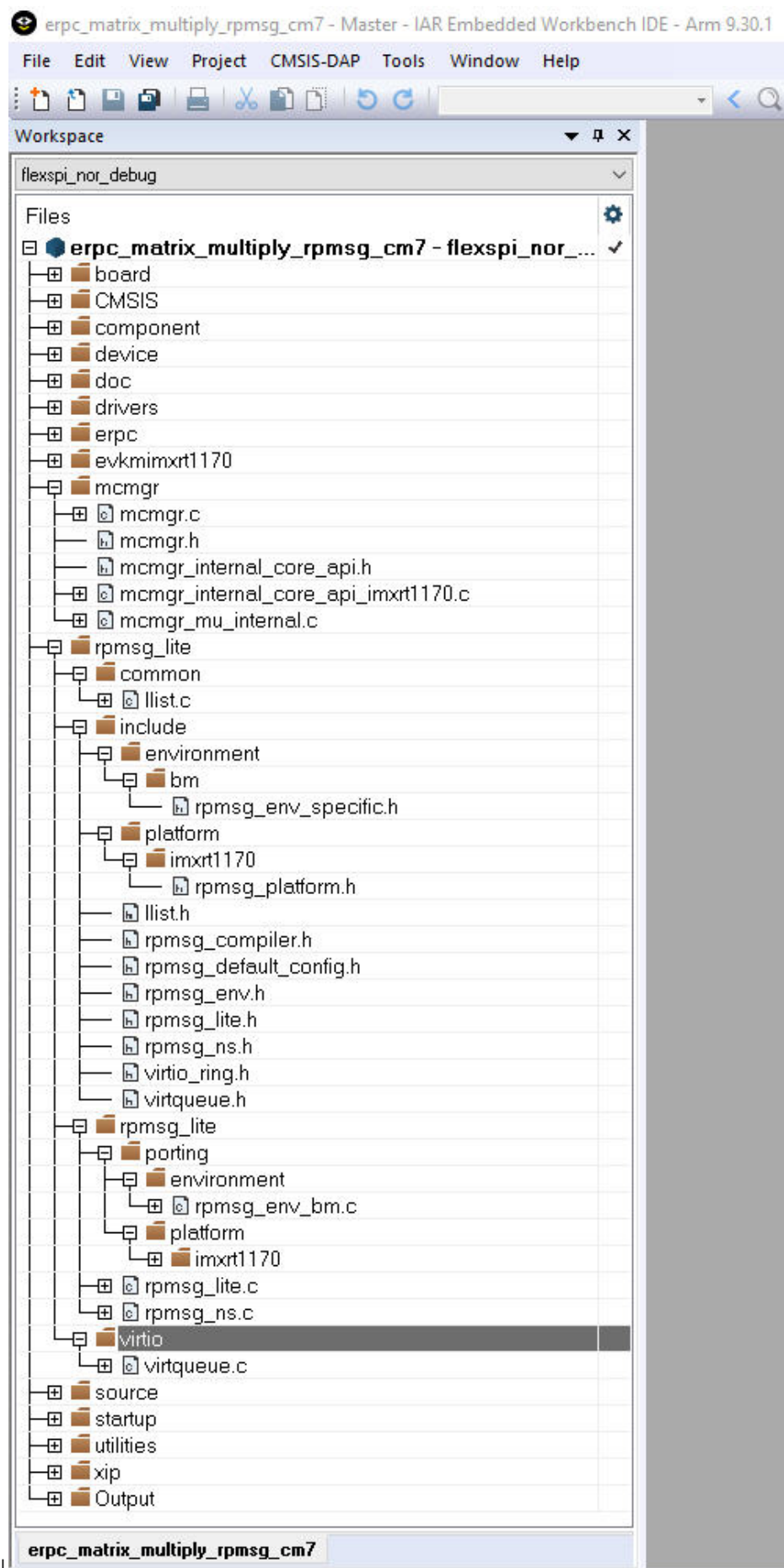
**Parent topic:** Multicore client application

**Client multicore infrastructure files** Because of the RPSMsg-Lite (transport layer), it is also necessary to include RPSMsg-Lite related files, which are in the following folder:

*<MCUXpressoSDK\_install\_dir>/middleware/multicore/rpsmsg\_lite/*

The multicore example applications also use the Multicore Manager software library to control the secondary core startup and shutdown. These source files are located in the following folder:

*<MCUXpressoSDK\_install\_dir>/middleware/multicore/mcmgr/*



**Parent topic:**Multicore client application

**Client user code** The client's user code is stored in the main\_core0.c file, located in the following folder:

<MCUXpressoSDK\_install\_dir>/boards/evkmimxrt1170/multicore\_example/erpc\_matrix\_multiply\_rpmsg/cm7

The main\_core0.c file contains the code for target board and eRPC initialization.

- After initialization, the secondary core is released from reset.
- When the secondary core is ready, the primary core initializes two matrix variables.
- The erpcMatrixMultiply eRPC function is called to issue the eRPC request and get the result.

It is possible to write the application-specific eRPC error handler. The eRPC error handler of the matrix multiply application is implemented in erpc\_error\_handler.h and erpc\_error\_handler.cpp files.

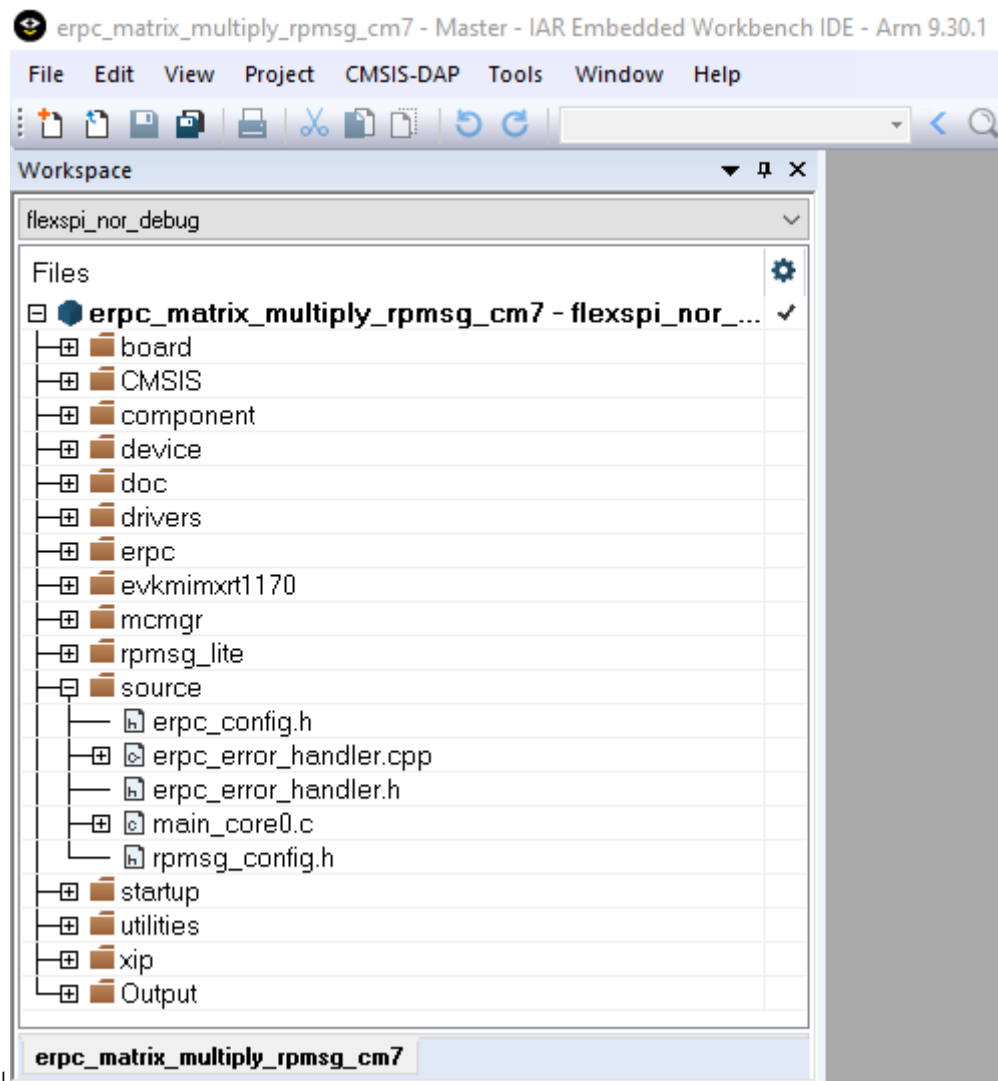
The matrix multiplication can be issued repeatedly, when pressing a software board button.

The eRPC-relevant code is captured in the following code snippet:

```
...
extern bool g_erpc_error_occurred;
...
/* Declare matrix arrays */
Matrix matrix1 = {0}, matrix2 = {0}, result_matrix = {0};
...
/* RPMsg-Lite transport layer initialization */
erpc_transport_t transport;
transport = erpc_transport_rpmsg_lite_master_init(src, dst,
ERPC_TRANSPORT_RPMSG_LITE_LINK_ID);
...
/* MessageBufferFactory initialization */
erpc_mbf_t message_buffer_factory;
message_buffer_factory = erpc_mbf_rpmsg_init(transport);
...
/* eRPC client side initialization */
erpc_client_t client;
client = erpc_client_init(transport, message_buffer_factory);
...
/* Set default error handler */
erpc_client_set_error_handler(client, erpc_error_handler);
...
while (1)
{
    /* Invoke the erpcMatrixMultiply function */
    erpcMatrixMultiply(matrix1, matrix2, result_matrix);
    ...
    /* Check if some error occurred in eRPC */
    if (g_erpc_error_occurred)
    {
        /* Exit program loop */
        break;
    }
    ...
}
```

Except for the application main file, there are configuration files for the RPMsg-Lite (rpmsg\_config.h) and eRPC (erpc\_config.h), located in the following folder:

<MCUXpressoSDK\_install\_dir>/boards/evkmimxrt1170/multicore\_examples/erpc\_matrix\_multiply\_rpmsg



**Parent topic:**Multicore client application

**Parent topic:**[Create an eRPC application](#)

**Multiprocessor server application** The “Matrix multiply” eRPC server project for multiprocessor applications is located in the `<MCUXpressoSDK_install_dir>/boards/<board_name>/multiprocessor_examples/erpc_server_matrix_multiply_<transport_layer>` folder.

Most of the multiprocessor application setup is the same as for the multicore application. The multiprocessor server application requires server-related generated files (server shim code), server infrastructure files, and the server user code. There is no need for server multicore infrastructure files (MCMGR and RPMsg-Lite). The RPMsg-Lite transport layer is replaced either by SPI or UART transports. The following table shows the required transport-related files per each transport type.

SPI	<eRPC base directory>/erpc_c/setup/erpc_setup_(d)spi_slave.cpp
	<eRPC base directory>/erpc_c/transports/erpc_(d)spi_slave_transport.hpp
	<eRPC base directory>/erpc_c/transports/erpc_(d)spi_slave_transport.cpp
UART	<eRPC base directory>/erpc_c/setup/erpc_setup_uart_cmsis.cpp



<eRPC base directory>/erpc\_c/transport/erpc\_uart\_cmsis\_transport.hpp

<eRPC base directory>/erpc\_c/transport/erpc\_uart\_cmsis\_transport.cpp

|

**Server user code** The server's user code is stored in the main\_server.c file, located in the <MCUXpressoSDK\_install\_dir>/boards/<board\_name>/multiprocessor\_examples/erpc\_server\_matrix\_multiply\_<transport\_layer>/ folder.

The eRPC-relevant code with UART as a transport is captured in the following code snippet:

```
/* erpcMatrixMultiply function user implementation */
void erpcMatrixMultiply(Matrix matrix1, Matrix matrix2, Matrix result_matrix)
{
    ...
}
int main()
{
    ...
    /* UART transport layer initialization, ERPC_DEMO_UART is the structure of CMSIS UART driver
    ↪operations */
    erpc_transport_t transport;
    transport = erpc_transport_cmsis_uart_init((void *)&ERPC_DEMO_UART);
    ...
    /* MessageBufferFactory initialization */
    erpc_mbf_t message_buffer_factory;
    message_buffer_factory = erpc_mbf_dynamic_init();
    ...
    /* eRPC server side initialization */
    erpc_server_t server;
    server = erpc_server_init(transport, message_buffer_factory);
    ...
    /* Adding the service to the server */
    erpc_service_t service = create_MatrixMultiplyService_service();
    erpc_add_service_to_server(server, service);
    ...
    while (1)
    {
        /* Process eRPC requests */
        erpc_status_t status = erpc_server_poll(server)
        /* handle error status */
        if (status != kErpcStatus_Success)
        {
            /* print error description */
            erpc_error_handler(status, 0);
            ...
        }
        ...
    }
}
```

**Parent topic:**Multiprocessor server application

**Multiprocessor client application** The “Matrix multiply” eRPC client project for multiprocessor applications is located in the <MCUXpressoSDK\_install\_dir>/boards/<board\_name>/multiprocessor\_examples/erpc\_client\_matrix\_multiply\_<transport\_layer>/iar/ folder.

Most of the multiprocessor application setup is the same as for the multicore application. The multiprocessor server application requires client-related generated files (server shim code),

client infrastructure files, and the client user code. There is no need for client multicore infrastructure files (MCMGR and RPSMsg-Lite). The RPSMsg-Lite transport layer is replaced either by SPI or UART transports. The following table shows the required transport-related files per each transport type.

SPI	<eRPC base directory>/erpc_c/setup/erpc_setup_(d)spi_master.cpp
<eRPC base directory>/erpc_c/	transports/ erpc_(d)spi_master_transport.hpp
<eRPC base directory>/erpc_c/	transports/ erpc_(d)spi_master_transport.cpp
UART	<eRPC base directory>/erpc_c/setup/erpc_setup_uart_cmsis.cpp
<eRPC base directory>/erpc_c/	transports/erpc_uart_cmsis_transport.hpp
<eRPC base directory>/erpc_c/	transports/erpc_uart_cmsis_transport.cpp

**Client user code** The client's user code is stored in the `main_client.c` file, located in the `<MCUXpressoSDK_install_dir>/boards/<board_name>/multiprocessor_examples/erpc_client_matrix_multiply_<transport_layer>/` folder.

The eRPC-relevant code with UART as a transport is captured in the following code snippet:

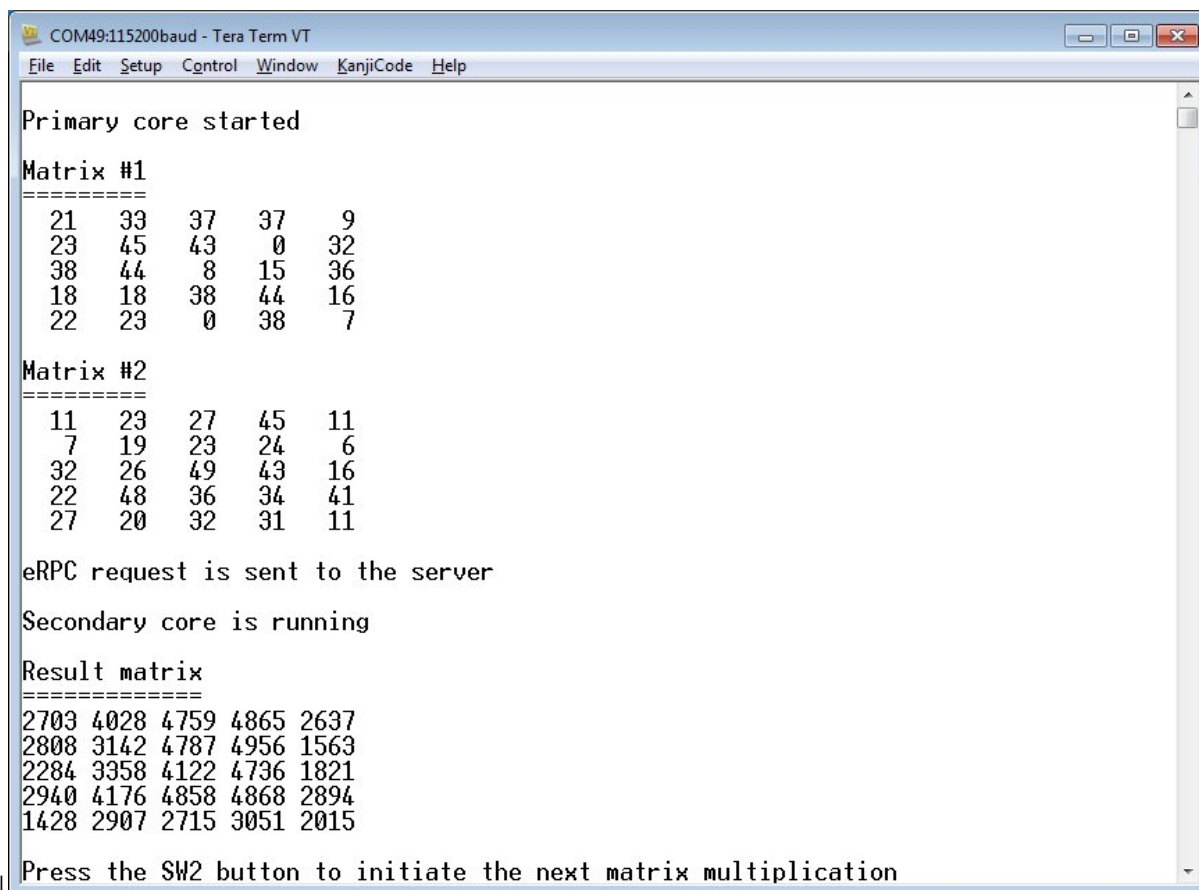
```
...
extern bool g_erpc_error_occurred;
...
/* Declare matrix arrays */
Matrix matrix1 = {0}, matrix2 = {0}, result_matrix = {0};
...
/* UART transport layer initialization, ERPC_DEMO_UART is the structure of CMSIS UART driver
↳operations */
erpc_transport_t transport;
transport = erpc_transport_cmsis_uart_init((void *)&ERPC_DEMO_UART);
...
/* MessageBufferFactory initialization */
erpc_mbf_t message_buffer_factory;
message_buffer_factory = erpc_mbf_dynamic_init();
...
/* eRPC client side initialization */
erpc_client_t client;
client = erpc_client_init(transport,message_buffer_factory);
...
/* Set default error handler */
erpc_client_set_error_handler(client, erpc_error_handler);
...
while (1)
{
    /* Invoke the erpcMatrixMultiply function */
    erpcMatrixMultiply(matrix1, matrix2, result_matrix);
    ...
    /* Check if some error occurred in eRPC */
    if (g_erpc_error_occurred)
    {
        /* Exit program loop */
        break;
    }
    ...
}
```

**Parent topic:**Multiprocessor client application

**Parent topic:**Multiprocessor server application

Parent topic:[Create an eRPC application](#)

**Running the eRPC application** Follow the instructions in *Getting Started with MCUXpresso SDK* (document MCUXSDKGSUG) (located in the <MCUXpressoSDK\_install\_dir>/docs folder), to load both the primary and the secondary core images into the on-chip memory, and then effectively debug the dual-core application. After the application is running, the serial console should look like:



```

COM49:115200baud - Tera Term VT
File Edit Setup Control Window KanjiCode Help

Primary core started

Matrix #1
=====
 21  33  37  37   9
 23  45  43   0  32
 38  44   8  15  36
 18  18  38  44  16
 22  23   0  38   7

Matrix #2
=====
 11  23  27  45  11
  7  19  23  24   6
 32  26  49  43  16
 22  48  36  34  41
 27  20  32  31  11

eRPC request is sent to the server

Secondary core is running

Result matrix
=====
2703 4028 4759 4865 2637
2808 3142 4787 4956 1563
2284 3358 4122 4736 1821
2940 4176 4858 4868 2894
1428 2907 2715 3051 2015

Press the SW2 button to initiate the next matrix multiplication

```

For multiprocessor applications that are running between PC and the target evaluation board or between two boards, follow the instructions in the accompanied example readme files that provide details about the proper board setup and the PC side setup (Python).

Parent topic:[Create an eRPC application](#)

Parent topic:[eRPC example](#)

**Other uses for an eRPC implementation** The eRPC implementation is generic, and its use is not limited to just embedded applications. When creating an eRPC application outside the embedded world, the same principles apply. For example, this manual can be used to create an eRPC application for a PC running the Linux operating system. Based on the used type of transport medium, existing transport layers can be used, or new transport layers can be implemented.

For more information and erpc updates see the [github.com/EmbeddedRPC](https://github.com/EmbeddedRPC).

**Note about the source code in the document** Example code shown in this document has the following copyright and BSD-3-Clause license:

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**Changelog eRPC** 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

### Fixed

- Python code of the eRPC infrastructure was updated to match the proper python code style, add type annotations and improve readability.

## 1.14.0

### Added

- Added Cmake/Kconfig support.
- Made java code jdk11 compliant, GitHub PR #432.
- Added imxrt1186 support into mu transport layer.
- erpcgen: Added assert for listType before usage, GitHub PR #406.

### Fixed

- eRPC: Sources reformatted.
- erpc: Fixed typo in semaphore get (mutex -> semaphore), and write it can fail in case of timeout, GitHub PR #446.
- erpc: Free the arbitrated client token from client manager, GitHub PR #444.

- erpc: Fixed Makefile, install the erpc\_simple\_server header, GitHub PR #447.
- erpc\_python: Fixed possible AttributeError and OSError on calling TCPTransport.close(), GitHub PR #438.
- Examples and tests consolidated.

### 1.13.0

#### Added

- erpc: Add BSD-3 license to endianness agnostic files, GitHub PR #417.
- eRPC: Add new Zephyr-related transports (zephyr\_uart, zephyr\_mbox).
- eRPC: Add new Zephyr-related examples.

#### Fixed

- eRPC,erpcgen: Fixing/improving markdown files, GitHub PR #395.
- eRPC: Fix Python client TCPTransports not being able to close, GitHub PR #390.
- eRPC,erpcgen: Align switch brackets, GitHub PR #396.
- erpc: Fix zephyr uart transport, GitHub PR #410.
- erpc: UART ZEPHYR Transport stop to work after a few transactions when using USB-CDC resolved, GitHub PR #420.

#### Removed

- eRPC,erpcgen: Remove cstbool library, GitHub PR #403.

### 1.12.0

#### Added

- eRPC: Add dynamic/static option for transport init, GitHub PR #361.
- eRPC,erpcgen: Winsock2 support, GitHub PR #365.
- eRPC,erpcgen: Feature/support multiple clients, GitHub PR #271.
- eRPC,erpcgen: Feature/buffer head - Framed transport header data stored in Message-Buffer, GitHub PR #378.
- eRPC,erpcgen: Add experimental Java support.

#### Fixed

- eRPC: Fix receive error value for spidev, GitHub PR #363.
- eRPC: UartTransport::init adaptation to changed driver.
- eRPC: Fix typo in assert, GitHub PR #371.
- eRPC,erpcgen: Move enums to enum classes, GitHub PR #379.
- eRPC: Fixed rpmsg tty transport to work with serial transport, GitHub PR #373.

### 1.11.0

#### Fixed

- eRPC: Makefiles update, GitHub PR #301.
- eRPC: Resolving warnings in Python, GitHub PR #325.
- eRPC: Python3.8 is not ready for usage of typing.Any type, GitHub PR #325.
- eRPC: Improved codec function to use reference instead of address, GitHub PR #324.
- eRPC: Fix NULL check for pending client creation, GitHub PR #341.
- eRPC: Replace sprintf with snprintf, GitHub PR #343.
- eRPC: Use MU\_SendMsg blocking call in MU transport.
- eRPC: New LPSPI and LPI2C transport layers.
- eRPC: Freeing static objects, GitHub PR #353.
- eRPC: Fixed casting in deinit functions, GitHub PR #354.
- eRPC: Align LIBUSBIO.GetNumPorts API use with libusb python module v. 2.1.11.
- erpcgen: Renamed temp variable to more generic one, GitHub PR #321.
- erpcgen: Add check that string read is not more than max length, GitHub PR #328.
- erpcgen: Move to g++ in pytest, GitHub PR #335.
- erpcgen: Use build=release for make, GitHub PR #334.
- erpcgen: Removed boost dependency, GitHub PR #346.
- erpcgen: Mingw support, GitHub PR #344.
- erpcgen: VS build update, GitHub PR #347.
- erpcgen: Modified name for common types macro scope, GitHub PR #337.
- erpcgen: Fixed memcpy for template, GitHub PR #352.
- eRPC,erpcgen: Change default build target to release + adding artefacts, GitHub PR #334.
- eRPC,erpcgen: Remove redundant includes, GitHub PR #338.
- eRPC,erpcgen: Many minor code improvements, GitHub PR #323.

### 1.10.0

#### Fixed

- eRPC: MU transport layer switched to blocking MU\_SendMsg() API use.

### 1.10.0

#### Added

- eRPC: Add TCP\_NODELAY option to python, GitHub PR #298.

## Fixed

- eRPC: MUPort adaptation to new supported SoCs.
- eRPC: Simplifying CI with installing dependencies using shell script, GitHub PR #267.
- eRPC: Using event for waiting for sock connection in TCP python server, formatting python code, C specific includes, GitHub PR #269.
- eRPC: Endianness agnostic update, GitHub PR #276.
- eRPC: Assertion added for functions which are returning status on freeing memory, GitHub PR #277.
- eRPC: Fixed closing arbitrator server in unit tests, GitHub PR #293.
- eRPC: Makefile updated to reflect the correct header names, GitHub PR #295.
- eRPC: Compare value length to used length() in reading data from message buffer, GitHub PR #297.
- eRPC: Replace EXPECT\_TRUE with EXPECT\_EQ in unit tests, GitHub PR #318.
- eRPC: Adapt rpmsg\_lite based transports to changed rpmsg\_lite\_wait\_for\_link\_up() API parameters.
- eRPC, erpcgen: Better distinguish which file can and cannot be linked by C linker, GitHub PR #266.
- eRPC, erpcgen: Stop checking if pointer is NULL before sending it to the erpc\_free function, GitHub PR #275.
- eRPC, erpcgen: Changed api to count with more interfaces, GitHub PR #304.
- erpcgen: Check before reading from heap the buffer boundaries, GitHub PR #287.
- erpcgen: Several fixes for tests and CI, GitHub PR #289.
- erpcgen: Refactoring erpcgen code, GitHub PR #302.
- erpcgen: Fixed assigning const value to enum, GitHub PR #309.
- erpcgen: Enable runTesttest\_enumErrorCode\_allDirection, serialize enums as int32 instead of uint32.

### 1.9.1

## Fixed

- eRPC: Construct the USB CDC transport, rather than a client, GitHub PR #220.
- eRPC: Fix premature import of package, causing failure when attempting installation of Python library in a clean environment, GitHub PR #38, #226.
- eRPC: Improve python detection in make, GitHub PR #225.
- eRPC: Fix several warnings with deprecated call in pytest, GitHub PR #227.
- eRPC: Fix freeing union members when only default need be freed, GitHub PR #228.
- eRPC: Fix making test under Linux, GitHub PR #229.
- eRPC: Assert costumizing, GitHub PR #148.
- eRPC: Fix corrupt clientList bug in TransportArbitrator, GitHub PR #199.
- eRPC: Fix build issue when invoking g++ with -Wno-error=free-nonheap-object, GitHub PR #233.
- eRPC: Fix inout cases, GitHub PR #237.

- eRPC: Remove ERPC\_PRE\_POST\_ACTION dependency on return type, GitHub PR #238.
- eRPC: Adding NULL to ptr when codec function failed, fixing memcpy when fail is present during deserialization, GitHub PR #253.
- eRPC: MessageBuffer usage improvement, GitHub PR #258.
- eRPC: Get rid of serial and enum34 dependency (enum34 is in python3 since 3.4 (from 2014)), GitHub PR #247.
- eRPC: Several MISRA violations addressed.
- eRPC: Fix timeout for Freertos semaphore, GitHub PR #251.
- eRPC: Use of rpmsg\_lite\_wait\_for\_link\_up() in rpmsg\_lite based transports, GitHub PR #223.
- eRPC: Fix codec nullptr dereferencing, GitHub PR #264.
- erpcgen: Fix two syntax errors in erpcgen Python output related to non-encapsulated unions, improved test for union, GitHub PR #206, #224.
- erpcgen: Fix serialization of list/binary types, GitHub PR #240.
- erpcgen: Fix empty list parsing, GitHub PR #72.
- erpcgen: Fix templates for malloc errors, GitHub PR #110.
- erpcgen: Get rid of encapsulated union declarations in global scale, improve enum usage in unions, GitHub PR #249, #250.
- erpcgen: Fix compile error:UniqueIdChecker.cpp:156:104:'sort' was not declared, GitHub PR #265.

## 1.9.0

### Added

- eRPC: Allow used LIBUSB\_SIO device index being specified from the Python command line argument.

### Fixed

- eRPC: Improving template usage, GitHub PR #153.
- eRPC: run\_clang\_format.py cleanup, GitHub PR #177.
- eRPC: Build TCP transport setup code into liberpc, GitHub PR #179.
- eRPC: Fix multiple definitions of g\_client error, GitHub PR #180.
- eRPC: Fix memset past end of buffer in erpc\_setup\_mbf\_static.cpp, GitHub PR #184.
- eRPC: Fix deprecated error with newer pytest version, GitHub PR #203.
- eRPC, erpcgen: Static allocation support and usage of rpmsg static FreeRTOSs related API, GitHub PR #168, #169.
- erpcgen: Remove redundant module imports in erpcgen, GitHub PR #196.

## 1.8.1

### Added

- eRPC: New i2c\_slave\_transport transport introduced.



### Fixed

- eRPC: Fix misra erpc c, GitHub PR #158.
- eRPC: Allow conditional compilation of message\_loggers and pre\_post\_action.
- eRPC: (D)SPI slave transports updated to avoid busy loops in rtos environments.
- erpcgen: Re-implement EnumMember::hasValue(), GitHub PR #159.
- erpcgen: Fixing several misra issues in shim code, erpcgen and unit tests updated, GitHub PR #156.
- erpcgen: Fix bison file, GitHub PR #156.

### 1.8.0

### Added

- eRPC: Support win32 thread, GitHub PR #108.
- eRPC: Add mbed support for malloc() and free(), GitHub PR #92.
- eRPC: Introduced pre and post callbacks for eRPC call, GitHub PR #131.
- eRPC: Introduced new USB CDC transport.
- eRPC: Introduced new Linux spidev-based transport.
- eRPC: Added formatting extension for VSC, GitHub PR #134.
- erpcgen: Introduce ustring type for unsigned char and force cast to char\*, GitHub PR #125.

### Fixed

- eRPC: Update makefile.
- eRPC: Fixed warnings and error with using MessageLoggers, GitHub PR #127.
- eRPC: Extend error msg for python server service handle function, GitHub PR #132.
- eRPC: Update CMSIS UART transport layer to avoid busy loops in rtos environments, introduce semaphores.
- eRPC: SPI transport update to allow usage without handshaking GPIO.
- eRPC: Native \_WIN32 erpc serial transport and threading.
- eRPC: Arbitrator deadlock fix, TCP transport updated, TCP setup functions introduced, GitHub PR #121.
- eRPC: Update of matrix\_multiply.py example: Add -serial and -baud argument, GitHub PR #137.
- eRPC: Update of .clang-format, GitHub PR #140.
- eRPC: Update of erpc\_framed\_transport.cpp: return error if received message has zero length, GitHub PR #141.
- eRPC, erpcgen: Fixed error messages produced by -Wall -Wextra -Wshadow -pedantic-errors compiler flags, GitHub PR #136, #139.
- eRPC, erpcgen: Core re-formatted using Clang version 10.
- erpcgen: Enable deallocation in server shim code when callback/function pointer used as out parameter in IDL.
- erpcgen: Removed '\$' character from generated symbol name in '\_\$union' suffix, GitHub PR #103.

- erpcgen: Resolved mismatch between C++ and Python for callback index type, GitHub PR #111.
- erpcgen: Python generator improvements, GitHub PR #100, #118.
- erpcgen: Fixed error messages produced by -Wall -Wextra -Wshadow -pedantic-errors compiler flags, GitHub PR #136.

#### 1.7.4

##### Added

- eRPC: Support MU transport unit testing.
- eRPC: Adding mbed os support.

##### Fixed

- eRPC: Unit test code updated to handle service add and remove operations.
- eRPC: Several MISRA issues in rpmsg-based transports addressed.
- eRPC: Fixed Linux/TCP acceptance tests in release target.
- eRPC: Minor documentation updates, code formatting.
- erpcgen: Whitespace removed from C common header template.

#### 1.7.3

##### Fixed

- eRPC: Improved the test\_callbacks logic to be more understandable and to allow requested callback execution on the server side.
- eRPC: TransportArbitrator::prepareClientReceive modified to avoid incorrect return value type.
- eRPC: The ClientManager and the ArbitratedClientManager updated to avoid performing client requests when the previous serialization phase fails.
- erpcgen: Generate the shim code for destroy of statically allocated services.

#### 1.7.2

##### Added

- eRPC: Add missing doxygen comments for transports.

##### Fixed

- eRPC: Improved support of const types.
- eRPC: Fixed Mac build.
- eRPC: Fixed serializing python list.
- eRPC: Documentation update.

### 1.7.1

#### Fixed

- eRPC: Fixed semaphore in static message buffer factory.
- erpcgen: Fixed MU received error flag.
- erpcgen: Fixed tcp transport.

### 1.7.0

#### Added

- eRPC: List names are based on their types. Names are more deterministic.
- eRPC: Service objects are as a default created as global static objects.
- eRPC: Added missing doxygen comments.
- eRPC: Added support for 64bit numbers.
- eRPC: Added support of program language specific annotations.

#### Fixed

- eRPC: Improved code size of generated code.
- eRPC: Generating crc value is optional.
- eRPC: Fixed CMSIS Uart driver. Removed dependency on KSDK.
- eRPC: Forbid users use reserved words.
- eRPC: Removed outByref for function parameters.
- eRPC: Optimized code style of callback functions.

### 1.6.0

#### Added

- eRPC: Added @nullable support for scalar types.

#### Fixed

- eRPC: Improved code size of generated code.
- eRPC: Improved eRPC nested calls.
- eRPC: Improved eRPC list length variable serialization.

### 1.5.0

### Added

- eRPC: Added support for unions type non-wrapped by structure.
- eRPC: Added callbacks support.
- eRPC: Added support @external annotation for functions.
- eRPC: Added support @name annotation.
- eRPC: Added Messaging Unit transport layer.
- eRPC: Added RPMSG Lite RTOS TTY transport layer.
- eRPC: Added version verification and IDL version verification between eRPC code and eRPC generated shim code.
- eRPC: Added support of shared memory pointer.
- eRPC: Added annotation to forbid generating const keyword for function parameters.
- eRPC: Added python matrix multiply example.
- eRPC: Added nested call support.
- eRPC: Added struct member “byref” option support.
- eRPC: Added support of forward declarations of structures
- eRPC: Added Python RPMsg Multiendpoint kernel module support
- eRPC: Added eRPC sniffer tool

### 1.4.0

### Added

- eRPC: New RPMsg-Lite Zero Copy (RPMsgZC) transport layer.

### Fixed

- eRPC: win\_flex\_bison.zip for windows updated.
- eRPC: Use one codec (instead of inCodec outCodec).

### [1.3.0]

### Added

- eRPC: New annotation types introduced (@length, @max\_length, ...).
- eRPC: Support for running both erpc client and erpc server on one side.
- eRPC: New transport layers for (LP)UART, (D)SPI.
- eRPC: Error handling support.

### [1.2.0]

### Added

- eRPC source directory organization changed.
- Many eRPC improvements.

**[1.1.0]**

**Added**

- Multicore SDK 1.1.0 ported to KSDK 2.0.0.

**[1.0.0]**

**Added**

- Initial Release



# 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 ChangeLog](#)

[FreeRTOS kernel Readme](#)

#### 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](#)

#### 4.1.4 corehttp

C language HTTP client library designed for embedded platforms.

#### 4.1.5 corejson

JSON parser.

## **Readme**

### **4.1.6 coremqtt**

MQTT publish/subscribe messaging library.

### **4.1.7 corepkcs11**

PKCS #11 key management library.

## **Readme**

### **4.1.8 freertos-plus-tcp**

Open source RTOS FreeRTOS Plus TCP.

## **Readme**