



MCUXpresso SDK Documentation

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This documentation contains information specific to the mc56f80000evk board.

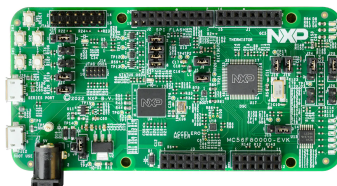
Chapter 1

MC56F80000-EVK

1.1 Overview

The MC56F80000-EVK is an ultra-low-cost development platform for Digital Signal Controller MC56F80xxx MCU.

- Form-factor compatible with the Arduino R3 pin layout.
- On board debugger(multilink) circuit enabling debugging and programming with Code-Warrior, it also enable a virtual series port.
- Peripherals enable rapid prototyping, including a 3-axis MEMS accelerometer, 6 PWM and 3 user LEDs, 4 user push buttons for direct interaction, two OPAMP external feedback circuits, a SPI interfaced Flash memory and 3 resistor dividers for ADC test.



MCU device and part on board is shown below:

- Device: MC56F80748
- PartNumber: MC56F80748VLH

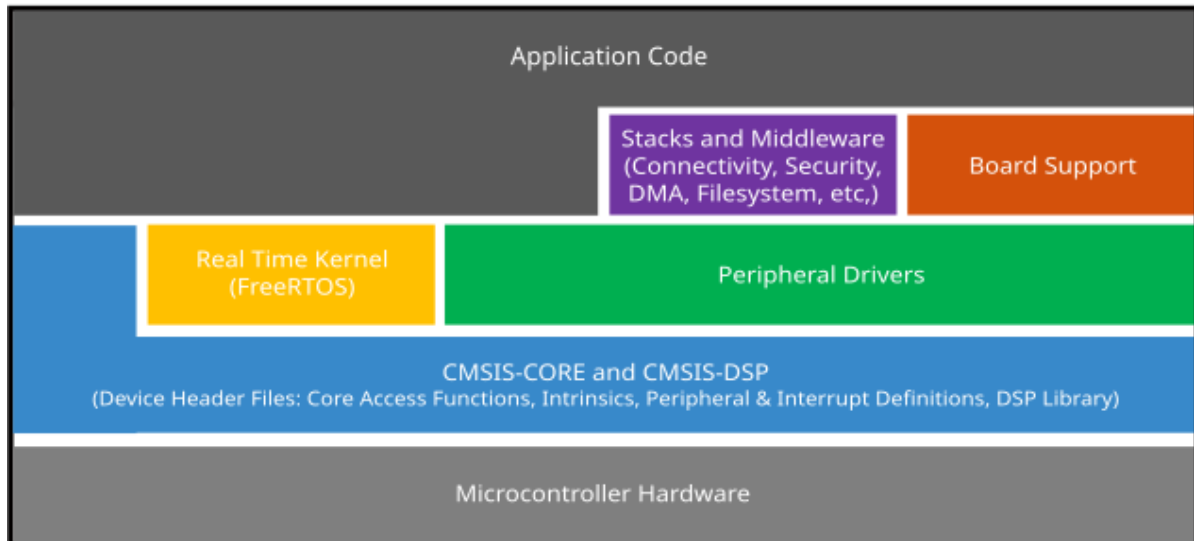
1.2 Getting Started with MCUXpresso SDK Package

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 full demo applications. The MCUXpresso SDK contains optional RTOS integrations such as FreeRTOS and Azure RTOS, and various other middleware to support rapid development. For supported toolchain versions, see *MCUXpresso SDK Release Notes* (document MCUXSDKRN). For more details about MCUXpresso SDK, see [MCUXpresso Software Development Kit \(SDK\)](#).



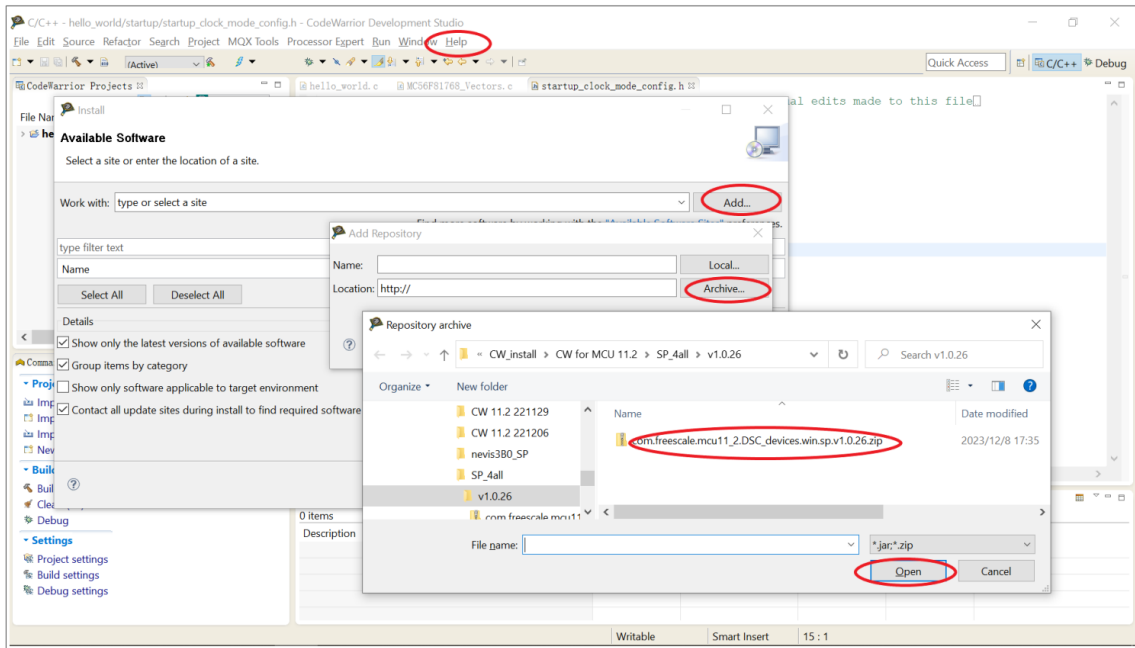
Build and run SDK example on codewarrior

Install CodeWarrior Take below codewarrior specific combination as example

- CodeWarrior Development Studio v11.2 + CodeWarrior for DSC v11.2 SP1 (Service Pack 1)

Steps to install CodeWarrior

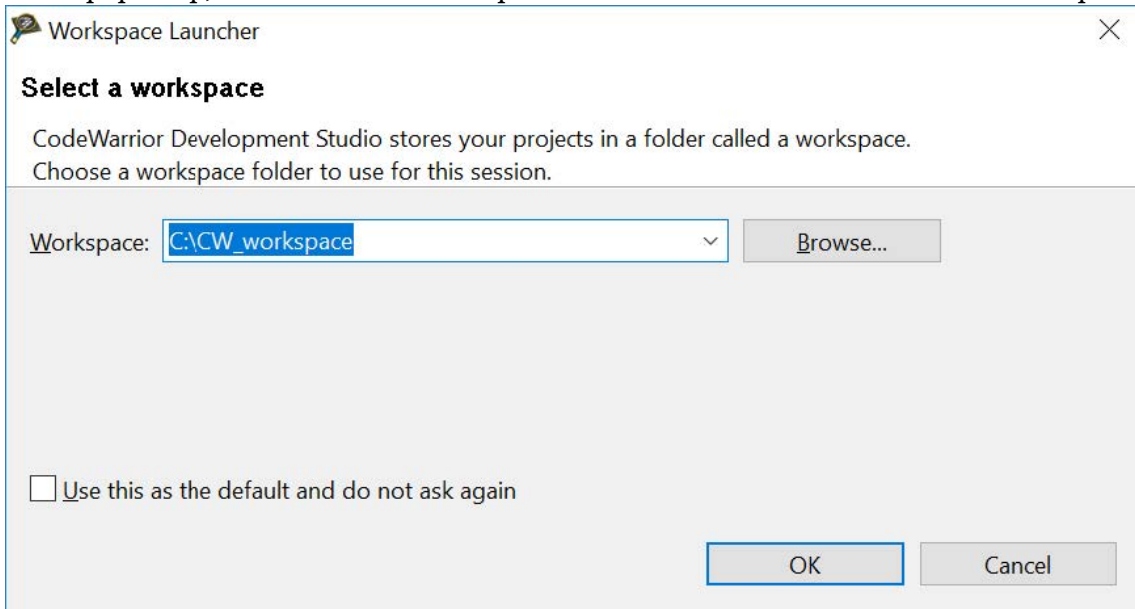
- Download the following packages from [CodeWarrior for 56800 Digital Signal Controller v11.2](#), and ensure to keep them in the same folder.
 - CodeWarrior for DSC v11.2: CW_MCU_v11.2_b221206.exe.
 - DSC support package: com.freescale.mcu11_2.dsc.updatesite.zip.
 - DSC device ServicePack1: com.freescale.mcu11_2.DSC_devices.win.sp.v1.0.26.zip.
- Install CodeWarrior for DSC v11.2.
- Install ServicePack1 within CodeWarrior from the menu. Click the **Help** menu -> select **Install new software** -> **Add** -> **Archive** -> select the downloaded SP1 -> open -> check **MCU v11.2 DSC Service Packs** -> click **Next**.

**NOTE**

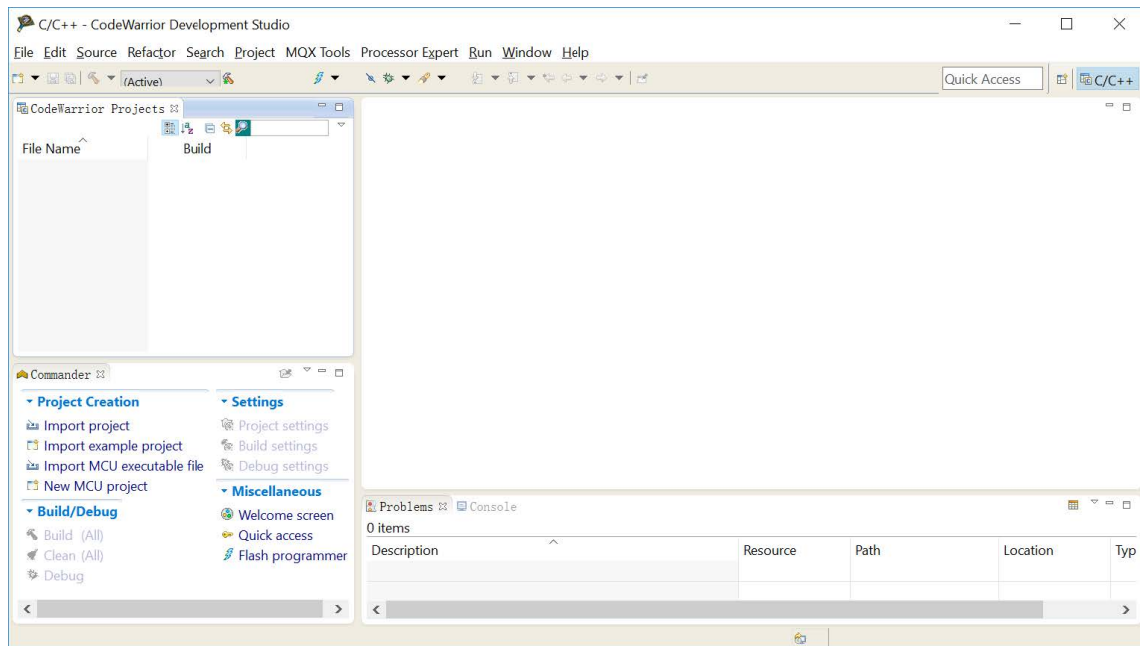
- CodeWarrior for DSC only support Windows.
- Check the corresponding board release note for specific requirement of codewarrior and service pack version.

Build an example application To build the hello_world example application, perform the following example steps:

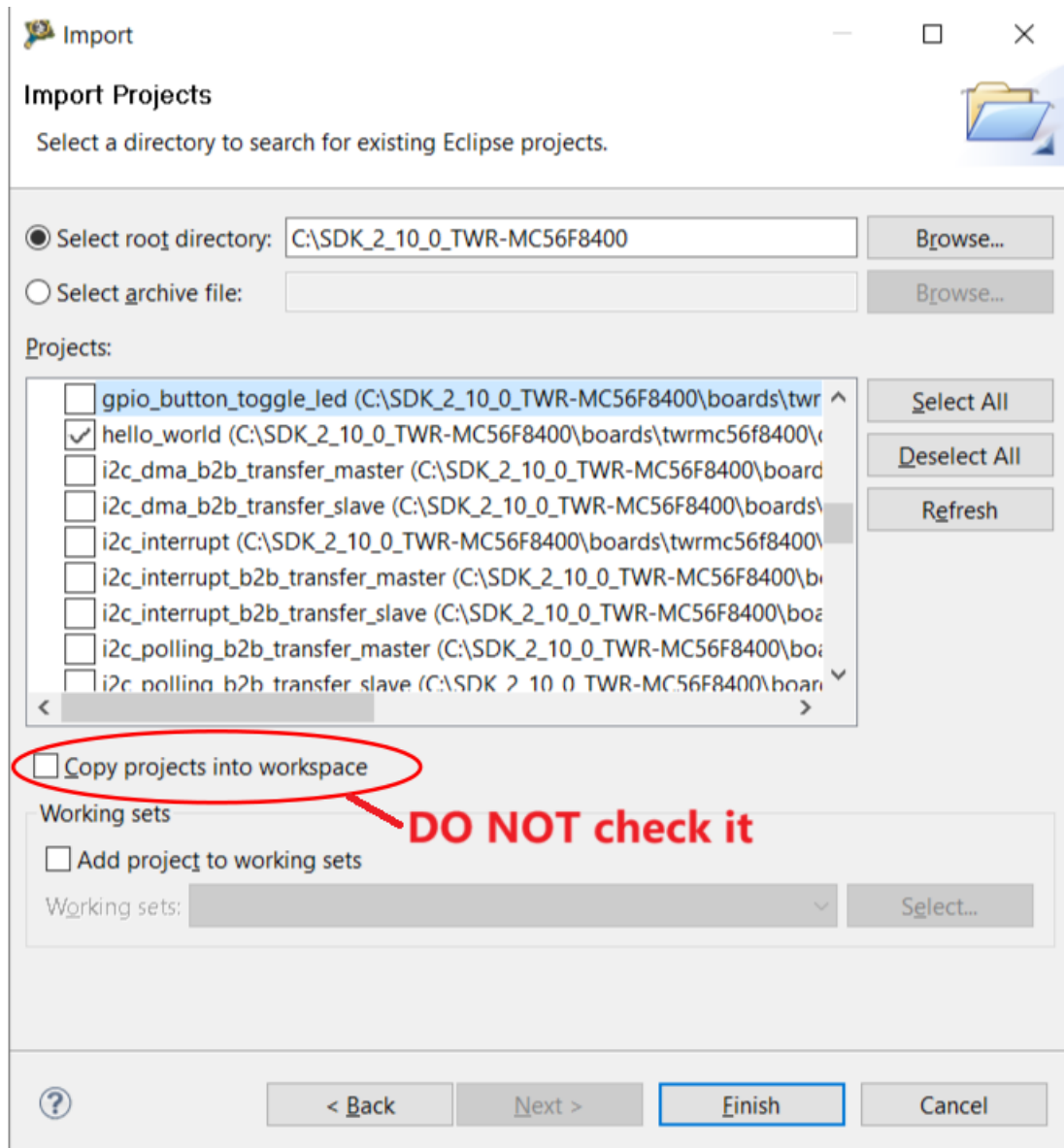
1. Launch CodeWarrior and in the workspace launcher, choose a workspace which holds the projects to use. If the dialogue box does not pop up, enter a workspace folder and create one workspace.



Then the CodeWarrior Development Studio workspace with empty projects appears.



2. Import the project into the workspace. Click **Import project** in the **Commander** pane. A form pops up. Click **Browse** to the SDK install directory. Take TWR-MC56F8400 SDK as an example, all available demo projects are shown. Select the `hello_world` project in the list and click **Finish**.

**NOTE**

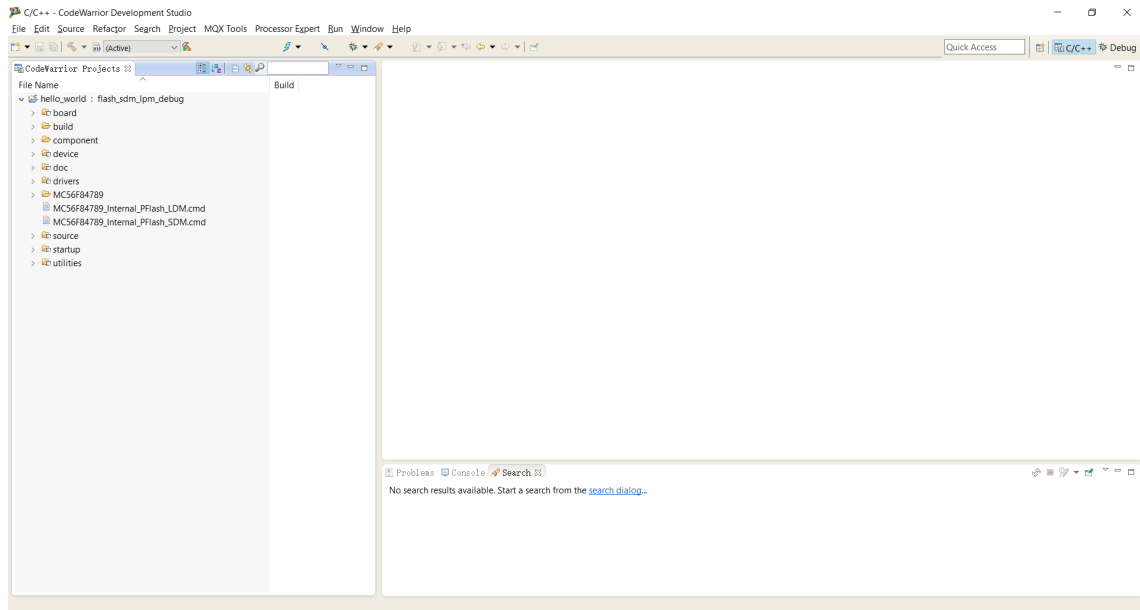
- If you already know the project location, navigate to the folder when clicking **Browse**, and only one project can be seen. To locate most example application workspace files, use the following path

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

Take TWR-MC56F8400 SDK as an example, the `hello_world` workspace is located in

```
<install_dir>/boards/twrmc56f8400/demo_apps/hello_world/codewarrior
```

3. Select the desired build target from the drop-down menu. For this example, select **hello_world** – **flash_sdm_lpm_debug**



4. To build the demo application, click **Build (All)** in the **Commander** pane.
5. The build completes without errors.

Board debugger setup Board debugger info:

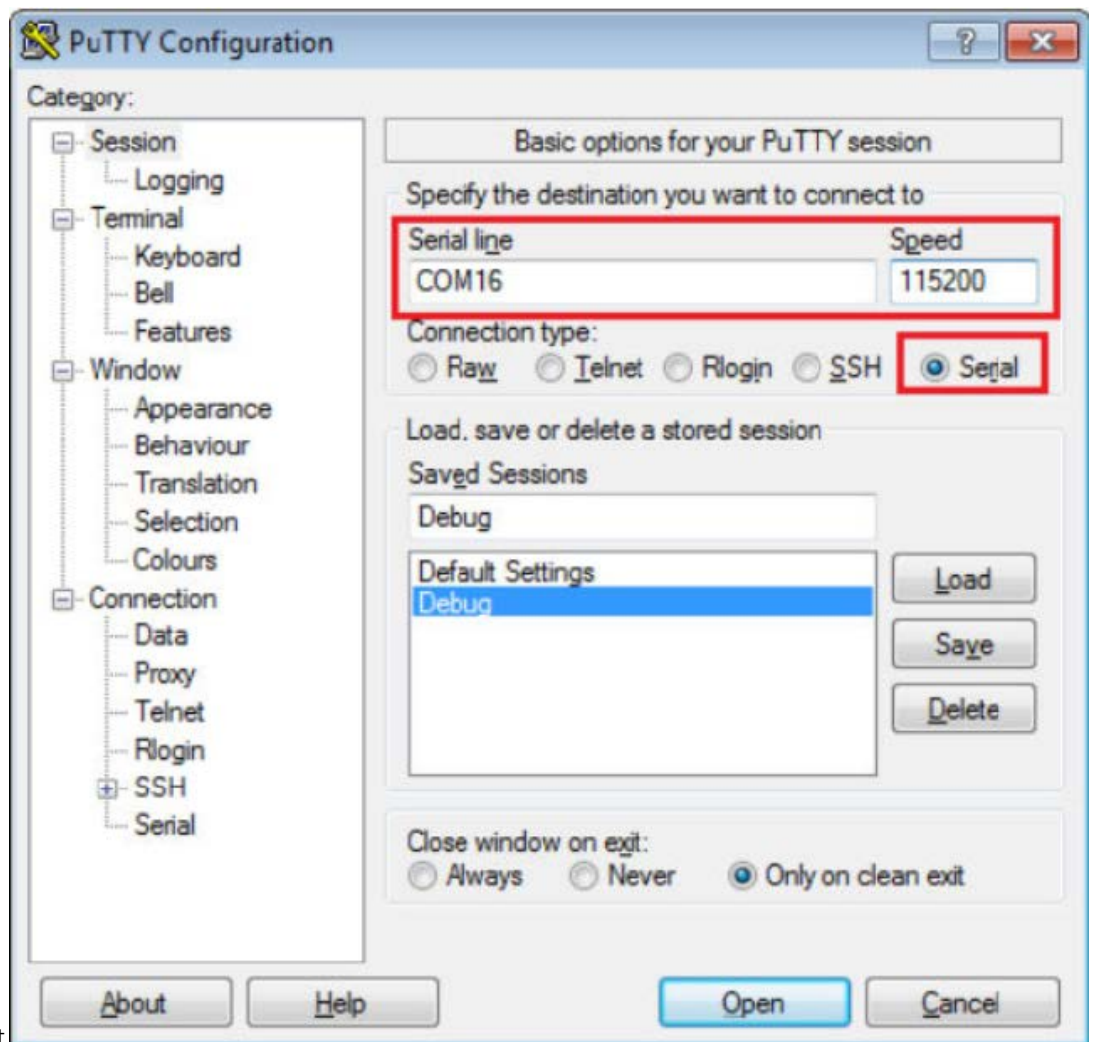
- Default debugger is multilink.
- Onboard debugger USB port is J12, which set the debugger and COM port.

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

- Connect USB cable between the host PC and the debugger USB port.
- Install the debugger driver and USB CDC driver as PC hint if it is the first time you run it on the PC. The debugger and USB CDC driver are provided by CodeWarrior by default.

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

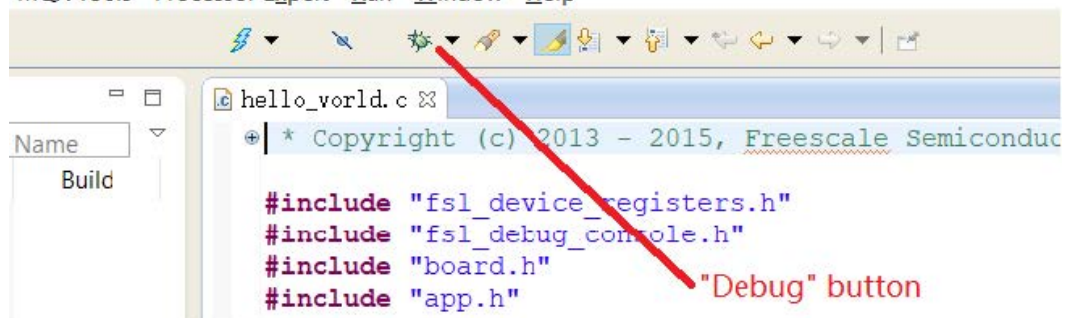
1. Open the terminal application on the PC, such as PuTTY or TeraTerm, and connect to the debug COM port (see [How to determine COM port](#)). Configure the terminal with these settings:
 - 115200, defined by BOARD_DEBUG_UART_BAUDRATE in the *board.h* file
 - No parity
 - 8 data bits



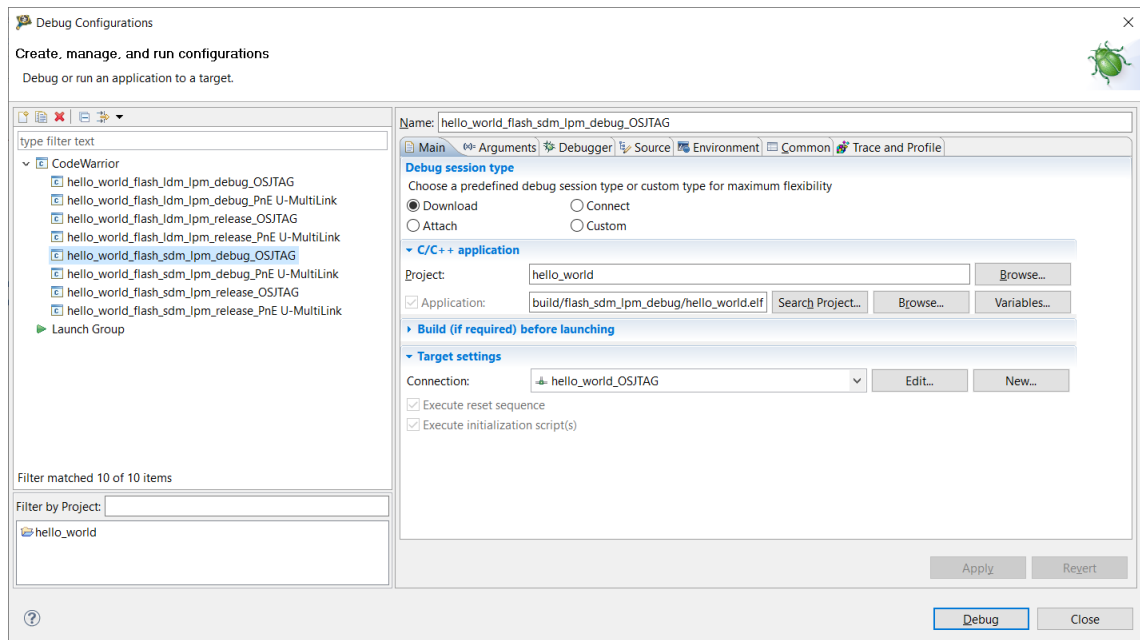
- 1 stop bit

- For this example (TWR-MC56F8400 hello_world), click **Debug** in the **Commander** pane, and select the hello_world_flash_sdm_lpm_debug_OSJTAG launch configuration. Then the application is downloaded onto target board and automatically runs to the main() function in the CodeWarrior Development Studio.

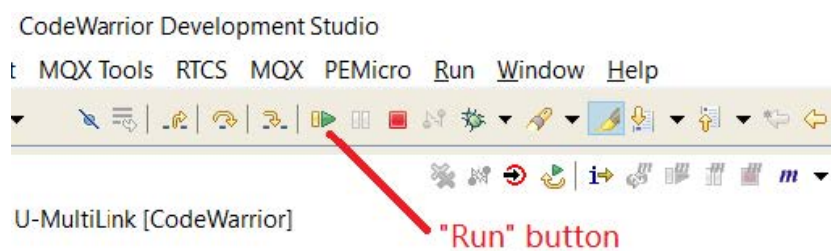
MQX Tools Processor Expert Run Window Help



tion.

**Note:**

- Generally there are four build configurations for DSC SDK examples: flash_sdm_lpm_debug, flash_sdm_lpm_release, flash_ldm_lpm_debug, and flash_ldm_lpm_release.
 - *_debug: uses optimization level 1
 - *_release: uses optimization level 4
 - sdm: small data memory model
 - ldm: large data memory model
 - lpm: large program memory model
- Select corresponding launch configuration based on build target and debugger type.
- Some examples may require specific hardware settings, check each demo readme document, which includes detail instructions for HW and SW settings.



3. To run the code, click **Run** on the toolbar.
4. The hello_world application is now running and a banner is displayed on the terminal.



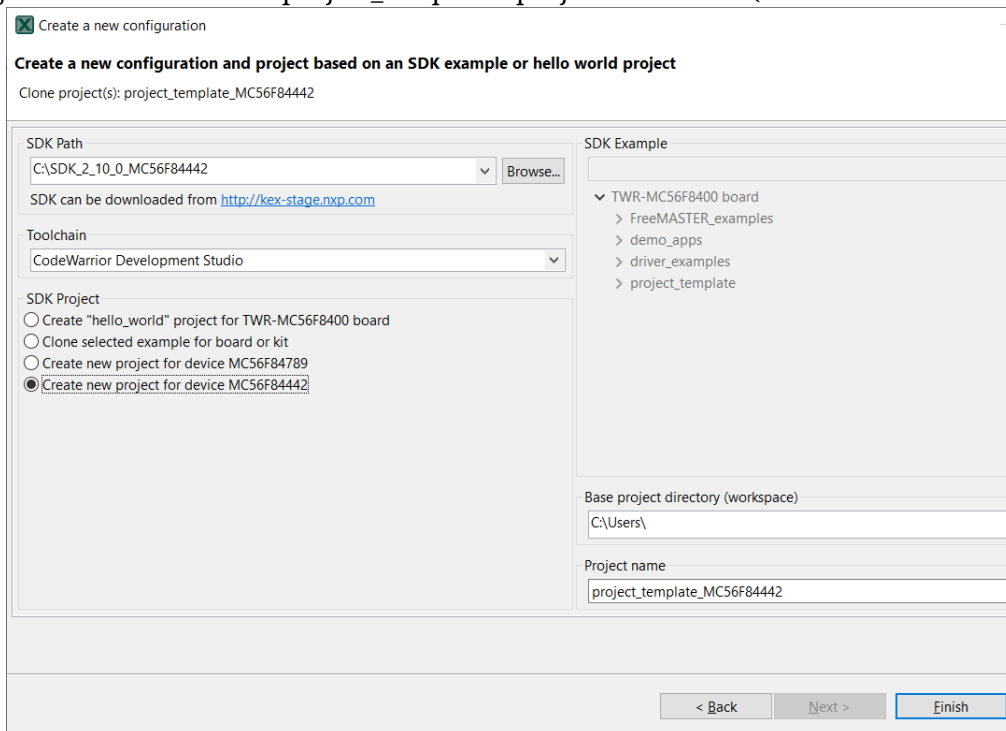
Project template for a specific DSC part

For device with specific part number, the easiest way to set up customer own project based on MCUXpresso DSC SDK peripheral driver, is the project_template. MCUXpresso Config Tool is used to generate the project_template.

The project_template provides basic MCUXpresso DSC SDK software framework, including startup, linker file, device header file, debug setting, peripheral driver, FreeMASTER, and so on.

Steps to generate the project_template for specific derivative part number by MCUXpresso Config Tool

1. Download the specific device SDK package and unzip it. note: The project template requires FreeMASTER, middleware FreeMASTER selection is a must when downloading DSC SDK from nxp website
2. Use MCUXpresso Config Tool to create a project_template project as below(take



MC56F84442 as example).

3. Import the generated template_project into CodeWarrior IDE and start the development.

NOTE

- The default created project template by Config Tool is `project_template_{part_number}`. User could modify the default name in **Project name** textbox.
- All peripheral drivers files are included in the generated `project_template` project. They are same as the peripheral drivers within SDK package. If some drivers are not used or required, users may delete them in CodeWarrior, or delete them directly under folder `${project_path}/drivers`.

How to determine COM port

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

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

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

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

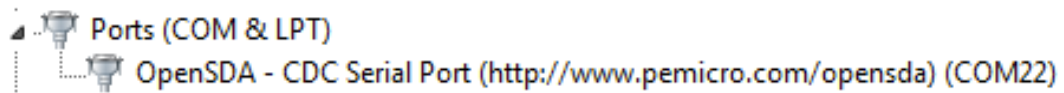
2. **Windows:** To determine the COM port open Device Manager in the Windows operating system. Click the **Start** menu and type **Device Manager** in the search bar.

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

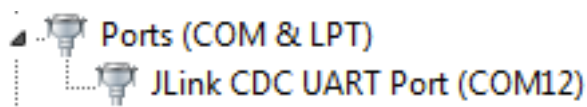
1. **CMSIS-DAP/mbed/DAPLink** interface:



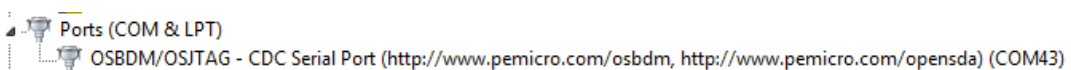
2. **P&E Micro:**



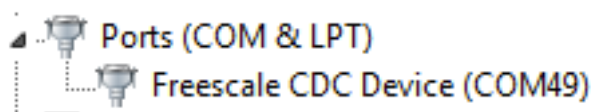
3. **J-Link:**



4. **P&E Micro OSJTAG:**



5. **MRB-KW01:**



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
- 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
- **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
- **Linux:** Use package manager or download from cmake.org
- **macOS:** Use Homebrew (brew install cmake) or download from 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
- **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
ARM GCC (Recommended)	Most users, free	ARM GCC Toolchain	ARMGCC_DIR
IAR EWARM	Professional development	IAR Systems	IAR_DIR
Keil MDK ARM Compiler	ARM ecosystem Advanced optimization	ARM Developer ARM Developer	MDK_DIR 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
arch/	Architecture-specific files	ARM CMSIS, build configurations
cmake/	Build system modules	CMake configuration and build rules
compo	Software components	Reusable software libraries and utilities
devices	Device support packages	MCU-specific headers, startup code, linker scripts
drivers	Peripheral drivers	Hardware abstraction layer for MCU peripherals
examp	Sample applications	Demonstration code and reference implementations
middle	Optional software stacks	Networking, graphics, security, and other libraries
rtos/	Operating system support	FreeRTOS integration
scripts	Build and utility scripts	West extensions and development tools
svd	Svd files for devices, this is optional because of large size. Customers run <code>west manifest config group.filter +optional</code> and <code>west update mcux-soc-svd</code> to get this folder.	

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

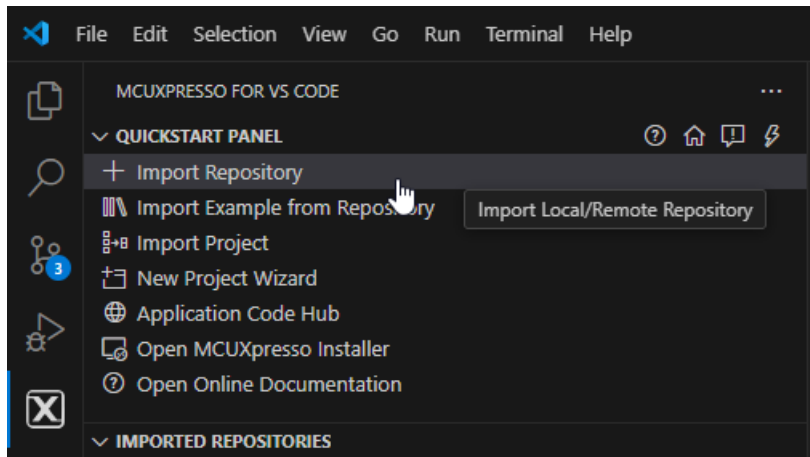
- SDK workspace initialized (GitHub Repository SDK or Repository-Layout SDK Package)
- Development tools installed per [Installation Guide](#)
- Visual Studio Code installed
- MCUXpresso for VS Code extension installed

Extension Installation

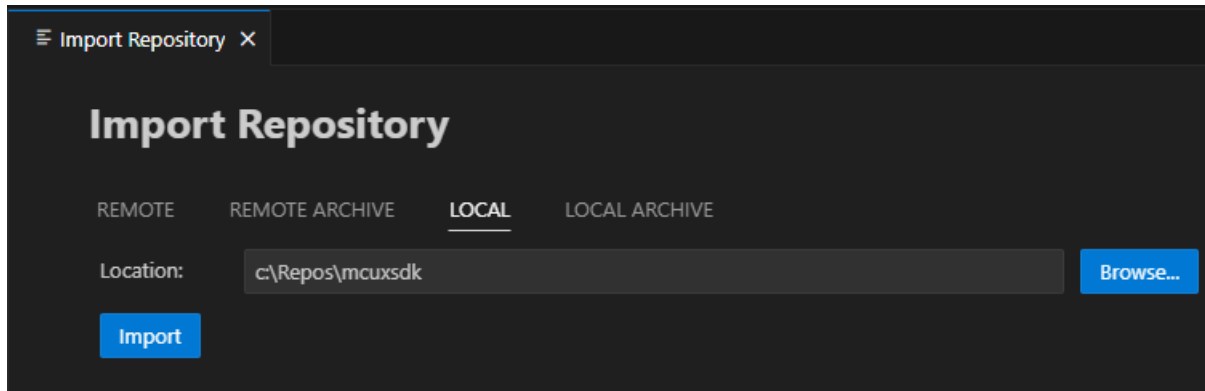
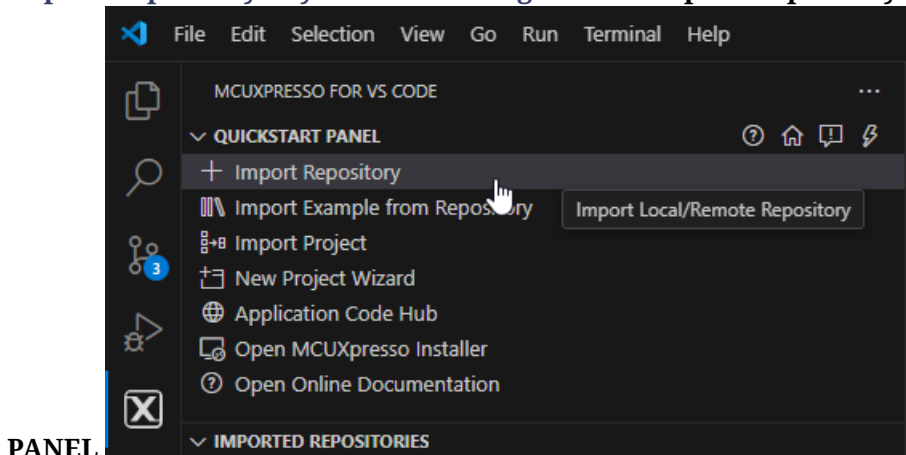
Install MCUXpresso for VS Code The MCUXpresso for VS Code extension provides integrated development capabilities for MCUXpresso SDK projects. Refer to the [MCUXpresso for VS Code Wiki](#) for detailed installation and setup instructions.

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.

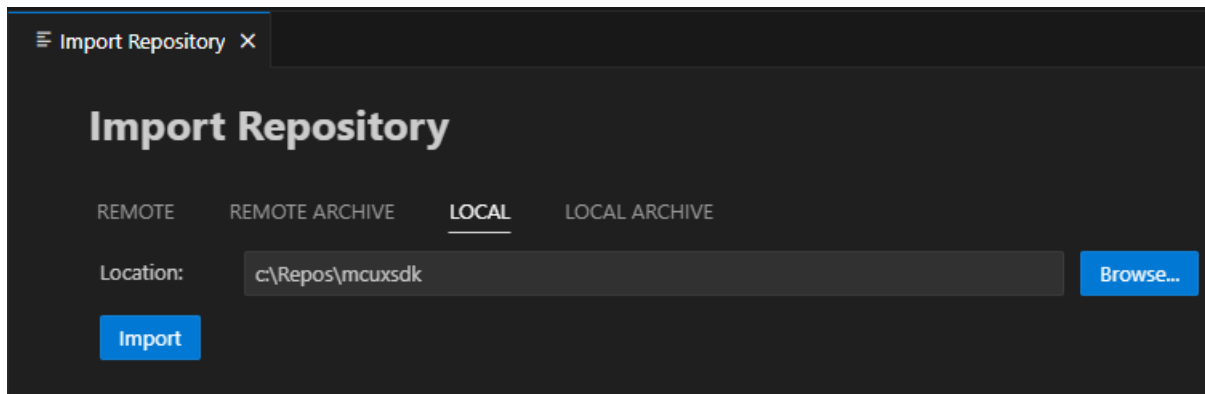
Import GitHub Repository SDK Click **Import Repository** from the **QUICKSTART PANEL**

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**.

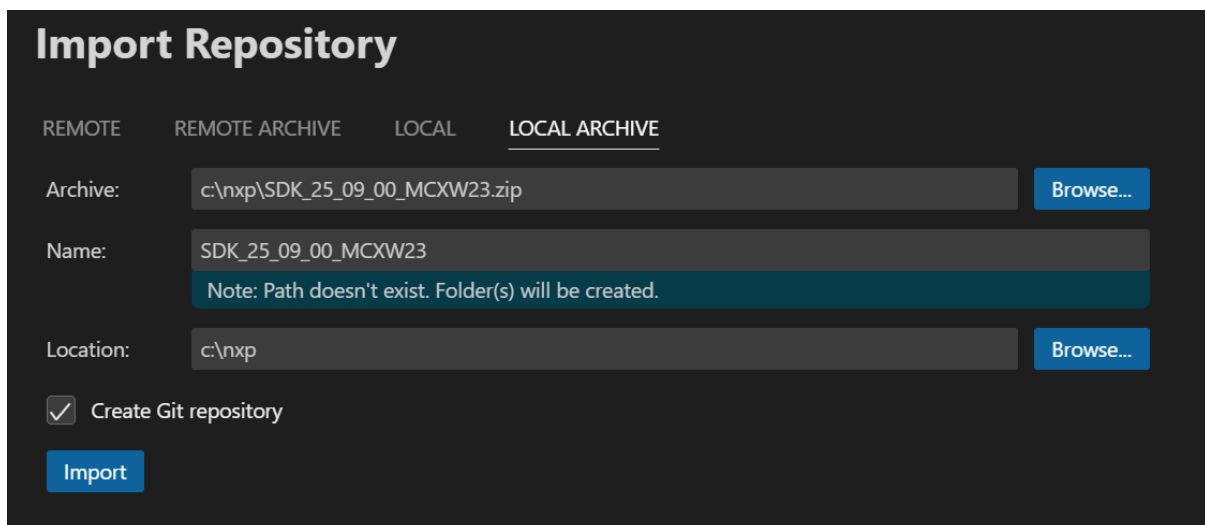
**Import Repository-Layout SDK Package** Click **Import Repository** from the **QUICKSTART**

PANEL

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



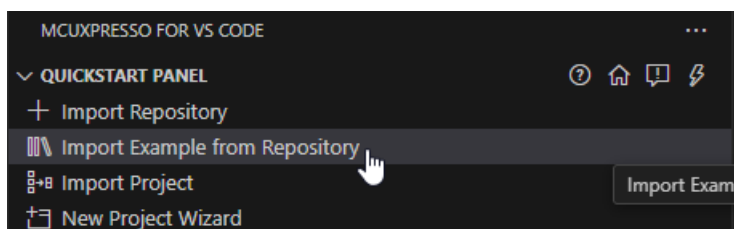
Else if the SDK is ZIP archive, select **Local Archive**, browse to the downloaded SDK ZIP file, fill the link of expect location, then click **Import**.



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

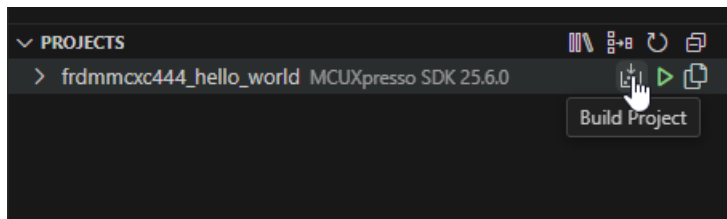
Trust Confirmation VS Code will prompt you to confirm if the imported files are trusted. Click **Yes** to proceed.

Building Projects

Build Process

1. Navigate to **PROJECTS** view

2. Find your project
3. Click the **Build Project** icon

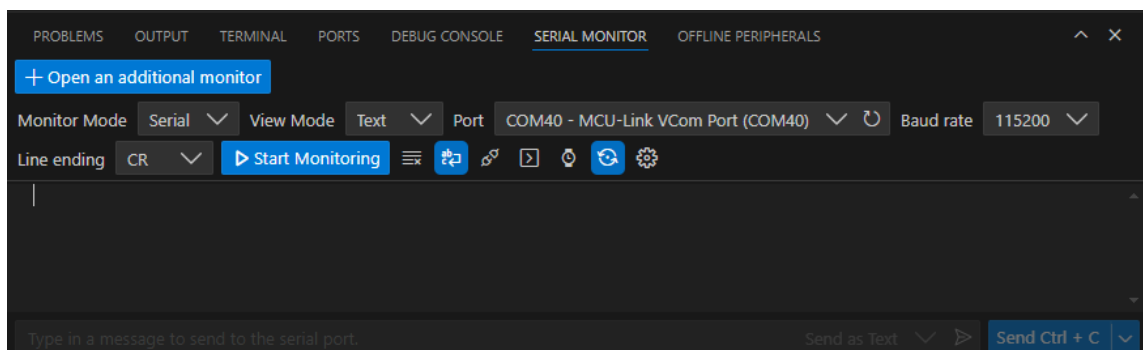


The integrated terminal will display build output at the bottom of the VS Code window.

Running and Debugging

Serial Monitor Setup

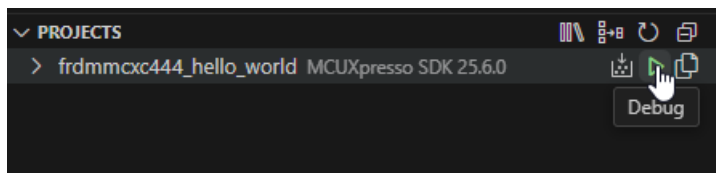
1. Open **Serial Monitor** from VS Code's integrated terminal



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

Debug Session

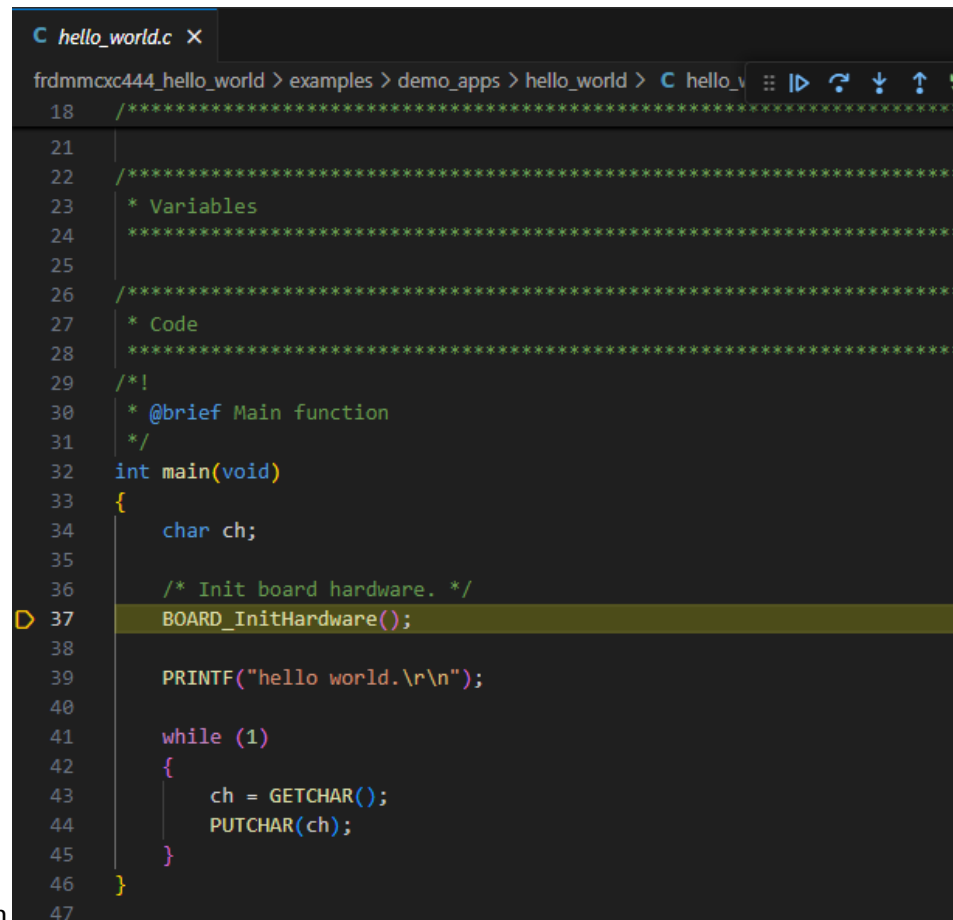
1. Navigate to **PROJECTS** view
2. Click the play button to initiate a debug session



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



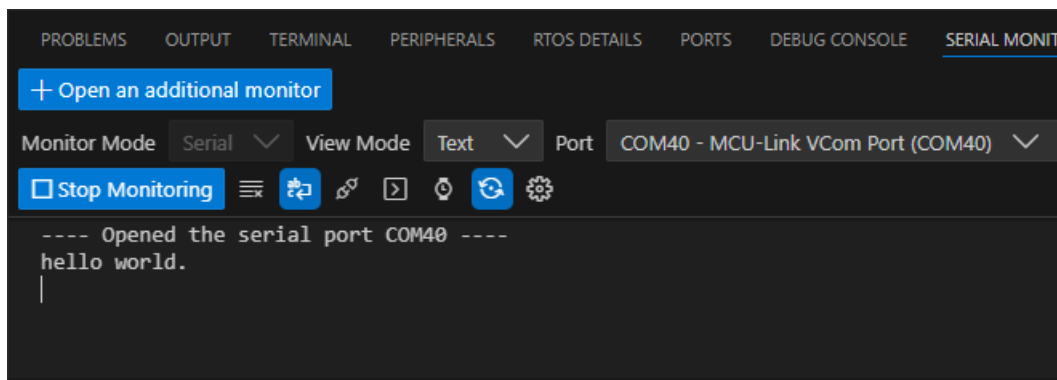
```

C hello_world.c X
frdm-mxc444_hello_world > examples > demo_apps > hello_world > C hello_w
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.

- CodeWarrior Development Studio v11.2 with CodeWarrior for DSC v11.2 SP1 (Service Pack 1)

Supported development systems

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

De- velop- ment boards	MCU devices			
MC56F8000-EVK	MC56F80623VLC, MC56F80648VLH, MC56F80736VLF, MC56F80746MLF,	MC56F80626VLF, MC56F80723VLC, MC56F80738VLH, MC56F80746VLF,	MC56F80643VLC, MC56F80726VLF, MC56F80743VFM, MC56F80748MLH,	MC56F80646VLF, MC56F80733VFM, MC56F80743VLC, MC56F80748VLH

Release contents

Table 1 provides an overview of the MCUXpresso DSC 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
Documentation	<install_dir>/docs
Driver, SoC header files, extension header files and feature header files	<install_dir>/devices/<device_name>
Peripheral Drivers	<install_dir>/devices/<device_name>/drivers
Utilities such as debug console	<install_dir>/devices/<device_name>/utilities
Middleware	<install_dir>/middleware

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.

Middleware

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

FreeMASTER FreeMASTER communication driver for 32-bit platforms.

Known Issues

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

PRINTF issue for program address space When project is compiled with SDM, print the address in program address space malfunction.

- Failed example when SDM
 - `PRINTF("%p", main);` Root cause: in SDM, `%p` is treated as 16-bit value, however `main` in program address space is still considered as 32-bit.
- Workaround(compliant with SDM and LDM)
 - `PRINTF("0x%lx", (uint32_t)main);`

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
-

CADC

[2.2.0]

- New Features
- Supported platforms which don't have ANA4 expansion MUX.

[2.1.0]

- Improvements
- Added some APIs to support some devices that equipped expansion mux.

[2.0.1]

- Bug Fixes
- Fixed the bug that channel mode set to wrong value.
- Fixed the bug that independent parallel mode set to wrong value.
- Fixed violations of the MISRA C-2012 rules.

[2.0.0]

- Initial version.
-

CLOCK

[2.0.0]

- Initial version.
-

CMP

[2.0.1]

- Improvements
- Supported MC56F82xxxx and MC56F84xxxx.
 - Bug Fixes
- Fixed violations of the MISRA C-2012 rules.

[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 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.
-

COP

[2.2.3]

- Bug Fixes
 - Fixed violations of MISRA C-2012 rule 10.3.

[2.2.2]

- Bug Fixes
- Added configuration of CWP bits in COP_Init, fixed write protection bEnableWriteProtect cannot be configured as part of cop_config_t.

[2.2.1]

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

[2.2.0]

- Improvements
- Updated cop_config_t member naming.
- Deleted COP_Disable API, added COP_Enable to enable/disable COP.

[2.1.0]

- Improvements
- API interface changes:
 - Renamed “COP_EnableInterrupts/COP_DisableInterrupts” to “COP_EnableInterrupt/COP_DisableInterrupt” and remove unnecessary parameter.
 - New Features
- Added APIs to enable/disable the COP COP Loss of Reference counter.

[2.0.0]

- Initial version.
-

CRC

[2.0.1]

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

[2.0.0]

- Initial version.
-

DMAMUX

[2.0.0]

- Initial version.
-

EDMA

[2.0.3]

- Fixed the MISRA-2012 violations.
- Fixed rule 10.3.

[2.0.2]

- Fixed the MISRA-2012 violations.
- Fixed rule 5.8, 9.2, 10.3, 10.4, 11.6.

[2.0.1]

- Code modification for SDM compliance

[2.0.0]

- Initial version.
-

EQDC

[2.0.0]

- Initial version.
 - Supported MC56F80xxx.
-

EVTG

[2.0.0]

- Initial version.
-

EWM

[2.0.2]

- Bug Fixes
- Fixed violations of MISRA C-2012 rule 10.3.

[2.0.1]

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

[2.0.0]

- Initial version.
-

FLASH

[3.0.0]

- Initial version — Basic FTFx IP command support
-

GPIO

[2.0.1]

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

[2.0.0]

- Initial version.
-

INTC

[2.0.1]

- Improvements
- Added doxygen comments.

[2.0.0]

- Initial version.
-

LPI2C

[2.0.2]

- Bug Fixes
- Fixed bug in eDMA transfer for SoCs whose rx and tx have different eDMA requests.

[2.0.1]

- Bug Fixes
- Fixed the MISRA-2012 violations.

[2.0.0]

- Initial version.
-

MCM

[2.0.1]

- Improvements
- Supported MC56F82xxx and MC56F84xxx.

[2.0.0]

- Initial version.
-

OPAMP

[2.0.0]

- Initial version.
-

PIT

[2.3.1]

- Bug Fixes
- Fixed violations of MISRA C-2012 rule 10.3.

[2.3.0]

- Improvements
- Filtered Preset input to reset PIT counter.
- Support SYNC_OUT output stretch and toggle mode.
- Added PIT_SetPresetFiltConfig() to set FILT register configurations.
- Added PIT_SetSyncOutConfig() to set SYNC register configurations.

[2.2.1]

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

[2.2.0]

- Improvements
- Updated pit_config_t member naming.
- Removed some APIs for prescaler and clock source selection.

[2.1.0]

- Improvements
- Updated PIT clock source and PIT prescaler with more meaningful comments.
- Updated PIT_SetTimerPeriod() and PIT_GetCurrentTimerCount() with 16-bit parameter.
- Deleted mask parameter for PIT_ClearStatusFlags/PIT_EnableInterrupts/PIT_DisableInterrupts.
- Added PIT_SetTimerClockSource() API to configure clock source.
- Added PIT_EnableSlaveMode() API to configure slave mode.

[2.0.1]

- New Features
- Added PIT_SetTimerPrescaler() API to configure clock prescaler value.

[2.0.0]

- Initial version.
-

PMC

[2.1.0]

- Improvements
- Added PMC_SetVrefTrim() and PMC_SetVcapTrim() APIs to support MC56F80xxx.

[2.0.0]

- Initial version.
-

eFlexPWM

[2.2.0]

- New Features
- Supported capture PWM input filter.
- Supported different PWM deadtime count register width.
 - Bug Fixes
- Fixed wrong pwm_sm_pwm_out_t enum order issue.

[2.1.1]

- Bug Fixes
- Fixed build error when soc not support Capture A/B features.

[2.1.0]

- Improvements
- Supported MC56F80xxx.

[2.0.2]

- Bug Fixes
- Fixed clear status flags API doesn't work issue.

[2.0.1]

- Improvements
- Supported MC56F82xxx and MC56F84xxx .
 - Bug Fixes
- Fixed violations of the MISRA C-2012 rules.

[2.0.0]

- Initial version.
-

QSCI

[2.0.4]

- Bug Fixes
- Fixed DMA transfer blocking issue by enabling tx idle interrupt after DMA transmission finishes, and invoke completion callback after tx idle interrupt occurs.

[2.0.3]

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

[2.0.2]

- Improvements
- Supported QSCI which has 13-bit integer and 3-bit fractional baud rate selection.

[2.0.1]

- Bug Fixes
- Fixed bug that when starting the non-blocking receive, the rx idle interrupt is not enabled, and when receiving is done the rx idle interrupt is not disabled.

[2.0.0]

- Initial version.
-

QTMR

[2.0.1]

- Improvements
- Supported to get TMR capture register address.
 - Bug Fixes
- Fixed violations of the MISRA C-2012 rules.

[2.0.0]

- Initial version.
-

Queued SPI

[2.1.1]

- Bug Fixes
- Fixed wrong baudrate calculation method.

[2.1.0]

- Bug Fixes
- Fixed wrong definitions of interrupt enable/disable masks.
- Fixed wrong usage of QSPI_DisableInterrupts.
- Fixed wrong type casts.
- Fixed bug for master blocking transfer of rx FIFO overflow.

[2.0.0]

- Initial version.
-

SIM

[2.0.0]

- Initial version.
-

DSC_XBARA

[2.0.1]

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

[2.0.0]

- Initial version.
-

Chapter 2

MC56F80748

2.1 CADC: 12-bit Cyclic Analog-to-Digital Converter Driver

`void CADC_Init(ADC_Type *base, const cadc_config_t *psConfig)`

Initializes the CADC module, such as scan mode, DMA trigger source, interrupt mask and so on.

This function is to make the initialization for using CADC module. The operations are:

- Enable the clock for CADC.
- Set power up delay and Idle work mode.
- Set DMA trigger source.
- Enable the interrupts(Including High/Low limit interrupt, zero crossing interrupt interrupt, end of scan interrupt and each sample slot's scan interrupt).
- Set scan mode.
- Set disabled sample slot for the scan.
- Set scan control options.
- Set selected channels' mode.
- Set gain for each channel.
- Config conteraA and converterB.

Note: The high limit value, low limit value, offset value and zerocrossing mode of each sample slot will not be configured in this function, to set those options, the APIs in “Sample Slot Control Interfaces” function group can be used.

Parameters

- `base` – CADC peripheral base address.
- `psConfig` – Pointer to configuration structure. See `cadc_config_t`.

`void CADC_GetDefaultConfig(cadc_config_t *psConfig)`

Gets an available pre-defined options(such as scan mode, DMA trigger source, interrupt mask and so on) for module's configuration.

This function initializes the module's configuration structure with an available settings. The default value are:

```
psConfig->eDMATriggerSource = kADC_DMATrigSrcEndofScan;
psConfig->eIdleWorkMode = kADC_IdleKeepNormal;
psConfig->u16PowerUpDelay = 26U;
psConfig->u32EnabledInterruptMask = 0U;
psConfig->eScanMode = kADC_ScanModeTriggeredParallelSimultaneous;
psConfig->uDisabledSampleSlot.u32SampleDisVal = 0xFF0F0UL;
psConfig->uScanControl.u32ScanCtrlVal = 0x0UL;
psConfig->eChannelGain[x] = kADC_SignalGainX1;
psConfig->sampleSlotScanInterruptEnableMask = kADC_NonSampleSlotMask;
For the default setting of converter, please see ADC_GetConverterDefaultConfig().
```

Parameters

- psConfig – Pointer to configuration structure. See `adc_config_t`.

`void ADC_Deinit(ADC_Type *base)`

De-initializes the ADC module, including power down both converter and disable the clock(Optional).

This function is to make the de-initialization for using ADC module. The operations are:

- Power down both converter.
- Disable the clock for ADC.

Parameters

- base – ADC peripheral base address.

`static inline void ADC_SetScanMode(ADC_Type *base, adc_scan_mode_t eScanMode)`

Sets the scan mode(such as Sequential scan mode, Simultaneous parallel scan mode, Independent parallel scan mode) of dual converters.

Parameters

- base – ADC peripheral base address.
- eScanMode – Dual converters' scan mode, please see `adc_scan_mode_t` for details.

`static inline void ADC_SetScanControl(ADC_Type *base, adc_scan_control_t uScanControl)`

The function provides the ability to pause and await new sync in the conversion sequence.

Parameters

- base – ADC peripheral base address.
- uScanControl – The scan control value, please refer to `adc_scan_control_t` for details.

`void ADC_SetChannelMode(ADC_Type *base, adc_channel_mode_t eChannelMode)`

Sets mode for the specific channel(Each channel can be set as single-end, fully differential and unipolar differential(Optional) mode).

Parameters

- base – ADC peripheral base address.
- eChannelMode – The channel mode to be set, please refer to `adc_channel_mode_t` for details.

```
void CADC_SetChannelGain(ADC_Type *base, cadc_channel_number_t eChannelNumber,
                        cadc_channel_gain_t eChannelGain)
```

Sets the gain(Supports X1, X2, X4) of selected channel.

Parameters

- base – CADC peripheral base address.
- eChannelNumber – The number of channel, please refer to *cadc_channel_number_t*.
- eChannelGain – The gain amplification, please refer to *cadc_channel_gain_t* for details.

```
void CADC_GetSampleSlotDefaultConfig(cadc_sample_slot_config_t *psConfig)
```

Gets sample slot default configuration including zero crossing mode, high limit value, low limit value and offset value.

```
psConfig->eZeroCrossingMode = kCADC_ZeroCrossingDisabled;
psConfig->u16HighLimitValue = 0x7FF8U;
psConfig->u16LowLimitValue  = 0x0U;
psConfig->u16OffsetValue    = 0x0U;
```

Parameters

- psConfig – Pointer to configuration structure. See *cadc_sample_slot_config_t*.

```
void CADC_SetSampleSlotConfig(ADC_Type *base, cadc_sample_slot_index_t eSampleIndex,
                             const cadc_sample_slot_config_t *psConfig)
```

Configures the options(including zero crossing mode, high limit value, low limit value and offset value) for sample slot.

Note: This function can be used to set high limit value, low limit value, offset value and zerocrossing mode of the sample slot.

Parameters

- base – CADC peripheral base address.
- eSampleIndex – Index of sample slot in conversion sequence. Please refer to *cadc_sample_slot_index_t*.
- psConfig – Pointer to configuration structure. See *cadc_sample_slot_config_t*.

```
void CADC_SetSampleSlotZeroCrossingMode(ADC_Type *base, cadc_sample_slot_index_t
                                         eSampleIndex,
                                         cadc_sample_slot_zero_crossing_mode_t
                                         eZeroCrossingMode)
```

Sets zero-crossing mode for the selected sample slot.

Parameters

- base – CADC peripheral base address.
- eSampleIndex – The index of sample slot. Please refer to *cadc_sample_slot_index_t* for details.
- eZeroCrossingMode – Zero crossing mode, please refer to *cadc_sample_slot_zero_crossing_mode_t* for details.

```
void CADC_RouteChannelToSampleSlot(ADC_Type *base, cadc_sample_slot_index_t
                                   eSampleIndex, cadc_channel_number_t
                                   eChannelNumber)
```

Routes the channel to the sample slot.

Parameters

- base – CADC peripheral base address.
- eSampleIndex – The index of sample slot, please refer to *cadc_sample_slot_index_t* for details.
- eChannelNumber – Sample channel number, please refer to *cadc_channel_number_t* for details.

```
static inline void CADC_SetSampleSlotLowLimitValue(ADC_Type *base,
                                                    cadc_sample_slot_index_t eSampleIndex,
                                                    uint16_t u16LowLimitValue)
```

Sets the low limit value(-32768 ~ 32767 with lower three bits of fixed value 0) for the specific sample slot.

Parameters

- base – CADC peripheral base address.
- eSampleIndex – The index of sample slot. Please refer to *cadc_sample_slot_index_t* for details.
- u16LowLimitValue – Low limit value(-32768 ~ 32767 with lower three bits of fixed value 0). Original value formation as hardware register, with 3-bits left shifted.

```
static inline void CADC_SetSampleSlotHighLimitValue(ADC_Type *base,
                                                     cadc_sample_slot_index_t eSampleIndex,
                                                     uint16_t u16HighLimitValue)
```

Sets the high limit value(-32768 ~ 32767 with lower three bits of fixed value 0) for the specific sample slot.

Parameters

- base – CADC peripheral base address.
- eSampleIndex – The index of sample slot. Please refer to *cadc_sample_slot_index_t* for details.
- u16HighLimitValue – High limit value(-32768 ~ 32767 with lower three bits of fixed value 0). Original value formation as hardware register, with 3-bits left shifted.

```
static inline void CADC_SetSampleSlotOffsetValue(ADC_Type *base, cadc_sample_slot_index_t
                                                  eSampleIndex, uint16_t u16OffsetValue)
```

Sets the offset value(-32768 ~ 32767 with lower three bits of fixed value 0) for the specific sample slot.

Parameters

- base – CADC peripheral base address.
- eSampleIndex – The index of sample slot. Please refer to *cadc_sample_slot_index_t* for details.
- u16OffsetValue – Offset value(-32768 ~ 32767 with lower three bits of fixed value 0). Original value formation as hardware register, with 3-bits left shifted.

```
static inline uint16_t ADC_GetSampleSlotResultValue(ADC_Type *base,
                                                    cadc_sample_slot_index_t eSampleIndex)
```

Gets the sample result value.

This function is to get the sample result value. The returned value keeps its original formation just like in hardware result register. It includes the sign bit as the MSB and 3-bit left shifted value.

Parameters

- `base` – ADC peripheral base address.
- `eSampleIndex` – Index of sample slot. For the counts of sample slots, please refer to `cadc_sample_slot_index_t` for details.

Returns

Sample's conversion value.

```
void ADC_GetConverterDefaultConfig(cadc_converter_config_t *psConfig)
```

Gets available pre-defined settings (such as clock divisor, reference voltage source, and so on) for each converter's configuration.

This function initializes each converter's configuration structure with an available settings. The default value are:

```
psConfig->u16ClockDivisor = 4U; (ADC clock = Peripheral clock / 5)
psConfig->eSpeedMode = kADC_SpeedMode0; (Chip specific)
psConfig->eHighReferenceVoltageSource = kADC_ReferenceVoltageVrefPad;
psConfig->eLowReferenceVoltageSource = kADC_ReferenceVoltageVrefPad;
psConfig->u16SampleWindowCount = 0U; (Chip specific)
psConfig->bEnableDMA = false;
psConfig->bPowerUp = false;
psConfig->bScanInitBySync = true;
```

Parameters

- `psConfig` – Pointer to configuration structure. See `cadc_converter_config_t`.

```
void ADC_SetConverterConfig(ADC_Type *base, cadc_converter_id_t eConverterId, const
                           cadc_converter_config_t *psConfig)
```

Configures the options (such as clock divisor, reference voltage source, and so on) for the converter.

This function can be used to configure the converter. The operations are:

- Set clock divisor;
- Set reference voltage source
- Enable/Disable DMA
- Power-up/power-down converter

Parameters

- `base` – ADC peripheral base address.
- `eConverterId` – The converter Id. See `cadc_converter_id_t`.
- `psConfig` – Pointer to configuration structure. See `cadc_converter_config_t`.

```
static inline void ADC_EnableConverter(ADC_Type *base, cadc_converter_id_t eConverterId,
                                       bool bEnable)
```

Changes the converter to stop mode or normal mode.

The conversion should only be launched after the converter is in normal mode. When in stop mode, the current scan is stopped and no further scans can start. All the software trigger and hardware trigger are ignored.

Parameters

- `base` – CADC peripheral base address.
- `eConverterId` – The converter Id. See `cadc_converter_id_t`.
- `bEnable` – Used to change the operation mode.
 - **true** Changed to normal mode.
 - **false** Changed to stop mode

```
static inline void CADC__EnableConverterSyncInput(ADC_Type *base, cadc_converter_id_t
                                                  eConverterId, bool bEnable)
```

Enables/Disables the external sync input pulse to initiate a scan.

Note: When in “Once” scan mode, this gate would be off automatically after an available sync is received. User needs to enable the input again manually if another sync signal is wanted.

Parameters

- `base` – CADC peripheral base address.
- `eConverterId` – The converter Id. See `cadc_converter_id_t`.
- `bEnable` – Enable the feature or not.
 - **true** Used a SYNC input pulse or START command to initiate a scan.
 - **false** Only use the START command to initiate a scan.

```
static inline void CADC__DoSoftwareTriggerConverter(ADC_Type *base, cadc_converter_id_t
                                                  eConverterId)
```

Uses software trigger to start a conversion sequence.

This function is to do the software trigger to the converter. The software trigger can used to start a conversion sequence.

Parameters

- `base` – CADC peripheral base address.
- `eConverterId` – The ID of the converter to be started. See `cadc_converter_id_t`.

```
static inline void CADC__SetConverterClockDivisor(ADC_Type *base, cadc_converter_id_t
                                                  eConverterId, uint16_t u16ClockDivisor)
```

Sets clock divisor(Range from 0 to 63) for converterA and conveter B.

Parameters

- `base` – CADC peripheral base address.
- `eConverterId` – The converter Id. See `cadc_converter_id_t`.
- `u16ClockDivisor` – Converter’s clock divisor for the clock source. Available setting range is 0-63.
 - When the clockDivisor is 0, the divisor is 2.
 - For all other clockDivisor values, the divisor is 1 more than the decimal value of clockDivisor: `clockDivisor + 1`

```
void CADC_SetConverterReferenceVoltageSource(ADC_Type *base, cadc_converter_id_t
                                             eConverterId, cadc_reference_voltage_source_t
                                             eHighReferenceVoltage,
                                             cadc_reference_voltage_source_t
                                             eLowReferenceVoltage)
```

Sets converter's reference voltage source(Including high reference voltage source and low reference voltage source).

Parameters

- base – CADC peripheral base address.
- eConverterId – The converter Id. See *cadc_converter_id_t*.
- eHighReferenceVoltage – High voltage reference source, please refer to *cadc_reference_voltage_source_t*.
- eLowReferenceVoltage – Low voltage reference source, please refer to *cadc_reference_voltage_source_t*.

```
void CADC_EnableConverterPower(ADC_Type *base, cadc_converter_id_t eConverterId, bool
                               bEnable)
```

Powers up/down the specific converter.

This function is to enable the power for the converter. The converter should be powered up before the conversion. Once this API is called to power up the converter, the converter would be powered on after a few moment (so-called power up delay, the function CADC_SetPowerUpDelay() can be used to set the power up delay), so that the power would be stable.

Parameters

- base – CADC peripheral base address.
- eConverterId – The converter to be powered. See *cadc_converter_id_t*.
- bEnable – Powers up/down the converter.
 - **true** Power up the specific converter.
 - **false** Power down the specific converter.

```
static inline void CADC_EnableConverterDMA(ADC_Type *base, cadc_converter_id_t
                                           eConverterId, bool bEnable)
```

Enables/Disables the converter's DMA feature.

Parameters

- base – CADC peripheral base address.
- eConverterId – The converter id. See *cadc_converter_id_t*.
- bEnable – Enables/Disables the DMA.
 - **true** Enable the converter's DMA.
 - **false** Disable the converter's DMA.

```
void CADC_SetConverterMuxAuxConfig(ADC_Type *base, cadc_converter_id_t eConverterId,
                                   const cadc_exp_mux_aux_config_t *psMuxAuxConfig)
```

Configures selected converter's expansion mux and aux settings.

Parameters

- base – ADC peripheral base address.

- `eConverterId` – The converter id, see `cadc_converter_id_t`.
- `psMuxAuxConfig` – Pointer to `cadc_exp_mux_aux_config_t` structure.

```
static inline void CADC__ResetConverterExpMuxScan(ADC_Type *base, cadc_converter_id_t
                                                    eConverterId)
```

Resets selected converter's expansion mux scan.

Parameters

- `base` – ADC peripheral base address.
- `eConverterId` – The converter id, see `cadc_converter_id_t`.

```
static inline void CADC__SetConverterExpansionMuxOperateMode(ADC_Type *base,
                                                             cadc_converter_id_t
                                                             eConverterId,
                                                             cadc_expansion_mux_operate_mode_t
                                                             eOperateMode)
```

Sets selected converter's expansion mux operate mode.

Parameters

- `base` – ADC peripheral base address.
- `eConverterId` – The converter id, see `cadc_converter_id_t`.
- `eOperateMode` – Used to set expansion mux operate mode.

```
static inline void CADC__SetConverterAuxiliaryControl(ADC_Type *base, cadc_converter_id_t
                                                         eConverterId, uint16_t u16AuxControl)
```

Sets selected converter's auxiliary control set.

Parameters

- `base` – ADC peripheral base address.
- `eConverterId` – The converter id, see `cadc_converter_id_t`.
- `u16AuxControl` – The mask of auxiliary control, should be the OR'ed value of `cadc_auxiliary_control_t`.

```
static inline void CADC__SetConverterMuxChannels(ADC_Type *base, cadc_converter_id_t
                                                         eConverterId, uint32_t
                                                         u32MuxChannelMask)
```

Sets selected converter's mux channels.

Parameters

- `base` – ADC peripheral base address.
- `eConverterId` – The converter id, see `cadc_converter_id_t`.
- `u32MuxChannelMask` – The mask of mux selection of all mux slots, should be the OR'ed value of `cadc_expansion_mux_selection_t`.

```
static inline void CADC__SetExpansionMuxAuxDisabledSlot(ADC_Type *base, cadc_converter_id_t
                                                         eConverterId,
                                                         cadc_expansion_disabled_mux_slot_t
                                                         eDisabledMuxSlot)
```

Set selected converter's mux and aux disabled slot.

Parameters

- `base` – ADC peripheral base address.
- `eConverterId` – The converter id, see `cadc_converter_id_t`.

- `eDisabledMuxSlot` – The mux slot to disabled, please refer to `cadc_expansion_disabled_mux_slot_t`.

static inline void `CADC_SetPowerUpDelay(ADC_Type *base, uint16_t u16PowerUpDelay)`

Sets power up delay(The number of ADC clocks to power up the converters before allowing a scan to start).

Parameters

- `base` – ADC peripheral base address.
- `u16PowerUpDelay` – The number of ADC clocks to power up an ADC converter. Ranges from 0 to 63.

static inline void `CADC_EnableAutoPowerDownMode(ADC_Type *base, bool bEnable)`

Enables/Disables auto-powerdown converters when the module is not in use for a scan.

Parameters

- `base` – ADC peripheral base address.
- `bEnable` – Enable/Disable auto-powerdown mode.
 - **true** Enable auto-powerdown mode, so when the module is not in use, it will auto-powerdown.
 - **false** Disable auto-powerdown mode, so when the module is not in use, the power will still on.

static inline void `CADC_SetDMATriggerSource(ADC_Type *base, cadc_dma_trigger_source_t eDMATriggerSource)`

Sets DMA trigger source(available selections are “End of scan” and “Sample Ready”).

Parameters

- `base` – ADC peripheral base address.
- `eDMATriggerSource` – DMA trigger source. Please refer to `cadc_dma_trigger_source_t` for details.

static inline void `CADC_EnableInterrupts(ADC_Type *base, uint32_t u32Mask)`

Enables the interrupts(such as high/low limit interrupts, end of scan interrupts, and so on).

Parameters

- `base` – ADC peripheral base address.
- `u32Mask` – Mask value for converters interrupt events. Should be the OR'ed value of `_cadc_interrupt_enable`.

static inline void `CADC_DisableInterrupts(ADC_Type *base, uint32_t u32Mask)`

Disables the interrupts(such as high/low limit interrupts, end of scan interrupts, and so on).

Parameters

- `base` – ADC peripheral base address.
- `u32Mask` – Mask value for converts interrupt events. Should be the OR'ed value of `_cadc_interrupt_enable`.

static inline uint16_t `CADC_GetMiscStatusFlags(ADC_Type *base)`

Gets Miscellaneous status flags, such as end of scan status flag, high/low limit interrupt flags and so on.

Note: This API will return the current status of the ADC module, including high limit interrupt status, low limit status flag, zero crossing interrupt status, End of scan interrupt status, conversion in progress status. But some status flags are not included in this function. To get sample slot ready status flag,

please invoking `CADC_GetSampleSlotReadyStatusFlags()`, to get sample slot limit violations status please invoking `CADC_ClearSampleSlotLowLimitStatusFlags()` and `CADC_GetSampleSlotHighLimitStatusFlags()`, to get zerocrossing status please invoking `CADC_GetSampleSlotZeroCrossingStatusFlags()`. To get converters' power status please invoke `CADC_GetPowerStatusFlag()`.

Parameters

- `base` – ADC peripheral base address.

Returns

Mask value for the event flags. See `_adc_misc_status_flags`.

```
static inline void CADC_ClearMiscStatusFlags(ADC_Type *base, uint16_t u16Flags)
```

Clears Miscellaneous status flags(Only for “end of scan” status flags).

Note: Only `kCADC_ConverterAEndOfScanFlag` and `kCADC_ConverterBEndOfScanFlag` can be cleared. And sample slot related status flags can not be cleared in this function. To clear the status flags of limit violations, please invoking `CADC_ClearSampleSlotLowLimitStatusFlags()` and `CADC_ClearSampleSlotHighLimitStatusFlags()`, to clear the status flags of zero crossing mode, please invoking `CADC_ClearSampleSlotZeroCrossingStatusFlags()`.

Parameters

- `base` – ADC peripheral base address.
- `u16Flags` – Mask value for the event flags to be cleared. See `_adc_misc_status_flags`. Only the enumeration `kCADC_ConverterAEndOfScanFlag` and `kCADC_ConverterBEndOfScanFlag` are useful.

```
static inline uint32_t CADC_GetSampleSlotReadyStatusFlags(ADC_Type *base)
```

Gets sample slots ready status flag, those status flags are cleared by reading the corresponding sample slots' result.

Parameters

- `base` – ADC peripheral base address.

```
static inline uint32_t CADC_GetSampleSlotLowLimitStatusFlags(ADC_Type *base)
```

Gets sample slot low limit status flags(Each bit represents one sample slot).

Parameters

- `base` – ADC peripheral base address.

Returns

The value of all sample slots' low limit status. Each bit represents one sample slot.

```
static inline void CADC_ClearSampleSlotLowLimitStatusFlags(ADC_Type *base, uint32_t u32SampleMask)
```

Clears sample slot's low limit status flags(Each bit represents one sample slot).

Parameters

- `base` – ADC peripheral base address.
- `u32SampleMask` – Mask value of sample slots. This parameter should be the OR'ed value of `adc_sample_slot_mask_t`.

static inline uint32_t ADC_GetSampleSlotHighLimitStatusFlags(ADC_Type *base)
Gets sample slot high limit status flags(Each bit represents one sample slot).

Parameters

- base – ADC peripheral base address.

Returns

The value of all sample slots' high limit status. Each bit represents each sample slot.

static inline void ADC_ClearSampleSlotHighLimitStatusFlags(ADC_Type *base, uint32_t
u32SampleMask)

Clears sample slot's high limit status flags(Each bit represents one sample slot).

Parameters

- base – ADC peripheral base address.
- u32SampleMask – Mask value of sample slots. This parameter should be the OR'ed value of `adc_sample_slot_mask_t`.

static inline uint32_t ADC_GetSampleSlotZeroCrossingStatusFlags(ADC_Type *base)
Gets sample slot zero crossing status flags(Each bit represents one sample slot).

Parameters

- base – ADC peripheral base address.

Returns

The value of all sample slots' zero crossing status. Each bit represents each sample slot.

static inline void ADC_ClearSampleSlotZeroCrossingStatusFlags(ADC_Type *base, uint32_t
u32SampleMask)

Clears sample slot's zero crossing status flags(Each bit represents one sample slot).

Parameters

- base – ADC peripheral base address.
- u32SampleMask – Mask value of sample slots. This parameter should be the OR'ed value of `adc_sample_slot_mask_t`.

static inline uint16_t ADC_GetPowerStatusFlags(ADC_Type *base)
Gets converters power status(Those power status can not be cleared).

Parameters

- base – ADC peripheral base address.

Returns

The mask value of the converters' power status flag, see `_adc_converter_power_status_flags`.

static inline uint16_t ADC_GetConverterExpMuxChannelScanCompStatusFlags(ADC_Type *base)
Gets converter's expansion mux channel scan complete status flags.

Parameters

- base – ADC peripheral base address.

Returns

uint16_t The mask value of converters' expansion mux channel scan status flags, see `_adc_expansion_mux_status_flags`.

```
static inline void CADC_ClearConverterExpMuxChannelScanCompStatusFlags(ADC_Type *base,
                                                                    uint16_t
                                                                    u16FlagMask)
```

Clears converter's expansion mux channel scan complete status flags.

Parameters

- base – CADC peripheral base address.
- u16FlagMask – The mask value of `_cadc_expansion_mux_status_flags`.

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enum `_cadc_misc_status_flags`

CADC miscellaneous status flags used to tell peripheral's miscellaneous status, such as zero-crossing, end of scan flags.

Values:

enumerator `kCADC_ZeroCrossingInterruptFlag`

Zero crossing encountered. IRQ pending if enabled Zero Crossing Interrupt.

enumerator `kCADC_HighLimitInterruptFlag`

High limit exceeded flag. IRQ pending if enabled high limit interrupt.

enumerator `kCADC_LowLimitInterruptFlag`

Low limit exceeded flag. IRQ pending if enabled low limit interrupt.

enumerator `kCADC_ConverterAInProgressFlag`

Conversion in progress, converter A.

enumerator `kCADC_ConverterBInProgressFlag`

Conversion in progress, converter B.

enumerator `kCADC_ConverterAEndOfScanFlag`

End of scan, converter A.

enumerator `kCADC_ConverterBEndOfScanFlag`

End of scan, converter B.

enumerator `kCADC_StatusAllFlags`

enum `_cadc_converter_power_status_flags`

The enumeration of converter power status.

Values:

enumerator `kCADC_ConverterAPowerDownFlag`

The converterA is powered down.

enumerator `kCADC_ConverterBPowerDownFlag`

The converterB is powered down.

enum `_cadc_expansion_mux_status_flags`

The enumeration of expansion mux channel scan complete interrupt request status flag.

Values:

enumerator `kCADC_ANA4ExpMuxAuxScanCompInterruptFlag`

ANA4 Expansion MUX Channel Scan Complete Interrupt flag.

enumerator `kCADC_ANB4ExpMuxAuxScanCompInterruptFlag`

ANB4 Expansion MUX Channel Scan Complete Interrupt flag.

enum _cadc_interrupt_enable

CADC Interrupts enumeration.

Values:

enumerator kCADC_Sample0ScanInterruptEnable

If sample0 is converted, generate the scan interrupt.

enumerator kCADC_Sample1ScanInterruptEnable

If sample1 is converted, generate the scan interrupt.

enumerator kCADC_Sample2ScanInterruptEnable

If sample2 is converted, generate the scan interrupt.

enumerator kCADC_Sample3ScanInterruptEnable

If sample3 is converted, generate the scan interrupt.

enumerator kCADC_Sample4ScanInterruptEnable

If sample4 is converted, generate the scan interrupt.

enumerator kCADC_Sample5ScanInterruptEnable

If sample5 is converted, generate the scan interrupt.

enumerator kCADC_Sample6ScanInterruptEnable

If sample6 is converted, generate the scan interrupt.

enumerator kCADC_Sample7ScanInterruptEnable

If sample7 is converted, generate the scan interrupt.

enumerator kCADC_Sample8ScanInterruptEnable

If sample8 is converted, generate the scan interrupt.

enumerator kCADC_Sample9ScanInterruptEnable

If sample9 is converted, generate the scan interrupt.

enumerator kCADC_Sample10ScanInterruptEnable

If sample10 is converted, generate the scan interrupt.

enumerator kCADC_Sample11ScanInterruptEnable

If sample11 is converted, generate the scan interrupt.

enumerator kCADC_Sample12ScanInterruptEnable

If sample12 is converted, generate the scan interrupt.

enumerator kCADC_Sample13ScanInterruptEnable

If sample13 is converted, generate the scan interrupt.

enumerator kCADC_Sample14ScanInterruptEnable

If sample14 is converted, generate the scan interrupt.

enumerator kCADC_Sample15ScanInterruptEnable

If sample15 is converted, generate the scan interrupt.

enumerator kCADC_ANA4ExpMuxScanCompleteInterruptEnable

If ANA4 expansion MUX channel scan complete, generate the interrupt.

enumerator kCADC_ANB4ExpMuxScanCompleteInterruptEnable

If ANB4 expansion MUX channel scan complete, generate the interrupt.

enumerator kCADC_HighLimitInterruptEnable

If the result value is greater than the high limit value, generate high limit interrupt.

enumerator kCADC_LowLimitInterruptEnable

If the result value is less than the low limit value, generate low limit interrupt.

enumerator kCADC_ZeroCrossingInterruptEnable

If the current value has a sign change from the previous result in the selected zero crossing mode, generate the zero crossing mode

enumerator kCADC_ConversionCompleteInterrupt0Enable

Upon the completion of the scan, generate the end of scan interrupt, when the scan mode is selected as sequential mode or simultaneous parallel mode. For looping scan mode, the interrupt will trigger after the completion of each iteration of loop.

enumerator kCADC_ConversionCompleteInterrupt1Enable

When the scan mode is independent parallel mode, up the completion of the converter scan, generate the end of scan interrupt. For looping scan mode, the interrupt will trigger after the completion of each iteration of loop.

enumerator kCADC_ALLInterruptEnable

enum _cadc_converter_id

CADC Converter identifier.

Values:

enumerator kCADC_ConverterA

Converter A.

enumerator kCADC_ConverterB

Converter B.

enum _cadc_idle_work_mode

The enumeration of work mode when the module is not used.

Values:

enumerator kCADC_IdleKeepNormal

Keep normal.

enumerator kCADC_IdleAutoPowerDown

Fall into power down mode automatically.

enum _cadc_dma_trigger_source

The enumeration of DMA trigger source.

Values:

enumerator kCADC_DMATrigSrcEndofScan

DMA trigger source is end of scan interrupt.

enumerator kCADC_DMATrigSrcSampleReady

DMA trigger source is RDY bits.

enum _cadc_scan_mode

The enumeration of dual converter's scan mode.

Values:

enumerator kCADC_ScanModeOnceSequential

Once (single) sequential.

enumerator kCADC_ScanModeOnceParallelIndependent

Once parallel independently.

enumerator kCADC_ScanModeLoopSequential

Loop sequential.

enumerator kCADC_ScanModeLoopParallelIndependent

Loop parallel independently.

enumerator kCADC_ScanModeTriggeredSequential

Triggered sequential.

enumerator kCADC_ScanModeTriggeredParallelIndependent

Triggered parallel independently.

enumerator kCADC_ScanModeOnceParallelSimultaneous

Once parallel simultaneously.

enumerator kCADC_ScanModeLoopParallelSimultaneous

Loop parallel simultaneously.

enumerator kCADC_ScanModeTriggeredParallelSimultaneous

Triggered parallel simultaneously.

enum __cadc_reference_voltage_source

The enumeration of converter's reference voltage source.

Values:

enumerator kCADC_ReferenceVoltageVrefPad

VREF pin.

enumerator kCADC_ReferenceVoltageChannelPad

ANx2 or ANx3 pin.

enum __cadc_channel_gain

The enumeration of sample slot connected channel gain.

Values:

enumerator kCADC_SignalGainX1

Gain x1.

enumerator kCADC_SignalGainX2

Gain x2.

enumerator kCADC_SignalGainX4

Gain x4.

enum __cadc_channel_mode

The enumeration of all channels' channel mode.

Values:

enumerator kCADC_ANA0_1_SingleEnd

ANA0 and ANA1 both configured as single ended inputs.

enumerator kCADC_ANA0_1_FullyDifferential

ANA0 configured as fully differential positive input, ANA1 configured as fully differential negative input.

enumerator kCADC_ANA0_1_UnipolarDifferential

ANA0 configured as unipolar differential positive input, ANA1 configured as unipolar differential negative input.

enumerator kCADC_ANA2_3_SingleEnd

ANA2 and ANA3 both configured as single ended inputs.

enumerator kCADC_ANA2_3_FullyDifferential

ANA2 configured as fully differential positive input, ANA3 configured as fully differential negative input.

enumerator kCADC_ANA2_3_UnipolarDifferential

ANA2 configured as unipolar differential positive input, ANA3 configured as unipolar differential negative input.

enumerator kCADC_ANB0_1_SingleEnd

ANB0 and ANB1 both configured as single ended inputs.

enumerator kCADC_ANB0_1_FullyDifferential

ANB0 configured as fully differential positive input, ANB1 configured as fully differential negative input.

enumerator kCADC_ANB0_1_UnipolarDifferential

ANB0 configured as unipolar differential positive input, ANB1 configured as unipolar differential negative input.

enumerator kCADC_ANB2_3_SingleEnd

ANB2 and ANB3 both configured as single ended inputs.

enumerator kCADC_ANB2_3_FullyDifferential

ANB2 configured as fully differential positive input, ANB3 configured as fully differential negative input.

enumerator kCADC_ANB2_3_UnipolarDifferential

ANB2 configured as unipolar differential positive input, ANB3 configured as unipolar differential negative input.

enumerator kCADC_ANA4_5_SingleEnd

ANA4 and ANA5 both configured as single ended inputs.

enumerator kCADC_ANA4_5_FullyDifferential

ANA4 configured as fully differential positive input, ANA5 configured as fully differential negative input.

enumerator kCADC_ANA4_5_UnipolarDifferential

ANA4 configured as unipolar differential positive input, ANA5 configured as unipolar differential negative input.

enumerator kCADC_ANA6_7_SingleEnd

ANA6 and ANA7 both configured as single ended inputs.

enumerator kCADC_ANA6_7_FullyDifferential

ANA6 configured as fully differential positive input, ANA7 configured as fully differential negative input.

enumerator kCADC_ANA6_7_UnipolarDifferential

ANA6 configured as unipolar differential positive input, ANA7 configured as unipolar differential negative input.

enumerator kCADC_ANB4_5_SingleEnd

ANB4 and ANB5 both configured as single ended inputs.

enumerator kCADC_ANB4_5_FullyDifferential

ANB4 configured as fully differential positive input, ANB5 configured as fully differential negative input.

enumerator kCADC_ANB4_5_UnipolarDifferential

ANB4 configured as unipolar differential positive input, ANB5 configured as unipolar differential negative input.

enumerator kCADC_ANB6_7_SingleEnd

ANB6 and ANB7 both configured as single ended inputs.

enumerator kCADC_ANB6_7_FullyDifferential

ANB6 configured as fully differential positive input, ANB7 configured as fully differential negative input.

enumerator kCADC_ANB6_7_UnipolarDifferential

ANB6 configured as unipolar differential positive input, ANB7 configured as unipolar differential negative input.

enum _cadc_channel_number

The enumerator of all channels that can be routed to the specific sample slot.

Values:

enumerator kCADC_SingleEndANA0_DiffANA0pANA1n

Single Ended ANA0 Signal Or Differential ANA0+, ANA1- signal.

enumerator kCADC_SingleEndANA1_DiffANA0pANA1n

Single Ended ANA1 Signal Or Differential ANA0+, ANA1- signal.

enumerator kCADC_SingleEndANA2_DiffANA2pANA3n

Single Ended ANA2 Signal Or Differential ANA2+, ANA3- signal.

enumerator kCADC_SingleEndANA3_DiffANA2pANA3n

Single Ended ANA3 Signal Or Differential ANA2+, ANA3- signal.

enumerator kCADC_SingleEndANA4_DiffANA4pANA5n

Single Ended ANA4 Signal Or Differential ANA4+, ANA5- signal.

enumerator kCADC_SingleEndANA5_DiffANA4pANA5n

Single Ended ANA5 Signal Or Differential ANA4+, ANA5- signal.

enumerator kCADC_SingleEndANA6_DiffANA6pANA7n

Single Ended ANA6 Signal Or Differential ANA6+, ANA7- signal.

enumerator kCADC_SingleEndANA7_DiffANA6pANA7n

Single Ended ANA7 Signal Or Differential ANA6+, ANA7- signal.

enumerator kCADC_SingleEndANB0_DiffANB0pANB1n

Single Ended ANB0 Signal Or Differential ANB0+, ANB1- signal.

enumerator kCADC_SingleEndANB1_DiffANB0pANB1n

Single Ended ANB1 Signal Or Differential ANB0+, ANB1- signal.

enumerator kCADC_SingleEndANB2_DiffANB2pANB3n

Single Ended ANB2 Signal Or Differential ANB2+, ANB3- signal.

enumerator kCADC_SingleEndANB3_DiffANB2pANB3n

Single Ended ANB3 Signal Or Differential ANB2+, ANB3- signal.

enumerator kCADC_SingleEndANB4_DiffANB4pANB5n

Single Ended ANB4 Signal Or Differential ANB4+, ANB5- signal.

enumerator kCADC_SingleEndANB5_DiffANB4pANB5n

Single Ended ANB5 Signal Or Differential ANB4+, ANB5- signal.

enumerator kCADC_SingleEndANB6_DiffANB6pANB7n

Single Ended ANB6 Signal Or Differential ANB6+, ANB7- signal.

enumerator kCADC_SingleEndANB7_DiffANB6pANB7n

Single Ended ANB7 Signal Or Differential ANB6+, ANB7- signal.

enum _cadc_sample_slot_mask

The enumeration of sample slot mask.

Values:

enumerator kCADC_NonSampleSlotMask

enumerator kCADC_SampleSlot0Mask

The mask of sample slot0.

enumerator kCADC_SampleSlot1Mask

The mask of sample slot1.

enumerator kCADC_SampleSlot2Mask

The mask of sample slot2.

enumerator kCADC_SampleSlot3Mask

The mask of sample slot3.

enumerator kCADC_SampleSlot4Mask

The mask of sample slot4.

enumerator kCADC_SampleSlot5Mask

The mask of sample slot5.

enumerator kCADC_SampleSlot6Mask

The mask of sample slot6.

enumerator kCADC_SampleSlot7Mask

The mask of sample slot7.

enumerator kCADC_SampleSlot8Mask

The mask of sample slot8.

enumerator kCADC_SampleSlot9Mask

The mask of sample slot9.

enumerator kCADC_SampleSlot10Mask

The mask of sample slot10.

enumerator kCADC_SampleSlot11Mask

The mask of sample slot11.

enumerator kCADC_SampleSlot12Mask

The mask of sample slot12.

enumerator kCADC_SampleSlot13Mask

The mask of sample slot13.

enumerator kCADC_SampleSlot14Mask

The mask of sample slot14.

enumerator kCADC_SampleSlot15Mask

The mask of sample slot15.

enumerator kCADC_AllSampleSlotsMask

The mask of all sample slots.

enum _cadc_sample_slot_index

The enumeration of sample slot index.

Values:

enumerator kCADC_SampleSlot0Index
The index of sample slot0.

enumerator kCADC_SampleSlot1Index
The index of sample slot1.

enumerator kCADC_SampleSlot2Index
The index of sample slot2.

enumerator kCADC_SampleSlot3Index
The index of sample slot3.

enumerator kCADC_SampleSlot4Index
The index of sample slot4.

enumerator kCADC_SampleSlot5Index
The index of sample slot5.

enumerator kCADC_SampleSlot6Index
The index of sample slot6.

enumerator kCADC_SampleSlot7Index
The index of sample slot7.

enumerator kCADC_SampleSlot8Index
The index of sample slot8.

enumerator kCADC_SampleSlot9Index
The index of sample slot9.

enumerator kCADC_SampleSlot10Index
The index of sample slot10.

enumerator kCADC_SampleSlot11Index
The index of sample slot11.

enumerator kCADC_SampleSlot12Index
The index of sample slot12.

enumerator kCADC_SampleSlot13Index
The index of sample slot13.

enumerator kCADC_SampleSlot14Index
The index of sample slot14.

enumerator kCADC_SampleSlot15Index
The index of sample slot15.

enum _cadc_sample_slot_sequential_mode_disabled
The enumeration for the sample slot to be disabled in sequential mode.

Values:

enumerator kCADC_Sample0Disabled
Disable Sample slot0, the scan will stop at sample slot0 in sequential scan mode

enumerator kCADC_Sample1Disabled
Disable Sample slot1, the scan will stop at sample slot1 in sequential scan mode

enumerator kCADC_Sample2Disabled
Disable Sample slot2, the scan will stop at sample slot2 in sequential scan mode

enumerator kCADC_Sample3Disabled

Disable Sample slot3, the scan will stop at sample slot3 in sequential scan mode

enumerator kCADC_Sample4Disabled

Disable Sample slot4, the scan will stop at sample slot4 in sequential scan mode

enumerator kCADC_Sample5Disabled

Disable Sample slot5, the scan will stop at sample slot5 in sequential scan mode

enumerator kCADC_Sample6Disabled

Disable Sample slot6, the scan will stop at sample slot6 in sequential scan mode

enumerator kCADC_Sample7Disabled

Disable Sample slot7, the scan will stop at sample slot7 in sequential scan mode

enumerator kCADC_Sample8Disabled

Disable Sample slot8, the scan will stop at sample slot8 in sequential scan mode

enumerator kCADC_Sample9Disabled

Disable Sample slot9, the scan will stop at sample slot9 in sequential scan mode

enumerator kCADC_Sample10Disabled

Disable Sample slot10, the scan will stop at sample slot10 in sequential scan mode

enumerator kCADC_Sample11Disabled

Disable Sample slot11, the scan will stop at sample slot11 in sequential scan mode

enumerator kCADC_Sample12Disabled

Disable Sample slot12, the scan will stop at sample slot12 in sequential scan mode

enumerator kCADC_Sample13Disabled

Disable Sample slot13, the scan will stop at sample slot13 in sequential scan mode

enumerator kCADC_Sample14Disabled

Disable Sample slot14, the scan will stop at sample slot14 in sequential scan mode

enumerator kCADC_Sample15Disabled

Disable Sample slot15, the scan will stop at sample slot15 in sequential scan mode

enum _cadc_sample_slot_simultParallel_mode_disabled

The enumeration for the sample slot to be disabled in simultaneous parallel mode.

Values:

enumerator kCADC_Sample0_8Disabled

Disable Sample slot0 and Sample Slot 8, in the simultaneous parallel mode the converter A and converter B will stop at Sample slot0 and Sample slot 8.

enumerator kCADC_Sample1_9Disabled

Disable Sample slot1 and Sample Slot 9, in the simultaneous parallel mode the converter A and converter B will stop at Sample slot1 and Sample slot 9.

enumerator kCADC_Sample2_10Disabled

Disable Sample slot2 and Sample Slot 10, in the simultaneous parallel mode the converter A and converter B will stop at Sample slot2 and Sample slot 10.

enumerator kCADC_Sample3_11Disabled

Disable Sample slot3 and Sample Slot 11, in the simultaneous parallel mode the converter A and converter B will stop at Sample slot3 and Sample slot 11.

enumerator kCADC_Sample4_12Disabled

Disable Sample slot4 and Sample Slot 12, in the simultaneous parallel mode the converter A and converter B will stop at Sample slot4 and Sample slot 12.

enumerator kCADC_Sample5_13Disabled

Disable Sample slot5 and Sample Slot 13, in the simultaneous parallel mode the converter A and converter B will stop at Sample slot5 and Sample slot 13.

enumerator kCADC_Sample6_14Disabled

Disable Sample slot6 and Sample Slot 14, in the simultaneous parallel mode the converter A and converter B will stop at Sample slot7 and Sample slot 14.

enumerator kCADC_Sample7_15Disabled

Disable Sample slot7 and Sample Slot 15, in the simultaneous parallel mode the converter A and converter B will stop at Sample slot7 and Sample slot 15.

enum _cadc_sample_slot_independentParallel_mode_convA_disabled

The enumeration for the sample slot to be disabled for the converter A in independent parallel mode.

Values:

enumerator kCADC_ConvASample0Disabled

Disable Sample slot0, the scan will stop at sample slot0 in sequential scan mode

enumerator kCADC_ConvASample1Disabled

Disable Sample slot1, the scan will stop at sample slot1 in sequential scan mode

enumerator kCADC_ConvASample2Disabled

Disable Sample slot2, the scan will stop at sample slot2 in sequential scan mode

enumerator kCADC_ConvASample3Disabled

Disable Sample slot3, the scan will stop at sample slot3 in sequential scan mode

enumerator kCADC_ConvASample4Disabled

Disable Sample slot4, the scan will stop at sample slot4 in sequential scan mode

enumerator kCADC_ConvASample5Disabled

Disable Sample slot5, the scan will stop at sample slot5 in sequential scan mode

enumerator kCADC_ConvASample6Disabled

Disable Sample slot6, the scan will stop at sample slot6 in sequential scan mode

enumerator kCADC_ConvASample7Disabled

Disable Sample slot7, the scan will stop at sample slot7 in sequential scan mode

enumerator kCADC_ConvASampleReserved

Reserved

enum _cadc_sample_slot_indParallel_mode_convB_disabled

The enumeration for the sample slot to be disabled for the converter B in independent parallel mode.

Values:

enumerator kCADC_ConvBSample8Disabled

Disable Sample slot8, the scan will stop at sample slot8 in sequential scan mode

enumerator kCADC_ConvBSample9Disabled

Disable Sample slot9, the scan will stop at sample slot9 in sequential scan mode

enumerator kCADC_ConvBSample10Disabled

Disable Sample slot10, the scan will stop at sample slot10 in sequential scan mode

enumerator kCADC_ConvBSample11Disabled

Disable Sample slot11, the scan will stop at sample slot11 in sequential scan mode

enumerator kCADC_ConvBSample12Disabled

Disable Sample slot12, the scan will stop at sample slot12 in sequential scan mode

enumerator kCADC_ConvBSample13Disabled

Disable Sample slot13, the scan will stop at sample slot13 in sequential scan mode

enumerator kCADC_ConvBSample14Disabled

Disable Sample slot14, the scan will stop at sample slot14 in sequential scan mode

enumerator kCADC_ConvBSample15Disabled

Disable Sample slot15, the scan will stop at sample slot15 in sequential scan mode

enumerator kCADC_ConvBSampleReserved

Reserved

enum _cadc_sample_slot_zero_crossing_mode

The enumeration for the sample slot's zero crossing event.

Values:

enumerator kCADC_ZeroCrossingDisabled

Zero Crossing disabled.

enumerator kCADC_ZeroCrossingForPtoNSign

Zero Crossing enabled for positive to negative sign change.

enumerator kCADC_ZeroCrossingForNtoPSign

Zero Crossing enabled for negative to positive sign change.

enumerator kCADC_ZeroCrossingForAnySignChanged

Zero Crossing enabled for any sign change.

enum _cadc_expansion_mux_operate_mode

The enumeration for expansion multiplexer.

Values:

enumerator kCADC_ExpMuxManualMode

MUX channel feeding to ANA4/ANB4 is selected as MUXSEL0.

enumerator kCADC_ExpMuxScanMode0

The sample completion of ANA4/ANB4 enables subsequent selected channel.

enumerator kCADC_ExpMuxScanMode1

The sample completion of ANA7/ANB7 enables subsequent selected channel.

enumerator kCADC_ExpMuxScanMode2

The sample completion of ANA4/ANB4 or ANA7/ANB7 enables subsequent selected channel.

enum _cadc_auxiliary_control

The enumeration of converter's auxiliary control.

Values:

enumerator kCADC_AuxSel0_Config0

Auxiliary select 0 controls AUX_SEL0 = 0, AUX_SEL1 = 0.

enumerator kCADC_AuxSel0_Config1

Auxiliary select 0 controls AUX_SEL0 = 1, AUX_SEL1 = 0.

enumerator kCADC_AuxSel0_Config2

Auxiliary select 0 controls AUX_SEL0 = 0, AUX_SEL1 = 1.

enumerator kCADC_AuxSel0_Config3
Auxiliary select 0 controls AUX_SEL0 = 1, AUX_SEL1 = 1.

enumerator kCADC_AuxSel1_Config0
Auxiliary select 1 controls AUX_SEL0 = 0, AUX_SEL1 = 0.

enumerator kCADC_AuxSel1_Config1
Auxiliary select 1 controls AUX_SEL0 = 1, AUX_SEL1 = 0.

enumerator kCADC_AuxSel1_Config2
Auxiliary select 1 controls AUX_SEL0 = 0, AUX_SEL1 = 1.

enumerator kCADC_AuxSel1_Config3
Auxiliary select 1 controls AUX_SEL0 = 1, AUX_SEL1 = 1.

enumerator kCADC_AuxSel2_Config0
Auxiliary select 2 controls AUX_SEL0 = 0, AUX_SEL1 = 0.

enumerator kCADC_AuxSel2_Config1
Auxiliary select 2 controls AUX_SEL0 = 1, AUX_SEL1 = 0.

enumerator kCADC_AuxSel2_Config2
Auxiliary select 2 controls AUX_SEL0 = 0, AUX_SEL1 = 1.

enumerator kCADC_AuxSel2_Config3
Auxiliary select 2 controls AUX_SEL0 = 1, AUX_SEL1 = 1.

enumerator kCADC_AuxSel3_Config0
Auxiliary select 3 controls AUX_SEL0 = 0, AUX_SEL1 = 0.

enumerator kCADC_AuxSel3_Config1
Auxiliary select 3 controls AUX_SEL0 = 1, AUX_SEL1 = 0.

enumerator kCADC_AuxSel3_Config2
Auxiliary select 3 controls AUX_SEL0 = 0, AUX_SEL1 = 1.

enumerator kCADC_AuxSel3_Config3
Auxiliary select 3 controls AUX_SEL0 = 1, AUX_SEL1 = 1.

enumerator kCADC_AuxSel4_Config0
Auxiliary select 4 controls AUX_SEL0 = 0, AUX_SEL1 = 0.

enumerator kCADC_AuxSel4_Config1
Auxiliary select 4 controls AUX_SEL0 = 1, AUX_SEL1 = 0.

enumerator kCADC_AuxSel4_Config2
Auxiliary select 4 controls AUX_SEL0 = 0, AUX_SEL1 = 1.

enumerator kCADC_AuxSel4_Config3
Auxiliary select 4 controls AUX_SEL0 = 1, AUX_SEL1 = 1.

enumerator kCADC_AuxSel5_Config0
Auxiliary select 5 controls AUX_SEL0 = 0, AUX_SEL1 = 0.

enumerator kCADC_AuxSel5_Config1
Auxiliary select 5 controls AUX_SEL0 = 1, AUX_SEL1 = 0.

enumerator kCADC_AuxSel5_Config2
Auxiliary select 5 controls AUX_SEL0 = 0, AUX_SEL1 = 1.

enumerator kCADC_AuxSel5_Config3
Auxiliary select 5 controls AUX_SEL0 = 1, AUX_SEL1 = 1.

enumerator kCADC_AuxSel6_Config0

Auxiliary select 6 controls AUX_SEL0 = 0, AUX_SEL1 = 0.

enumerator kCADC_AuxSel6_Config1

Auxiliary select 6 controls AUX_SEL0 = 1, AUX_SEL1 = 0.

enumerator kCADC_AuxSel6_Config2

Auxiliary select 6 controls AUX_SEL0 = 0, AUX_SEL1 = 1.

enumerator kCADC_AuxSel6_Config3

Auxiliary select 6 controls AUX_SEL0 = 1, AUX_SEL1 = 1.

enumerator kCADC_AuxSel7_Config0

Auxiliary select 7 controls AUX_SEL0 = 0, AUX_SEL1 = 0.

enumerator kCADC_AuxSel7_Config1

Auxiliary select 7 controls AUX_SEL0 = 1, AUX_SEL1 = 0.

enumerator kCADC_AuxSel7_Config2

Auxiliary select 7 controls AUX_SEL0 = 0, AUX_SEL1 = 1.

enumerator kCADC_AuxSel7_Config3

Auxiliary select 7 controls AUX_SEL0 = 1, AUX_SEL1 = 1.

enum _cadc_expansion_disabled_mux_slot

The enumeration for the expansion mux slot to be disabled.

Values:

enumerator kCADC_ExpMuxNoDisable

Expansion mux scan not disabled.

enumerator kCADC_ExpMux0Disable

Expansion mux slot 0.

enumerator kCADC_ExpMux1Disable

Expansion mux slot 1.

enumerator kCADC_ExpMux2Disable

Expansion mux slot 2.

enumerator kCADC_ExpMux3Disable

Expansion mux slot 3.

enumerator kCADC_ExpMux4Disable

Expansion mux slot 4.

enumerator kCADC_ExpMux5Disable

Expansion mux slot 5.

enumerator kCADC_ExpMux6Disable

Expansion mux slot 6.

enumerator kCADC_ExpMux7Disable

Expansion mux slot 7.

enum _cadc_expansion_mux_selection

The enumeration of expanssion mux selection.

Values:

enumerator kCADC_MuxSel0_Channel0

MUX's channel 0 for MUXSEL0.

enumerator kCADC_MuxSel0_Channel1
MUX's channel 1 for MUXSEL0.

enumerator kCADC_MuxSel0_Channel2
MUX's channel 2 for MUXSEL0.

enumerator kCADC_MuxSel0_Channel3
MUX's channel 3 for MUXSEL0.

enumerator kCADC_MuxSel0_Channel4
MUX's channel 4 for MUXSEL0.

enumerator kCADC_MuxSel0_Channel5
MUX's channel 5 for MUXSEL0.

enumerator kCADC_MuxSel0_Channel6
MUX's channel 6 for MUXSEL0.

enumerator kCADC_MuxSel0_Channel7
MUX's channel 7 for MUXSEL0.

enumerator kCADC_MuxSel1_Channel0
MUX's channel 0 for MUXSEL1.

enumerator kCADC_MuxSel1_Channel1
MUX's channel 1 for MUXSEL1.

enumerator kCADC_MuxSel1_Channel2
MUX's channel 2 for MUXSEL1.

enumerator kCADC_MuxSel1_Channel3
MUX's channel 3 for MUXSEL1.

enumerator kCADC_MuxSel1_Channel4
MUX's channel 4 for MUXSEL1.

enumerator kCADC_MuxSel1_Channel5
MUX's channel 5 for MUXSEL1.

enumerator kCADC_MuxSel1_Channel6
MUX's channel 6 for MUXSEL1.

enumerator kCADC_MuxSel1_Channel7
MUX's channel 7 for MUXSEL1.

enumerator kCADC_MuxSel2_Channel0
MUX's channel 0 for MUXSEL2.

enumerator kCADC_MuxSel2_Channel1
MUX's channel 1 for MUXSEL2.

enumerator kCADC_MuxSel2_Channel2
MUX's channel 2 for MUXSEL2.

enumerator kCADC_MuxSel2_Channel3
MUX's channel 3 for MUXSEL2.

enumerator kCADC_MuxSel2_Channel4
MUX's channel 4 for MUXSEL2.

enumerator kCADC_MuxSel2_Channel5
MUX's channel 5 for MUXSEL2.

enumerator kCADC_MuxSel2_Channel6
MUX's channel 6 for MUXSEL2.

enumerator kCADC_MuxSel2_Channel7
MUX's channel 7 for MUXSEL2.

enumerator kCADC_MuxSel3_Channel0
MUX's channel 0 for MUXSEL3.

enumerator kCADC_MuxSel3_Channel1
MUX's channel 1 for MUXSEL3.

enumerator kCADC_MuxSel3_Channel2
MUX's channel 2 for MUXSEL3.

enumerator kCADC_MuxSel3_Channel3
MUX's channel 3 for MUXSEL3.

enumerator kCADC_MuxSel3_Channel4
MUX's channel 4 for MUXSEL3.

enumerator kCADC_MuxSel3_Channel5
MUX's channel 5 for MUXSEL3.

enumerator kCADC_MuxSel3_Channel6
MUX's channel 6 for MUXSEL3.

enumerator kCADC_MuxSel3_Channel7
MUX's channel 7 for MUXSEL3.

enumerator kCADC_MuxSel4_Channel0
MUX's channel 0 for MUXSEL4.

enumerator kCADC_MuxSel4_Channel1
MUX's channel 1 for MUXSEL4.

enumerator kCADC_MuxSel4_Channel2
MUX's channel 2 for MUXSEL4.

enumerator kCADC_MuxSel4_Channel3
MUX's channel 3 for MUXSEL4.

enumerator kCADC_MuxSel4_Channel4
MUX's channel 4 for MUXSEL4.

enumerator kCADC_MuxSel4_Channel5
MUX's channel 5 for MUXSEL4.

enumerator kCADC_MuxSel4_Channel6
MUX's channel 6 for MUXSEL4.

enumerator kCADC_MuxSel4_Channel7
MUX's channel 7 for MUXSEL4.

enumerator kCADC_MuxSel5_Channel0
MUX's channel 0 for MUXSEL5.

enumerator kCADC_MuxSel5_Channel1
MUX's channel 1 for MUXSEL5.

enumerator kCADC_MuxSel5_Channel2
MUX's channel 2 for MUXSEL5.

enumerator kCADC_MuxSel5_Channel3
MUX's channel 3 for MUXSEL5.

enumerator kCADC_MuxSel5_Channel4
MUX's channel 4 for MUXSEL5.

enumerator kCADC_MuxSel5_Channel5
MUX's channel 5 for MUXSEL5.

enumerator kCADC_MuxSel5_Channel6
MUX's channel 6 for MUXSEL5.

enumerator kCADC_MuxSel5_Channel7
MUX's channel 7 for MUXSEL5.

enumerator kCADC_MuxSel6_Channel0
MUX's channel 0 for MUXSEL6.

enumerator kCADC_MuxSel6_Channel1
MUX's channel 1 for MUXSEL6.

enumerator kCADC_MuxSel6_Channel2
MUX's channel 2 for MUXSEL6.

enumerator kCADC_MuxSel6_Channel3
MUX's channel 3 for MUXSEL6.

enumerator kCADC_MuxSel6_Channel4
MUX's channel 4 for MUXSEL6.

enumerator kCADC_MuxSel6_Channel5
MUX's channel 5 for MUXSEL6.

enumerator kCADC_MuxSel6_Channel6
MUX's channel 6 for MUXSEL6.

enumerator kCADC_MuxSel6_Channel7
MUX's channel 7 for MUXSEL6.

enumerator kCADC_MuxSel7_Channel0
MUX's channel 0 for MUXSEL7.

enumerator kCADC_MuxSel7_Channel1
MUX's channel 1 for MUXSEL7.

enumerator kCADC_MuxSel7_Channel2
MUX's channel 2 for MUXSEL7.

enumerator kCADC_MuxSel7_Channel3
MUX's channel 3 for MUXSEL7.

enumerator kCADC_MuxSel7_Channel4
MUX's channel 4 for MUXSEL7.

enumerator kCADC_MuxSel7_Channel5
MUX's channel 5 for MUXSEL7.

enumerator kCADC_MuxSel7_Channel6
MUX's channel 6 for MUXSEL7.

enumerator kCADC_MuxSel7_Channel7
MUX's channel 7 for MUXSEL7.

`typedef enum _cadc_converter_id cadc_converter_id_t`

CADC Converter identifier.

`typedef enum _cadc_idle_work_mode cadc_idle_work_mode_t`

The enumeration of work mode when the module is not used.

`typedef enum _cadc_dma_trigger_source cadc_dma_trigger_source_t`

The enumeration of DMA trigger source.

`typedef enum _cadc_scan_mode cadc_scan_mode_t`

The enumeration of dual converter's scan mode.

`typedef enum _cadc_reference_voltage_source cadc_reference_voltage_source_t`

The enumeration of converter's reference voltage source.

`typedef enum _cadc_channel_gain cadc_channel_gain_t`

The enumeration of sample slot connected channel gain.

`typedef enum _cadc_channel_mode cadc_channel_mode_t`

The enumeration of all channels' channel mode.

`typedef enum _cadc_channel_number cadc_channel_number_t`

The enumerator of all channels that can be routed to the specific sample slot.

`typedef enum _cadc_sample_slot_mask cadc_sample_slot_mask_t`

The enumeration of sample slot mask.

`typedef enum _cadc_sample_slot_index cadc_sample_slot_index_t`

The enumeration of sample slot index.

`typedef enum _cadc_sample_slot_sequential_mode_disabled`

`cadc_sample_slot_sequential_mode_disabled_t`

The enumeration for the sample slot to be disabled in sequential mode.

`typedef enum _cadc_sample_slot_simultParallel_mode_disabled`

`cadc_sample_slot_simultParallel_mode_disabled_t`

The enumeration for the sample slot to be disabled in simultaneous parallel mode.

`typedef enum _cadc_sample_slot_independentParallel_mode_convA_disabled`

`cadc_sample_slot_independentParallel_mode_convA_disabled_t`

The enumeration for the sample slot to be disabled for the converter A in independent parallel mode.

`typedef enum _cadc_sample_slot_indParallel_mode_convB_disabled`

`cadc_sample_slot_independentParallel_mode_convB_disabled_t`

The enumeration for the sample slot to be disabled for the converter B in independent parallel mode.

`typedef enum _cadc_sample_slot_zero_crossing_mode cadc_sample_slot_zero_crossing_mode_t`

The enumeration for the sample slot's zero crossing event.

`typedef enum _cadc_expansion_mux_operate_mode cadc_expansion_mux_operate_mode_t`

The enumeration for expansion multiplexer.

`typedef struct _cadc_sample_slot_independentParallel_mode_disabled`

`cadc_sample_slot_independentParallel_mode_disabled_t`

The structure of the disabled sample slots in independent parallel mode.

`typedef union _cadc_sample_slot_disabled cadc_sample_slot_disabled_t`

The union of disabled sample slot for each scan mode.

```
typedef struct _cadc_sample_config cadc_sample_slot_config_t
```

The structure for configuring the sample slot.

```
typedef struct _cadc_scan_ctrl_sequential_mode cadc_scan_ctrl_seq_mode_t
```

Cadc scan control for sequential scan mode.

Note: Each member of this structure represent one bit of the word. Asserted the structure's member means delay sample until a new sync input occurs. Cleared the structure's member means perform sample immediately after the completion of the current sample.

```
typedef struct _cadc_scan_ctrl_simultParallel_mode cadc_scan_ctrl_simultParallel_mode_t
```

Cadc scan control for simultaneous parallel scan mode.

Note: Each member of this structure represent one bit of the word. Asserted the structure's member means delay sample until a new sync input occurs. Cleared the structure's member means perform sample immediately after the completion of the current sample.

```
typedef struct _cadc_scan_ctrl_independent_parallel_mode_converterA
```

```
cadc_scan_ctrl_independent_parallel_mode_converterA_t
```

The scan ctrl struture for converterA in independent scan mode.

```
typedef struct _cadc_scan_ctrl_independent_parallel_mode_converterB
```

```
cadc_scan_ctrl_independent_parallel_mode_converterB_t
```

The scan ctrl struture for converterB in independent scan mode.

```
typedef union _cadc_scan_ctrl_independent_parallel_mode
```

```
cadc_scan_ctrl_independent_parallel_mode_t
```

The union for converters in independent parallel mode.

```
typedef union _cadc_scan_control cadc_scan_control_t
```

The union of the scan control for each scan mode.

```
typedef enum _cadc_auxiliary_control cadc_auxiliary_control_t
```

The enumeration of conveter's auxiliary control.

```
typedef enum _cadc_expansion_disabled_mux_slot cadc_expansion_disabled_mux_slot_t
```

The enumeration for the expansion mux slot to be disabled.

```
typedef enum _cadc_expansion_mux_selection cadc_expansion_mux_selection_t
```

The enumeration of expansion mux selection.

```
typedef struct _cadc_exp_mux_aux_config cadc_exp_mux_aux_config_t
```

The structure for configuring Cyclic ADC's expansion setting.

```
typedef struct _cadc_converter_config cadc_converter_config_t
```

The structure for configuring each converter.

```
typedef struct _cadc_config cadc_config_t
```

The structure for configuring the Cyclic ADC's setting.

```
CADC_SAMPLE_SLOTS_COUNT
```

Macro for CADC sample slot count.

```
struct _cadc_sample_slot_independentParallel_mode_disabled
```

#include <fsl_cadc.h> The structure of the disabled sample slots in independent parallel mode.

Public Members

cadc_sample_slot_independentParallel_mode_convA_disabled_t eConverterA

The sample slot to be disabled for the converter A, when the scan mode is set as independent parallel mode.

cadc_sample_slot_independentParallel_mode_convB_disabled_t eConverterB

The sample slot to be disabled for the converter B, when the scan mode is set as independent parallel mode.

union *_cadc_sample_slot_disabled*

#include <fsl_cadc.h> The union of disabled sample slot for each scan mode.

Public Members

uint32_t u32SampleDisVal

The 32 bits width of disabled sample slot value. This member used to get the disabled sample slot which sets in different scan modes in word type. This member is not recommended to be used to set the disabled sample slot. This member is designed to be used in driver level only, the application should not use this member.

cadc_sample_slot_sequential_mode_disabled_t eSequentialModeDisSample

If the scan mode is selected as sequential mode, the application must use this member to set the disabled sample slot. This member is used to set disabled sample slot when the scan mode is selected as sequential mode. The scan will stop at the first disabled sample slot in that mode. So for the application, this member should be set as one sample slot index that the scan will stop.

cadc_sample_slot_simultParallel_mode_disabled_t eSimultParallelModeDisSample

In simultaneous parallel scan mode, the application must use this member to set the disabled sample slot. In that scan mode, the scan will stop when either converter encounters a disabled sample.

cadc_sample_slot_independentParallel_mode_disabled_t sIndependentParallelModeDisSample

In independent parallel scan mode, the application must use this member to set the disabled sample slot. In that scan mode, the converter will stop scan when it encounters a disabled sample slot. In this mode, the disabled sample slot for converterA and converterB may different.

struct *_cadc_sample_config*

#include <fsl_cadc.h> The structure for configuring the sample slot.

Public Members

cadc_sample_slot_zero_crossing_mode_t eZeroCrossingMode

Zero crossing mode.

uint16_t u16HighLimitValue

High limit value. Original value formation as hardware register, with 3-bits left shifted.

uint16_t u16LowLimitValue

Low limit value. Original value formation as hardware register, with 3-bits left shifted.

uint16_t u16OffsetValue

Offset value. Original value formation as hardware register, with 3-bits left shifted.

```
struct _cadc_scan_ctrl_sequential_mode
#include <fsl_cadc.h> Cadc scan control for sequential scan mode.
```

Note: Each member of this structure represent one bit of the word. Asserted the structure's member means delay sample until a new sync input occurs. Cleared the structure's member means perform sample immediately after the completion of the current sample.

Public Members

uint32_t bitSample0
Control whether delay sample0 until a new sync input occurs.

uint32_t bitSample1
Control whether delay sample1 until a new sync input occurs.

uint32_t bitSample2
Control whether delay sample2 until a new sync input occurs.

uint32_t bitSample3
Control whether delay sample3 until a new sync input occurs.

uint32_t bitSample4
Control whether delay sample4 until a new sync input occurs.

uint32_t bitSample5
Control whether delay sample5 until a new sync input occurs.

uint32_t bitSample6
Control whether delay sample6 until a new sync input occurs.

uint32_t bitSample7
Control whether delay sample7 until a new sync input occurs.

uint32_t bitSample8
Control whether delay sample8 until a new sync input occurs.

uint32_t bitSample9
Control whether delay sample9 until a new sync input occurs.

uint32_t bitSample10
Control whether delay sample10 until a new sync input occurs.

uint32_t bitSample11
Control whether delay sample11 until a new sync input occurs.

uint32_t bitSample12
Control whether delay sample12 until a new sync input occurs.

uint32_t bitSample13
Control whether delay sample13 until a new sync input occurs.

uint32_t bitSample14
Control whether delay sample14 until a new sync input occurs.

uint32_t bitSample15
Control whether delay sample15 until a new sync input occurs.

uint32_t bitsReserved
Reserved 16 bits.

```
struct _cadc_scan_ctrl_simultParallel_mode
#include <fsl_cadc.h> Cadc scan control for simultaneous parallel scan mode.
```

Note: Each member of this structure represent one bit of the word. Asserted the structure's member means delay sample until a new sync input occurs. Cleared the structure's member means perform sample immediately after the completion of the current sample.

Public Members

uint32_t bitSample0_8
Control whether delay sample0 and sample8 until a new sync input occurs.

uint32_t bitSample1_9
Control whether delay sample1 and sample9 until a new sync input occurs.

uint32_t bitSample2_10
Control whether delay sample2 and sample10 until a new sync input occurs.

uint32_t bitSample3_11
Control whether delay sample3 and sample11 until a new sync input occurs.

uint32_t bitsReserved1
Reserved 4 bits.

uint32_t bitSample4_12
Control whether delay sample4 and sample12 until a new sync input occurs.

uint32_t bitSample5_13
Control whether delay sample5 and sample13 until a new sync input occurs.

uint32_t bitSample6_14
Control whether delay sample6 and sample14 until a new sync input occurs.

uint32_t bitSample7_15
Control whether delay sample7 and sample15 until a new sync input occurs.

uint32_t bitsReserved2
Reserved 4 bits.

uint32_t bitsReserved3
Reserved 16 bits.

```
struct _cadc_scan_ctrl_independent_parallel_mode_converterA
#include <fsl_cadc.h> The scan ctrl struture for converterA in independent scan mode.
```

Public Members

uint32_t bitSample0
Control whether delay converterA's sample0 until a new sync input occurs.

uint32_t bitSample1
Control whether delay converterA's sample1 until a new sync input occurs.

uint32_t bitSample2
Control whether delay converterA's sample2 until a new sync input occurs.

uint32_t bitSample3
Control whether delay converterA's sample3 until a new sync input occurs.

uint32_t bitsReserved1

Reserved 4 bits.

uint32_t bitSample4

Control whether delay converterA's sample4 until a new sync input occurs.

uint32_t bitSample5

Control whether delay converterA's sample5 until a new sync input occurs.

uint32_t bitSample6

Control whether delay converterA's sample6 until a new sync input occurs.

uint32_t bitSample7

Control whether delay converterA's sample7 until a new sync input occurs.

uint32_t bitsReserved2

Reserved 4 bits

uint32_t bitsReserved3

Reserved 16 bits.

struct _cadsc_scan_ctrl_independent_parallel_mode_converterB

#include <fsl_cadc.h> The scan ctrl struture for converterB in independent scan mode.

Public Members

uint32_t bitsReserved1

Reserved 4 bits.

uint32_t bitSample8

Control whether delay converterB's sample8 until a new sync input occurs.

uint32_t bitSample9

Control whether delay converterB's sample9 until a new sync input occurs.

uint32_t bitSample10

Control whether delay converterB's sample10 until a new sync input occurs.

uint32_t bitSample11

Control whether delay converterB's sample11 until a new sync input occurs.

uint32_t bitsReserved2

Reserved 4 bits.

uint32_t bitSample12

Control whether delay converterB's sample12 until a new sync input occurs.

uint32_t bitSample13

Control whether delay converterB's sample13 until a new sync input occurs.

uint32_t bitSample14

Control whether delay converterB's sample14 until a new sync input occurs.

uint32_t bitSample15

Control whether delay converterB's sample15 until a new sync input occurs.

uint32_t bitsReserved3

Reserved 16 bits.

union _cadsc_scan_ctrl_independent_parallel_mode

#include <fsl_cadc.h> The union for converters in independent parallel mode.

Public Members

cadc_scan_ctrl_independent_parallel_mode_converterA_t sConverterA

Scan control for converterA.

cadc_scan_ctrl_independent_parallel_mode_converterB_t sConverterB

Scan control for converterB.

union *_cadc_scan_control*

#include <fsl_cadc.h> The union of the scan control for each scan mode.

Public Members

uint32_t *u32ScanCtrlVal*

The 32 bits value of the scan control value.

cadc_scan_ctrl_seq_mode_t sSequential

Scan control for sequential scan mode.

cadc_scan_ctrl_simultParallel_mode_t sSimultParallel

Scan control for simultaneous parallel scan mode.

cadc_scan_ctrl_independent_parallel_mode_t uIndependentParallel

Scan control for independent scan mode.

struct *_cadc_exp_mux_aux_config*

#include <fsl_cadc.h> The structure for configuring Cyclic ADC's expansion setting.

Public Members

uint16_t *u16AuxControl*

The mask of auxiliary control, should be the OR'ed value of *cadc_auxiliary_control_t*.

uint32_t *u32MuxChannelMask*

The mask of mux selection of all mux slots, should be the OR'ed value of *cadc_expansion_mux_selection_t*.

cadc_expansion_disabled_mux_slot_t disabledMuxSlot

mux slot to disabled in the scan.

struct *_cadc_converter_config*

#include <fsl_cadc.h> The structure for configuring each converter.

Public Members

uint16_t *u16ClockDivisor*

Converter's clock divisor for the clock source. Available setting range is 0-63.

- When the clockDivisor is 0, the divisor is 2.
- For all other clockDivisor values, the divisor is 1 more than the decimal value of clockDivisor: clockDivisor + 1

cadc_reference_voltage_source_t eHighReferenceVoltageSource

High voltage reference source.

cadc_reference_voltage_source_t eLowReferenceVoltageSource

Low reference voltage source.

`bool bEnableDMA`

Enable/Disable DMA.

`bool bPowerUp`

Power up or power down the converter.

`bool bScanInitBySync`

The member user to control the initiate method of the scan.

- **true** Use a SYNC input pulse or START command to initiate a scan.
- **false** Scan is initiated by the assertion of START command only.

`cadc_exp_mux_aux_config_t muxAuxConfig`

Configuration of expansion mux and auxiliary control.

`struct __cadc_config`

`#include <fsl_cadc.h>` The structure for configuring the Cyclic ADC's setting.

Public Members

`cadc_idle_work_mode_t eIdleWorkMode`

Idle work mode for the module.

`cadc_dma_trigger_source_t eDMATriggerSource`

Selects the dma trigger source for the module.

`uint16_t u16PowerUpDelay`

The number of ADC clocks to power up the converters (if powered up), before allowing a scan to start. The available range is 0 to 63 .

`uint32_t u32EnabledInterruptMask`

The mask of the interrupts to be enabled, should be the OR'ed value of `_cadc_interrupt_enable`.

`cadc_scan_mode_t eScanMode`

The scan mode of the module.

`cadc_sample_slot_disabled_t uDisabledSampleSlot`

The member used to config the which sample slot is disabled for the scan. The scan will continue until the first disabled sample slot is encountered.

`cadc_scan_control_t uScanControl`

Scan control provides the ability to pause and await a new sync signal while current sample completed.

`uint32_t u32ChannelModeMask`

The mask of each channel's mode, should be the OR'ed value of `cadc_channel_mode_t`. Each channel supports single-end and differential(Fully differentail and Unipolar differential). Some devices also support alternate source mode.

`cadc_channel_gain_t eChannelGain[(ADC_RSLT_COUNT)]`

The gain value for each channel. Each element of the array represents the gain of the channel. E.g. `eChannelGain[0]` means channel gain of channel0, which is ANA0.

`cadc_channel_number_t eSampleSlot[(ADC_RSLT_COUNT)]`

The channel assigned to each sample slot. The index of the array represents sample slot index.

cadc_converter_config_t sConverterA

The configuration for converterA.

cadc_converter_config_t sConverterB

The configuration for converterB.

2.2 The Driver Change Log

2.3 CADC Peripheral and Driver Overview

2.4 Clock Driver

enum *_clock_ip_name*

List of IP clock name.

Values:

enumerator kCLOCK_GPIOF

GPIOF clock

enumerator kCLOCK_GPIOE

GPIOE clock

enumerator kCLOCK_GPIOD

GPIOD clock

enumerator kCLOCK_GPIOC

GPIOC clock

enumerator kCLOCK_GPIOB

GPIOB clock

enumerator kCLOCK_GPIOA

GPIOA clock

enumerator kCLOCK_TA3

Timer A3 clock

enumerator kCLOCK_TA2

Timer A2 clock

enumerator kCLOCK_TA1

Timer A1 clock

enumerator kCLOCK_TA0

Timer A0 clock

enumerator kCLOCK_LPI2C0

LPI2C0 clock

enumerator kCLOCK_QSPI0

QSPI0 clock

enumerator kCLOCK_QSCI1

QSCI1 clock

enumerator kCLOCK_QSCI0

QSCI0 clock

enumerator kCLOCK_PIT2
PIT 2 clock

enumerator kCLOCK_PIT1
PIT 1 clock

enumerator kCLOCK_PIT0
PIT 0 clock

enumerator kCLOCK_QDC
QDC clock

enumerator kCLOCK_CRC
CRC clock

enumerator kCLOCK_CYCADC
Cyclic ADC clock

enumerator kCLOCK_CMPC
Comparator C clock

enumerator kCLOCK_CMPB
Comparator B clock

enumerator kCLOCK_CMPA
Comparator A clock

enumerator kCLOCK_PWMACH3
Enhanced Flexible PWM A3 clock

enumerator kCLOCK_PWMACH2
Enhanced Flexible PWM A2 clock

enumerator kCLOCK_PWMACH1
Enhanced Flexible PWM A1 clock

enumerator kCLOCK_PWMACH0
Enhanced Flexible PWM A0 clock

enumerator kCLOCK_OPAMPB
OPAMP B clock

enumerator kCLOCK_OPAMPA
OPAMP A clock

enumerator kCLOCK_NOGATE
Peripheral without clock gate control

enumerator kCLOCK_EDMA

enumerator kCLOCK_EWM

enumerator kCLOCK_XBARA

enumerator kCLOCK_NUM
Total IP clock number

enum _clock_name

List of system-level clock name.

Values:

enumerator kCLOCK_Mstr2xCk
Master 2x clock which feed to core and peripheral

enumerator kCLOCK_SysClk

MCU system/core clock

enumerator kCLOCK_BusClk

Bus clock

enumerator kCLOCK_Bus2xClk

Bus 2x clock

enumerator kCLOCK_FlashClk

Flash clock

enumerator kCLOCK_FastIrcClk

Fast internal RC oscillator, 8M/2M

enumerator kCLOCK_SlowIrcClk

Slow internal RC oscillator, 200K

enumerator kCLOCK_CrystalOscClk

Crystal oscillator

enumerator kCLOCK_ExtClk

The selected external clock, it could be crystal oscillator, clkin0, clkin1

enumerator kCLOCK_MstrOscClk

The selected master oscillator clock

enumerator kCLOCK_PllDiv2Clk

PLL output divide 2

enum _clock_crystal_osc_mode

Crystal oscillator mode.

Values:

enumerator kCLOCK_CrystalOscModeFSP

Full swing pierce, high power mode

enumerator kCLOCK_CrystalOscModeLCP

Loop controlled pierce, low power mode

enum _clock_ext_clk_src

List of external clock source.

Values:

enumerator kCLOCK_ExtClkSrcCrystalOsc

External clock source is crystal oscillator

enumerator kCLOCK_ExtClkSrcClkin

External clock source is clock in

enum _clock_ext_clkin_sel

List of clock-in source.

Values:

enumerator kCLOCK_SelClkIn0

Clock in 0 is selected as CLKIN

enumerator kCLOCK_SelClkIn1

Clock in 1 is selected as CLKIN

enum _clock_mstr_osc_clk_src

List of master oscillator source.

Values:

enumerator kCLOCK_MstrOscClkSrcFirc
8M/2M, fast internal RC oscillator

enumerator kCLOCK_MstrOscClkSrcExt
External clock

enumerator kCLOCK_MstrOscClkSrcSirc
200K, slow internal RC oscillator

enum _clock_mstr_2x_clk_src

List of master 2x clock source.

Values:

enumerator kCLOCK_Mstr2xClkSrcMstrOsc
Master oscillator clock

enumerator kCLOCK_Mstr2xClkSrcPlldiv2
PLL output divide 2

enum _clock_output_clk_src

List of output clock source.

Values:

enumerator kCLOCK_OutputClkSrc_Sys
MCU system/core clock

enumerator kCLOCK_OutputClkSrc_Mstr2x
Master 2x clock

enumerator kCLOCK_OutputClkSrc_BusDiv2
Bus clock div 2

enumerator kCLOCK_OutputClkSrc_MstrOSC
Master oscillator clock

enumerator kCLOCK_OutputClkSrc_Firc
Fast IRC clock, 8M/2M

enumerator kCLOCK_OutputClkSrc_Sirc
Slow IRC clock, 200K

enum _clock_output_clk_div

List of output clock divider.

Values:

enumerator kCLOCK_OutputDiv1
output clock = selectedClock/1U

enumerator kCLOCK_OutputDiv2
output clock = selectedClock/2U

enumerator kCLOCK_OutputDiv4
output clock = selectedClock/4U

enumerator kCLOCK_OutputDiv8
output clock = selectedClock/8U

enumerator kCLOCK_OutputDiv16
output clock = selectedClock/16U

enumerator kCLOCK_OutputDiv32
output clock = selectedClock/32U

enumerator kCLOCK_OutputDiv64
output clock = selectedClock/64U

enumerator kCLOCK_OutputDiv128
output clock = selectedClock/128U

enum _clock_protection

List of clock register protection mode.

Values:

enumerator kCLOCK_Protection_Off
No protection, and could be changed any time

enumerator kCLOCK_Protection_On
Protected, and could be changed any time

enumerator kCLOCK_Protection_OffLock
No protection and get locked until chip reset

enumerator kCLOCK_Protection_OnLock
Protected and get locked until chip reset

enum _clock_ip_clk_src

List of specific IP's clock source.

Values:

enumerator kCLOCK_IPClkSrc_BusClk
Bus clock

enumerator kCLOCK_IPClkSrc_Bus2xClk
Bus 2x clock

enum _clock_firc_sel

Fast IRC selection.

Values:

enumerator kCLOCK_FircSel_8M
FIRC normal mode, output 8M

enumerator kCLOCK_FircSel_2M
FIRC standby mode, output 2M

enum _clock_mode

MCU working mode selection.

Values:

enumerator kCLOCK_Mode_Normal
Normal mode, bus:flash clock rate = 2:1

enumerator kCLOCK_Mode_Fast
Fast mode, bus:flash clock rate = 4:1

enum _clock_postsacle

Mstr 2x clock postsacle divider.

Values:

enumerator kCLOCK_PostscaleDiv1

Mast 2X clock = clkSrc / 1

enumerator kCLOCK_PostscaleDiv2

Mast 2X clock = clkSrc / 2

enumerator kCLOCK_PostscaleDiv4

Mast 2X clock = clkSrc / 4

enumerator kCLOCK_PostscaleDiv8

Mast 2X clock = clkSrc / 8

enumerator kCLOCK_PostscaleDiv16

Mast 2X clock = clkSrc / 16

enumerator kCLOCK_PostscaleDiv32

Mast 2X clock = clkSrc / 32

enumerator kCLOCK_PostscaleDiv64

Mast 2X clock = clkSrc / 64

enumerator kCLOCK_PostscaleDiv128

Mast 2X clock = clkSrc / 128

enumerator kCLOCK_PostscaleDiv256

Mast 2X clock = clkSrc / 256

enum _clock_pll_monitor_type

PLL monitor type structure.

Values:

enumerator kCLOCK_PllMonitorUnLockCoarse

PLL coarse unlock, due to loss of reference clock, power unstable...etc.

enumerator kCLOCK_PllMonitorUnLockFine

PLL fine unlock, due to loss of reference clock, power unstable...etc.

enumerator kCLOCK_PllMonitorLostofReferClk

PLL lost reference clock.

enumerator kCLOCK_PllMonitorAll

All PLL monitor type.

enum _pit_count_clock_source

Describes PIT clock source.

Values:

enumerator kPIT_CountClockSource0

PIT count clock sourced from IP bus clock

enumerator kPIT_CountClockSource1

PIT count clock sourced from alternate clock 1

enumerator kPIT_CountClockSource2

PIT count clock sourced from alternate clock 2

enumerator kPIT_CountClockSource3

PIT count clock sourced from alternate clock 3

enumerator kPIT_CountBusClk

PIT count clock sourced from bus clock

enumerator kPIT_CountCrystalOscClk

PIT count clock sourced from crystal clock

enumerator kPIT_CountFircClk

PIT count clock sourced from fast IRC(8M/2M) clock

enumerator kPIT_CountSircClk

PIT count clock sourced from slow IRC(200KHz) clock

enum _ewm_lpo_clock_source

Describes EWM clock source.

Values:

enumerator kEWM_LpoClockSource0

EWM clock sourced from lpo_clk[0]

enumerator kEWM_LpoClockSource1

EWM clock sourced from lpo_clk[1]

enumerator kEWM_LpoClockSource2

EWM clock sourced from lpo_clk[2]

enumerator kEWM_LpoClockSource3

EWM clock sourced from lpo_clk[3]

enumerator kEWM_Lpo8MHz2MHzIRCClock

EWM clock sourced from 8MHz/2MHz IRC clock

enumerator kEWM_LpoCrystalClock

EWM clock sourced from crystal clock

enumerator kEWM_LpoBusClock

EWM clock sourced from IP Bus clock

enumerator kEWM_Lpo200KHzIRCClock

EWM clock sourced from 200KHz IRC clock

typedef enum _clock_ip_name clock_ip_name_t

List of IP clock name.

typedef enum _clock_name clock_name_t

List of system-level clock name.

typedef enum _clock_crystal_osc_mode clock_crystal_osc_mode_t

Crystal oscillator mode.

typedef enum _clock_ext_clk_src clock_ext_clk_src_t

List of external clock source.

typedef enum _clock_ext_clkin_sel clock_ext_clkin_sel_t

List of clock-in source.

typedef enum _clock_mstr_osc_clk_src clock_mstr_osc_clk_src_t

List of master oscillator source.

```
typedef enum _clock_mstr_2x_clk_src clock_mstr_2x_clk_src_t
```

List of master 2x clock source.

```
typedef enum _clock_output_clk_src clock_output_clk_src_t
```

List of output clock source.

```
typedef enum _clock_output_clk_div clock_output_clk_div_t
```

List of output clock divider.

```
typedef enum _clock_protection clock_protection_t
```

List of clock register protection mode.

```
typedef enum _clock_ip_clk_src clock_ip_clk_src_t
```

List of specific IP's clock source.

```
typedef enum _clock_firc_sel clock_firc_sel_t
```

Fast IRC selection.

```
typedef enum _clock_mode clock_mode_t
```

MCU working mode selection.

```
typedef enum _clock_postscale clock_postscale_t
```

Mstr 2x clock postscale divider.

```
typedef struct _clock_protection_config clock_protection_config_t
```

Clock register protection configuration.

```
typedef struct _clock_output_config clock_output_config_t
```

Clock output configuration.

```
typedef struct _clock_config clock_config_t
```

mcu clock configuration structure.

This is the key configuration structure of clock driver, which define the system clock behavior. The function `CLOCK_SetClkConfig` deploy this configuration structure onto SOC.

```
typedef enum _clock_pll_monitor_type clock_pll_monitor_type_t
```

PLL monitor type structure.

```
typedef enum _pit_count_clock_source pit_count_clock_source_t
```

Describes PIT clock source.

```
typedef enum _ewm_lpo_clock_source ewm_lpo_clock_source_t
```

Describes EWM clock source.

```
static inline void CLOCK_EnableClock(clock_ip_name_t eIpClkName)
```

Enable IPs clock.

Parameters

- eIpClkName – IP clock name.

```
static inline void CLOCK_DisableClock(clock_ip_name_t eIpClkName)
```

Disable IPs clock.

Parameters

- eIpClkName – IP clock name.

```
static inline void CLOCK_EnableClockInStopMode(clock_ip_name_t eIpClkName)
```

Enable IPs clock in STOP mode.

Parameters

- eIpClkName – IP clock name.

```
static inline void CLOCK_DisableClockInStopMode(clock_ip_name_t eIpClkName)
```

Disable IPs clock in STOP mode.

Parameters

- eIpClkName – IP clock name.

```
static inline void CLOCK_ConfigQsciClockSrc(clock_ip_name_t eQsciClkName, clock_ip_clk_src_t  
eClkSrc)
```

Configure QSCI clock source.

QSCI clock could be bus or bus_2x clock. Default is bus clock.

Parameters

- eQsciClkName – IP(only QSCI is valid) clock name.
- eClkSrc – Clock source.

```
static inline void CLOCK_ConfigI2cClockSrc(clock_ip_clk_src_t eClkSrc)
```

Configure LPI2C clock source.

LPI2C clock could be bus or bus_2x clock. Default is bus clock.

Parameters

- eClkSrc – Clock source.

```
static inline void CLOCK_SetSlowIrcTrim(uint16_t u16Trim)
```

Set trim value to 200K slow internal RC oscillator.

The factory trim value is loaded during reset. User may call this function to fine tune the 200K IRC oscillator.

Parameters

- u16Trim – Slow internal RC oscillator trim value.

```
static inline void CLOCK_SetFastIrc8MTrim(uint16_t u16Trim)
```

Set trim value to fast internal RC 8M oscillator.

The factory trim value is loaded during reset. User may call this function to fine tune the FIRC 8M oscillator.

Parameters

- u16Trim – Fast internal 8M RC oscillator trim value. Check OSCTL3 register for u16Trim format.

```
static inline void CLOCK_SetFastIrc2MTrim(uint16_t u16Trim)
```

Set trim value to fast internal RC 2M oscillator.

The factory trim value is loaded during reset. User may call this function to fine tune the FIRC 2M oscillator.

Parameters

- u16Trim – Fast internal 2M RC oscillator trim value. Check OSCTL4 register for u16Trim format.

```
static inline bool CLOCK_GetCrystalOscFailureStatus(void)
```

Get crystal oscillator failure status.

Note: This function should be called only when crystal osc is on and its monitor(MON_ENABLE in OSCTL2 register) is enabled.

Returns

Crystal oscillator status. true: Crystal oscillator frequency is below 680KHz(typical). false: No clock failure or crystal oscillator is off.

static inline void CLOCK_SetPllLossOfRefererntTripPoint(uint8_t u8Trip)

Set PLL loss of reference trip point.

The trip point default value is 2.

Parameters

- u8Trip – Trip point for loss of reference.

static inline void CLOCK_ClearPLLMonitorFlag(*clock_pll_monitor_type_t* eType)

Clear PLL monitor flag.

Parameters

- eType – PLL monitor type.

static inline void CLOCK_EnableFircOutput(bool bEnable)

Enable/Disable FIRC output.

Note: It is not allowed to disable FIRC output when FIRC is selected as master osc clock source. Note: Disable FIRC output doesn't turn off FIRC, FIRC still works but its output is cut off. Note: For the case FIRC is powered on and output disabled, enable FIRC output doesn't require startup time.

Parameters

- bEnable – Enable or disable output.

uint32_t CLOCK_GetFreq(*clock_name_t* eClkName)

Get system-level clock frequency.

Parameters

- eClkName – System-level clock name.

Returns

The required clock's frequency in Hz.

uint32_t CLOCK_GetIpClkSrcFreq(*clock_ip_name_t* eIpClkName)

Get IP clock frequency.

Parameters

- eIpClkName – IP clock name.

Returns

The required IP clock's frequency in Hz.

void CLOCK_SetClkin0Freq(uint32_t u32Freq)

Set Clock IN 0 frequency.

It is a must to call this function in advance if system is operated by clkin0.

Parameters

- u32Freq – Clock IN 0 frequency in Hz.

void CLOCK_SetClkin1Freq(uint32_t u32Freq)

Set Clock IN 1 frequency.

It is a must to call this function in advance if system is operated by clkin1.

Parameters

- u32Freq – Clock IN 1 frequency in Hz.

`void CLOCK_SetXtalFreq(uint32_t u32Freq)`

Set crystal oscillator frequency.

It is a must to call this function in advance if system is operated by crystal oscillator.

Parameters

- `u32Freq` – Crystal oscillator frequency in Hz.

`void CLOCK_SetProtectionConfig(clock_protection_config_t *psConfig)`

Config clock register access protection mode.

Parameters

- `psConfig` – Pointer for protection configuration.

`void CLOCK_SetOutputClockConfig(clock_output_config_t *psConfig)`

Config output clock.

Parameters

- `psConfig` – Pointer for clock output configuration.

`void CLOCK_SetClkConfig(clock_config_t *psConfig)`

Config mcu operation clock.

Parameters

- `psConfig` – Pointer for clock configuration.

`uint32_t CLOCK_EvaluateExtClkFreq(void)`

Evaluate external clock frequency and return its frequency in Hz.

This function should be called only when internal FIRC is on and 8M is selected. The evaluated result accuracy depends on:

- a. FIRC accuracy, now it is +/-3% for full temperature range.
- b. Truncation error, because the external clock and FIRC is not synchronised.
- c. External clock frequency, low accuracy for lower external clock frequency.
- d. MCU mstr 2x clock.

For example, for namely 8M external clock, evaluated result may be range in 8M+/-7%.

Returns

Evaluated external frequency in Hz.

`void CLOCK_EnablePLLMonitorInterrupt(clock_pll_monitor_type_t eType, bool bEnable)`

Enable/Disable PLL monitor interrupt.

This function should be called only when PLL is on and its reference clock is external clock. This function is for safety purpose when external clock is lost due to HW failure. The normal flow to call this function:

- a. Call `CLOCK_SetClkConfig` to enable PLL and external clock to feed the PLL.
- b. Call `CLOCK_ClearPLLMonitorFlag`.
- c. Call `CLOCK_SetPllLossofRefererntTripPoint` (optional, setting value is for `kCLOCK_PllMonitorLostofReferClk` type).
- d. Call this function.
- e. Enable OCCS interrupt with highest priority 3.
- f. When OCCS interrupt occurs, recover clock from the disaster in `OCCS_DriveISRHandler` function. Such kind of clock recovery is application dependent, and a demo `OCCS_DriveISRHandler` has been shown in `fsl_clock.c`

Parameters

- eType – PLL monitor type.
- bEnable – Enable or disable.

FSL_CLOCK_DRIVER_VERSION

CLOCK driver version 2.0.0.

SDK_DEVICE_MAXIMUM_CPU_CLOCK_FREQUENCY

Definition for delay API in clock driver, users can redefine it.

GPIO_CLOCKS

Clock ip name array for GPIO.

TMR_CLOCKS

Clock ip name array for quad timer.

LPI2C_CLOCKS

Clock ip name array for LPI2C.

QSPI_CLOCKS

Clock ip name array for queued SPI.

QSCI_CLOCKS

Clock ip name array for queued SCI.

PIT_CLOCKS

Clock ip name array for PIT.

QDC_CLOCKS

Clock ip name array for QDC.

CRC_CLOCKS

Clock ip name array for CRC.

CADC_CLOCKS

Clock ip name array for cyclic ADC.

CMP_CLOCKS

Clock ip name array for CMP.

PWM_CLOCKS

Clock ip name array for PWM.

OPAMP_CLOCKS

Clock ip name array for OPAMP.

EDMA_CLOCKS

Clock ip name array for EDMA.

EWM_CLOCKS

Clock ip name array for EWM.

XBARA_CLOCKS

Clock ip name array for XBARA.

CLK_GATE_GET_REG_INDEX(x)

CLK_GATE_GET_BIT_INDEX(x)

clock_protection_t eFrqEP

FRQEP bit field in OCCS PROT register, protect COD & ZSRC.

clock_protection_t eOscEP

OSCEP bit field in OCCS PROT register, protect OSCTL1, OSCTL2, OSCTL3, OSCTL4, PRECS.

clock_protection_t ePllep

PLLEP bit field in OCCS PROT register, protect PLLDP, LOCIE, LORTP, PLLDB bitfield.

bool bClkOut0En

Clock output 0 enable, CLKDIS0 bit field in SIM CLKOUT register

bool bClkOut1En

Clock output 1 enable, CLKDIS1 bit field in SIM CLKOUT register

clock_output_clk_src_t eClkOut0Src

Clock output 0 clock source, CLKOSL0 bit field in SIM CLKOUT register

clock_output_clk_src_t eClkOut1Src

Clock output 1 clock source, CLKOSL1 bit field in SIM CLKOUT register

clock_output_clk_div_t eClkDiv

Clock output divider, CLKODIV bit field in SIM CLKOUT register ,it apply to clkout0 & clkout1

bool bCrystalOscEnable

Crystal oscillator enable, COPD bit field in OCCS OSCTL2 register

bool bFircEnable

Fast internal RC oscillator enable, ROPD bit field in OCCS OSCTL1 register

bool bSircEnable

Slow internal RC oscillator enable, ROPD200K bit field in OCCS OSCTL2 register

bool bPllep

PLL enable, PLLPD bit field in OCCS CTRL register

bool bCrystalOscMonitorEnable

Crystal oscillator monitor enable, MON_ENABLE bit field in OCCS OSCTL2 register

clock_firc_sel_t eFircSel

Fast IRC mode selection, 8M or 2M, ROSB bit field in OCCS OSCTL1 register

clock_crystal_osc_mode_t eCrystalOscMode

Crystal oscillator mode, COHL bit field in OCCS OSCTL1 register

clock_ext_clk_src_t eExtClkSrc

External clock source, EXT_SEL bit field in OCCS OSCTL1 register

clock_ext_clkin_sel_t eClkInSel

Clock IN selection(0 or 1), CLKINSEL bit field in SIM MISC0 register

clock_mstr_osc_clk_src_t eMstrOscClkSrc

Master oscillator selection, PRECS bit field in OCCS CTRL register. When selected kCLOCK_MstrOscClkSrcExt, make sure corresponding pins(crystal osc or clkin pin) has been configured.

clock_mstr_2x_clk_src_t eMstr2xClkSrc

Master 2x clock selection, ZSRC bit field in OCCS CTRL register

clock_postscale_t eMstr2xClkPostScale

Master 2x clock post scale, COD bit field in OCCS DIVBY register

uint32_t u32PllepFreq

Required PLL output frequency before divide 2

FSL_SDK_DISABLE_DRIVER_CLOCK_CONTROL

Configure whether driver controls clock.

When set to 0, peripheral drivers will enable clock in initialize function and disable clock in de-initialize function. When set to 1, peripheral driver will not control the clock, application could control the clock out of the driver.

Note: All drivers share this feature switcher. If it is set to 1, application should handle clock enable and disable for all drivers.

struct _clock_protection_config

#include <fsl_clock.h> Clock register protection configuration.

struct _clock_output_config

#include <fsl_clock.h> Clock output configuration.

struct _clock_config

#include <fsl_clock.h> mcu clock configuration structure.

This is the key configuration structure of clock driver, which define the system clock behavior. The function CLOCK_SetClkConfig deploy this configuration structure onto SOC.

2.5 Driver Change Log

2.6 CMP: Comparator Driver

void CMP_GetDefaultConfig(*cmp_config_t* *psConfig)

Initializes the CMP user configuration structure.

This function initializes the user configuration structure to the default values. It is corresponding to the continuous mode configurations.

Parameters

- psConfig – pointer of *cmp_config_t*.

void CMP_Init(CMP_Type *base, const *cmp_config_t* *psConfig)

Initializes the CMP.

This function initializes the CMP module. The operations included are as follows.

- Enable the clock for CMP module.
- Configure the comparator according to the CMP configuration structure.

Parameters

- base – CMP peripheral base address.
- psConfig – Pointer to the configuration structure.

void CMP_Deinit(CMP_Type *base)

De-initializes the CMP module.

This function de-initializes the CMP module. The operations included are as follows.

- Disabling the CMP module.
- Disabling the clock for CMP module.

Parameters

- `base` – CMP peripheral base address.

static inline void CMP_Enable(CMP_Type *base, bool bEnable)

Enables/disables the CMP module.

Parameters

- `base` – CMP peripheral base address.
- `bEnable` – Enables or disables the module.

static inline void CMP_SetInputChannel(CMP_Type *base, cmp_input_mux_t ePlusChannel, cmp_input_mux_t eMinusChannel)

Sets the input channels for the comparator.

This function sets the input channels for the comparator. Note that two input channels cannot be set the same way in the application. When the user selects the same input from the analog mux to the positive and negative port, the comparator is disabled automatically.

Parameters

- `base` – CMP peripheral base address.
- `ePlusChannel` – Plus side input channel number.
- `eMinusChannel` – Minus side input channel number.

static inline void CMP_SelectOutputSource(CMP_Type *base, cmp_output_source_t eOutputSource)

Select comparator output source.

Parameters

- `base` – CMP peripheral base address.
- `eOutputSource` – The output signal to be set, please reference `cmp_output_source_t` for details.

static inline void CMP_EnableOuputPin(CMP_Type *base, bool bEnable)

Enable/Disable Comparator output pin.

Parameters

- `base` – CMP peripheral base address.
- `bEnable` – Enable/Disable comparator output pin. `true` — CMPO is available on the associate CMPO output pin. `false` — CMPO is not available on the associate CMPO output pin.

static inline uint8_t CMP_GetComparatorOutput(CMP_Type *base)

Get Comparator output.

Parameters

- `base` – CMP peripheral base address.

Return values

`current` – analog comparator output 0 or 1

static inline void CMP_SetHysteresisLevel(CMP_Type *base, cmp_hysteresis_level_t eHysteresisLevel)

Sets hysteresis level.

Parameters

- `base` – CMP peripheral base address.
- `eHysteresisLevel` – The programmable hysteresis level to be set, please refer to `cmp_hysteresis_level_t` for details.

```
static inline void CMP_SetComparasionSpeedMode(CMP_Type *base,  
                                              cmp_comparasion_speed_mode_t  
                                              eComparatorSpeedMode)
```

Sets comparison speed mode.

Parameters

- base – CMP peripheral base address.
- eComparatorSpeedMode – The comparison speed mode, please reference `cmp_comparasion_speed_mode_t` for details.

```
static inline void CMP_EnableInvertOutput(CMP_Type *base, bool bEnable)
```

Enable/Disable comparator invert feature.

Parameters

- base – CMP peripheral base address.
- bEnable – Enable/Disable comparator invert feature. `true` — Inverts the comparator output. `false` — Does not invert the comparator output.

```
static inline void CMP_EnableWindow(CMP_Type *base, bool bEnable)
```

Enable the window function.

Parameters

- base – CMP peripheral base address.
- bEnable – `true` is enable, `false` is disable.

```
static inline void CMP_SetWindowOutputMode(CMP_Type *base, cmp_window_output_mode_t  
                                           eWindowOutputMode)
```

Set the window output mode.

Parameters

- base – CMP peripheral base address.
- eWindowOutputMode – `cmp_window_output_mode_t`.

```
static inline void CMP_EnableExternalSampleMode(CMP_Type *base, bool bEnable)
```

Enable/Disable external Sample mode.

Parameters

- base – CMP peripheral base address.
- bEnable – `true` is using external sample mode, `false` is using interface sample mode.

```
static inline void CMP_SetExternalSampleCount(CMP_Type *base, cmp_external_sample_count_t  
                                              eSampleCount)
```

Sets external sample count.

Parameters

- base – CMP peripheral base address.
- eSampleCount – The number of consecutive samples that must agree prior to the comparator output filter accepting a new output state, `cmp_external_sample_count_t`.

```
static inline void CMP_SetInternalFilterCount(CMP_Type *base, cmp_filter_count_t eFilterCount)
```

Sets internal filter count.

Parameters

- `base` – CMP peripheral base address.
- `eFilterCount` – The number of consecutive samples that must agree prior to the comparator output filter accepting a new output state, `cmp_filter_count_t`.

static inline void `CMP_SetInternalFilterPeriod(CMP_Type *base, uint8_t u8FilterPeriod)`

Sets the internal filter period. It is used as the divider to bus clock.

Parameters

- `base` – CMP peripheral base address.
- `u8FilterPeriod` – Filter Period. The divider to the bus clock. Available range is 0-255.

void `CMP_SetDACConfig(CMP_Type *base, const cmp_dac_config_t *psConfig)`

Configures the internal DAC.

Parameters

- `base` – CMP peripheral base address.
- `psConfig` – Pointer to the configuration structure.

static inline void `CMP_SetDACOutputVoltage(CMP_Type *base, uint8_t u8OutputVoltageDivider)`

Sets DAC output voltage.

Parameters

- `base` – CMP peripheral base address.
- `u8OutputVoltageDivider` – The digital value which is related to the desired DAC output voltage,

static inline void `CMP_EnableInternalDAC(CMP_Type *base, bool bEnable)`

Enable/Disable internal DAC.

Parameters

- `base` – CMP peripheral base address.
- `bEnable` – Enable/Disable internal DAC. `true` Enable internal DAC. `false` Disable internal DAC.

static inline void `CMP_SetDACReferenceVoltageSource(CMP_Type *base, cmp_dac_vref_source_t eDACVrefSource)`

Sets internal DAC's reference voltage source.

Parameters

- `base` – CMP peripheral base address.
- `eDACVrefSource` – reference voltage source, please `cmp_dac_vref_source_t`

static inline void `CMP_EnableInterrupt(CMP_Type *base, cmp_interrupt_request_t eInterruptRequest)`

Interrupt request to enable.

Parameters

- `base` – CMP peripheral base address.
- `eInterruptRequest` – Mask value for interrupts. See `cmp_interrupt_request_t`.

static inline *cmp_output_flag_t* CMP_GetStatusFlags(CMP_Type *base)

Gets the status flags.

Parameters

- base – CMP peripheral base address.

Return values

Mask – value for the asserted flags. *cmp_output_flag_t*.

static inline void CMP_ClearStatusFlags(CMP_Type *base, *cmp_output_flag_t* eOutputFlag)

Clears the status flags.

Parameters

- base – CMP peripheral base address.
- eOutputFlag – Mask value for the output flags, *cmp_output_flag_t*

static inline void CMP_EnableDMA(CMP_Type *base, *cmp_dma_request_t* eDMARequestType)

Enables CMP DMA request.

Parameters

- base – CMP peripheral base address.
- eDMARequestType – eDMA request type, *cmp_dma_request_t*

static inline uint32_t CMP_GetComparatorResultRegisterAddress(CMP_Type *base)

Get CMP result register address for DMA access.

Parameters

- base – CMP peripheral base address.

Returns

The CMP result register address.

FSL_CMP_DRIVER_VERSION

CMP driver version.

enum *_cmp_interrupt_request*

CMP Interrupt request type definition.

Values:

enumerator kCMP_InterruptRequestDisabled
interrupt disabled

enumerator kCMP_InterruptRequestEnableOutputRisingEdge
Comparator interrupt request enable rising edge.

enumerator kCMP_InterruptRequestEnableOutputFallingEdge
Comparator interrupt request enable falling edge.

enumerator kCMP_InterruptRequestEnableAll
comparator interrupt request enable on rising edge or falling edge

enum *_cmp_dma_request*

CMP DMA request type definition.

Values:

enumerator kCMP_DMAResultRequestDisabled
DMA disabled

enumerator kCMP_DMAResultRequestEnableOutputRisingEdge
Comparator dma request enable on rising edge.

enumerator kCMP_DMARequestEnableOutputFallingEdge

Comparator dma request enable on falling edge.

enumerator kCMP_DMARequestEnableAll

comparator dma request enable on rising edge or falling edge

enum _cmp_output_flag

CMP output flags' mask.

Values:

enumerator kCMP_OutputFlagRisingEdge

Rising-edge on the comparison output has occurred.

enumerator kCMP_OutputFlagFallingEdge

Falling-edge on the comparison output has occurred.

enumerator kCMP_OutputFlagBothEdge

Rising-edge and Falling-edge on the comparison output has occurred.

enum _cmp_hysteresis_level

CMP Hysteresis level.

Values:

enumerator kCMP_HysteresisLevel0

Hysteresis level 0.

enumerator kCMP_HysteresisLevel1

Hysteresis level 1.

enumerator kCMP_HysteresisLevel2

Hysteresis level 2.

enumerator kCMP_HysteresisLevel3

Hysteresis level 3.

enum _cmp_comparasion_speed_mode

CMP compassion speed mode enumerator.

Values:

enumerator kCMP_ComparsionModeLowSpeed

Low-Speed Comparison mode has lower current consumption

enumerator kCMP_ComparsionModeHighSpeed

High-Speed Comparison mode has higher current consumption.

enum _cmp_dac_vref_source

CMP DAC Voltage Reference source.

Values:

enumerator kCMP_DACVrefSourceVin1

Vin1 is selected as a resistor ladder network supply reference Vin.

enumerator kCMP_DACVrefSourceVin2

Vin2 is selected as a resistor ladder network supply reference Vin.

enum _cmp_window_output_mode

CMP output value of window.

Values:

enumerator kCMP_WindowOutputLastLatchedValue

When WINDOW signal changes from 1 to 0, COUTA output holds the last latched value before WINDOW signal falls to 0

enumerator kCMP_WindowOutputZeroValue

When WINDOW signal changes from 1 to 0, COUTA output is forced to 0

enum _cmp_filter_count

CMP filter count.

Values:

enumerator kCMP_FilterCountDisable

filter is disabled

enumerator kCMP_FilterCount1

1 sample must agrees, the comparator output is simply sampled

enumerator kCMP_FilterCount2

2 consecutive samples must agrees

enumerator kCMP_FilterCount3

3 consecutive samples must agrees

enumerator kCMP_FilterCount4

4 consecutive samples must agrees

enumerator kCMP_FilterCount5

5 consecutive samples must agrees

enumerator kCMP_FilterCount6

6 consecutive samples must agrees

enumerator kCMP_FilterCount7

7 consecutive samples must agrees

enum _cmp_external_sample_count

CMP external sample count.

Values:

enumerator kCMP_ExternalSampleCount1

1 sample must agrees, the comparator output is simply sampled

enumerator kCMP_ExternalSampleCount2

2 consecutive samples must agrees

enumerator kCMP_ExternalSampleCount3

3 consecutive samples must agrees

enumerator kCMP_ExternalSampleCount4

4 consecutive samples must agrees

enumerator kCMP_ExternalSampleCount5

5 consecutive samples must agrees

enumerator kCMP_ExternalSampleCount6

6 consecutive samples must agrees

enumerator kCMP_ExternalSampleCount7

7 consecutive samples must agrees

enum *_cmp_output_source*

CMP output source enumerator.

Values:

enumerator *kCMP_OutputSourceFromFilterCOUT*

Set the filtered comparator output to equal COUT.

enumerator *kCMP_OutputSourceFromUnfilteredCOUTA*

Set the unfiltered comparator output to equal COUTA.

enum *_cmp_work_mode*

CMP work mode definition.

Values:

enumerator *kCMP_WorkModeWindowBypassAndNoExternalSample*
window block bypassed, external sampling mode disabled

enumerator *kCMP_WorkModeWindowBypassAndExternalSample*
window block bypassed, external SAMPLE mode enable

enumerator *kCMP_WorkModeWindowEnabledAndNoExternalSample*
window block enabled, external sampling mode disabled

typedef enum *_cmp_interrupt_request* *cmp_interrupt_request_t*

CMP Interrupt request type definition.

typedef enum *_cmp_dma_request* *cmp_dma_request_t*

CMP DMA request type definition.

typedef enum *_cmp_output_flag* *cmp_output_flag_t*

CMP output flags' mask.

typedef enum *_cmp_hysteresis_level* *cmp_hysteresis_level_t*

CMP Hysteresis level.

typedef enum *_cmp_comparasion_speed_mode* *cmp_comparasion_speed_mode_t*

CMP compassion speed mode enumerator.

typedef enum *_cmp_dac_vref_source* *cmp_dac_vref_source_t*

CMP DAC Voltage Reference source.

typedef enum *_cmp_window_output_mode* *cmp_window_output_mode_t*

CMP output value of window.

typedef enum *_cmp_filter_count* *cmp_filter_count_t*

CMP filter count.

typedef enum *_cmp_external_sample_count* *cmp_external_sample_count_t*

CMP external sample count.

typedef enum *_cmp_output_source* *cmp_output_source_t*

CMP output source enumerator.

typedef enum *_cmp_work_mode* *cmp_work_mode_t*

CMP work mode definition.

typedef struct *_cmp_dac_config* *cmp_dac_config_t*

CMP internal DAC configuration structure.


```
typedef union _cmp_dma_interrupt_config cmp_dma_interrupt_config_t  
    CMP dma/interrupt configure union.
```

Note: , the interrupt request and dma request cannot be used at the same time, that is to say When DMA support is enabled by setting SCR[DMAEN] and the interrupt is enabled by setting SCR[IER], SCR[IEF], or both, the corresponding change on COUT forces a DMA transfer request rather than a CPU interrupt instead

```
typedef struct _cmp_config cmp_config_t  
    CMP configuration structure.
```

```
struct _cmp_dac_config  
    #include <fsl_cmp.h> CMP internal DAC configuration structure.
```

Public Members

cmp_dac_vref_source_t eDACVrefSource
 DAC reference voltage source.

uint8_t u8DACOutputVoltageDivider
 divider Value for the DAC Output Voltage, DAC output voltage = (VREF / 256) * (u8DACOutputVoltageDivider + 1).

bool bEnableInternalDAC
 flag to control if the internal DAC need to be enabled

```
union _cmp_dma_interrupt_config  
    #include <fsl_cmp.h> CMP dma/interrupt configure union.
```

Note: , the interrupt request and dma request cannot be used at the same time, that is to say When DMA support is enabled by setting SCR[DMAEN] and the interrupt is enabled by setting SCR[IER], SCR[IEF], or both, the corresponding change on COUT forces a DMA transfer request rather than a CPU interrupt instead

Public Members

cmp_dma_request_t eDMARequest
 dma request type

cmp_interrupt_request_t eInterruptRequest
 interrupt request type

```
struct _cmp_config  
    #include <fsl_cmp.h> CMP configuration structure.
```

Public Members

cmp_hysteresis_level_t eHysteresisLevel
 CMP hysteresis level

cmp_comparasion_speed_mode_t eComparasionSpeedMode
 CMP comparison speed mode

cmp_work_mode_t eWorkMode

CMP work mode

cmp_input_mux_t ePlusInput

CMP plus input mux, the definition of this enum is in soc header file

cmp_input_mux_t eMinusInput

CMP minus input mux, the definition of this enum is in soc header file

cmp_dac_config_t sDacConfig

CMP internal DAC configuration structure *cmp_dac_config_t*

bool bInvertComparatorOutputPolarity

Inverted comparator output polarity.

cmp_window_output_mode_t eWindowOutputMode

only works when cmp work mode is kCMP_WorkModeWindowEnabledAndNoExternalSample

cmp_filter_count_t eFilterCount

Filter Count. Available range is 0-7, 0 is disable internal filter can be used in internal sampling mode only.

uint8_t u8FilterPeriod

Filter Period. The divider to the bus clock. Available range is 0-255, can be used in internal sampling mode. When the filter clock from internal divided bus clock, setting the sample period to 0 will disable the filter

cmp_external_sample_count_t eExternalSampleCount

Available range is 1 - 7, used in external sampling mode only

cmp_output_source_t eOutputSource

cmp output source

bool bEnableOutputPin

the comparator output(CMPO) is driven out on the associated CMPO output pin

cmp_dma_interrupt_config_t uDmaInterruptConfig

CMP interrupt/dma configuration

bool bCMPEnable

flag to control if CMP module start immediately when the configuration is done

2.7 The Driver Change Log

2.8 CMP Peripheral and Driver Overview

2.9 COP: Computer Operating Properly(Watchdog) Driver

void COP_Init(COP_Type *base, const *cop_config_t* *psConfig)

Initializes the COP module with input configuration.

Call this function to do initialization configuration for COP module. The configurations are:

- COP configuration write protect enablement
- Clock source selection for COP module
- Prescaler configuration to the input clock source

- Counter timeout value
- Window value
- WAIT/STOP work mode enablement
- Interrupt enable/disable and interrupt timing value
- Loss of reference counter enablement
- COP enable/disable

note: Once set `bEnableWriteProtect=true`, the CTRL, INTVAL, WINDOW and TOUT registers are read-only.

Parameters

- base – COP peripheral base address.
- psConfig – The pointer to COP configuration structure, `cop_config_t`.

`void COP_GetDefaultConfig(cop_config_t *psConfig)`

Prepares an available pre-defined setting for module's configuration.

This function initializes the COP configuration structure to default values.

```
psConfig->bEnableWriteProtect = false;
psConfig->bEnableWait = false;
psConfig->bEnableStop = false;
psConfig->bEnableLossOfReference = false;
psConfig->bEnableInterrupt = false;
psConfig->bEnableCOP = false;
psConfig->ePrescaler = kCOP_ClockPrescalerDivide1;
psConfig->u16TimeoutCount = 0xFFFFU;
psConfig->u16WindowCount = 0xFFFFU;
psConfig->u16InterruptCount = 0xFFU;
psConfig->eClockSource = kCOP_RoscClockSource;
```

Parameters

- psConfig – Pointer to the COP configuration structure, `cop_config_t`.

`static inline void COP_Enable(COP_Type *base, bool bEnable)`

Enable/Disable the COP module.

This function disables the COP Watchdog. To disable the COP Watchdog, call `COP_Enable(base, false)`.

Parameters

- base – COP peripheral base address.
- bEnable – Enable the feature or not.

`static inline void COP_EnableLossOfReferenceCounter(COP_Type *base, bool bEnable)`

Enables or disables the COP Loss of Reference counter.

This function writes a value into the COP_CTRL register to enable or disable the COP Loss of Reference counter.

Parameters

- base – COP peripheral base address.
- bEnable – Enable the feature or not.

```
static inline void COP_SetTimeoutCount(COP_Type *base, uint16_t u16TimeoutCount)
```

Sets the COP timeout value.

This function sets the COP timeout value, if `psConfig->bEnableWriteProtect` is set to true for calling `WDOG_Init`, the set does not take effect. It should be ensured that the time-out value for the COP is always greater than interrupt time + 40 bus clock cycles. This function writes a value into `COP_TOUT` register, when COP count down to zero from the timeout count value, `COP_RST_B` signal will be asserted. There are some considerations for setting the timeout count after COP is enabled:

- The recommended procedure for changing TIMEOUT is to disable the COP by invoking `COP_Enable()`, then call the function `COP_SetTimeoutCount`, and then re-enable the by invoking `COP_Enable()` again.
- Alternatively, call the function `COP_SetTimeoutCount`, then feed the COP by invoking `COP_Refresh()` to reload the timeout.

Parameters

- `base` – COP peripheral base address
- `u16TimeoutCount` – COP timeout value, count of COP clock tick. Use macro definition `MSEC_TO_COUNT` to convert value in ms to count of ticks, the COP clock rate is source clock divide prescaler.

```
static inline void COP_SetInterruptCount(COP_Type *base, uint16_t u16InterruptCount)
```

Sets the COP interrupt value.

This function sets the COP interrupt value, if `psConfig->bEnableWriteProtect` is set to true for calling `WDOG_Init`, the set does not take effect. This function writes a value into `COP_INTVAL` register, if COP interrupt is enabled and COP count down to the interrupt value configured, an interrupt will be triggered. Ensure the COP counter is disabled while the function is called.

Parameters

- `base` – COP peripheral base address
- `u16InterruptCount` – COP interrupt value, count of COP clock tick. Use macro definition `MSEC_TO_COUNT` to convert value in ms to count of ticks, the COP clock rate is source clock divide prescaler.

```
static inline void COP_SetWindowCount(COP_Type *base, uint16_t u16WindowCount)
```

Sets the COP window value.

This function sets the COP window value, if `psConfig->bEnableWriteProtect` is set to true for calling `WDOG_Init`, the set does not take effect. This function writes a value into `COP_WINDOW` register. Ensure the COP counter is disabled while the function is called.

Parameters

- `base` – COP peripheral base address
- `u16WindowCount` – COP window value, count of COP clock tick. Use macro definition `MSEC_TO_COUNT` to convert value in ms to count of ticks, the COP clock rate is source clock divide prescaler.

```
void COP_Refresh(COP_Type *base)
```

Refreshes the COP timer.

This function feeds/services the COP.

Parameters

- `base` – COP peripheral base address.

static inline void COP_EnableInterrupt(COP_Type *base)

Enables the COP interrupt, if psConfig->bEnableWriteProtect is set to true for calling WDOG_Init, the operation does not take effect.

This function writes a value into the COP_CTRL register to enable the COP interrupt.

Parameters

- base – COP peripheral base address

static inline void COP_DisableInterrupt(COP_Type *base)

Disables the COP interrupt, if psConfig->bEnableWriteProtect is set to true for calling WDOG_Init, the operation does not take effect.

This function writes a value into the COP_CTRL register to disable the COP interrupt.

Parameters

- base – COP peripheral base address

FSL_COP_DRIVER_VERSION

COP driver version.

COP_FIRST_WORD_OF_REFRESH

COP refresh key word.

First word of refresh sequence

COP_SECOND_WORD_OF_REFRESH

Second word of refresh sequence

enum _cop_clock_source

enumeration for COP clock source selection.

Values:

enumerator kCOP_RoscClockSource

COP clock sourced from Relaxation oscillator (ROSC)

enumerator kCOP_CoscClockSource

COP clock sourced from Crystal oscillator (COSCs)

enumerator kCOP_BusClockSource

COP clock sourced from IP Bus clock

enumerator kCOP_LpoClockSource

COP clock sourced from Low speed oscillator

enum _cop_clock_prescaler

enumeration for COP clock prescaler to input source clock.

Values:

enumerator kCOP_ClockPrescalerDivide1

Divided by 1

enumerator kCOP_ClockPrescalerDivide16

Divided by 16

enumerator kCOP_ClockPrescalerDivide256

Divided by 256

enumerator kCOP_ClockPrescalerDivide1024

Divided by 1024

```
typedef enum _cop_clock_source cop_clock_source_t
    enumeration for COP clock source selection.
typedef enum _cop_clock_prescaler cop_clock_prescaler_t
    enumeration for COP clock prescaler to input source clock.
typedef struct _cop_config cop_config_t
    structure for COP module initialization configuration.
struct _cop_config
    #include <fsl_cop.h> structure for COP module initialization configuration.
```

Public Members

```
bool bEnableWriteProtect
    Set COP Write protected
bool bEnableStop
    Enable or disable COP in STOP mode
bool bEnableWait
    Enable or disable COP in WAIT mode
bool bEnableLossOfReference
    Enable or disable COP loss of reference counter
bool bEnableInterrupt
    Enables or disables COP interrupt
bool bEnableCOP
    Enables or disables COP module
cop_clock_source_t eClockSource
    Set COP clock source
cop_clock_prescaler_t ePrescaler
    Set COP clock prescaler
uint16_t u16TimeoutCount
    Timeout count in clock cycles, Use macro definition MSEC_TO_COUNT to convert value
    in ms to count of ticks, the COP clock rate is source clock divide prescaler.
uint16_t u16WindowCount
    Window count in clock cycles, Use macro definition MSEC_TO_COUNT to convert value
    in ms to count of ticks, the COP clock rate is source clock divide prescaler.
uint16_t u16InterruptCount
    Interrupt count in clock cycles, Use macro definition MSEC_TO_COUNT to convert
    value in ms to count of ticks, the COP clock rate is source clock divide prescaler.
```

2.10 The Driver Change Log

2.11 COP Peripheral and Driver Overview

2.12 CRC: Cyclic Redundancy Check Driver

`void CRC_Init(CRC_Type *base, const crc_config_t *psConfig)`

Enables and configures the CRC peripheral module.

This function enables the clock gate in the SIM module for the CRC peripheral. It also configures the CRC module and starts a checksum computation by writing the seed.

Parameters

- `base` – CRC peripheral address.
- `psConfig` – CRC module configuration structure.

`void CRC_Deinit(CRC_Type *base)`

Disables the CRC peripheral module.

This function disables the clock gate in the SIM module for the CRC peripheral.

Parameters

- `base` – CRC peripheral address.

`static inline void CRC_GetDefaultConfig(crc_config_t *psConfig, crc_protocol_type_t eCrcProtocol)`

Provide default CRC protocol configuration.

The purpose of this API is to initialize the configuration structure to default value for `CRC_Init` to use. Provides the configuration of commonly used CRC protocols. refer to `crc_protocol_type_t`.

This is an example:

```
crc_config_t sConfig;
//LoadCRC-16/MAXIM protocol configuration.
CRC_GetDefaultConfig(&sConfig, kCRC_Crc16);
CRC_Init(CRC, &sConfig);
```

Parameters

- `psConfig` – CRC protocol configuration structure.
- `eCrcProtocol` – CRC protocol type. refer to `crc_protocol_type_t`

`static inline void CRC_SetSeedValue(CRC_Type *base, uint32_t u32CrcSeedValue)`

Set the CRC seed value.

This function is help to write a 16/32 bit CRC seed value.

Parameters

- `base` – CRC peripheral address.
- `u32CrcSeedValue` – The value of seed.

`static inline void CRC_SetPolynomial(CRC_Type *base, uint32_t u32CrcPolynomial)`

Set the value of the polynomial for the CRC calculation.

Write a 16-bit or 32-bit polynomial to CRC Polynomial register for the CRC calculation.

Parameters

- `base` – CRC peripheral address.
- `u32CrcPolynomial` – The CRC polynomial.

`static inline void CRC_SetWriteTransposeType(CRC_Type *base, crc_transpose_type_t eTransposeIn)`

Set CRC type of transpose of write data.

This function help to configure CRC type of transpose of write data.

Parameters

- base – CRC peripheral address.
- eTransposeIn – Type Of transpose for input. See `crc_transpose_type_t`

```
static inline void CRC_SetReadTransposeType(CRC_Type *base, crc_transpose_type_t
                                           eTransposeOut)
```

Set CRC type of transpose of read data.

This function help to configure CRC type of transpose of read data.

Parameters

- base – CRC peripheral address.
- eTransposeOut – Type Of transpose for output. See `crc_transpose_type_t`

```
static inline void CRC_EnableComplementChecksum(CRC_Type *base, bool bEnable)
```

Enable/Disable complement of read CRC checksum.

Set complement of read CRC checksum. Some CRC protocols require the final checksum to be XORed with 0xFFFFFFFF or 0xFFFF.

Parameters

- base – CRC peripheral address.
- bEnable – True or false. True if the result shall be complement of the actual checksum.

```
static inline void CRC_SetProtocolWidth(CRC_Type *base, crc_bits_t eCrcBits)
```

Set bit width of CRC protocol.

Selects 16-bit or 32-bit CRC protocol.

Parameters

- base – CRC peripheral address.
- eCrcBits – 16 or 32 bit CRC protocol. See `crc_bits_t`

```
void CRC_WriteData(CRC_Type *base, const uint8_t *pu8Data, uint32_t u32DataSize)
```

Writes data to the CRC module.

Writes input data buffer bytes to the CRC data register. The configured type of transpose is applied.

Parameters

- base – CRC peripheral address.
- pu8Data – Input data stream, MSByte in data[0].
- u32DataSize – Size in bytes of the input data buffer.

```
static inline uint32_t CRC_Get32bitResult(CRC_Type *base)
```

Reads the 32-bit checksum from the CRC module.

Reads the CRC data register (either an intermediate or the final checksum). The configured type of transpose and complement is applied.

Parameters

- base – CRC peripheral address.

Returns

An intermediate or the final 32-bit checksum, after transpose and complement operations configured.

uint16_t CRC_Get16bitResult(CRC_Type *base)

Reads a 16-bit checksum from the CRC module.

Reads the CRC data register (either an intermediate or the final checksum). The configured type of transpose and complement is applied.

Parameters

- base – CRC peripheral address.

Returns

An intermediate or the final 16-bit checksum, after transpose and complement operations configured.

FSL_CRC_DRIVER_VERSION

CRC driver version. Version.

enum __crc_protocol_type

CRC protocol type.

Values:

enumerator kCRC_Crc16

CRC-16/MAXIM protocol.

enumerator kCRC_Crc16CCITT

CRC-16-CCITT protocol.

enumerator kCRC_Crc16Kermit

CRC-16/KERMIT protocol.

enumerator kCRC_Crc32

CRC-32 protocol.

enumerator kCRC_Crc32Posix

CRC-32/POSIX protocol.

enum __crc_bits

CRC protocol bit width.

Values:

enumerator kCRC_Bits16

Generate 16-bit CRC code.

enumerator kCRC_Bits32

Generate 32-bit CRC code.

enum __crc_transpose_type

CRC type of transpose of read/write data.

Values:

enumerator kCRC_TransposeNone

No transpose.

enumerator kCRC_TransposeBits

Transpose bits in bytes.

enumerator kCRC_TransposeBitsAndBytes

Transpose bytes and bits in bytes.

enumerator kCRC_TransposeBytes

Transpose bytes.

```
typedef enum _crc_protocol_type crc_protocol_type_t
```

CRC protocol type.

```
typedef enum _crc_bits crc_bits_t
```

CRC protocol bit width.

```
typedef enum _crc_transpose_type crc_transpose_type_t
```

CRC type of transpose of read/write data.

```
typedef struct _crc_config crc_config_t
```

CRC protocol configuration.

This structure holds the configuration for the CRC protocol.

```
struct _crc_config
```

#include <fsl_crc.h> CRC protocol configuration.

This structure holds the configuration for the CRC protocol.

Public Members

```
uint32_t u32CrcPolynomial
```

CRC Polynomial, MSBit first. Example polynomial: $0x1021 = 1_0000_0010_0001 = x^{12} + x^5 + 1$

```
uint32_t u32CrcSeedValue
```

Starting checksum value

```
bool bEnableComplementChecksum
```

Enable/Disable complement of read CRC checksum.

```
crc_transpose_type_t eTransposeIn
```

Select type of transpose of input data.

```
crc_transpose_type_t eTransposeOut
```

Select type of transpose of output data.

```
crc_bits_t eCrcBits
```

Select 16-bit or 32-bit CRC protocol.

2.13 The Driver Change Log

2.14 CRC Peripheral and Driver Overview

2.15 DMAMUX: DMA Channel Multiplexer Driver

```
static inline void DMAMUX_ConnectChannelToTriggerSource(DMAMUX_Type *base,  
                                                         dmamux_dma_channel_t eChannel,  
                                                         dma_request_source_t eSource)
```

Connect the DMAMUX channel to trigger source.

This function will connect a source to the specify dma channel and enable that channel

Parameters

- base – DMAMUX peripheral base address.
- eChannel – DMAMUX channel index, dmamux_dma_channel_t.

- eSource – DMA request source.

```
static inline void DMAMUX_DisconnectChannelFromTriggerSource(DMAMUX_Type *base,  
                                                            dmamux_dma_channel_t  
                                                            eChannel)
```

Disconnect the DMAMUX channel.

This function will disable the specified channel and reset the channel source.

Parameters

- base – DMAMUX peripheral base address.
- eChannel – DMAMUX channel index, dmamux_dma_channel_t.

FSL_DMAMUX_DRIVER_VERSION
DMAMUX driver version.

enum _dmamux_dma_channel
List of Dmamux dma channels.

Values:

enumerator kDMAMUX_DMACHannel0
Dmamux dma channel 0

enumerator kDMAMUX_DMACHannel1
Dmamux dma channel 1

enumerator kDMAMUX_DMACHannel2
Dmamux dma channel 2

enumerator kDMAMUX_DMACHannel3
Dmamux dma channel 3

typedef enum _dmamux_dma_channel dmamux_dma_channel_t
List of Dmamux dma channels.

2.16 The Driver Change Log

2.17 DMAMUX Peripheral and Driver Overview

2.18 The Driver Change Log

2.19 EDMA: Enhanced Direct Memory Access Driver

```
void EDMA_GetDefaultConfig(edma_config_t *psConfig)  
Get default edma peripheral configuration.
```

Note: This function will reset all of the configuration structure members to zero firstly, then apply default configurations to the structure.

Parameters

- psConfig – pointer to user's eDMA config structure, see edma_config_t for detail.

void EDMA_Init(DMA_Type *base, *edma_config_t* *psConfig)

EDMA initialization.

Parameters

- base – eDMA peripheral base address.
- psConfig – pointer to user's eDMA config structure, see *edma_transfer_config_t* for detail.

void EDMA_Deinit(DMA_Type *base)

EDMA De-initialization.

Parameters

- base – eDMA peripheral base address.

static inline void EDMA_EnableContinuousChannelLinkMode(DMA_Type *base, bool bEnable)

Enable/Disable arbitration before the channel been activate by minor loop link trigger from itself.

A minor loop channel link made to itself does not go through channel arbitration before being activated again. Upon minor loop completion, the channel activates again if that channel has a minor loop channel link enabled and the link channel is itself. This effectively applies the minor loop offsets and restarts the next minor loop.

Note: Do not use continuous link mode with a channel linking to itself if there is only one minor loop iteration per service request, for example, if the channel's NBYTES value is the same as either the source or destination size. The same data transfer profile can be achieved by simply increasing the NBYTES value, which provides more efficient, faster processing.

Parameters

- base – EDMA peripheral base address.
- bEnable – true is channel link to itself without arbitration false is channel link to itself with arbitration

static inline void EDMA_EnableMinorLoopMapping(DMA_Type *base, bool bEnable)

Enable/Disable redefine the minor loop bytes register.

The TCDn.word2 is redefined to include individual enable fields, an offset field and the NBYTES field, the offset will be applied to source/destination address after minor loop complete

Parameters

- base – EDMA peripheral base address.
- bEnable – true is minor loop bytes register redefined to individual enable/offset/minor loop bytes fields. false is minor loop bytes register defined as minor loop bytes fields only.

static inline void EDMA_EnableHaltOnError(DMA_Type *base, bool bEnable)

Enable/Disable the eDMA halt when error occur feature.

Any error causes the HALT bit to set will cause the EDMA halt. Subsequently, all service requests are ignored until the HALT bit is cleared

Parameters

- base – EDMA peripheral base address.
- bEnable – true is Stall the start of any new channels when error occur. false is eDMA service request operation normal when error occur.

static inline void EDMA_SetArbitration(DMA_Type *base, *edma_arbitration_type_t* eArbitration)
set EDMA arbitration type to fixed priority or round robin.

Parameters

- base – EDMA peripheral base address.
- eArbitration – Arbitration by priority or round robin, *edma_arbitration_type_t*.

```
void EDMA_GetChannelDefaultTransferConfig(edma_channel_transfer_config_t *psTransfer,  
uint32_t u32SrcAddr, uint32_t u32DstAddr,  
uint32_t u32BytesEachRequest, uint32_t  
u32TotalBytes, edma_channel_transfer_width_t  
eTransferWidth, edma_channel_transfer_type_t  
eTransferType)
```

Get channel default transfer configuration.

Note: 1. This function will reset all of the configuration structure members to zero firstly, then apply default configurations to the structure.

- a. No interrupt enabled by this function by default, if application would like to use DMA interrupt please enable it manually by `psTransfer->u16EnabledInterruptMask = _edma_channel_interrupt`
-

Parameters

- psTransfer – pointer to user's eDMA channel configure structure, see *edma_channel_transfer_config_t* for detail.
- u32SrcAddr – source address, must be byte address.
- u32DstAddr – destination address, must be byte address.
- u32BytesEachRequest – bytes to be transferred in each request(namely, in each minor loop).
- u32TotalBytes – total bytes to be transferred.
- eTransferWidth – it represents how many bits are transferred in each read/write.
- eTransferType – eDMA channel transfer type.

```
void EDMA_SetChannelTransferConfig(DMA_Type *base, edma_channel_t eChannel,  
                                edma_channel_transfer_config_t *psTransfer)
```

EDMA set channel transfer configurations.

Note: 1.This function must not be called while the channel transfer is ongoing or it causes unpredictable results. 2.The psLinkTCD must be configured before invoke this API if scatter/gather function is needed 3.The edma channel request may be enabled after the channel transfer configure done according to the transfer configurations.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.
- psTransfer – pointer to user's eDMA channel configure structure, see *edma_channel_transfer_config_t* for detail.

```
void EDMA_SetChannelMinorLoopOffset(DMA_Type *base, edma_channel_t eChannel, bool
                                     bEnableSrcMinorLoopOffset, bool
                                     bEnableDestMinorLoopOffset, int32_t
                                     i32MinorLoopOffset)
```

Configures the eDMA channel minor loop offset value.

The minor offset means that the signed-extended value is added to the source address or destination address after each minor loop.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.
- bEnableSrcMinorLoopOffset – True is enable source address minor offset, otherwise is disable
- bEnableDestMinorLoopOffset – True is enable source address minor offset, otherwise is disable
- i32MinorLoopOffset – Minor loop offset value.

```
void EDMA_SetChannelPreemption(DMA_Type *base, edma_channel_t eChannel, bool
                               bSuspendedByHighPriorityChannel, bool
                               bSuspendLowPriorityChannel, uint8_t u8Priority)
```

Configures the eDMA channel preemption configurations.

This function configures the channel preemption attribute and the priority of the channel.

Note: , this function is used only in fixed-priority channel arbitration mode.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number
- bSuspendedByHighPriorityChannel – True is the channel can be suspended by high priority channel, otherwise cannot.
- bSuspendLowPriorityChannel – True is the channel can suspend low priority channel, otherwise cannot.
- u8Priority – Channel priority.

```
void EDMA_EnableMinorLoopChannelLink(DMA_Type *base, edma_channel_t eChannel,
                                     edma_channel_t eLinkChannel)
```

Enable the minor loop channel link and configure the linked channel number.

This function configures the minor link mode. The minor link means that the channel link is triggered every time that the minor loop bytes transferred complete.

Note: Users should ensure that DONE flag is cleared before calling this interface, or the configuration is invalid.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.
- eLinkChannel – The linked channel number.

```
static inline void EDMA_DisableMinorLoopChannelLink(DMA_Type *base, edma_channel_t
                                                    eChannel)
```

Disable the minor loop channel link for the eDMA transfer.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.

```
void EDMA_EnableMajorLoopChannelLink(DMA_Type *base, edma_channel_t eChannel,
                                      edma_channel_t eLinkChannel)
```

Enable the major loop channel link and configure the linked channel number.

This function configures the major link mode. The major link means that the channel link is triggered when the CITER is exhausted.

Note: Users should ensure that DONE flag is cleared before calling this interface, or the configuration is invalid.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.
- eLinkChannel – The linked channel number.

```
static inline void EDMA_DisableMajorLoopChannelLink(DMA_Type *base, edma_channel_t
                                                    eChannel)
```

Disable the major loop channel link for the eDMA transfer.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.

```
void EDMA_SetChannelBandWidth(DMA_Type *base, edma_channel_t eChannel,
                              edma_channel_bandwidth_t eBandWidth)
```

Sets the edma channel stall cycles after each R/W.

Because the eDMA processes the minor loop, it continuously generates read/write sequences until the minor count is exhausted. The bandwidth forces the eDMA to stall after the completion of each read/write access to control the bus request bandwidth seen by the crossbar switch.

Note: : 1.If the source and destination sizes are equal, this field is ignored between the first and second transfers and after the last write of each minor loop. This behavior is a side effect of reducing start-up latency. 2.When executing a large, zero wait-stated memory-to-memory transfer, insert bandwidth control using the TCD_CSR[BWC] bits to avoid: •* Starvation of another master accessing the memory. •* Any delay in writing a TCD duloop the transfer.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.
- eBandWidth – A bandwidth setting, which can be one of the *edma_channel_bandwidth_t*

```
void EDMA__SetChannelModulo(DMA_Type *base, edma_channel_t eChannel,  
                           edma_channel_modulo_t eSrcModulo, edma_channel_modulo_t  
                           eDestModulo)
```

Sets the source address range and the destination address range for the eDMA transfer.

This function defines a specific address range of source/destination address, after the source/destination address hits the range boundary, source/destination address will wrap to origin value.

Setting this field provides the ability to implement a circular data queue easily. For data queues require loop power-of-2 size bytes, the queue should start at a 0-modulo-size address and the SMOD field should be set to the appropriate value for the queue, freezing the desired number of upper address bits. The value programmed into this field specifies the number of lower address bits allowed to change

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.
- eSrcModulo – A source modulo value.
- eDestModulo – A destination modulo value.

```
static inline void EDMA__EnableChannelAsyncRequestInStopMode(DMA_Type *base,  
                                                            edma_channel_t eChannel,  
                                                            bool bEnable)
```

Enables the edma channel async request in stop mode.

The EARS register is used to enable or disable the DMA requests in Enable Request Register (ERQ) by AND'ing the bits of these two registers in stop mode only.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.
- bEnable – The command to enable (true) or disable (false).

```
static inline void EDMA__EnableChannelAutoStopRequest(DMA_Type *base, edma_channel_t  
                                                      eChannel, bool bEnable)
```

Enables the edma channel auto disable request after major loop complete.

The eDMA hardware automatically clears the corresponding ERQ bit when the current major iteration count reaches zero.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.
- bEnable – The command to enable (true) or disable (false).

```
void EDMA__SetChannelMajorLoopOffset(DMA_Type *base, edma_channel_t eChannel, int32_t  
                                     i32SourceOffset, int32_t i32DestOffset)
```

Configures the eDMA channel major loop offset feature.

Adjustment value added to the source/destination address at the completion of the major iteration count

Parameters

- base – eDMA peripheral base address.
- eChannel – edma channel number.

- i32SourceOffset – source address offset.
- i32DestOffset – destination address offset.

```
static inline void EDMA__EnableChannelRequest(DMA_Type *base, edma_channel_t eChannel,  
                                              bool bEnable)
```

Enable/disable the eDMA hardware channel request.

This function enables the hardware channel request.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.
- bEnable – true is start, false is stop.

```
static inline void EDMA__SoftwareTriggerChannelStart(DMA_Type *base, edma_channel_t  
                                                    eChannel)
```

Starts the eDMA transfer by using the software trigger.

This function starts a minor loop transfer only, the channel will halt when minor loop complete, so application should re-call the function to start the transfer again.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.

```
uint32_t EDMA__GetChannelRemainingMajorLoopCount(DMA_Type *base, edma_channel_t  
                                                  eChannel)
```

Gets the remaining major loop count from the eDMA current channel TCD.

This function checks the TCD (Transfer Control Descriptor) status for a specified eDMA channel and returns the number of major loop count that has not finished.

Note: 1. This function can only be used to get unfinished major loop count of transfer without the next TCD, or it might be inaccuracy.

- a. The unfinished/remaining transfer bytes cannot be obtained directly from registers while the channel is running. Because to calculate the remaining bytes, the initial NBYTES configured in DMA_TCDn_NBYTES_MLNO register is needed while the eDMA IP does not support getting it while a channel is active. In another word, the NBYTES value reading is always the actual (decrementing) NBYTES value the dma_engine is working with while a channel is running. Consequently, to get the remaining transfer bytes, a software-saved initial value of NBYTES (for example copied before enabling the channel) is needed. The formula to calculate it is shown below: $\text{RemainingBytes} = \text{RemainingMajorLoopCount} * \text{NBYTES}(\text{initially configured})$
-

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.

Return values

Major – loop count which has not been transferred yet for the current TCD.

```
void EDMA__EnableChannelInterrupts(DMA_Type *base, edma_channel_t eChannel, uint16_t  
                                   u16InterruptsMask, bool bEnable)
```

Enables the edma channel interrupts according to a provided mask, the mask is a logical OR of enumerator members `_edma_channel_interrupt_enable`.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.
- u16InterruptsMask – the mask is a logical OR of enumerator members `_edma_channel_interrupt_enable`.
- bEnable – true is enable, false is disable.

uint16_t EDMA_GetChannelStatusFlags(DMA_Type *base, *edma_channel_t* eChannel)

Gets the eDMA channel status flags.

Note: if the function return error status, application can call EDMA_GetErrorStatusFlags for the detail error status.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.

Return values

The – mask of channel status flags. Users need to use the `_edma_channel_status_flags` type to decode the return variables.

void EDMA_ClearChannelStatusFlags(DMA_Type *base, *edma_channel_t* eChannel, uint16_t u16StatusFlags)

Clears the eDMA channel status flags.

Parameters

- base – eDMA peripheral base address.
- eChannel – eDMA channel number.
- u16StatusFlags – The mask of channel status to be cleared. Users need to use the defined `_edma_channel_status_flags` type.

static inline uint32_t EDMA_GetErrorStatusFlags(DMA_Type *base)

Gets the eDMA channel error status flags.

Parameters

- base – eDMA peripheral base address.

Returns

The mask of error status flags. Users need to use the `_edma_error_status_flags` type to decode the return variables.

void EDMA_ConfigChannelSoftwareTCD(*edma_channel_tcd_t* *psTcd, *edma_channel_transfer_config_t* *psTransfer)

Sets TCD fields according to the user's channel transfer configuration structure, `edma_channel_transfer_config_t`.

Application should be careful about the TCD pool buffer storage class,

- For the platform has cache, the software TCD should be put in non cache section
- The TCD pool buffer should have a consistent storage class.

Note: Application should be careful when using the minor loop offset feature with this function, please make sure the EMLM bit is asserted, although

EDMA_InitChannel will set this bit by default, if the bit is cleared, application can use EDMA_EnableMinorLoopMapping to enable the feature.

Note: This function enables the auto stop request feature.

Parameters

- psTcd – Pointer to the TCD structure.
- psTransfer – channel transfer configuration pointer.

```
void EDMA__InstallChannelSoftwareTCD(DMA_Type *base, edma_channel_t eChannel,
                                     edma_channel_tcd_t *psTcd)
```

Push content of software TCD structure into hardware TCD register.

Parameters

- base – EDMA peripheral base address.
- eChannel – EDMA channel number.
- psTcd – Point to TCD structure.

```
void EDMA__TransferCreateHandle(DMA_Type *base, edma_handle_t *psHandle, edma_channel_t
                               eChannel, edma_channel_tcd_t *psTcdPool, uint32_t
                               u32TcdCount, edma_transfer_callback_t pfCallback, void
                               *pUserData)
```

Creates the eDMA channel handle.

This function is called if using the transactional API for eDMA. This function initializes the internal state of the eDMA handle.

Parameters

- base – eDMA peripheral base address.
- psHandle – eDMA handle pointer. The eDMA handle stores callback function and parameters.
- eChannel – eDMA channel number.
- psTcdPool – A memory pool to store TCDs. It must be 32 bytes aligned.
- u32TcdCount – The number of TCD slots.
- pfCallback – eDMA callback function pointer.
- pUserData – A parameter for the callback function.

```
status_t EDMA__TransferSubmitSingleTransfer(edma_handle_t *psHandle,
                                             edma_channel_transfer_config_t *psTransfer)
```

Submits the eDMA single transfer configuration.

Application can submit single transfer when

- channel is idle, the transfer request will be submitted to eDMA channel TCD register directly
- channel is idle, a previous transfer request is pending, the new transfer request will be submitted to the installed TCD pool and linked to the pending one.
- channel is active, the transfer request will be submitted to the installed TCD pool and linked to previous one.

It is suggest that application should check the return value of this function to make sure that the transfer request is submitted successfully.

Note: , 1.Please be aware of that tcd pool maintain is unprotect by default, that is to say, the behavior of multiple task trying to access the same channel is undefine, application can protect the channel by itself or overwrite EDMA_ENTER_CRITICAL_SECTION/EDMA_LEAVE_CRITICAL_SECTION to have edma driver protect the TCD pool maintain. 2.Since the destination major loop offset feature register is reused as scatter gather tcd address, so the two features cannot be used together; if the destination major loop offset feature is used, then the transfer request will be submit hardware TCD directly.

Parameters

- psHandle – eDMA handle pointer.
- psTransfer – pointer to user's eDMA channel configure structure, see edma_channel_transfer_config_t for detail.

Return values

- kStatus_Success – It means submit transfer request succeed.
- kStatus_EDMA_ChannelQueueFull – It means TCD queue is full. Submit transfer request is not allowed.

status_t EDMA_TransferSubmitLoopTransfer(*edma_handle_t* *psHandle,
 edma_channel_transfer_config_t *psTransfer,
 uint32_t transferLoopCount)

Submits the eDMA scatter gather transfer configurations.

The function is target for submit loop transfer request, the ring transfer request means that the transfer request TAIL is link to HEAD, such as, A->B->C->D->A, or A->A

To use the ring transfer feature, the application should allocate several transfer object, such as

```
edma_channel_transfer_config_t transfer[2];  
EDMA_TransferSubmitLoopTransfer(psHandle, &transfer, 2U);
```

Then eDMA driver will link transfer[0] and transfer[1] to each other

Note: Application should check the return value of this function to avoid transfer request submit failed

Parameters

- psHandle – eDMA handle pointer
- psTransfer – pointer to user's eDMA channel configure structure, see edma_channel_transfer_config_t for detail
- transferLoopCount – the count of the transfer ring, if loop count is 1, that means that the one will link to itself.

Return values

- kStatus_Success – It means submit transfer request succeed
- kStatus_EDMA_ChannelBusy – channel is in busy status

- `kStatus_EDMA_ChannelQueueFull` – It means TCD pool is not len enough for the ring transfer request

`void EDMA_TransferStart(edma_handle_t *psHandle)`

eDMA starts transfer.

This function enables the channel request. Users can call this function after submitting the transfer request or before submitting the transfer request.

Parameters

- `psHandle` – eDMA handle pointer.

`void EDMA_TransferStop(edma_handle_t *psHandle)`

eDMA stops transfer.

This function disables the channel request to pause the transfer. Users can call `EDMA_StartTransfer()` again to resume the transfer.

Parameters

- `psHandle` – eDMA handle pointer.

`void EDMA_TransferAbort(edma_handle_t *psHandle)`

eDMA aborts transfer.

This function disables the channel request and clear transfer status bits. Users can submit another transfer after calling this API.

Parameters

- `psHandle` – DMA handle pointer.

`void EDMA_TransferHandleIRQ(edma_handle_t *psHandle)`

eDMA IRQ handler for the current major loop transfer completion.

This function clears the channel major interrupt flag and calls the callback function if it is not NULL.

Note: For the case using TCD queue, when the major iteration count is exhausted, additional Interfaces are performed. These include the final address adjustments and reloading of the BITER field into the CITER. Assertion of an optional interrupt request also occurs at this time, as does a possible fetch of a new TCD from memory using the scatter/gather address pointer included in the descriptor (if scatter/gather is enabled).

For instance, when the time interrupt of TCD[0] happens, the TCD[1] has already been loaded into the eDMA engine. As `sga` and `sga_index` are calculated based on the `DLAST_SGA` bit field lies in the `TCD_CSR` register, the `sga_index` in this case should be 2 (`DLAST_SGA` of TCD[1] stores the address of TCD[2]). Thus, the “`tcdUsed`” updated should be (`tcdUsed - 2U`) which indicates the number of TCDs can be loaded in the memory pool (because TCD[0] and TCD[1] have been loaded into the eDMA engine at this point already.).

For the last two continuous ISRs in a scatter/gather process, they both load the last TCD (The last ISR does not load a new TCD) from the memory pool to the eDMA engine when major loop completes. Therefore, ensure that the header and `tcdUsed` updated are identical for them. `tcdUsed` are both 0 in this case as no TCD to be loaded.

See the “eDMA basic data flow” in the eDMA Functional description section of the Reference Manual for further details.

Parameters

- `psHandle` – eDMA handle pointer.

`FSL_EDMA_DRIVER_VERSION`

EDMA driver version.

`_edma_transfer_status` eDMA transfer status The enumerator used for transactional interface only.

Values:

enumerator `kStatus_EDMA_ChannelQueueFull`

TCD queue is full.

enumerator `kStatus_EDMA_ChannelBusy`

Channel is busy and can't handle the transfer request.

enum `_edma_channel_transfer_type`

eDMA transfer type

Values:

enumerator `kEDMA_ChannelTransferMemoryToMemory`

Transfer type from memory to memory assume that the both source and destination address are incremental

enumerator `kEDMA_ChannelTransferPeripheralToMemory`

Transfer type peripher to memory assume that the source address is fixed

enumerator `kEDMA_ChannelTransferMemoryToPeripheral`

Transfer type from memory to peripheral assume that the destination address is fixed

enumerator `kEDMA_ChannelTransferPeripheralToPeripheral`

Transfer type from Peripheral to peripheral assume that both source and destination address are fixed

enum `_edma_channel_interrupt_enable`

eDMA interrupt source

The eDMA peripheral support generate interrupt when half of the total request bytes transferred or all of the request bytes transferred.

Values:

enumerator `kEDMA_ChannelErrorInterruptEnable`

Enable error interrupt

enumerator `kEDMA_ChannelMajorLoopCompleteInterruptEnable`

Enable interrupt while major count exhausted.

enumerator `kEDMA_ChannelMajorLoopHalfCompleteInterruptEnable`

Enable interrupt while major count to half value.

enumerator `kEDMA_ChannelAllInterruptEnable`

Enable all the interrupt.

enum `_edma_channel_status_flags`

`_edma_channel_status_flags` eDMA channel status flags.

Values:

enumerator `kEDMA_ChannelStatusErrorFlag`

eDMA error flag, an error occurred in a transfer

enumerator `kEDMA_ChannelStatusMajorLoopCompleteFlag`

Major loop complete flag, set while transfer finished, CITER value exhausted

enumerator `kEDMA_ChannelStatusMajorLoopHalfCompleteFlag`

Major loop half complete flag

enum _edma_error_status_flags

_edma_error_status_flags eDMA channel detail error status flags.

Values:

enumerator kEDMA_ChannelDestinationBusErrorFlag

Bus error on destination address

enumerator kEDMA_ChannelSourceBusErrorFlag

Bus error on the source address

enumerator kEDMA_ChannelScatterGatherErrorFlag

Error on the Scatter/Gather address, not 32byte aligned.

enumerator kEDMA_ChannelNbytesErrorFlag

NBYTES/CITER configuration error

enumerator kEDMA_ChannelDestinationOffsetErrorFlag

Destination offset not aligned with destination size

enumerator kEDMA_ChannelDestinationAddressErrorFlag

Destination address not aligned with destination size

enumerator kEDMA_ChannelSourceOffsetErrorFlag

Source offset not aligned with source size

enumerator kEDMA_ChannelSourceAddressErrorFlag

Source address not aligned with source size

enumerator kEDMA_ChannelErrorChannelFlag

Error channel number of the canceled channel number

enumerator kEDMA_ChannelPriorityErrorFlag

Channel priority is not unique.

enumerator kEDMA_ChannelTransferCanceledFlag

Transfer canceled

enumerator kEDMA_ChannelValidFlag

No error occurred, this bit is 0. Otherwise, it is 1.

enum _edma_arbitration_type

eDMA arbitration type

Values:

enumerator kEDMA_ArbitrationFixedPriority

channel arbitration by fixed priority

enumerator kEDMA_ArbitrationRoundRobin

Channel arbitration by round robin

enum _edma_channel

edma channel index

Values:

enumerator kEDMA_Channel0

EDMA channel 0

enumerator kEDMA_Channel1

EDMA channel 1

enumerator kEDMA_Channel2

EDMA channel 2

enumerator kEDMA_Channel3

EDMA channel 3

enum _edma_channel_transfer_width

eDMA transfer width configuration

Values:

enumerator kEDMA_ChannelTransferWidth8Bits

Source/Destination data transfer width is 1 byte every time

enumerator kEDMA_ChannelTransferWidth16Bits

Source/Destination data transfer width is 2 bytes every time

enumerator kEDMA_ChannelTransferWidth32Bits

Source/Destination data transfer width is 4 bytes every time

enumerator kEDMA_ChannelTransferWidth128Bits

Source/Destination data transfer size is 16 bytes every time

enum _edma_channel_modulo

eDMA channel modulo configuration

The eDMA modulo feature can be used to specify the address range of the source/destination address, it is useful to implement a circular data queue.

Values:

enumerator kEDMA_ChannelModuloDisable

Disable modulo

enumerator kEDMA_ChannelModulo2bytes

Circular buffer size is 2 bytes.

enumerator kEDMA_ChannelModulo4bytes

Circular buffer size is 4 bytes.

enumerator kEDMA_ChannelModulo8bytes

Circular buffer size is 8 bytes.

enumerator kEDMA_ChannelModulo16bytes

Circular buffer size is 16 bytes.

enumerator kEDMA_ChannelModulo32bytes

Circular buffer size is 32 bytes.

enumerator kEDMA_ChannelModulo64bytes

Circular buffer size is 64 bytes.

enumerator kEDMA_ChannelModulo128bytes

Circular buffer size is 128 bytes.

enumerator kEDMA_ChannelModulo256bytes

Circular buffer size is 256 bytes.

enumerator kEDMA_ChannelModulo512bytes

Circular buffer size is 512 bytes.

enumerator kEDMA_ChannelModulo1Kbytes

Circular buffer size is 1 K bytes.

enumerator kEDMA_ChannelModulo2Kbytes
Circular buffer size is 2 K bytes.

enumerator kEDMA_ChannelModulo4Kbytes
Circular buffer size is 4 K bytes.

enumerator kEDMA_ChannelModulo8Kbytes
Circular buffer size is 8 K bytes.

enumerator kEDMA_ChannelModulo16Kbytes
Circular buffer size is 16 K bytes.

enumerator kEDMA_ChannelModulo32Kbytes
Circular buffer size is 32 K bytes.

enumerator kEDMA_ChannelModulo64Kbytes
Circular buffer size is 64 K bytes.

enumerator kEDMA_ChannelModulo128Kbytes
Circular buffer size is 128 K bytes.

enumerator kEDMA_ChannelModulo256Kbytes
Circular buffer size is 256 K bytes.

enumerator kEDMA_ChannelModulo512Kbytes
Circular buffer size is 512 K bytes.

enumerator kEDMA_ChannelModulo1Mbytes
Circular buffer size is 1 M bytes.

enumerator kEDMA_ChannelModulo2Mbytes
Circular buffer size is 2 M bytes.

enumerator kEDMA_ChannelModulo4Mbytes
Circular buffer size is 4 M bytes.

enumerator kEDMA_ChannelModulo8Mbytes
Circular buffer size is 8 M bytes.

enumerator kEDMA_ChannelModulo16Mbytes
Circular buffer size is 16 M bytes.

enumerator kEDMA_ChannelModulo32Mbytes
Circular buffer size is 32 M bytes.

enumerator kEDMA_ChannelModulo64Mbytes
Circular buffer size is 64 M bytes.

enumerator kEDMA_ChannelModulo128Mbytes
Circular buffer size is 128 M bytes.

enumerator kEDMA_ChannelModulo256Mbytes
Circular buffer size is 256 M bytes.

enumerator kEDMA_ChannelModulo512Mbytes
Circular buffer size is 512 M bytes.

enumerator kEDMA_ChannelModulo1Gbytes
Circular buffer size is 1 G bytes.

enumerator kEDMA_ChannelModulo2Gbytes
Circular buffer size is 2 G bytes.

enum `_edma_channel_bandwidth`

edma channel Bandwidth control

Generally, as the eDMA processes the minor loop, it continuously generates read/write sequences until the minor count is exhausted. This bandwidth field forces the eDMA to stall after the completion of each read/write access to control the bus request bandwidth.

The default configuration is `kEDMA_BandwidthStallNone`.

Values:

enumerator `kEDMA_ChannelBandwidthStallNone`

No eDMA engine stalls.

enumerator `kEDMA_ChannelBandwidthStall4Cycle`

eDMA engine stalls for 4 cycles after each read/write.

enumerator `kEDMA_ChannelBandwidthStall8Cycle`

eDMA engine stalls for 8 cycles after each read/write.

typedef enum `_edma_channel_transfer_type` `edma_channel_transfer_type_t`

eDMA transfer type

typedef enum `_edma_arbitration_type` `edma_arbitration_type_t`

eDMA arbitration type

typedef enum `_edma_channel` `edma_channel_t`

edma channel index

typedef enum `_edma_channel_transfer_width` `edma_channel_transfer_width_t`

eDMA transfer width configuration

typedef enum `_edma_channel_modulo` `edma_channel_modulo_t`

eDMA channel modulo configuration

The eDMA modulo feature can be used to specify the address range of the source/destination address, it is useful to implement a circular data queue.

typedef enum `_edma_channel_bandwidth` `edma_channel_bandwidth_t`

edma channel Bandwidth control

Generally, as the eDMA processes the minor loop, it continuously generates read/write sequences until the minor count is exhausted. This bandwidth field forces the eDMA to stall after the completion of each read/write access to control the bus request bandwidth.

The default configuration is `kEDMA_BandwidthStallNone`.

typedef struct `_edma_channel_Preemption_config` `edma_channel_Preemption_config_t`

eDMA channel priority configuration, useful to the fixed priority arbitration type

typedef struct `_edma_channel_tcd` `edma_channel_tcd_t`

edma channel software tcd definition

typedef struct `_edma_channel_transfer_config` `edma_channel_transfer_config_t`

edma channel transfer configuration

The transfer configuration structure support full feature configuration of the transfer control descriptor.

1.To perform a simple transfer, below members should be initialized at least .u32SrcAddr - source address .u32DstAddr - destination address .eSrcWidthOfEachTransfer - data width of source address .eDstWidthOfEachTransfer - data width of destination address, normally it should be as same as eSrcWidthOfEachTransfer .u32BytesEachRequest - bytes to be transferred in each DMA request .u32TotalBytes - total bytes to be transferred

.i16SrcOffsetOfEachTransfer - offset value in bytes unit to be applied to source address as each source read is completed .i16DstOffsetOfEachTransfer - offset value in bytes unit to be applied to destination address as each destination write is completed bEnableChannelRequest - channel request can be enabled together with transfer configure submission

2.The transfer configuration structure also support advance feature: Programmable source/destination address range(MODULO) Programmable minor loop offset Programmable major loop offset Programmable channel chain feature Programmable channel transfer control descriptor link feature

Note: User should pay attention to the transfer size alignment limitation

- a. the u32BytesEachRequest should align with the eSrcWidthOfEachTransfer and the eDstWidthOfEachTransfer that is to say $u32BytesEachRequest \% eSrcWidthOfEachTransfer$ should be 0
 - b. the i16SrcOffsetOfEachTransfer and i16DstOffsetOfEachTransfer must be aligne with transfer width
 - c. the u32TotalBytes should align with the u32BytesEachRequest
 - d. the u32SrcAddr should align with the eSrcWidthOfEachTransfer
 - e. the u32DstAddr should align with the eDstWidthOfEachTransfer
 - f. the u32SrcAddr should align with eSrcAddrModulo if modulo feature is enabled
 - g. the u32DstAddr should align with eDstAddrModulo if modulo feature is enabled If any-one of above condition can not be satisfied, the edma interfaces will generate assert error.
-

```
typedef struct _edma_config edma_config_t  
edma configuration structure
```

This structure target for whole edma module configurations.

```
typedef struct _edma_handle edma_handle_t  
handler for eDMA
```

```
typedef void (*edma_transfer_callback_t)(edma_handle_t *psHandle, void *pUserData, bool  
bTransferDone, uint32_t u32Tcds)
```

Define callback function for eDMA.

This callback function is called in the EDMA interrupt handler function. In normal mode, running into callback function means the transfer users need is done. In scatter gather mode, run into callback function means a transfer control block (tcd) is finished. Not all transfer finished, users can get the finished tcd numbers using interface EDMA_GetUnusedTCDNumber.

Param handle

EDMA handle pointer, users shall not touch the values inside.

Param userData

The callback user parameter pointer. Users can use this parameter to involve things users need to change in EDMA callback function.

Param transferDone

If the current loaded transfer done. In normal mode it means if all transfer done. In scatter gather mode, this parameter shows is the current transfer block in EDMA register is done. As the load of core is different, it will be different if the new tcd loaded into EDMA registers while this callback called. If true, it always means new tcd still not loaded into registers, while false means new tcd already loaded into registers.

Param tcds

How many tcds are done from the last callback. This parameter only used in scatter gather mode. It tells user how many tcds are finished between the last callback and this.

EDMA_ENTER_CRITICAL_SECTION()

edma transactional tcd pool resource protection lock definition Application should overwrite below two macros if multi task trying to access the same channel.

EDMA_LEAVE_CRITICAL_SECTION()

struct _edma_channel_Preemption_config

#include <fsl_edma.h> edma channel priority configuration, useful to the fixed priority arbitration type

Public Members

bool bSuspendedByHighPriorityChannel

a channel can be suspended by other channel with higher priority

bool bSuspendLowPriorityChannel

a channel can suspend other channel with low priority

uint8_t u8ChannelPriority

Channel priority

struct _edma_channel_transfer_config

#include <fsl_edma.h> edma channel transfer configuration

The transfer configuration structure support full feature configuration of the transfer control descriptor.

1.To perform a simple transfer, below members should be initialized at least .u32SrcAddr - source address .u32DstAddr - destination address .eSrcWidthOfEachTransfer - data width of source address .eDstWidthOfEachTransfer - data width of destination address, normally it should be as same as eSrcWidthOfEachTransfer .u32BytesEachRequest - bytes to be transferred in each DMA request .u32TotalBytes - total bytes to be transferred .i16SrcOffsetOfEachTransfer - offset value in bytes unit to be applied to source address as each source read is completed .i16DstOffsetOfEachTransfer - offset value in bytes unit to be applied to destination address as each destination write is completed bEnableChannelRequest - channel request can be enabled together with transfer configure submission

2.The transfer configuration structure also support advance feature: Programmable source/destination address range(MODULO) Programmable minor loop offset Programmable major loop offset Programmable channel chain feature Programmable channel transfer control descriptor link feature

Note: User should pay attention to the transfer size alignment limitation

- a. the u32BytesEachRequest should align with the eSrcWidthOfEachTransfer and the eDstWidthOfEachTransfer that is to say $u32BytesEachRequest \% eSrcWidthOfEachTransfer$ should be 0
- b. the i16SrcOffsetOfEachTransfer and i16DstOffsetOfEachTransfer must be aligne with transfer width
- c. the u32TotalBytes should align with the u32BytesEachRequest
- d. the u32SrcAddr should align with the eSrcWidthOfEachTransfer
- e. the u32DstAddr should align with the eDstWidthOfEachTransfer

- f. the `u32SrcAddr` should align with `eSrcAddrModulo` if modulo feature is enabled
 - g. the `u32DstAddr` should align with `eDstAddrModulo` if modulo feature is enabled If any-one of above condition can not be satisfied, the edma interfaces will generate assert error.
-

Public Members

`uint32_t u32SrcAddr`
source address

`uint32_t u32DstAddr`
destination address

`edma_channel_transfer_width_t eSrcWidthOfEachTransfer`
source width of each transfer

`edma_channel_transfer_width_t eDstWidthOfEachTransfer`
destination width of each transfer

`uint32_t u32BytesEachMinorLoop`
bytes in each minor loop or each request range: $1 - (2^{30} - 1)$ when minor loop mapping is enabled range: $1 - (2^{10} - 1)$ when minor loop mapping is enabled and source or dest minor loop offset is enabled range: $1 - (2^{32} - 1)$ when minor loop mapping is disabled

`uint16_t u16MinorLoopCountsEachMajorLoop`
minor loop counts in each major loop, should be 1 at least for each transfer range: $(0 - (2^{15} - 1))$ when minor loop channel link is disabled range: $(0 - (2^9 - 1))$ when minor loop channel link is enabled total bytes in a transfer = `u16MinorLoopCountsEachMajorLoop * u32BytesEachMinorLoop`

`uint16_t u16EnabledInterruptMask`
channel interrupt to enable, can be OR'ed value of `_edma_channel_interrupt_enable`

`int16_t i16SrcOffsetOfEachTransfer`
Sign-extended offset value in byte unit applied to the current source address to form the next-state value as each source read is completed

`edma_channel_modulo_t eSrcAddrModulo`
source circular data queue range

`int32_t i32SrcMajorLoopOffset`
source major loop offset

`int16_t i16DstOffsetOfEachTransfer`
Sign-extended offset value in byte unit applied to the current destination address to form the next-state value as each destination write is completed.

`edma_channel_modulo_t eDstAddrModulo`
destination circular data queue range

`int32_t i32DstMajorLoopOffset`
destination major loop offset

`bool bEnableSrcMinorLoopOffset`
enable source minor loop offset

`bool bEnableDstMinorLoopOffset`
enable dest minor loop offset

`int32_t i32MinorLoopOffset`
burst offset, the offset will be applied after minor loop update

`bool bEnableChannelMajorLoopLink`
channel link when major loop complete

`edma_channel_t eMajorLoopLinkChannel`
major loop link channel number

`bool bEnableChannelMinorLoopLink`
channel link when minor loop complete

`edma_channel_t eMinorLoopLinkChannel`
minor loop link channel number

`edma_channel_bandwidth_t eChannelBandWidth`
channel bandwidth

`bool bDisableRequestAfterMajorLoopComplete`
the channel's ERQ bit can be cleared after the major loop complete automatically

`bool bEnableChannelRequest`
enable the channel request signal

`edma_channel_tcd_t *psLinkTCD`
pointer to the link transfer control descriptor

`struct __edma_channel_tcd`

#include <fsl_edma.h> eDMA software Transfer control descriptor structure.

This structure is same as eDMA hardware channel TCD registers, user doesn't need to understand the structures, since eDMA driver will responsible for configure it.

The software TCD is useful to configure a software TCD which is linked by the channel hardware TCD to have scatter/gather feature without using transactional interface.

Public Members

`__IO uint32_t u32SADDR`
SADDR register, used to save source address

`__IO uint16_t u16SOFF`
SOFF register, offset bytes added to source address every transfer

`__IO uint16_t u16ATTR`
ATTR register, source/destination transfer size and modulo

`__IO uint32_t u32NBYTES`
Nbytes register, minor loop length in bytes

`__IO uint32_t u32SLAST`
SLAST register, adjustment value added to the source address at the completion of the major loop

`__IO uint32_t u32DADDR`
DADDR register, used for destination address

`__IO uint16_t u16DOFF`
DOFF register, offset bytes added to destination address every transfer

`__IO uint16_t u16CITER`
CITER register, current minor loop numbers, for unfinished minor loop.

__IO uint32_t u32DLAST_SGA
DLASTSGA register, next tcd address used in scatter-gather mode

__IO uint16_t u16CSR
CSR register, for TCD control status

__IO uint16_t u16BITER
BITER register, begin minor loop count.

struct __edma_config
#include <fsl_edma.h> edma configuration structure
This structure target for whole edma module configurations.

Public Members

bool bEnableContinuousLinkMode
Enable (true) continuous link mode. Upon minor loop completion, the channel activates again if that channel has a minor loop channel link enabled and the link channel is itself.

bool bEnableHaltOnError
Enable (true) transfer halt on error. Any error causes the HALT bit to set. Subsequently, all service requests are ignored until the HALT bit is cleared.

bool bEnableDmaInDebugMode
Enable(true) eDMA debug mode. When in debug mode, the eDMA stalls the start of a new channel. Executing channels are allowed to complete.

bool bEnableMinorLoopMapping
TCDn.word2 is redefined to include individual enable fields, an offset field, and the NBYTES field. The individual enable fields allow the minor loop offset to be applied to the source address, the destination address, or both. The NBYTES field is reduced when either offset is enabled

edma_arbitration_type_t eArbitrationType
Enable (true) round robin channel arbitration method or fixed priority arbitration is used for channel selection

edma_channel_preemption_config_t sChannelPreemptionConfig[1]
channel preemption configuration

edma_channel_transfer_config_t *psChannelTransferConfig[1]
channel transfer configuration pointer

struct __edma_handle
#include <fsl_edma.h> eDMA transfer handle structure

Public Members

edma_transfer_callback_t pfCallback
Callback function for major count exhausted.

void *pUserData
Callback function parameter.

DMA_Type *psBase
eDMA peripheral base address.

edma_channel_tcd_t *psTcdPool

Pointer to memory stored TCDs.

edma_channel_t eChannel

eDMA channel number.

volatile uint8_t u8Header

The first TCD index. Should point to the next TCD to be loaded into the eDMA engine.

volatile uint8_t u8Tail

The last TCD index. Should point to the next TCD to be stored into the memory pool.

volatile uint8_t u8TcdUsed

The number of used TCD slots. Should reflect the number of TCDs can be used/loaded in the memory.

volatile uint8_t u8TcdSize

The total number of TCD slots in the queue.

2.20 The Driver Change Log

2.21 EDMA Peripheral and Driver Overview

2.22 EQDC: Enhanced Quadrature Decoder Driver

void EQDC_Init(EQDC_Type *base, const *eqdc_config_t* *psConfig)

Initializes the EQDC module.

This function initializes the EQDC by enabling the IP bus clock (optional).

Parameters

- base – EQDC peripheral base address.
- psConfig – Pointer to configuration structure.

void EQDC_GetDefaultConfig(*eqdc_config_t* *psConfig)

Gets an available pre-defined configuration.

The default value are:

```
psConfig->bEnableReverseDirection    = false;
psConfig->bCountOnce                  = false;
psConfig->eOperateMode                 = kEQDC_QuadratureDecodeOperationMode;
psConfig->eCountMode                   = kEQDC_QuadratureX4;
psConfig->eHomeEnableInitPosCounterMode = kEQDC_HomeInitPosCounterDisabled;
psConfig->eIndexPresetInitPosCounterMode = kEQDC_IndexInitPosCounterDisabled;
psConfig->bEnableDma                    = false;
psConfig->bBufferedRegisterLoadMode     = false;
psConfig->bEnableTriggerInitPositionCounter = false;
psConfig->bEnableTriggerClearPositionRegisters = false;
psConfig->bEnableTriggerHoldPositionRegisters = false;
psConfig->bEnableWatchdog               = false;
psConfig->u16WatchdogTimeoutValue       = 0xFFFFU;
psConfig->bFilterPhaseA                 = 0U;
psConfig->bFilterPhaseB                 = 0U;
psConfig->bFilterIndPre                  = 0U;
psConfig->bFilterHomEna                  = 0U;
```

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```

psConfig->bFilterClockSourceselection      = false;
psConfig->eFilterSampleCount              = kEQDC_Filter3Samples;
psConfig->u8FilterSamplePeriod            = 0U;
psConfig->eOutputPulseMode                = kEQDC_OutputPulseOnCounterEqualCompare;
psConfig->u32PositionCompareValue[0]      = 0xFFFFFFFFU;
psConfig->u32PositionCompareValue[1]      = 0xFFFFFFFFU;
psConfig->u32PositionCompareValue[2]      = 0xFFFFFFFFU;
psConfig->u32PositionCompareValue[3]      = 0xFFFFFFFFU;
psConfig->eRevolutionCountCondition        = kEQDC_RevolutionCountOnIndexPulse;
psConfig->bEnableModuloCountMode           = false;
psConfig->u32PositionModulusValue          = 0U;
psConfig->u32PositionInitialValue         = 0U;
psConfig->u32PositionCounterValue         = 0U;
psConfig->bEnablePeriodMeasurement         = false;
psConfig->ePrescaler                      = kEQDC_Prescaler1;
psConfig->u16EnabledInterruptsMask        = 0U;

```

Parameters

- psConfig – Pointer to configuration structure.

void EQDC_Deinit(EQDC_Type *base)

De-initializes the EQDC module.

This function deinitializes the EQDC by disabling the IP bus clock (optional).

Parameters

- base – EQDC peripheral base address.

void EQDC_SetOperateMode(EQDC_Type *base, *eqdc_operate_mode_t* eOperateMode)

Initializes the mode of operation.

This function initializes mode of operation by enabling the IP bus clock (optional).

Parameters

- base – EQDC peripheral base address.
- eOperateMode – Select operation mode.

static inline void EQDC_SetCountMode(EQDC_Type *base, *eqdc_count_mode_t* eCountMode)

Initializes the mode of count.

These bits control the basic counting and behavior of Position Counter and Position Difference Counter. Setting CTRL[REV] to 1 can reverse the counting direction. 1.In quadrature Mode (CTRL[PH1] = 0): 00b - CM0: Normal/Reverse Quadrature X4 01b - CM1: Normal/Reverse Quadrature X2 10b - CM2: Normal/Reverse Quadrature X1 11b - CM3: Reserved 2.In Single Phase Mode (CTRL[PH1] = 1): 00b - CM0: UP/DOWN Pulse Count Mode 01b - CM1: Signed Mode, count PHASEA rising/falling edge, position counter counts up when PHASEB is low and counts down when PHASEB is high 10b - CM2: Signed Count Mode, count PHASEA rising edge only, position counter counts up when PHASEB is low and counts down when PHASEB is high 11b - CM3: Reserved

Parameters

- base – EQDC peripheral base address.
- eCountMode – Select count mode.

static inline void EQDC_EnableWatchdog(EQDC_Type *base, bool bEnable)

Enable watchdog for EQDC module.

Parameters

- base – EQDC peripheral base address

- bEnable – Enables or disables the watchdog

static inline void EQDC_SetWatchdogTimeout(EQDC_Type *base, uint16_t u16Timeout)

Set watchdog timeout value.

Parameters

- base – EQDC peripheral base address
- u16Timeout – Number of clock cycles, plus one clock cycle that the watchdog timer counts before timing out

static inline void EQDC_EnableDMA(EQDC_Type *base, bool bEnable)

Enable DMA for EQDC module.

Parameters

- base – EQDC peripheral base address
- bEnable – Enables or disables the DMA

static inline void EQDC_SetBufferedRegisterLoadUpdateMode(EQDC_Type *base)

Set Buffered Register Load (Update) Mode.

This bit selects the loading time point of the buffered compare registers UCOMPx/LCOMPx, x=0~3, initial register (UNIT/LINIT), and modulus register (UMOD/LMOD). Buffered registers are loaded and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address

static inline void EQDC_ClearBufferedRegisterLoadUpdateMode(EQDC_Type *base)

Clear Buffered Register Load (Update) Mode.

Buffered Register Load (Update) Mode bit selects the loading time point of the buffered compare registers UCOMPx/LCOMPx, x=0~3, initial register (UNIT/LINIT), and modulus register (UMOD/LMOD). Buffered registers are loaded and take effect immediately upon CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address

static inline void EQDC_SetEqdcLdok(EQDC_Type *base)

Set load okay.

Load okay enables that the outer-set values of buffered compare registers (UCOMPx/LCOMPx, x=0~3), initial register(UNIT/LINIT) and modulus register(UMOD/LMOD) can be loaded into their inner-sets and take effect. When LDOK is set, this loading action occurs at the next position counter roll-over or roll-under if CTRL2[LDMOD] is set, or it occurs immediately if CTRL2[LDMOD] is cleared. LDOK is automatically cleared after the values in outer-set is loaded into the inner-set.

Parameters

- base – EQDC peripheral base address.

static inline uint8_t EQDC_GetEqdcLdok(EQDC_Type *base)

Get load okay.

Parameters

- base – EQDC peripheral base address.

static inline void EQDC_ClearEqdcLdok(EQDC_Type *base)

Clear load okay.

Parameters

- base – EQDC peripheral base address.

static inline uint32_t EQDC_GetStatusFlags(EQDC_Type *base)

Get the status flags.

Parameters

- base – EQDC peripheral base address.

Returns

Logical OR'ed value of the status flags, `_eqdc_status_flags`.

static inline void EQDC_ClearStatusFlags(EQDC_Type *base, uint32_t u32Flags)

Clear the status flags.

Parameters

- base – EQDC peripheral base address.
- u32Flags – Logical OR'ed value of the flags to clear, `_eqdc_status_flags`.

static inline uint16_t EQDC_GetSignalStatusFlags(EQDC_Type *base)

Get the signals' real-time status.

Parameters

- base – EQDC peripheral base address.

Returns

Logical OR'ed value of the real-time signal status, `_eqdc_signal_status`.

static inline *eqdc_count_direction_flag_t* EQDC_GetLastCountDirection(EQDC_Type *base)

Get the direction of the last count.

Parameters

- base – EQDC peripheral base address.

Returns

Direction of the last count.

static inline void EQDC_EnableInterrupts(EQDC_Type *base, uint32_t u32Interrupts)

Enable the interrupts.

Parameters

- base – EQDC peripheral base address.
- u32Interrupts – Logical OR'ed value of the interrupts, `_eqdc_interrupt_enable`.

static inline void EQDC_DisableInterrupts(EQDC_Type *base, uint32_t u32Interrupts)

Disable the interrupts.

Parameters

- base – EQDC peripheral base address.
- u32Interrupts – Logical OR'ed value of the interrupts, `_eqdc_interrupt_enable`.

static inline void EQDC_DoSoftwareLoadInitialPositionValue(EQDC_Type *base)

Load the initial position value to position counter.

Software trigger to load the initial position value (UNIT and LINIT) contents to position counter (UPOS and LPOS), so that to provide the consistent operation the position counter registers.

Parameters

- base – EQDC peripheral base address.

```
static inline void EQDC_SetInitialPositionValue(EQDC_Type *base, uint32_t
                                              u32PositionInitValue)
```

Set initial position value for EQDC module.

Set the position counter initial value (UNIT, LINIT). After writing values to the UNIT and LINIT registers, the values are “buffered” into outer-set registers temporarily. Values will be loaded into inner-set registers and take effect using the following two methods:

- a. If CTRL2[LDMODE] is 1, “buffered” values are loaded into inner-set and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.
- b. If CTRL2[LDMODE] is 0, “buffered” values are loaded into inner-set and take effect immediately when CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address
- u32PositionInitValue – Position initial value

```
static inline void EQDC_SetPositionCounterValue(EQDC_Type *base, uint32_t
                                              u32PositionCounterValue)
```

Set position counter value.

Set the position counter value (POS or UPOS, LPOS).

Parameters

- base – EQDC peripheral base address
- u32PositionCounterValue – Position counter value

```
static inline void EQDC_SetPositionModulusValue(EQDC_Type *base, uint32_t
                                              u32PositionModulusValue)
```

Set position counter modulus value.

Set the position counter modulus value (UMOD, LMOD). After writing values to the UMOD and LMOD registers, the values are “buffered” into outer-set registers temporarily. Values will be loaded into inner-set registers and take effect using the following two methods:

- a. If CTRL2[LDMODE] is 1, “buffered” values are loaded into inner-set and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.
- b. If CTRL2[LDMODE] is 0, “buffered” values are loaded into inner-set and take effect immediately when CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address
- u32PositionModulusValue – Position modulus value

```
static inline void EQDC_SetPositionCompare0Value(EQDC_Type *base, uint32_t
                                              u32PositionComp0Value)
```

Set position counter compare 0 value.

Set the position counter compare 0 value (UCOMP0, LCOMP0). After writing values to the UCOMP0 and LCOMP0 registers, the values are “buffered” into outer-set registers temporarily. Values will be loaded into inner-set registers and take effect using the following two methods:

- a. If CTRL2[LDMODE] is 1, “buffered” values are loaded into inner-set and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.

- b. If CTRL2[LDMODE] is 0, “buffered” values are loaded into inner-set and take effect immediately when CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address
- u32PositionComp0Value – Position modulus value

```
static inline void EQDC_SetPositionCompare1Value(EQDC_Type *base, uint32_t
                                                u32PositionComp1Value)
```

Set position counter compare 1 value.

Set the position counter compare 1 value (UCOMP1, LCOMP1). After writing values to the UCOMP1 and LCOMP1 registers, the values are “buffered” into outer-set registers temporarily. Values will be loaded into inner-set registers and take effect using the following two methods:

- a. If CTRL2[LDMODE] is 1, “buffered” values are loaded into inner-set and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.
- b. If CTRL2[LDMODE] is 0, “buffered” values are loaded into inner-set and take effect immediately when CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address
- u32PositionComp1Value – Position modulus value

```
static inline void EQDC_SetPositionCompare2Value(EQDC_Type *base, uint32_t
                                                u32PositionComp2Value)
```

Set position counter compare 2 value.

Set the position counter compare 2 value (UCOMP2, LCOMP2). After writing values to the UCOMP2 and LCOMP2 registers, the values are “buffered” into outer-set registers temporarily. Values will be loaded into inner-set registers and take effect using the following two methods:

- a. If CTRL2[LDMODE] is 1, “buffered” values are loaded into inner-set and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.
- b. If CTRL2[LDMODE] is 0, “buffered” values are loaded into inner-set and take effect immediately when CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address
- u32PositionComp2Value – Position modulus value

```
static inline void EQDC_SetPositionCompare3Value(EQDC_Type *base, uint32_t
                                                u32PositionComp3Value)
```

Set position counter compare 3 value.

Set the position counter compare 3 value (UCOMP3, LCOMP3). After writing values to the UCOMP3 and LCOMP3 registers, the values are “buffered” into outer-set registers temporarily. Values will be loaded into inner-set registers and take effect using the following two methods:

- a. If CTRL2[LDMODE] is 1, “buffered” values are loaded into inner-set and take effect at the next roll-over or roll-under if CTRL[LDOK] is set.
- b. If CTRL2[LDMODE] is 0, “buffered” values are loaded into inner-set and take effect immediately when CTRL[LDOK] is set.

Parameters

- base – EQDC peripheral base address
- u32PositionComp3Value – Position modulus value

```
static inline uint32_t EQDC_GetPosition(EQDC_Type *base)
```

Get the current position counter's value.

Parameters

- base – EQDC peripheral base address.

Returns

Current position counter's value.

```
static inline uint32_t EQDC_GetHoldPosition(EQDC_Type *base)
```

Get the hold position counter's value.

The position counter (POS or UPOS, LPOS) value is loaded to hold position (POSH or UPOSH, LPOSH) when:

- a. Position register (POS or UPOS, LPOS), or position difference register (POSD), or revolution register (REV) is read.
- b. TRIGGER happens and TRIGGER is enabled to update the hold registers.

Parameters

- base – EQDC peripheral base address.

Returns

Hold position counter's value.

```
static inline uint32_t EQDC_GetHoldPosition1(EQDC_Type *base)
```

Get the hold position counter1's value.

The Upper Position Counter Hold Register 1(UPOSH1) shares the same address with UCOMP1. When read, this register means the value of UPOSH1, which is the upper 16 bits of POSH1. The Lower Position Counter Hold Register 1(LPOSH1) shares the same address with LCOMP1. When read, this register means the value of LPOSH1, which is the lower 16 bits of POSH1. Position counter is captured into POSH1 on the rising edge of ICAP[1].

Parameters

- base – EQDC peripheral base address.

Returns

Hold position counter1's value.

```
static inline uint32_t EQDC_GetHoldPosition2(EQDC_Type *base)
```

Get the hold position counter2's value.

The Upper Position Counter Hold Register 2(UPOSH2) shares the same address with UCOMP2. When read, this register means the value of UPOSH2, which is the upper 16 bits of POSH2. The Lower Position Counter Hold Register 2(LPOSH2) shares the same address with LCOMP2. When read, this register means the value of LPOSH2, which is the lower 16 bits of POSH2. Position counter is captured into POSH2 on the rising edge of ICAP[2].

Parameters

- base – EQDC peripheral base address.

Returns

Hold position counter2's value.

```
static inline uint32_t EQDC_GetHoldPosition3(EQDC_Type *base)
```

Get the hold position counter3's value.

The Upper Position Counter Hold Register 3(UPOSH3) shares the same address with UCOMP3. When read, this register means the value of UPOSH3, which is the upper 16 bits of POSH3. The Lower Position Counter Hold Register 3(LPOSH3) shares the same address with LCOMP3. When read, this register means the value of LPOSH3, which is the lower 16 bits of POSH3. Position counter is captured into POSH3 on the rising edge of ICAP[3].

Parameters

- base – EQDC peripheral base address.

Returns

Hold position counter3's value.

```
static inline uint16_t EQDC_GetPositionDifference(EQDC_Type *base)
```

Get the position difference counter's value.

Parameters

- base – EQDC peripheral base address.

Returns

The position difference counter's value.

```
static inline uint16_t EQDC_GetHoldPositionDifference(EQDC_Type *base)
```

Get the hold position difference counter's value.

The position difference (POSD) value is loaded to hold position difference (POSDH) when:

- Position register (POS or UPOS, LPOS), or position difference register (POSD), or revolution register (REV) is read. When Period Measurement is enabled (CTRL3[PMEN] = 1), POSDH will only be updated when reading POSD.
- TRIGGER happens and TRIGGER is enabled to update the hold registers.

Parameters

- base – EQDC peripheral base address.

Returns

Hold position difference counter's value.

```
static inline uint16_t EQDC_GetRevolution(EQDC_Type *base)
```

Get the revolution counter's value.

Get the revolution counter (REV) value.

Parameters

- base – EQDC peripheral base address.

Returns

The revolution counter's value.

```
static inline uint16_t EQDC_GetHoldRevolution(EQDC_Type *base)
```

Get the hold revolution counter's value.

The revolution counter (REV) value is loaded to hold revolution (REXH) when:

- Position register (POS or UPOS, LPOS), or position difference register (POSD), or revolution register (REV) is read.
- TRIGGER happens and TRIGGER is enabled to update the hold registers.

Parameters

- base – EQDC peripheral base address.

Returns

Hold position revolution counter's value.

```
static inline uint16_t EQDC_GetLastEdgeTime(EQDC_Type *base)
```

Get the last edge time.

Last edge time (LASTEDGE) is the time since the last edge occurred on PHASEA or PHASEB. The last edge time register counts up using the peripheral clock after prescaler. Any edge on PHASEA or PHASEB will reset this register to 0 and start counting. If the last edge timer count reaches 0xffff, the counting will stop in order to prevent an overflow. Counting will continue when an edge occurs on PHASEA or PHASEB.

Parameters

- base – EQDC peripheral base address.

Returns

The last edge time.

```
static inline uint16_t EQDC_GetHoldLastEdgeTime(EQDC_Type *base)
```

Get the hold last edge time.

The hold of last edge time (LASTEDGEH) is update to last edge time (LASTEDGE) when the position difference register (POSD) is read.

Parameters

- base – EQDC peripheral base address.

Returns

Hold of last edge time.

```
static inline uint16_t EQDC_GetPositionDifferencePeriod(EQDC_Type *base)
```

Get the Position Difference Period counter value.

The Position Difference Period counter (POSDPER) counts up using the prescaled peripheral clock. When reading the position difference register (POSD), the last edge time (LASTEDGE) will be loaded to position difference period counter (POSDPER). If the POSDPER count reaches 0xffff, the counting will stop in order to prevent an overflow. Counting will continue when an edge occurs on PHASEA or PHASEB.

Parameters

- base – EQDC peripheral base address.

Returns

The position difference period counter value.

```
static inline uint16_t EQDC_GetBufferedPositionDifferencePeriod(EQDC_Type *base)
```

Get buffered Position Difference Period counter value.

The Bufferd Position Difference Period (POSDPERBFR) value is updated with the position difference period counter (POSDPER) when any edge occurs on PHASEA or PHASEB.

Parameters

- base – EQDC peripheral base address.

Returns

The buffered position difference period counter value.

```
static inline uint16_t EQDC_GetHoldPositionDifferencePeriod(EQDC_Type *base)
```

Get Hold Position Difference Period counter value.

The hold position difference period (POSDPERH) is updated with the value of buffered position difference period (POSDPERBFR) when the position difference (POSD) register is read.

Parameters

- base – EQDC peripheral base address.

Returns

The hold position difference period counter value.

FSL_EQDC_DRIVER_VERSION

EQDC driver version.

enum __eqdc_status_flags

EQDC status flags, these flags indicate the counter's events. .

Values:

enumerator kEQDC_HomeEnableTransitionFlag

HOME/ENABLE signal transition occurred.

enumerator kEQDC_IndexPresetPulseFlag

INDEX/PRESET pulse occurred.

enumerator kEQDC_WatchdogTimeoutFlag

Watchdog timeout occurred.

enumerator kEQDC_SimultPhaseChangeFlag

Simultaneous change of PHASEA and PHASEB occurred.

enumerator kEQDC_CountDirectionChangeFlag

Count direction change interrupt enable.

enumerator kEQDC_PositionRollOverFlag

Position counter rolls over from 0xFFFFFFFF to 0, or from MOD value to INIT value.

enumerator kEQDC_PositionRollUnderFlag

Position register roll under from 0 to 0xFFFFFFFF, or from INIT value to MOD value.

enumerator kEQDC_PositionCompare0Flag

Position counter match the COMP0 value.

enumerator kEQDC_PositionCompare1Flag

Position counter match the COMP1 value.

enumerator kEQDC_PositionCompare2Flag

Position counter match the COMP2 value.

enumerator kEQDC_PositionCompare3Flag

Position counter match the COMP3 value.

enumerator kEQDC_StatusAllFlags

enum __eqdc_signal_status

Signal status, these flags indicate the raw and filtered input signal status. .

Values:

enumerator kEQDC_SignalStatusRawHomeEnable

Raw HOME/ENABLE input.

enumerator kEQDC_SignalStatusRawIndexPreset

Raw INDEX/PRESET input.

enumerator kEQDC_SignalStatusRawPhaseB

Raw PHASEB input.

enumerator kEQDC_SignalStatusRawPhaseA

Raw PHASEA input.

enumerator kEQDC_SignalStatusFilteredHomeEnable

The filtered HOME/ENABLE input.

enumerator kEQDC_SignalStatusFilteredIndexPreset

The filtered INDEX/PRESET input.

enumerator kEQDC_SignalStatusFilteredPhaseB

The filtered PHASEB input.

enumerator kEQDC_SignalStatusFilteredPhaseA

The filtered PHASEA input.

enumerator kEQDC_SignalStatusPositionCompare0Flag

Position Compare 0 Flag Output.

enumerator kEQDC_SignalStatusPositionCompare1Flag

Position Compare 1 Flag Output.

enumerator kEQDC_SignalStatusPositionCompare2Flag

Position Compare 2 Flag Output.

enumerator kEQDC_SignalStatusPositionCompare3Flag

Position Compare 3 Flag Output.

enumerator kEQDC_SignalStatusCountDirectionFlagHold

Count Direction Flag Hold.

enumerator kEQDC_SignalStatusCountDirectionFlag

Count Direction Flag Output.

enumerator kEQDC_SignalStatusAllFlags

enum _eqdc_interrupt_enable

Interrupt enable/disable mask. .

Values:

enumerator kEQDC_HomeEnableTransitionInterruptEnable

HOME/ENABLE signal transition interrupt enable.

enumerator kEQDC_IndexPresetPulseInterruptEnable

INDEX/PRESET pulse interrupt enable.

enumerator kEQDC_WatchdogTimeoutInterruptEnable

Watchdog timeout interrupt enable.

enumerator kEQDC_SimultPhaseChangeInterruptEnable

Simultaneous PHASEA and PHASEB change interrupt enable.

enumerator kEQDC_PositionRollOverInterruptEnable

Roll-over interrupt enable.

enumerator kEQDC_PositionRollUnderInterruptEnable

Roll-under interrupt enable.

enumerator kEQDC_PositionCompare0InterruptEnable

Position compare 0 interrupt enable.

enumerator kEQDC_PositionCompare1InterruptEnable

Position compare 1 interrupt enable.

enumerator kEQDC_PositionCompare2InterruptEnable

Position compare 2 interrupt enable.

enumerator kEQDC_PositionCompare3InterruptEnable

Position compare 3 interrupt enable.

enumerator kEQDC_AllInterruptEnable

enum _eqdc_home_enable_init_pos_counter_mode

Define HOME/ENABLE signal's trigger mode.

Values:

enumerator kEQDC_HomeInitPosCounterDisabled

Don't use HOME/ENABLE signal to initialize the position counter.

enumerator kEQDC_HomeInitPosCounterOnRisingEdge

Use positive going edge to trigger initialization of position counters.

enumerator kEQDC_HomeInitPosCounterOnFallingEdge

Use negative going edge to trigger initialization of position counters.

enum _eqdc_index_preset_init_pos_counter_mode

Define INDEX/PRESET signal's trigger mode.

Values:

enumerator kEQDC_IndexInitPosCounterDisabled

INDEX/PRESET pulse does not initialize the position counter.

enumerator kEQDC_IndexInitPosCounterOnRisingEdge

Use INDEX/PRESET pulse rising edge to initialize position counter.

enumerator kEQDC_IndexInitPosCounterOnFallingEdge

Use INDEX/PRESET pulse falling edge to initialize position counter.

enum _eqdc_operate_mode

Define type for decoder operation mode.

The Quadrature Decoder operates in following 4 operation modes: 1.Quadrature Decode(QDC) Operation Mode (CTRL[PH1] = 0,CTRL2[OPMODE] = 0) In QDC operation mode, Module uses PHASEA, PHASEB, INDEX, HOME, TRIGGER and ICAP[3:1] to decode the PHASEA and PHASEB signals from Speed/Position sensor. 2.Quadrature Count(QCT) Operation Mode (CTRL[PH1] = 0,CTRL2[OPMODE] = 1) In QCT operation mode, Module uses PHASEA, PHASEB, PRESET, ENABLE, TRIGGER and ICAP[3:1] to count the PHASEA and PHASEB signals from Speed/Position sensor. 3.Single Phase Decode(PH1DC) Operation Mode (CTRL[PH1] = 1,CTRL2[OPMODE] = 0) In PH1DC operation mode, the module uses PHASEA, PHASEB, INDEX, HOME, TRIGGER and ICAP[3:1] to decode the PHASEA and PHASEB signals from Speed/Position sensor. 4.Single Phase Count(PH1CT) Operation Mode (CTRL[PH1] = 1,CTRL2[OPMODE] = 1) In PH1CT operation mode, the module uses PHASEA, PHASEB, PRESET, ENABLE, TRIGGER and ICAP[3:1] to count the PHASEA and PHASEB signals from Speed/Position sensor.

Values:

enumerator kEQDC_QuadratureDecodeOperationMode

Use standard quadrature decoder with PHASEA/PHASEB, INDEX/HOME.

enumerator kEQDC_QuadratureCountOperationMode

Use quadrature count operation mode with PHASEA/PHASEB, PRESET/ENABLE.

enumerator kEQDC_SinglePhaseDecodeOperationMode

Use single phase quadrature decoder with PHASEA/PHASEB, INDEX/HOME.

enumerator kEQDC_SinglePhaseCountOperationMode

Use single phase count decoder with PHASEA/PHASEB, PRESET/ENABLE.

enum _eqdc_count_mode

Define type for decoder count mode.

In decode mode, it uses the standard quadrature decoder with PHASEA and PHASEB, PHASEA = 0 and PHASEB = 0 mean reverse direction.

- If PHASEA leads PHASEB, then motion is in the positive direction.
- If PHASEA trails PHASEB, then motion is in the negative direction. In single phase mode, there are three count modes:
- In Signed Count mode (Single Edge). Both position counter (POS) and position difference counter (POSD) count on the input PHASEA rising edge while the input PHASEB provides the selected position counter direction (up/down). If CTRL[REV] is 1, then the position counter will count in the opposite direction.
- In Signed Count mode (double edge), both position counter (POS) and position difference counter (POSD) count the input PHASEA on both rising edge and falling edge while the input PHASEB provides the selected position counter direction (up/down).
- In UP/DOWN Pulse Count mode. Both position counter (POS) and position difference counter (POSD) count in the up direction when input PHASEA rising edge occurs. Both counters count in the down direction when input PHASEB rising edge occurs. If CTRL[REV] is 1, then the position counter will count in the opposite direction.

Values:

enumerator kEQDC_QuadratureX4

Active on kEQDC_QuadratureDecodeOperationMode/kEQDC_QuadratureCountOperationMode.

enumerator kEQDC_QuadratureX2

Active on kEQDC_QuadratureDecodeOperationMode/kEQDC_QuadratureCountOperationMode.

enumerator kEQDC_QuadratureX1

Active on kEQDC_QuadratureDecodeOperationMode/kEQDC_QuadratureCountOperationMode.

enumerator kEQDC_UpDownPulseCount

Active on kEQDC_SinglePhaseDecodeOperationMode/kEQDC_SinglePhaseCountOperationMode.

enumerator kEQDC_SignedCountDoubleEdge

Active on kEQDC_SinglePhaseDecodeOperationMode/kEQDC_SinglePhaseCountOperationMode.

enumerator kEQDC_SignedCountSingleEdge

Active on kEQDC_SinglePhaseDecodeOperationMode/kEQDC_SinglePhaseCountOperationMode.

enum _eqdc_output_pulse_mode

Define type for the condition of POSMATCH pulses.

Values:

enumerator kEQDC_OutputPulseOnCounterEqualCompare

POSMATCH pulses when a match occurs between the position counters (POS) and the compare value (UCOMPx/LCOMPx)(x range is 0-3).

enumerator kEQDC_OutputPulseOnReadingPositionCounter

POSMATCH pulses when reading position counter(POS and LPOS), revolution counter(REV), position difference counter(POSD).

enum _eqdc_revolution_count_condition

Define type for determining how the revolution counter (REV) is incremented/decremented.

Values:

enumerator kEQDC_RevolutionCountOnIndexPulse

Use INDEX pulse to increment/decrement revolution counter.

enumerator kEQDC_RevolutionCountOnRollOverModulus

Use modulus counting roll-over/under to increment/decrement revolution counter.

enum __eqdc_filter_sample_count

Input Filter Sample Count.

The Input Filter Sample Count represents the number of consecutive samples that must agree, before the input filter accepts an input transition

Values:

enumerator kEQDC_Filter3Samples

3 samples.

enumerator kEQDC_Filter4Samples

4 samples.

enumerator kEQDC_Filter5Samples

5 samples.

enumerator kEQDC_Filter6Samples

6 samples.

enumerator kEQDC_Filter7Samples

7 samples.

enumerator kEQDC_Filter8Samples

8 samples.

enumerator kEQDC_Filter9Samples

9 samples.

enumerator kEQDC_Filter10Samples

10 samples.

enum __eqdc_count_direction_flag

Count direction.

Values:

enumerator kEQDC_CountDirectionDown

Last count was in down direction.

enumerator kEQDC_CountDirectionUp

Last count was in up direction.

enum __eqdc_prescaler

Prescaler used by Last Edge Time (LASTEDGE) and Position Difference Period Counter (POS-DPER).

Values:

enumerator kEQDC_Prescaler1

Prescaler value 1.

enumerator kEQDC_Prescaler2

Prescaler value 2.

enumerator kEQDC_Prescaler4

Prescaler value 4.

enumerator kEQDC_Prescaler8

Prescaler value 8.

enumerator kEQDC_Prescaler16

Prescaler value 16.

enumerator kEQDC_Prescaler32

Prescaler value 32.

enumerator kEQDC_Prescaler64

Prescaler value 64.

enumerator kEQDC_Prescaler128

Prescaler value 128.

enumerator kEQDC_Prescaler256

Prescaler value 256.

enumerator kEQDC_Prescaler512

Prescaler value 512.

enumerator kEQDC_Prescaler1024

Prescaler value 1024.

enumerator kEQDC_Prescaler2048

Prescaler value 2048.

enumerator kEQDC_Prescaler4096

Prescaler value 4096.

enumerator kEQDC_Prescaler8192

Prescaler value 8192.

enumerator kEQDC_Prescaler16384

Prescaler value 16384.

enumerator kEQDC_Prescaler32768

Prescaler value 32768.

`typedef enum _eqdc_home_enable_init_pos_counter_mode`

`eqdc_home_enable_init_pos_counter_mode_t`

Define HOME/ENABLE signal's trigger mode.

`typedef enum _eqdc_index_preset_init_pos_counter_mode`

`eqdc_index_preset_init_pos_counter_mode_t`

Define INDEX/PRESET signal's trigger mode.

`typedef enum _eqdc_operate_mode eqdc_operate_mode_t`

Define type for decoder operation mode.

The Quadrature Decoder operates in following 4 operation modes: 1.Quadrature Decode(QDC) Operation Mode (CTRL[PH1] = 0,CTRL2[OPMODE] = 0) In QDC operation mode, Module uses PHASEA, PHASEB, INDEX, HOME, TRIGGER and ICAP[3:1] to decode the PHASEA and PHASEB signals from Speed/Position sensor. 2.Quadrature Count(QCT) Operation Mode (CTRL[PH1] = 0,CTRL2[OPMODE] = 1) In QCT operation mode, Module uses PHASEA, PHASEB, PRESET, ENABLE, TRIGGER and ICAP[3:1] to count the PHASEA and PHASEB signals from Speed/Position sensor. 3.Single Phase Decode(PH1DC) Operation Mode (CTRL[PH1] = 1,CTRL2[OPMODE] = 0) In PH1DC operation mode, the module uses PHASEA, PHASEB, INDEX, HOME, TRIGGER and ICAP[3:1] to decode the PHASEA and PHASEB signals from Speed/Position sensor. 4.Single Phase Count(PH1CT) Operation Mode (CTRL[PH1] = 1,CTRL2[OPMODE] = 1) In PH1CT operation mode, the module uses PHASEA, PHASEB, PRESET, ENABLE, TRIGGER and ICAP[3:1] to count the PHASEA and PHASEB signals from Speed/Position sensor.

`typedef enum _eqdc_count_mode eqdc_count_mode_t`

Define type for decoder count mode.

In decode mode, it uses the standard quadrature decoder with PHASEA and PHASEB, PHASEA = 0 and PHASEB = 0 mean reverse direction.

- If PHASEA leads PHASEB, then motion is in the positive direction.
- If PHASEA trails PHASEB, then motion is in the negative direction. In single phase mode, there are three count modes:
- In Signed Count mode (Single Edge). Both position counter (POS) and position difference counter (POSD) count on the input PHASEA rising edge while the input PHASEB provides the selected position counter direction (up/down). If CTRL[REV] is 1, then the position counter will count in the opposite direction.
- In Signed Count mode (double edge), both position counter (POS) and position difference counter (POSD) count the input PHASEA on both rising edge and falling edge while the input PHASEB provides the selected position counter direction (up/down).
- In UP/DOWN Pulse Count mode. Both position counter (POS) and position difference counter (POSD) count in the up direction when input PHASEA rising edge occurs. Both counters count in the down direction when input PHASEB rising edge occurs. If CTRL[REV] is 1, then the position counter will count in the opposite direction.

`typedef enum _eqdc_output_pulse_mode eqdc_output_pulse_mode_t`

Define type for the condition of POSMATCH pulses.

`typedef enum _eqdc_revolution_count_condition eqdc_revolution_count_condition_t`

Define type for determining how the revolution counter (REV) is incremented/decremented.

`typedef enum _eqdc_filter_sample_count eqdc_filter_sample_count_t`

Input Filter Sample Count.

The Input Filter Sample Count represents the number of consecutive samples that must agree, before the input filter accepts an input transition

`typedef enum _eqdc_count_direction_flag eqdc_count_direction_flag_t`

Count direction.

`typedef enum _eqdc_prescaler eqdc_prescaler_t`

Prescaler used by Last Edge Time (LASTEDGE) and Position Difference Period Counter (POSDPER).

`typedef struct _eqdc_config eqdc_config_t`

Define user configuration structure for EQDC module.

`EQDC_CTRL_W1C_FLAGS`

W1C bits in EQDC CTRL registers.

`EQDC_INTCTRL_W1C_FLAGS`

W1C bits in EQDC INTCTRL registers.

`EQDC_CTRL_INT_EN`

Interrupt enable bits in EQDC CTRL registers.

`EQDC_INTCTRL_INT_EN`

Interrupt enable bits in EQDC INTCTRL registers.

`EQDC_CTRL_INT_FLAGS`

Interrupt flag bits in EQDC CTRL registers.

EQDC_INTCTRL_INT_FLAGS

Interrupt flag bits in EQDC INTCTRL registers.

struct __eqdc_config

#include <fsl_eqdc.h> Define user configuration structure for EQDC module.

Public Members

bool bEnableReverseDirection

Enable reverse direction counting.

bool bCountOnce

Selects modulo loop or one shot counting mode.

bool bEnableDma

Enable DMA for new written buffer values of COMPx/INIT/MOD(x range is 0-3)

bool bBufferedRegisterLoadMode

selects the loading time point of the buffered compare registers UCOMPx/LCOMPx, x=0~3, initial register (UINIT/LINIT), and modulus register (UMOD/LMOD).

bool bEnableTriggerInitPositionCounter

Initialize position counter with initial register(UINIT, LINIT) value on TRIGGER's rising edge.

bool bEnableTriggerClearPositionRegisters

Clear position counter(POS), revolution counter(REV), position difference counter (POSD) on TRIGGER's rising edge.

bool bEnableTriggerHoldPositionRegisters

Load position counter(POS), revolution counter(REV), position difference counter (POSD) values to hold registers on TRIGGER's rising edge.

bool bFilterPhaseA

Filter operation on PHASEA input, when write 1, it means filter for PHASEA input is bypassed.

bool bFilterPhaseB

Filter operation on PHASEB input, when write 1, it means filter for PHASEB input is bypassed.

bool bFilterIndPre

Filter operation on INDEX/PRESET input, when write 1, it means filter for INDEX/PRESET input is bypassed.

bool bFilterHomEna

Filter operation on HOME/ENABLE input, when write 1, it means filter for HOME/ENABLE input is bypassed.

bool bEnableWatchdog

Enable the watchdog to detect if the target is moving or not.

uint16_t u16WatchdogTimeoutValue

Watchdog timeout count value. It stores the timeout count for the quadrature decoder module watchdog timer.

eqdc_prescaler_t ePrescaler

Prescaler.

bool bFilterClockSourceselection

Filter Clock Source selection.

eqdc_filter_sample_count_t eFilterSampleCount

Input Filter Sample Count. This value should be chosen to reduce the probability of noisy samples causing an incorrect transition to be recognized. The value represent the number of consecutive samples that must agree prior to the input filter accepting an input transition.

uint8_t u8FilterSamplePeriod

Input Filter Sample Period. This value should be set such that the sampling period is larger than the period of the expected noise. This value represents the sampling period (in IPBus clock cycles) of the decoder input signals. The available range is 0 - 255.

eqdc_operate_mode_t eOperateMode

Selects operation mode.

eqdc_count_mode_t eCountMode

Selects count mode.

eqdc_home_enable_init_pos_counter_mode_t eHomeEnableInitPosCounterMode

Select how HOME/Enable signal used to initialize position counters.

eqdc_index_preset_init_pos_counter_mode_t eIndexPresetInitPosCounterMode

Select how INDEX/Preset signal used to initialize position counters.

eqdc_output_pulse_mode_t eOutputPulseMode

The condition of POSMATCH pulses.

uint32_t u32PositionCompareValue[4]

Position compare 0 ~ 3 value. The available value is a 32-bit number.

eqdc_revolution_count_condition_t eRevolutionCountCondition

Revolution Counter Modulus Enable.

bool bEnableModuloCountMode

Enable Modulo Counting.

uint32_t u32PositionModulusValue

Position modulus value. Only used when bEnableModuloCountMode is true. The available value is a 32-bit number.

uint32_t u32PositionInitialValue

Position initial value. The available value is a 32-bit number.

uint32_t u32PositionCounterValue

Position counter value. When Modulo mode enabled, the u32PositionCounterValue should be in the range of u32PositionInitialValue and u32PositionModulusValue.

bool bEnablePeriodMeasurement

Enable period measurement. When enabled, the position difference hold register (POSDH) is only updated when position difference register (POSD) is read.

uint16_t u16EnabledInterruptsMask

Mask of interrupts to be enabled, should be OR'ed value of *_eqdc_interrupt_enable*.

2.23 EQDC Peripheral and Driver Overview

2.24 EVTG: Event Generator Driver

`void EVTG_Init(EVTG_Type *base, evtg_index_t eEvtgIndex, evtg_config_t *psConfig)`
Initialize EVTG with a user configuration structure.

Parameters

- base – EVTG base address.
- eEvtgIndex – EVTG instance index.
- psConfig – EVTG initial configuration structure pointer.

`static inline void EVTG_GetDefaultConfig(evtg_config_t *psConfig, evtg_flipflop_mode_t eFlipflopMode)`

Loads default values to the EVTG configuration structure.

The purpose of this API is to initialize the configuration structure to default value for `EVTG_Init()` to use. The Flip-Flop can be configured as Bypass mode, RS trigger mode, T-FF mode, D-FF mode, JK-FF mode, Latch mode. Please check RM INTC chapter for more details.

Parameters

- psConfig – EVTG initial configuration structure pointer.
- eFlipflopMode – EVTG flip flop mode. see @ ref `_evtg_flipflop_mode`

`static inline void EVTG_ForceFlipflopInitOutput(EVTG_Type *base, evtg_index_t eEvtgIndex, evtg_flipflop_init_output_t eFlipflopInitOutputValue)`

Force Flip-flop initial output value to be presented on flip-flop positive output.

Parameters

- base – EVTG base address.
- eEvtgIndex – EVTG instance index.
- eFlipflopInitOutputValue – EVTG flip-flop initial output control. see `evtg_flipflop_init_output_t`

`static inline void EVTG_SetProductTermInput(EVTG_Type *base, evtg_index_t eEvtgIndex, evtg_aoi_index_t eAOIIndex, evtg_aoi_product_term_t eProductTerm, evtg_input_index_t eInputIndex, evtg_aoi_input_config_t eInput)`

Configure each input value of AOI product term. Each selected input term in each product term can be configured to produce a logical 0 or 1 or pass the true or complement of the selected event input. Adapt to some simple aoi expressions.

Parameters

- base – EVTG base address.
- eEvtgIndex – EVTG instance index.
- eAOIIndex – EVTG AOI index. see enum ref `evtg_aoi_index_t`
- eProductTerm – EVTG product term index.
- eInputIndex – EVTG input index.
- eInput – EVTG input configuration with enum `evtg_aoi_input_config_t`.

`void EVTG_ConfigAOIProductTerm(EVTG_Type *base, evtg_index_t eEvtgIndex, evtg_aoi_index_t eAOIIndex, evtg_aoi_product_term_t eProductTerm, evtg_aoi_product_term_config_t *psProductTermConfig)`

Configure AOI product term by initializing the product term configuration structure.

Parameters

- base – EVTG base address.
- eEvtgIndex – EVTG instance index.
- eAOIIndex – EVTG AOI index. see enum evtg_aoi_index_t
- eProductTerm – EVTG AOI product term index.
- psProductTermConfig – Pointer to EVTG product term configuration structure. see ref _evtg_aoi_product_term_config

FSL_EVTG_DRIVER_VERSION

EVTG driver version.

enum _evtg_index

EVTG instance index.

Values:

enumerator kEVTG_Index0

EVTG instance index 0.

enumerator kEVTG_Index1

EVTG instance index 1.

enumerator kEVTG_Index2

EVTG instance index 2.

enumerator kEVTG_Index3

EVTG instance index 3.

enum _evtg_input_index

EVTG input index.

Values:

enumerator kEVTG_InputA

EVTG input A.

enumerator kEVTG_InputB

EVTG input B.

enumerator kEVTG_InputC

EVTG input C.

enumerator kEVTG_InputD

EVTG input D.

enum _evtg_aoi_index

EVTG AOI index.

Values:

enumerator kEVTG_AOI0

EVTG AOI index 0.

enumerator kEVTG_AOI1

EVTG AOI index 1.

enum _evtg_aoi_product_term

EVTG AOI product term index.

Values:

enumerator kEVTG_ProductTerm0

EVTG AOI product term index 0.

enumerator kEVTG_ProductTerm1
EVTG AOI product term index 1.

enumerator kEVTG_ProductTerm2
EVTG AOI product term index 2.

enumerator kEVTG_ProductTerm3
EVTG AOI product term index 3.

enum _evtg_aoi_input_config
EVTG input configuration.

Values:

enumerator kEVTG_Input_LogicZero
Force input in product term to a logical zero.

enumerator kEVTG_Input_DirectPass
Pass input in product term.

enumerator kEVTG_Input_Complement
Complement input in product term.

enumerator kEVTG_Input_LogicOne
Force input in product term to a logical one.

enum _evtg_aoi_outfilter_count
EVTG AOI Output Filter Sample Count.

Values:

enumerator kEVTG_AOIOutFilter_SampleCount3
EVTG AOI output filter sample count is 3.

enumerator kEVTG_AOIOutFilter_SampleCount4
EVTG AOI output filter sample count is 4.

enumerator kEVTG_AOIOutFilter_SampleCount5
EVTG AOI output filter sample count is 5.

enumerator kEVTG_AOIOutFilter_SampleCount6
EVTG AOI output filter sample count is 6.

enumerator kEVTG_AOIOutFilter_SampleCount7
EVTG AOI output filter sample count is 7.

enumerator kEVTG_AOIOutFilter_SampleCount8
EVTG AOI output filter sample count is 8.

enumerator kEVTG_AOIOutFilter_SampleCount9
EVTG AOI output filter sample count is 9.

enumerator kEVTG_AOIOutFilter_SampleCount10
EVTG AOI output filter sample count is 10.

enum _evtg_outfdbk_override_input
EVTG output feedback override control mode. When FF is configured as JK-FF mode, need EVTG_OUTA feedback to EVTG input and replace one of the four inputs.

Values:

enumerator kEVTG_Output_OverrideInputA
Replace input A.

enumerator kEVTG_Output_OverrideInputB

Replace input B.

enumerator kEVTG_Output_OverrideInputC

Replace input C.

enumerator kEVTG_Output_OverrideInputD

Replace input D.

enum _evtg_flipflop_mode

EVTG flip flop mode configuration.

Values:

enumerator kEVTG_FFMode_Bypass

Bypass mode (default). In this mode, user can choose to enable or disable input sync logic and filter function.

enumerator kEVTG_FFMode_RSTTrigger

RS trigger mode. In this mode, user can choose to enable or disable input sync logic and filter function.

enumerator kEVTG_FFMode_TFF

T-FF mode. In this mode, input sync or filter has to be enabled to remove the possible glitch.

enumerator kEVTG_FFMode_DFF

D-FF mode. In this mode, input sync or filter has to be enabled to remove the possible glitch.

enumerator kEVTG_FFMode_JKFF

JK-FF mode. In this mode, input sync or filter has to be enabled to remove the possible glitch.

enumerator kEVTG_FFMode_Latch

Latch mode. In this mode, input sync or filter has to be enabled to remove the possible glitch.

enum _evtg_flipflop_initoutput

EVTG flip-flop initial value.

Values:

enumerator kEVTG_FF_InitOut0

Configure the positive output of flip-flop as 0.

enumerator kEVTG_FF_InitOut1

Configure the positive output of flip-flop as 1.

typedef enum _evtg_index evtg_index_t

EVTG instance index.

typedef enum _evtg_input_index evtg_input_index_t

EVTG input index.

typedef enum _evtg_aoi_index evtg_aoi_index_t

EVTG AOI index.

typedef enum _evtg_aoi_product_term evtg_aoi_product_term_t

EVTG AOI product term index.

typedef enum _evtg_aoi_input_config evtg_aoi_input_config_t

EVTG input configuration.

typedef enum *_evtg_aoi_outfilter_count* evtg_aoi_outfilter_count_t

EVTG AOI Output Filter Sample Count.

typedef enum *_evtg_outfdbk_override_input* evtg_outfdbk_override_input_t

EVTG output feedback override control mode. When FF is configured as JK-FF mode, need EVTG_OUTA feedback to EVTG input and replace one of the four inputs.

typedef enum *_evtg_flipflop_mode* evtg_flipflop_mode_t

EVTG flip flop mode configuration.

typedef enum *_evtg_flipflop_initoutput* evtg_flipflop_init_output_t

EVTG flip-flop initial value.

typedef struct *_evtg_aoi_outfilter_config* evtg_aoi_outfilter_config_t

The structure for configuring an AOI output filter sample.

AOI output filter sample count represent the number of consecutive samples that must agree prior to the AOI output filter accepting an transition. AOI output filter sample period represent the sampling period (in IP bus clock cycles) of the AOI output signals. Each AOI output is sampled multiple times at the rate specified by this period.

For the modes with Filter function enabled, filter delay is “(FILT_CNT + 3) x FILT_PER + 2”.

typedef struct *_evtg_aoi_product_term_config* evtg_aoi_product_term_config_t

The structure for configuring an AOI product term.

typedef struct *_evtg_aoi_config* evtg_aoi_config_t

EVTG AOI configuration structure.

typedef struct *_evtg_config* evtg_config_t

EVTG configuration covering all configurable fields.

struct *_evtg_aoi_outfilter_config*

#include <fsl_evgtg.h> The structure for configuring an AOI output filter sample.

AOI output filter sample count represent the number of consecutive samples that must agree prior to the AOI output filter accepting an transition. AOI output filter sample period represent the sampling period (in IP bus clock cycles) of the AOI output signals. Each AOI output is sampled multiple times at the rate specified by this period.

For the modes with Filter function enabled, filter delay is “(FILT_CNT + 3) x FILT_PER + 2”.

Public Members

evtg_aoi_outfilter_count_t eSampleCount

EVTG AOI output filter sample count. refer to *evtg_aoi_outfilter_count_t*.

uint8_t u8SamplePeriod

EVTG AOI output filter sample period, within 0~255. If sample period value is 0x00 (default), then the input filter is bypassed.

struct *_evtg_aoi_product_term_config*

#include <fsl_evgtg.h> The structure for configuring an AOI product term.

Public Members

evtg_aoi_input_config_t eAInput

Input A configuration.

evtg_aoi_input_config_t eBInput

Input B configuration.

evtg_aoi_input_config_t eCInput

Input C configuration.

evtg_aoi_input_config_t eDInput

Input D configuration.

struct *__evtg_aoi_config*

#include <fsl_evtg.h> EVTG AOI configuration structure.

Public Members

evtg_aoi_outfilter_config_t sAOIOutFilterConfig

EVTG AOI output filter sample configuration structure.

evtg_aoi_product_term_config_t sProductTerm0

Configure AOI product term0.

evtg_aoi_product_term_config_t sProductTerm1

Configure AOI product term1.

evtg_aoi_product_term_config_t sProductTerm2

Configure AOI product term2.

evtg_aoi_product_term_config_t sProductTerm3

Configure AOI product term3.

struct *__evtg_config*

#include <fsl_evtg.h> EVTG configuration covering all configurable fields.

Public Members

bool bEnableInputASync

Enable/Disable EVTG A input synchronous with bus clk.

bool bEnableInputBSync

Enable/Disable EVTG B input synchronous with bus clk.

bool bEnableInputCSync

Enable/Disable EVTG C input synchronous with bus clk.

bool bEnableInputDSync

Enable/Disable EVTG D input synchronous with bus clk.

evtg_outfdbk_override_input_t eOutfdbkOverrideinput

EVTG output feedback to EVTG input and replace one of the four inputs.

evtg_flipflop_mode_t eFlipflopMode

Flip-Flop can be configured as one of Bypass mode, RS trigger mode, T-FF mode, D-FF mode, JK-FF mode, Latch mode.

bool bEnableFlipflopInitOutput

Flip-flop initial output value enable/disable.

evtg_flipflop_init_output_t eFlipflopInitOutputValue

Flip-flop initial output value configuration.

evtg_aoi_config_t sAOI0Config

Configure EVTG AOI0.

evtg_aoi_config_t sAOI1Config

Configure EVTG AOI1.

2.25 The Driver Change Log

2.26 EVTG Peripheral and Driver Overview

2.27 EWM: External Watchdog Monitor Driver

`void EWM_Init(EWM_Type *base, const ewm_config_t *psConfig)`

Initializes the EWM peripheral.

This function is used to initialize the EWM. After calling, the EWM runs immediately according to the configuration.

This is an example.

```
ewm_config_t psConfig;
EWM_GetDefaultConfig(&psConfig);
psConfig.compareHighValue = 0xAAU;
EWM_Init(ewm_base,&psConfig);
```

Note: Except for the interrupt enable control bit, other control bits and registers are write once after a CPU reset. Modifying them more than once generates a bus transfer error.

Parameters

- `base` – EWM peripheral base address
- `psConfig` – The configuration of the EWM

`void EWM_Deinit(EWM_Type *base)`

Deinitializes the EWM peripheral.

This function is used to shut down the EWM.

Parameters

- `base` – EWM peripheral base address

`void EWM_GetDefaultConfig(ewm_config_t *psConfig)`

Initializes the EWM configuration structure.

This function initializes the EWM configuration structure to default values. The default values are as follows.

```
ewmConfig->bEnableEWM = true;
ewmConfig->bEnableEWMInput = false;
ewmConfig->eInputAssertState = kEWM_EwmInZeroAssert;
ewmConfig->bEnableInterrupt = false;
ewmConfig->eClockSource = kEWM_LpoClockSource0;
ewmConfig->u8ClockDivder = 0;
ewmConfig->u8CompareLowValue = 0;
ewmConfig->u8CompareHighValue = 0xFEU;
```

See also:

`ewm_config_t`

Parameters

- psConfig – Pointer to the EWM configuration structure.

static inline void EWM_EnableInterrupt(EWM_Type *base)

Enables the EWM interrupt.

This function enables the EWM interrupt.

Parameters

- base – EWM peripheral base address

static inline void EWM_DisableInterrupt(EWM_Type *base)

Disables the EWM interrupt.

This function disables the EWM interrupt.

Parameters

- base – EWM peripheral base address

void EWM_Refresh(EWM_Type *base)

Services the EWM.

This function resets the EWM counter to zero.

Parameters

- base – EWM peripheral base address

FSL_EWM_DRIVER_VERSION

EWM driver version.

enum _ewm_input_assert_state

Assert pin voltage configuration.

Values:

enumerator kEWM_EwmInZeroAssert

EWM-in assert with low-voltage logic

enumerator kEWM_EwmInOneAssert

EWM-in assert with high-voltage logic

typedef enum _ewm_input_assert_state ewm_input_assert_state_t

Assert pin voltage configuration.

typedef struct _ewm_config ewm_config_t

Data structure for EWM configuration.

This structure is used to configure the EWM.

struct _ewm_config

#include <fsl_ewm.h> Data structure for EWM configuration.

This structure is used to configure the EWM.

Public Members

uint8_t bEnableEWM

Enable EWM module

uint8_t bEnableEWMInput

Enable EWM_in input

uint8_t bEnableInterrupt

Enable EWM interrupt

ewm_input_assert_state_t eInputAssertState
EWM_in signal assertion state select

ewm_lpo_clock_source_t eClockSource
Clock source select

uint8_t u8ClockDivder
EWM counter clock is clockSource/(clockDivder+1)

uint8_t u8CompareLowValue
Compare low-register value

uint8_t u8CompareHighValue
Compare high-register value, maximum setting is 0xFE

2.28 The Driver Change Log

2.29 EWM Peripheral and Driver Overview

2.30 C90TFS Flash Driver

2.31 ftfx adapter

2.32 ftfx controller

FTFx driver status codes.

Values:

enumerator *kStatus_FTFx_Success*
API is executed successfully

enumerator *kStatus_FTFx_InvalidArgument*
Invalid argument

enumerator *kStatus_FTFx_SizeError*
Error size

enumerator *kStatus_FTFx_AlignmentError*
Parameter is not aligned with the specified baseline

enumerator *kStatus_FTFx_AddressError*
Address is out of range

enumerator *kStatus_FTFx_AccessError*
Invalid instruction codes and out-of bound addresses

enumerator *kStatus_FTFx_ProtectionViolation*
The program/erase operation is requested to execute on protected areas

enumerator *kStatus_FTFx_CommandFailure*
Run-time error during command execution.

enumerator kStatus_FTFx_UnknownProperty
Unknown property.

enumerator kStatus_FTFx_EraseKeyError
API erase key is invalid.

enumerator kStatus_FTFx_RegionExecuteOnly
The current region is execute-only.

enumerator kStatus_FTFx_ExecuteInRamFunctionNotReady
Execute-in-RAM function is not available.

enumerator kStatus_FTFx_PartitionStatusUpdateFailure
Failed to update partition status.

enumerator kStatus_FTFx_SetFlexramAsEepromError
Failed to set FlexRAM as EEPROM.

enumerator kStatus_FTFx_RecoverFlexramAsRamError
Failed to recover FlexRAM as RAM.

enumerator kStatus_FTFx_SetFlexramAsRamError
Failed to set FlexRAM as RAM.

enumerator kStatus_FTFx_RecoverFlexramAsEepromError
Failed to recover FlexRAM as EEPROM.

enumerator kStatus_FTFx_CommandNotSupported
Flash API is not supported.

enumerator kStatus_FTFx_SwapSystemNotInUninitialized
Swap system is not in an uninitialized state.

enumerator kStatus_FTFx_SwapIndicatorAddressError
The swap indicator address is invalid.

enumerator kStatus_FTFx_ReadOnlyProperty
The flash property is read-only.

enumerator kStatus_FTFx_InvalidPropertyValue
The flash property value is out of range.

enumerator kStatus_FTFx_InvalidSpeculationOption
The option of flash prefetch speculation is invalid.

enumerator kStatus_FTFx_CommandOperationInProgress
The option of flash command is processing.

kStatusGroupGeneric
FTFx driver status group.

kStatusGroupFtfxDriver

kFTFx_ApiEraseKey

void FTFx_API_Init(*ftfx_config_t* *config)
Initializes the global flash properties structure members.
This function checks and initializes the Flash module for the other Flash APIs.

Parameters

- config – Pointer to the storage for the driver runtime state.

status_t FTFx_CMD_Erase(*ftfx_config_t* *config, uint32_t start, uint32_t lengthInBytes, uint32_t key)

Erases the flash sectors encompassed by parameters passed into function.

This function erases the appropriate number of flash sectors based on the desired start address and length.

Parameters

- config – The pointer to the storage for the driver runtime state.
- start – The start address of the desired flash memory to be erased. The start address does not need to be sector-aligned but must be word-aligned.
- lengthInBytes – The length, given in bytes (not words or long-words) to be erased. Must be word-aligned.
- key – The value used to validate all flash erase APIs.

Return values

- kStatus_FTFx_Success – API was executed successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_AlignmentError – The parameter is not aligned with the specified baseline.
- kStatus_FTFx_AddressError – The address is out of range.
- kStatus_FTFx_EraseKeyError – The API erase key is invalid.
- kStatus_FTFx_ExecuteInRamFunctionNotReady – Execute-in-RAM function is not available.
- kStatus_FTFx_AccessError – Invalid instruction codes and out-of bounds addresses.
- kStatus_FTFx_ProtectionViolation – The program/erase operation is requested to execute on protected areas.
- kStatus_FTFx_CommandFailure – Run-time error during the command execution.

status_t FTFx_CMD_EraseAll(*ftfx_config_t* *config, uint32_t key)

Erases entire flash.

Parameters

- config – Pointer to the storage for the driver runtime state.
- key – A value used to validate all flash erase APIs.

Return values

- kStatus_FTFx_Success – API was executed successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_EraseKeyError – API erase key is invalid.
- kStatus_FTFx_ExecuteInRamFunctionNotReady – Execute-in-RAM function is not available.
- kStatus_FTFx_AccessError – Invalid instruction codes and out-of bounds addresses.
- kStatus_FTFx_ProtectionViolation – The program/erase operation is requested to execute on protected areas.
- kStatus_FTFx_CommandFailure – Run-time error during command execution.

- `kStatus_FTFx_PartitionStatusUpdateFailure` – Failed to update the partition status.

`status_t FTFx_CMD_Program(ftfx_config_t *config, uint32_t start, const uint8_t *src, uint32_t lengthInBytes)`

Programs flash with data at locations passed in through parameters.

This function programs the flash memory with the desired data for a given flash area as determined by the start address and the length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be programmed. Must be word-aligned.
- `src` – A pointer to the source buffer of data that is to be programmed into the flash.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with the specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_ProgramOnce(ftfx_config_t *config, uint8_t index, const uint8_t *src, uint32_t lengthInBytes)`

Programs Program Once Field through parameters.

This function programs the Program Once Field with the desired data for a given flash area as determined by the index and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `index` – The index indicating which area of the Program Once Field to be programmed.
- `src` – A pointer to the source buffer of data that is to be programmed into the Program Once Field.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.

- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_ReadOnce(ftfx_config_t *config, uint8_t index, uint8_t *dst, uint32_t lengthInBytes)`

Reads the Program Once Field through parameters.

This function reads the read once feild with given index and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `index` – The index indicating the area of program once field to be read.
- `dst` – A pointer to the destination buffer of data that is used to store data to be read.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_VerifyErase(ftfx_config_t *config, uint32_t start, uint32_t lengthInBytes, uint8_t margin)`

Verifies an erasure of the desired flash area at a specified margin level.

This function checks the appropriate number of flash sectors based on the desired start address and length to check whether the flash is erased to the specified read margin level.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be verified. The start address does not need to be sector-aligned but must be word-aligned.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be verified. Must be word-aligned.
- `margin` – Read margin choice.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_VerifyEraseAll(ftfx_config_t *config, uint8_t margin)`

Verifies erasure of the entire flash at a specified margin level.

This function checks whether the flash is erased to the specified read margin level.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `margin` – Read margin choice.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_CMD_VerifyProgram(ftfx_config_t *config, uint32_t start, uint32_t lengthInBytes, const uint8_t *expectedData, uint8_t margin, uint32_t *failedAddress, uint32_t *failedData)`

Verifies programming of the desired flash area at a specified margin level.

This function verifies the data programed in the flash memory using the Flash Program Check Command and compares it to the expected data for a given flash area as determined by the start address and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be verified. Must be word-aligned.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be verified. Must be word-aligned.
- `expectedData` – A pointer to the expected data that is to be verified against.

- `margin` – Read margin choice.
- `failedAddress` – A pointer to the returned failing address.
- `failedData` – A pointer to the returned failing data. Some derivatives do not include failed data as part of the FCCOBx registers. In this case, zeros are returned upon failure.

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FTFx_REG_GetSecurityState(ftfx_config_t *config, ftfx_security_state_t *state)`

Returns the security state via the pointer passed into the function.

This function retrieves the current flash security status, including the security enabling state and the backdoor key enabling state.

Parameters

- `config` – A pointer to storage for the driver runtime state.
- `state` – A pointer to the value returned for the current security status code:

Return values

- `kStatus_FTFx_Success` – API was executed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.

`enum _ftfx_partition_flexram_load_option`

Enumeration for the FlexRAM load during reset option.

Values:

enumerator `kFTFx_PartitionFlexramLoadOptLoadedWithValidEepromData`
FlexRAM is loaded with valid EEPROM data during reset sequence.

enumerator `kFTFx_PartitionFlexramLoadOptNotLoaded`
FlexRAM is not loaded during reset sequence.

`enum _ftfx_security_state`

Enumeration for the three possible FTFx security states.

Values:

enumerator `kFTFx_SecurityStateNotSecure`
Flash is not secure.

enumerator `kFTFx_SecurityStateBackdoorEnabled`
Flash backdoor is enabled.

enumerator kFTFx_SecurityStateBackdoorDisabled

Flash backdoor is disabled.

enum _ftfx_flexram_function_option

Enumeration for the two possible options of set FlexRAM function command.

Values:

enumerator kFTFx_FlexramFuncOptAvailableAsRam

An option used to make FlexRAM available as RAM

enumerator kFTFx_FlexramFuncOptAvailableForEeprom

An option used to make FlexRAM available for EEPROM

enum _ftfx_swap_state

Enumeration for the possible flash Swap status.

Values:

enumerator kFTFx_SwapStateUninitialized

Flash Swap system is in an uninitialized state.

enumerator kFTFx_SwapStateReady

Flash Swap system is in a ready state.

enumerator kFTFx_SwapStateUpdate

Flash Swap system is in an update state.

enumerator kFTFx_SwapStateUpdateErased

Flash Swap system is in an updateErased state.

enumerator kFTFx_SwapStateComplete

Flash Swap system is in a complete state.

enumerator kFTFx_SwapStateDisabled

Flash Swap system is in a disabled state.

enum _ftfx_memory_type

Enumeration for FTFx memory type.

Values:

enumerator kFTFx_MemTypePflash

enumerator kFTFx_MemTypeFlexnvm

typedef enum _ftfx_partition_flexram_load_option ftfx_partition_flexram_load_opt_t

Enumeration for the FlexRAM load during reset option.

typedef enum _ftfx_security_state ftfx_security_state_t

Enumeration for the three possible FTFx security states.

typedef enum _ftfx_flexram_function_option ftfx_flexram_func_opt_t

Enumeration for the two possible options of set FlexRAM function command.

typedef enum _ftfx_swap_state ftfx_swap_state_t

Enumeration for the possible flash Swap status.

typedef struct _ftfx_special_mem ftfx_spec_mem_t

ftfx special memory access information.

typedef struct _ftfx_mem_descriptor ftfx_mem_desc_t

Flash memory descriptor.

typedef struct *_ftfx_ops_config* ftfx_ops_config_t

Active FTFx information for the current operation.

typedef struct *_ftfx_ifr_descriptor* ftfx_ifr_desc_t

Flash IFR memory descriptor.

typedef struct *_ftfx_config* ftfx_config_t

Flash driver state information.

An instance of this structure is allocated by the user of the flash driver and passed into each of the driver APIs.

kFTFx_ResourceOptionFlashIfr

Macro for the two possible options of flash read resource command.

Select code for Program flash 0 IFR, Program flash swap 0 IFR, Data flash 0 IFR

kFTFx_ResourceOptionVersionId

Select code for the version ID

kFTFx_MarginValueNormal

Macro for supported FTFx margin levels.

kFTFx_MarginValueUser

Apply the 'User' margin to the normal read-1 level.

kFTFx_MarginValueFactory

Apply the 'Factory' margin to the normal read-1 level.

kFTFx_MarginValueInvalid

Not real margin level, Used to determine the range of valid margin level.

struct *_ftfx_special_mem*

#include <fsl_ftfx_controller.h> ftfx special memory access information.

Public Members

uint32_t base

Base address of flash special memory.

uint32_t size

size of flash special memory.

uint32_t count

flash special memory count.

struct *_ftfx_mem_descriptor*

#include <fsl_ftfx_controller.h> Flash memory descriptor.

Public Members

uint32_t blockBase

A base address of the flash block

uint32_t totalSize

The size of the flash block.

uint32_t sectorSize

The size in bytes of a sector of flash.

uint32_t blockCount

A number of flash blocks.

struct __ftfx__ops__config

#include <fsl_ftfx_controller.h> Active FTFx information for the current operation.

Public Members

uint32_t convertedAddress

A converted address for the current flash type.

struct __ftfx__ifr__descriptor

#include <fsl_ftfx_controller.h> Flash IFR memory descriptor.

union function_ptr_t

#include <fsl_ftfx_controller.h>

Public Members

uint32_t commadAddr

void (*callFlashCommand)(volatile uint8_t *FTMRx_fstat)

struct __ftfx__config

#include <fsl_ftfx_controller.h> Flash driver state information.

An instance of this structure is allocated by the user of the flash driver and passed into each of the driver APIs.

Public Members

uint32_t flexramBlockBase

The base address of the FlexRAM/acceleration RAM

uint32_t flexramTotalSize

The size of the FlexRAM/acceleration RAM

uint16_t eepromTotalSize

The size of EEPROM area which was partitioned from FlexRAM

function_ptr_t runCmdFuncAddr

An buffer point to the flash execute-in-RAM function.

struct ____unnamed4____

Public Members

uint8_t type

Type of flash block.

uint8_t index

Index of flash block.

struct feature

struct addrAligment

struct feature

struct resRange

Public Members

uint8_t versionIdStart

Version ID start address

uint32_t pflashIfrStart

Program Flash 0 IFR start address

uint32_t dflashIfrStart

Data Flash 0 IFR start address

uint32_t pflashSwapIfrStart

Program Flash Swap IFR start address

struct idxInfo

2.33 ftfx feature

FTFx_DRIVER_IS_FLASH_RESIDENT

Flash driver location.

Used for the flash resident application.

FTFx_DRIVER_IS_EXPORTED

Flash Driver Export option.

Used for the MCUXpresso SDK application.

FTFx_FLASH1_HAS_PROT_CONTROL

Indicates whether the secondary flash has its own protection register in flash module.

FTFx_FLASH1_HAS_XACC_CONTROL

Indicates whether the secondary flash has its own Execute-Only access register in flash module.

FTFx_DRIVER_HAS_FLASH1_SUPPORT

Indicates whether the secondary flash is supported in the Flash driver.

FTFx_FLASH_COUNT

FTFx_FLASH1_IS_INDEPENDENT_BLOCK

2.34 Ftftx FLASH Driver

status_t FLASH_Init(*flash_config_t* *config)

Initializes the global flash properties structure members.

This function checks and initializes the Flash module for the other Flash APIs.

Parameters

- config – Pointer to the storage for the driver runtime state.

Return values

- kStatus_FTFx_Success – API was executed successfully.
- kStatus_FTFx_InvalidArgument – An invalid argument is provided.
- kStatus_FTFx_ExecuteInRamFunctionNotReady – Execute-in-RAM function is not available.

- `kStatus_FTFx_PartitionStatusUpdateFailure` – Failed to update the partition status.

`status_t FLASH_Erase(flash_config_t *config, uint32_t start, uint32_t lengthInBytes, uint32_t key)`

Erases the Dflash sectors encompassed by parameters passed into function.

This function erases the appropriate number of flash sectors based on the desired start address and length.

Parameters

- `config` – The pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be erased. The start address does not need to be sector-aligned but must be word-aligned.
- `lengthInBytes` – The length, given in bytes (not words or long-words) to be erased. Must be word-aligned.
- `key` – The value used to validate all flash erase APIs.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the appropriate number of flash sectors based on the desired start address and length were erased successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – The parameter is not aligned with the specified baseline.
- `kStatus_FTFx_AddressError` – The address is out of range.
- `kStatus_FTFx_EraseKeyError` – The API erase key is invalid.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FLASH_EraseAll(flash_config_t *config, uint32_t key)`

Erases entire flexnvm.

Parameters

- `config` – Pointer to the storage for the driver runtime state.
- `key` – A value used to validate all flash erase APIs.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the all pflash and flexnvm were erased successfully, the swap and eeprom have been reset to unconfigured state.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_EraseKeyError` – API erase key is invalid.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.

- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during command execution.
- `kStatus_FTFx_PartitionStatusUpdateFailure` – Failed to update the partition status.

`status_t` FLASH_Program(*flash_config_t* *config, uint32_t start, uint8_t *src, uint32_t lengthInBytes)

Programs flash with data at locations passed in through parameters.

This function programs the flash memory with the desired data for a given flash area as determined by the start address and the length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be programmed. Must be word-aligned.
- `src` – A pointer to the source buffer of data that is to be programmed into the flash.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the desired data were programed successfully into flash based on desired start address and length.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with the specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t` FLASH_ProgramOnce(*flash_config_t* *config, uint8_t index, uint8_t *src, uint32_t lengthInBytes)

Program the Program-Once-Field through parameters.

This function Program the Program-once-feild with given index and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `index` – The index indicating the area of program once field to be read.

- `src` – A pointer to the source buffer of data that is used to store data to be write.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; The index indicating the area of program once field was programed successfully.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FLASH_ReadOnce(flash_config_t *config, uint8_t index, uint8_t *dst, uint32_t lengthInBytes)`

Reads the Program Once Field through parameters.

This function reads the read once feild with given index and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `index` – The index indicating the area of program once field to be read.
- `dst` – A pointer to the destination buffer of data that is used to store data to be read.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be programmed. Must be word-aligned.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the data have been successfuly read form Program flash0 IFR map and Program Once field based on index and length.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t FLASH_VerifyErase(flash_config_t *config, uint32_t start, uint32_t lengthInBytes, uint8_t margin)`

Verifies an erasure of the desired flash area at a specified margin level.

This function checks the appropriate number of flash sectors based on the desired start address and length to check whether the flash is erased to the specified read margin level.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be verified. The start address does not need to be sector-aligned but must be word-aligned.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be verified. Must be word-aligned.
- `margin` – Read margin choice.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the specified FLASH region has been erased.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t` FLASH_VerifyEraseAll(*flash_config_t* *config, uint8_t margin)

Verifies erasure of the entire flash at a specified margin level.

This function checks whether the flash is erased to the specified read margin level.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `margin` – Read margin choice.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; all program flash and flexnvm were in erased state.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

`status_t` FLASH_VerifyProgram(*flash_config_t* *config, uint32_t start, uint32_t lengthInBytes, const uint8_t *expectedData, uint8_t margin, uint32_t *failedAddress, uint32_t *failedData)

Verifies programming of the desired flash area at a specified margin level.

This function verifies the data programmed in the flash memory using the Flash Program Check Command and compares it to the expected data for a given flash area as determined by the start address and length.

Parameters

- `config` – A pointer to the storage for the driver runtime state.
- `start` – The start address of the desired flash memory to be verified. Must be word-aligned.
- `lengthInBytes` – The length, given in bytes (not words or long-words), to be verified. Must be word-aligned.
- `expectedData` – A pointer to the expected data that is to be verified against.
- `margin` – Read margin choice.
- `failedAddress` – A pointer to the returned failing address.
- `failedData` – A pointer to the returned failing data. Some derivatives do not include failed data as part of the FCCOBx registers. In this case, zeros are returned upon failure.

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the desired data have been successfully programed into specified FLASH region.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.
- `kStatus_FTFx_AlignmentError` – Parameter is not aligned with specified baseline.
- `kStatus_FTFx_AddressError` – Address is out of range.
- `kStatus_FTFx_ExecuteInRamFunctionNotReady` – Execute-in-RAM function is not available.
- `kStatus_FTFx_AccessError` – Invalid instruction codes and out-of bounds addresses.
- `kStatus_FTFx_ProtectionViolation` – The program/erase operation is requested to execute on protected areas.
- `kStatus_FTFx_CommandFailure` – Run-time error during the command execution.

status_t FLASH_GetSecurityState(*flash_config_t* *config, *ftfx_security_state_t* *state)

Returns the security state via the pointer passed into the function.

This function retrieves the current flash security status, including the security enabling state and the backdoor key enabling state.

Parameters

- `config` – A pointer to storage for the driver runtime state.
- `state` – A pointer to the value returned for the current security status code:

Return values

- `kStatus_FTFx_Success` – API was executed successfully; the security state of flash was stored to state.
- `kStatus_FTFx_InvalidArgument` – An invalid argument is provided.

status_t FLASH_GetProperty(*flash_config_t* *config, *flash_property_tag_t* whichProperty, *uint32_t* *value)

Returns the desired flash property.

Parameters

- config – A pointer to the storage for the driver runtime state.
- whichProperty – The desired property from the list of properties in enum *flash_property_tag_t*
- value – A pointer to the value returned for the desired flash property.

Return values

- *kStatus_FTFx_Success* – API was executed successfully; the flash property was stored to value.
- *kStatus_FTFx_InvalidArgument* – An invalid argument is provided.
- *kStatus_FTFx_UnknownProperty* – An unknown property tag.

FSL_FLASH_DRIVER_VERSION

Flash driver version for SDK.

Version 3.0.0.

enum *_flash_protection_state*

Enumeration for the three possible flash protection levels.

Values:

enumerator *kFLASH_ProtectionStateUnprotected*

Flash region is not protected.

enumerator *kFLASH_ProtectionStateProtected*

Flash region is protected.

enumerator *kFLASH_ProtectionStateMixed*

Flash is mixed with protected and unprotected region.

enum *_flash_property_tag*

Enumeration for various flash properties.

Values:

enumerator *kFLASH_PropertyPflash0SectorSize*

Pflash sector size property.

enumerator *kFLASH_PropertyPflash0TotalSize*

Pflash total size property.

enumerator *kFLASH_PropertyPflash0BlockSize*

Pflash block size property.

enumerator *kFLASH_PropertyPflash0BlockCount*

Pflash block count property.

enumerator *kFLASH_PropertyPflash0BlockBaseAddr*

Pflash block base address property.

enumerator *kFLASH_PropertyPflash0FacSupport*

Pflash fac support property.

enumerator *kFLASH_PropertyPflash0AccessSegmentSize*

Pflash access segment size property.

```

enumerator kFLASH_PropertyPflash0AccessSegmentCount
    Pflash access segment count property.
enumerator kFLASH_PropertyPflash1SectorSize
    Pflash sector size property.
enumerator kFLASH_PropertyPflash1TotalSize
    Pflash total size property.
enumerator kFLASH_PropertyPflash1BlockSize
    Pflash block size property.
enumerator kFLASH_PropertyPflash1BlockCount
    Pflash block count property.
enumerator kFLASH_PropertyPflash1BlockBaseAddr
    Pflash block base address property.
enumerator kFLASH_PropertyPflash1FacSupport
    Pflash fac support property.
enumerator kFLASH_PropertyPflash1AccessSegmentSize
    Pflash access segment size property.
enumerator kFLASH_PropertyPflash1AccessSegmentCount
    Pflash access segment count property.
enumerator kFLASH_PropertyFlexRamBlockBaseAddr
    FlexRam block base address property.
enumerator kFLASH_PropertyFlexRamTotalSize
    FlexRam total size property.
typedef enum _flash_protection_state flash_prot_state_t
    Enumeration for the three possible flash protection levels.
typedef union _pflash_protection_status pflash_prot_status_t
    PFlash protection status.
typedef enum _flash_property_tag flash_property_tag_t
    Enumeration for various flash properties.
typedef struct _flash_config flash_config_t
    Flash driver state information.

    An instance of this structure is allocated by the user of the flash driver and passed into each
    of the driver APIs.

kStatus_FLASH_Success
kFLASH_ApiEraseKey
union _pflash_protection_status
    #include <fsl_ftfx_flash.h> PFlash protection status.

```

Public Members

```

uint32_t protl
    PROT[31:0] .
uint32_t proth
    PROT[63:32].

```

```
uint8_t protsl
    PROTS[7:0] .
uint8_t protsh
    PROTS[15:8] .
uint8_t reserved[2]
```

```
struct _flash_config
```

#include <fsl_ftfx_flash.h> Flash driver state information.

An instance of this structure is allocated by the user of the flash driver and passed into each of the driver APIs.

2.35 ftfx utilities

MAKE_VERSION(major, minor, bugfix)

Constructs the version number for drivers.

MAKE_STATUS(group, code)

Constructs a status code value from a group and a code number.

FOUR_CHAR_CODE(a, b, c, d)

Constructs the four character code for the Flash driver API key.

ALIGN_DOWN(x, a)

Alignment(down) utility.

ALIGN_UP(x, a)

Alignment(up) utility.

B1P4(b)

bytes2word utility.

B1P3(b)

B1P2(b)

B1P1(b)

B2P3(b)

B2P2(b)

B2P1(b)

B3P2(b)

B3P1(b)

BYTE2WORD_1_3(x, y)

BYTE2WORD_2_2(x, y)

BYTE2WORD_3_1(x, y)

BYTE2WORD_1_1_2(x, y, z)

BYTE2WORD_1_2_1(x, y, z)

BYTE2WORD_2_1_1(x, y, z)

BYTE2WORD_1_1_1_1(x, y, z, w)

2.36 GPIO: General-Purpose Input/Output Driver

`void GPIO_PinInit(GPIO_Type *base, gpio_pin_t ePin, const gpio_config_t *psConfig)`

Initializes a GPIO pin with provided structure `gpio_config_t` covering all configuration fields.

To initialize the GPIO, define a pin configuration, as either input or output, in the user file. Then, call the `GPIO_PinInit()` function.

This is function to configure all GPIO Pin configurable fields.

```
gpio_config_t sConfig = {
    .eDirection    = kGPIO_DigitalOutput,
    .eMode         = kGPIO_ModeGpio,
    .eOutMode      = kGPIO_OutputOpenDrain,
    .eSlewRate     = kGPIO_SlewRateFast,
    .eOutLevel     = kGPIO_OutputLow,
    .eDriveStrength = kGPIO_DriveStrengthLow,
    .ePull         = kGPIO_PullDisable,
    .eInterruptMode = kGPIO_InterruptDisable,
}
GPIO_PinInit(GPIOA, kGPIO_Pin1, &sConfig);
```

Note: If GPIO glitch is critical for your application, do not use this API instead using the API in GPIO pin configuration interfaces to do with the glitch during GPIO mode transition in accordance to your board design.

Parameters

- `base` – GPIO peripheral base pointer (GPIOA, GPIOB, GPIOC, and so on.)
- `ePin` – GPIO pin identifier. User enumerator provided by `gpio_pin_t`. Note that not all Pins existed in SoC and user need to check the data sheet.
- `psConfig` – GPIO pin configuration pointer

`static inline void GPIO_PinSetPeripheralMode(GPIO_Type *base, gpio_pin_t ePin, gpio_peripheral_mode_t eMode)`

Configure the GPIO Pin as Peripheral mode or GPIO mode for one pin.

Configure GPIO can be configured as Peripheral mode or GPIO mode for one pin.

Parameters

- `base` – GPIO peripheral base pointer
- `ePin` – GPIO pin identifier. User enumerator provided by `gpio_pin_t`. Note that not all Pins existed in SoC and user need to check the data sheet.
- `eMode` – Peripheral mode or GPIO mode for this pin. See `gpio_peripheral_mode_t`

`static inline void GPIO_PinSetPeripheralMux(gpio_peripheral_mux_t eMux)`

Configure the multiplexing of GPIO pins to different peripheral.

Configure the MUX of GPIO pins to different peripheral functionality.

Note: User still need to call the `GPIO_PinSetPeripheralMode`.

Parameters

- eMux – GPIO peripheral MUX when configured as peripheral mode.

```
static inline void GPIO_PinSetDirection(GPIO_Type *base, gpio_pin_t ePin, gpio_direction_t
                                     eDirection)
```

Configure the GPIO pin as Input or Output for one pin.

Configure the GPIO pin as Input or Output for one pin.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by *gpio_pin_t*. Note that not all Pins existed in SoC and user need to check the data sheet.
- eDirection – Direction of GPIO pin. *gpio_direction_t*

```
static inline void GPIO_PinSetOutputMode(GPIO_Type *base, gpio_pin_t ePin,
                                     gpio_output_mode_t eOutMode)
```

Configure GPIO pin output as Push-Pull or Open-Drain for one pin.

Configure GPIO pin output as Push-Pull or Open-Drain. This function applies while pin is configured as output. See *gpio_direction_t* and API *GPIO_PinSetDirection*.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by *gpio_pin_t*. Note that not all Pins existed in SoC and user need to check the data sheet.
- eOutMode – Push-Pull/Open-Drain output mode. See *gpio_output_mode_t*.

```
static inline void GPIO_PinSetDriveStrength(GPIO_Type *base, gpio_pin_t ePin,
                                     gpio_output_drive_strength_t eDriveStrength)
```

Configure High/Low drive strength when Pin is configured as output for one pin.

Configure High/Low drive strength when Pin is configured as output. See *gpio_direction_t* and API *GPIO_PinSetDirection*.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by *gpio_pin_t*. Note that not all Pins existed in SoC and user need to check the data sheet.
- eDriveStrength – High/Low driver strength. See *gpio_output_drive_strength_t*

```
static inline void GPIO_PinSetSlewRate(GPIO_Type *base, gpio_pin_t ePin,
                                     gpio_output_slew_rate_t eSlewRate)
```

Configure GPIO pin Fast/Slow slew rate when pin is configured as output.

Configure GPIO pin Fast/Slow slew rate when pin is configured as output. See *gpio_direction_t* and API *GPIO_PinSetDirection*.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by *gpio_pin_t*. Note that not all Pins existed in SoC and user need to check the data sheet.
- eSlewRate – Fast/Slow slewrate. See *gpio_output_slew_rate_t*

```
static inline void GPIO_PinSetPullResistorMode(GPIO_Type *base, gpio_pin_t ePin,  
                                              gpio_pull_mode_t ePullMode)
```

Configure Pull resistor for GPIO pin to Disable/Pull-Up/Pull-Down.

Configure Pull resistor for GPIO pin to Disable/Pull-Up/Pull-Down.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by *gpio_pin_t*. Note that not all Pins existed in SoC and user need to check the data sheet.
- ePullMode – Pull Mode as Disable/Pull-Up/Pull-Down. See *gpio_pull_mode_t*

```
static inline void GPIO_PinWrite(GPIO_Type *base, gpio_pin_t ePin, gpio_output_level_t  
                                eOutput)
```

Set GPIO Pin as High/Low voltage level on Output.

Set GPIO Pin as High/Low voltage level on Output.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by *gpio_pin_t*. Note that not all Pins existed in SoC and user need to check the data sheet.
- eOutput – Output as High level or Low Level. See *gpio_output_level_t*.

```
static inline void GPIO_PortSet(GPIO_Type *base, uint16_t u16Pins)
```

Set GPIO multiple pins output High voltage level without impact pins.

Set GPIO multiple pins output High voltage level without impact other pins. Multiple pins are configured by OR enumerator from *gpio_pin_t*

Parameters

- base – GPIO peripheral base pointer
- u16Pins – GPIO pins which is ORed by *gpio_pin_t*. # kGPIO_Pin0 | kGPIO_Pin3 means Pin 0 and Pin 3.

```
static inline void GPIO_PinSet(GPIO_Type *base, gpio_pin_t ePin)
```

Output High voltage level for GPIO Pin when configured as Output.

Output High voltage level for GPIO Pin when configured as Output.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by *gpio_pin_t*. Note that not all Pins existed in SoC and user need to check the data sheet.

```
static inline void GPIO_PortClear(GPIO_Type *base, uint16_t u16Pins)
```

Set GPIO multiple pins belong to same PORT output Low voltage level when these pins are configured as output.

Set GPIO multiple pins belong to same PORT output Low voltage level when these pins are configured as output. Multiple pins are configured by ORing enumerators from *gpio_pin_t*

Parameters

- base – GPIO peripheral base pointer
- u16Pins – GPIO pins which is ORed by *gpio_pin_t*. # kGPIO_Pin0 | kGPIO_Pin3 means Pin 0 and Pin 3.

static inline void GPIO_PinClear(GPIO_Type *base, *gpio_pin_t* ePin)

Output Low voltage level for GPIO Pin when configured as Output.

Output Low voltage level for GPIO Pin when configured as Output.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by *gpio_pin_t*. Note that not all Pins existed in SoC and user need to check the data sheet.

static inline void GPIO_PortToggle(GPIO_Type *base, uint16_t u16Pins)

Toggle GPIO multiple pins belong to same PORT when these pins are configured as output.

Toggle GPIO multiple pins belong to same PORT when these pins are configured as output.

Multiple pins are configured by ORing enumerators from *gpio_pin_t*

Parameters

- base – GPIO peripheral base pointer
- u16Pins – GPIO pins which is ORed by *gpio_pin_t*. # kGPIO_Pin0 | kGPIO_Pin3 means Pin 0 and Pin 3.

static inline void GPIO_PinToggle(GPIO_Type *base, *gpio_pin_t* ePin)

Toggle the GPIO output voltage level when configured as Output.

Toggle the GPIO output voltage level when configured as Output.

Note: GPIO peripheral register do not get register to toggle directly. It is implemented by read back the GPIO output level and write to the register with reverted level.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by *gpio_pin_t*. Note that not all Pins existed in SoC and user need to check the data sheet.

static inline uint16_t GPIO_PortRead(GPIO_Type *base)

Read High/Low voltage level for multiple GPIO pins from the pin or the data bus.

Read High/Low voltage level for multiple GPIO pins from the pin if the pin is configured as input or the data bus. When the device comes out of reset, GPIO pins are configured as inputs with internal pull disabled. As a result, the reset value of this pin is undefined. For different PORT, the available pins number is different. User need use the return value to OR with the *gpio_pin_t* to decide whether that pin is logic high or low.

```
if (GPIO_PortRead(GPIOA) & (uint16_t)kGPIO_Pin0)
{
    //GPIOA Pin 0 is High
}
else
{
    //GPIOA Pin 0 is Low
}
```

Parameters

- base – GPIO peripheral base pointer

Returns

Voltage level for multiple GPIO pins from the pin or the data bus.


```
static inline uint8_t GPIO_PinRead(GPIO_Type *base, gpio_pin_t ePin)
```

Read High/Low voltage level for one GPIO pin from the pin or the data bus.

Read High/Low voltage level from the pin if the pin is configured as input or the data bus.

Note: When the device comes out of reset, GPIO pins are configured as inputs with internal pull disabled. As a result, the reset value of this pin is undefined.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by gpio_pin_t. Note that not all Pins existed in SoC and user need to check the data sheet.

Return values

- 1 – Voltage level for one GPIO pin from the pin or the data bus is high.
- 0 – Voltage level for one GPIO pin from the pin or the data bus is low.

```
static inline uint16_t GPIO_PortReadRawData(GPIO_Type *base)
```

Read Raw voltage high/low level data from the pins or peripheral bus for multiple pins belong to same PORT.

Read Raw voltage high/low level data from the pins or peripheral bus. Values are not clocked and are subject to change at any time. Read several times to ensure a stable value. The reset value of this register depends on the default PIN state. User need use the return value to OR with the gpio_pin_t to decide whether that pin is logic high or low.

```
if (GPIO_PortReadRawData(GPIOA) & (uint16_t)kGPIO_Pin0)
{
    //GPIOA Pin 0 is High
}
else
{
    //GPIOA Pin 0 is Low
}
```

Parameters

- base – GPIO peripheral base pointer

Returns

Voltage high/low level data from the pins or peripheral bus for multiple pins belong to same PORT.

```
static inline uint8_t GPIO_PinReadRawData(GPIO_Type *base, gpio_pin_t ePin)
```

Read Raw logic level data from the pins or peripheral bus for one pin.

Read Raw voltage high/low level data from the pins or peripheral bus. Values are not clocked and are subject to change at any time. Read several times to ensure a stable value. The reset value of this register depends on the default PIN state.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by gpio_pin_t. Note that not all Pins existed in SoC and user need to check the data sheet.

Return values

- 1 – Raw voltage level data from the pins or peripheral bus is high.

- 0 – Raw voltage level data from the pins or peripheral bus is low.

```
static inline void GPIO_PinSetInterruptConfig(GPIO_Type *base, gpio_pin_t ePin,  
                                              gpio_interrupt_mode_t eIntConfig)
```

Configure GPIO Pin interrupt detection condition.

Configure GPIO Pin interrupt detection condition

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by *gpio_pin_t*. Note that not all Pins existed in SoC and user need to check the data sheet.
- eIntConfig – Interrupt detection condition for rising edge/down edge or no detection. See *gpio_interrupt_mode_t*

```
static inline void GPIO_PortAssertSWInterrupts(GPIO_Type *base, uint16_t u16Pins)
```

Assert software interrupt for multiple pins belong to same port which will generate interrupt.

This API is only for software testing of a software interrupt capability. When the software interrupt is asserted, an interrupt is generated. The interrupt is generated continually until this software interrupt is de-asserted.

Parameters

- base – GPIO peripheral base pointer
- u16Pins – GPIO pins which is ORed by *gpio_pin_t*. # kGPIO_Pin0 | kGPIO_Pin3 means Pin 0 and Pin 3.

```
static inline void GPIO_PortDeassertSWInterrupts(GPIO_Type *base, uint16_t u16Pins)
```

De-Assert software interrupt for multiple pins belong to same port which will stop generating interrupt.

This API is only for software testing of a software interrupt capability.

Parameters

- base – GPIO peripheral base pointer
- u16Pins – GPIO pins which is ORed by *gpio_pin_t*. # kGPIO_Pin0 | kGPIO_Pin3 means Pin 0 and Pin 3.

```
static inline void GPIO_PinAssertSWInterrupt(GPIO_Type *base, gpio_pin_t ePin)
```

Assert software interrupt for one pin which will generate interrupt.

This API is only for software testing of a software interrupt capability. When the software interrupt is asserted, an interrupt is generated. The interrupt is generated continually until this software interrupt is de-asserted.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by *gpio_pin_t*. Note that not all Pins existed in SoC and user need to check the data sheet.

```
static inline void GPIO_PinDeassertSWInterrupt(GPIO_Type *base, gpio_pin_t ePin)
```

De-Assert software interrupt for one pin which will stop generating interrupt.

This API is only for software testing of a software interrupt capability.

Parameters

- base – GPIO peripheral base pointer

- `ePin` – GPIO pin identifier. User enumerator provided by `gpio_pin_t`. Note that not all Pins existed in SoC and user need to check the data sheet.

static inline void GPIO_PortEnableInterrupts(GPIO_Type *base, uint16_t u16Pins)

Enable interrupt detection for multiple pins belong to same port.

This API is to enable interrupt detection on rising edge or falling edge.

Parameters

- `base` – GPIO peripheral base pointer
- `u16Pins` – GPIO pins which is ORed by `gpio_pin_t`. # `kGPIO_Pin0` | `kGPIO_Pin3` means Pin 0 and Pin 3.

static inline void GPIO_PortDisableInterrupts(GPIO_Type *base, uint16_t u16Pins)

Disable interrupt detection for multiple pins belong to same port.

This API is to disable interrupt detection on rising edge or falling edge.

Parameters

- `base` – GPIO peripheral base pointer
- `u16Pins` – GPIO pins which is ORed by `gpio_pin_t`. # `kGPIO_Pin0` | `kGPIO_Pin3` means Pin 0 and Pin 3.

static inline void GPIO_PinEnableInterrupt(GPIO_Type *base, *gpio_pin_t* ePin)

Enable interrupt detection for one pin.

This API is to enable interrupt detection on rising edge or falling edge.

Parameters

- `base` – GPIO peripheral base pointer
- `ePin` – GPIO pin identifier. User enumerator provided by `gpio_pin_t`. Note that not all Pins existed in SoC and user need to check the data sheet.

static inline void GPIO_PinDisableInterrupt(GPIO_Type *base, *gpio_pin_t* ePin)

Disable interrupt detection for one pin.

This API is to disable interrupt detection on rising edge or falling edge.

Parameters

- `base` – GPIO peripheral base pointer
- `ePin` – GPIO pin identifier. User enumerator provided by `gpio_pin_t`. Note that not all Pins existed in SoC and user need to check the data sheet.

static inline uint16_t GPIO_PortGetInterruptPendingStatusFlags(GPIO_Type *base)

Get interrupt pending status flags all pins belong to same port.

Get interrupt pending status flags for all pins belong to same port. User need to use the `gpio_pin_t` to OR with the return value, if the result is not 0, this flag is set. otherwise, this flag is not set.

Note: this flags can only be cleared by calling `GPIO_PortClearEdgeDetectedStatusFlag` if it is caused by edge detected or by calling `GPIO_PortEnableSWInterrupt` if it is caused by SW interrupt.

```
if (GPIO_PortGetInterruptPendingStatusFlags(GPIOA) & (uint16_t)kGPIO_Pin0)
{
    //Interrupt occurred on GPIOA Pin 0.
}
else
```

(continues on next page)

(continued from previous page)

```
{  
    //No Interrupt on GPIOA Pin 0.  
}
```

Parameters

- base – GPIO peripheral base pointer

Returns

Interrupt pending status flags all pins belong to same port.

```
static inline uint16_t GPIO_PinGetInterruptPendingStatusFlags(GPIO_Type *base, gpio_pin_t  
                                                             ePin)
```

Get interrupt pending status flags for one pin.

Get interrupt pending status flags for one pin.

Note: this flags can only be cleared by calling `GPIO_PortClearEdgeDetectedStatusFlag` if it is caused by edge detected or by calling `GPIO_PortEnableSWInterrupt` if it is caused by SW interrupt.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by `gpio_pin_t`. Note that not all Pins existed in SoC and user need to check the data sheet.

Return values

- 1 – Interrupt occurred.
- 0 – No Interrupt.

```
static inline uint16_t GPIO_PortGetEdgeDetectedStatusFlags(GPIO_Type *base)
```

Get Edge detected status flags for all pins belong to same port.

Get edge detected status flags for all pins in the PORT. This status flag can only be detected when interrupt detection is enabled by `GPIO_PortEnableInterrupt` or `GPIO_PinEnableInterrupt`.

```
if (GPIO_PortGetEdgeDetectedStatusFlags(GPIOA) & (uint16_t)kGPIO_Pin0)  
{  
    //An edge detected on GPIOA Pin 0.  
}  
else  
{  
    //No edge detected on GPIOA Pin 0.  
}
```

Parameters

- base – GPIO peripheral base pointer

Returns

Detected edge status flags for all pins belong to same port.

```
static inline uint8_t GPIO_PinGetEdgeDetectedStatusFlag(GPIO_Type *base, gpio_pin_t ePin)
```

Get Edge detected status flags for one pin.

Get edge detected status flags for one pin. This status flag can only be detected when interrupt detection is enabled by GPIO_PortEnableInterrupt or GPIO_PinEnableInterrupt.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by gpio_pin_t. Note that not all Pins existed in SoC and user need to check the data sheet.

Return values

- 1 – An edge detected.
- 0 – No edge detected.

```
static inline void GPIO_PortClearEdgeDetectedStatusFlags(GPIO_Type *base, uint16_t u16Pins)
```

Clear Edge detected status flags for multiple pins belong to same port.

Clear Edge Detected status flags for multiple pins belong to same port.

Parameters

- base – GPIO peripheral base pointer
- u16Pins – GPIO pins which is ORed by gpio_pin_t. # kGPIO_Pin0 | kGPIO_Pin3 means Pin 0 and Pin 3.

```
static inline void GPIO_PinClearEdgeDetectedStatusFlags(GPIO_Type *base, gpio_pin_t ePin)
```

Clear Edge detected status flags for one pin.

Clear Edge Detected status flags for one pin.

Parameters

- base – GPIO peripheral base pointer
- ePin – GPIO pin identifier. User enumerator provided by gpio_pin_t. Note that not all Pins existed in SoC and user need to check the data sheet.

```
FSL_GPIO_DRIVER_VERSION
```

GPIO driver version.

```
enum _gpio_pin
```

GPIO Pin identifier with each pin get a unique bit thus they can be ORed.

Values:

```
enumerator kGPIO_Pin0
```

GPIO PORT Pin 0.

```
enumerator kGPIO_Pin1
```

GPIO PORT Pin 1.

```
enumerator kGPIO_Pin2
```

GPIO PORT Pin 2.

```
enumerator kGPIO_Pin3
```

GPIO PORT Pin 3.

```
enumerator kGPIO_Pin4
```

GPIO PORT Pin 4.

```
enumerator kGPIO_Pin5
```

GPIO PORT Pin 5.

```
enumerator kGPIO_Pin6
```

GPIO PORT Pin 6.

enumerator kGPIO_Pin7

GPIO PORT Pin 7.

enumerator kGPIO_Pin8

GPIO PORT Pin 8.

enumerator kGPIO_Pin9

GPIO PORT Pin 9.

enumerator kGPIO_Pin10

GPIO PORT Pin 10.

enumerator kGPIO_Pin11

GPIO PORT Pin 11.

enumerator kGPIO_Pin12

GPIO PORT Pin 12.

enumerator kGPIO_Pin13

GPIO PORT Pin 13.

enumerator kGPIO_Pin14

GPIO PORT Pin 14.

enumerator kGPIO_Pin15

GPIO PORT Pin 15.

enum _gpio_peripheral_mode

GPIO Pin peripheral/gpio mode option.

Values:

enumerator kGPIO_ModeGpio

Set GPIO pin as GPIO Mode.

enumerator kGPIO_ModePeripheral

Set GPIO pin as Peripheral Mode.

enum _gpio_direction

GPIO Pin input/output direction option.

Values:

enumerator kGPIO_DigitalInput

Set GPIO pin as digital input.

enumerator kGPIO_DigitalOutput

Set GPIO pin as digital output.

enum _gpio_pull_mode

GPIO Pin pull resistor mode option.

Values:

enumerator kGPIO_PullDown

Internal pull-down resistor is enabled.

enumerator kGPIO_PullUp

Internal pull-up resistor is enabled.

enumerator kGPIO_PullDisable

Internal pull-up/down resistor is disabled.

enum _gpio_output_mode

GPIO Pin output mode option.

Values:

enumerator kGPIO_OutputOpenDrain

Open drain output mode.

enumerator kGPIO_OutputPushPull

Push pull output mode.

enum _gpio_output_level

GPIO Pin output High/Low level option.

Values:

enumerator kGPIO_OutputLow

Set GPIO pin output low voltage level.

enumerator kGPIO_OutputHigh

Set GPIO pin output high voltage level.

enum _gpio_output_slew_rate

GPIO Pin output Fast/Slow slew rate option.

Values:

enumerator kGPIO_SlewRateFast

Set GPIO pin output Fast slew rate.

enumerator kGPIO_SlewRateSlow

Set GPIO pin output Slow slew rate.

enum _gpio_output_drive_strength

GPIO Pin output High/Low drive strength option.

Values:

enumerator kGPIO_DriveStrengthLow

Set GPIO pin output Low-drive strength.

enumerator kGPIO_DriveStrengthHigh

Set GPIO pin output High-drive strength.

enum _gpio_interrupt_mode

GPIO Pin interrupt detect option.

Values:

enumerator kGPIO_InterruptRisingEdge

Interrupt on rising edge.

enumerator kGPIO_InterruptFallingEdge

Interrupt on falling edge.

enumerator kGPIO_InterruptDisable

Interrupt is disabled.

typedef enum _gpio_pin gpio_pin_t

GPIO Pin identifier with each pin get a unique bit thus they can be ORed.

typedef enum _gpio_peripheral_mode gpio_peripheral_mode_t

GPIO Pin peripheral/gpio mode option.

typedef enum *_gpio_direction* gpio_direction_t

GPIO Pin input/output direction option.

typedef enum *_gpio_pull_mode* gpio_pull_mode_t

GPIO Pin pull resistor mode option.

typedef enum *_gpio_output_mode* gpio_output_mode_t

GPIO Pin output mode option.

typedef enum *_gpio_output_level* gpio_output_level_t

GPIO Pin output High/Low level option.

typedef enum *_gpio_output_slew_rate* gpio_output_slew_rate_t

GPIO Pin output Fast/Slow slew rate option.

typedef enum *_gpio_output_drive_strength* gpio_output_drive_strength_t

GPIO Pin output High/Low drive strength option.

typedef enum *_gpio_interrupt_mode* gpio_interrupt_mode_t

GPIO Pin interrupt detect option.

typedef struct *_gpio_config* gpio_config_t

GPIO Pin configuration covering all configurable fields when GPIO is configured in GPIO mode.

GPIO_MUX_ENUM_TO_PORT_INDEX(emux)

Helper MACRO function to extract Port Index. (GPIOA, GPIOB, GPIOC, and so on.) The fields located in bit 8 - bit 11.

GPIO_MUX_ENUM_TO_PIN_INDEX(emux)

Helper MACRO function to extract Pin Index. The fields located in bit 4 - bit 7.

GPIO_MUX_ENUM_TO_REG_VALUE(emux)

Helper MACRO function to extract Pin mux config register value. The fields located in bit 0 - bit 1.

GPIO_MUX_ENUM_TO_PIN_MASK(emux)

Helper MACRO function to extract Pin mux config mask.

GPIO_MUX_ENUM_TO_PIN_VALUE(emux)

Helper MACRO function to extract Pin mux config register value on a GPIO Pin.

struct *_gpio_config*

#include <fsl_gpio.h> GPIO Pin configuration covering all configurable fields when GPIO is configured in GPIO mode.

Public Members

gpio_direction_t eDirection

GPIO direction, input or output

gpio_peripheral_mode_t eMode

GPIO mode as peripheral or GPIO

gpio_peripheral_mux_t eMux

Set the peripheral type if GPIO is configured as peripheral

gpio_output_mode_t eOutMode

GPIO Open-Drain/Push-Pull output mode.

gpio_output_slew_rate_t eSlewRate

GPIO Fast/Slow slew rate output mode.

gpio_output_level_t eOutLevel

GPIO Output High/Low level.

gpio_output_drive_strength_t eDriveStrength

GPIO output Drive strength High/Low.

gpio_pull_mode_t ePull

GPIO Pull resistor mode configuration.

gpio_interrupt_mode_t eInterruptMode

GPIO interrupt detection condition configuration.

2.37 The Driver Change Log

2.38 GPIO Peripheral and Driver Overview

2.39 INTC: Interrupt Controller Driver

static inline void INTC_SetIRQPriorityNum(IRQn_Type eIrq, uint8_t u8PriorityNum)

Disable IRQ or Enable IRQ with priority.

There are similar function in fsl_common:

- EnableIRQWithPriority,
- DisableIRQ,
- EnableIRQ,
- IRQ_SetPriority.

This function is faster and simpler than those in fsl_common. Generally, this function and IRQ functions in fsl_common are either-or, don't use them together for same IRQn type, but feasible that different IRQn type use them simultaneously, for example: It is OK OCCS_IRQn use INTC_SetIRQPriorityLevel, and ADC12_CC1_IRQn use EnableIRQWithPriority. It is NOT OK that OCCS_IRQn use INTC_SetIRQPriorityLevel and EnableIRQWithPriority simultaneously.

Note: Please note a none-zero priority number does directly map to priority level, simple summary is as below, you could check RM INTC chapter for more details.

- Some IPs have priority level 1~3, maps priority number 1 to priority 1, 2 to priority 2, 3 to priority 3.
 - Some IPs have priority level 0~2, maps priority number 1 to priority 0, 2 to priority 1, 3 to priority 2.
-

Parameters

- eIrq – The IRQ number.
- u8PriorityNum – IRQ interrupt priority number.
 - 0: disable IRQ.

- 1-3: enable IRQ and set its priority, 3 is the highest priority for this IRQ and 1 is the lowest priority.

static inline void INTC_SetVectorBaseAddress(uint32_t u32VectorBaseAddr)

Set the base address vector table. The value in INTC_VBA is used as the upper 13 bits of the interrupt vector VAB[20:0].

Parameters

- u32VectorBaseAddr – Vector table base address. The address requires 256 words (512 bytes) aligned. Take the vector table in MC56F83xxx_Vectors.c as example for how to implement this table.

static inline void INTC_SetFastIRQVectorHandler0(vector_type_t eVector, fast_irq_handler pfHandler)

Set the IRQ handler for fast IRQ0. The INTC takes the vector address from the appropriate FIVAL0 and FIVAH0 registers, instead of generating an address that is an offset from the vector base address (VBA).

Parameters

- eVector – The vector number.
- pfHandler – Pointer to the fast IRQ handler function, see fast_irq_handler definition for more info.

static inline void INTC_SetFastIRQVectorHandler1(vector_type_t eVector, fast_irq_handler pfHandler)

Set the IRQ handler for fast IRQ1. The INTC takes the vector address from the appropriate FIVAL1 and FIVAH1 registers, instead of generating an address that is an offset from the vector base address (VBA).

Parameters

- eVector – The eVector number.
- pfHandler – Pointer to the fast IRQ handler function, see @ ref fast_irq_handler definition for more info.

static inline uint8_t INTC_GetIRQPermittedPriorityLevel(void)

Get IRQ permitted priority levels. Interrupt exceptions may be nested to allow the servicing of an IRQ with higher priority than the current exception.

The return value indicate the priority level needed for a new IRQ to interrupt the current interrupt being sent to the Core.

Return values

- 0 – Required nested exception priority levels are 0, 1, 2, or 3.
- 1 – Required nested exception priority levels are 1, 2, or 3.
- 2 – Required nested exception priority levels are 2 or 3.
- 3 – Required nested exception priority level is 3.

static inline bool INTC_GetPendingIRQ(vector_type_t eVector)

Check if IRQ is pending for execution. Before the ISR is entered, IRQ is pending. After the ISR is entered, the IRQ is not pending.

Parameters

- eVector – The IRQ vector number.

Return values

True – if interrupt is pending, otherwise return false.

`static inline uint16_t INTC_GetLatestRespondedVectorNumber(void)`

Get the latest responded IRQ's vector number. It shows the Vector Address Bus used at the time the last IRQ was taken.

Note: Return value of the function call could be different according to where the function call is invoked.

- when called in normal ISR handler, it returns current ISR's vector number defined in `vector_type_t`.
 - when called in fast IRQ handler, it returns the lower address bits of the jump address.
 - when called in none ISR handler code, it returns previous responded IRQ vector number defined in `vector_type_t` or fast IRQ low address bits.
-

Returns

The latest vector number.

`FSL_INTC_DRIVER_VERSION`

INTC driver version.

`typedef void (*fast_irq_handler)(void)`

The handle of the fast irq handler function.

Normally this function should be guarded by: `#pragma interrupt fast` and `#pragma interrupt off`.

`INTC_DisableIRQ(x)`

Macro to disable the IRQ.

`INTC_PEND_REG_INDEX(x)`

Helper Macro function to extract IRQ pending register index comparing to `INTC_IRQP0`.

`INTC_PEND_BIT_INDEX(x)`

Helper Macro function to extract pending IRQs bit index.

`INTC_TYPE_REG_INDEX(x)`

Helper Macro function to extract IRQ priority register index comparing to `INTC_IRP0`.

`INTC_TYPE_BIT_INDEX(x)`

Helper Macro function to extract IRQs priority bit index.

2.40 The Driver Change Log

2.41 INTC Peripheral and Driver Overview

2.42 Common Driver

`status_t EnableIRQWithPriority(IRQn_Type irq, uint8_t priNum)`

Enable the IRQ, and also set the interrupt priority.

- Some IPs maps 1 to priority 1, 2 to priority 2, 3 to priority 3
- Some IPs maps 1 to priority 0, 2 to priority 1, 3 to priority 2

User should check chip's RM to get its corresponding interrupt priority.

When `priNum` set as 0, then `SDK_DSC_DEFAULT_INT_PRIO` is set instead. When `priNum` set as number larger than 3, then only the 2 LSB take effect, for example, setting `priNum` to 5 is the same with setting it to 1.

This function configures INTC module, application could call the INTC driver directly for the same purpose.

Note: The parameter `priNum` is range in 1~3, and its value is **NOT** directly map to interrupt priority.

Parameters

- `irq` – The IRQ to enable.
- `priNum` – Priority number set to interrupt controller register. Larger number means higher priority. The allowed range is 1~3, and its value is **NOT** directly map to interrupt priority. In other words, the same priority number means different interrupt priority levels for different IRQ, please check reference manual for the relationship. When pass in 0, then `SDK_DSC_DEFAULT_INT_PRIO` is set to priority register.

Returns

Currently only returns `kStatus_Success`, will enhance in the future.

status_t DisableIRQ(IRQn_Type irq)

Disable specific interrupt.

This function configures INTC module, application could call the INTC driver directly for the same purpose.

Parameters

- `irq` – The IRQ to disable.

Returns

Currently only returns `kStatus_Success`, will enhance in the future.

status_t EnableIRQ(IRQn_Type irq)

Enable specific interrupt.

The recommended workflow is calling `IRQ_SetPriority` first, then call `EnableIRQ`. If `IRQ_SetPriority` is not called first, then the interrupt is enabled with default priority value `SDK_DSC_DEFAULT_INT_PRIO`.

Another recommended workflow is calling `EnableIRQWithPriority` directly, it is the same with calling `IRQ_SetPriority + EnableIRQ`.

This function configures INTC module, application could call the INTC driver directly for the same purpose.

Parameters

- `irq` – The IRQ to enable.

Returns

Currently only returns `kStatus_Success`, will enhance in the future.

status_t IRQ_SetPriority(IRQn_Type irq, uint8_t priNum)

Set the IRQ priority.

- Some IPs maps 1 to priority 1, 2 to priority 2, 3 to priority 3

- Some IPs maps 1 to priority 0, 2 to priority 1, 3 to priority 2

User should check chip's RM to get its corresponding interrupt priority

When `priNum` set as 0, then `SDK_DSC_DEFAULT_INT_PRIO` is set instead. When `priNum` set as number larger than 3, then only the 2 LSB take effect, for example, setting `priNum` to 5 is the same with setting it to 1.

This function configures INTC module, application could call the INTC driver directly for the same purpose.

Note: The parameter `priNum` is range in 1~3, and its value is **NOT** directly map to interrupt priority.

Parameters

- `irq` – The IRQ to set.
- `priNum` – Priority number set to interrupt controller register. Larger number means higher priority, 0 means disable the interrupt. The allowed range is 0~3, and its value is **NOT** directly map to interrupt priority. In other words, the same priority number means different interrupt priority levels for different IRQ, please check reference manual for the relationship.

Returns

Currently only returns `kStatus_Success`, will enhance in the future.

`FSL_COMMON_DRIVER_VERSION`

common driver version.

`DEBUG_CONSOLE_DEVICE_TYPE_NONE`

No debug console.

`DEBUG_CONSOLE_DEVICE_TYPE_UART`

Debug console based on UART.

`DEBUG_CONSOLE_DEVICE_TYPE_LPUART`

Debug console based on LPUART.

`DEBUG_CONSOLE_DEVICE_TYPE_LPSCI`

Debug console based on LPSCI.

`DEBUG_CONSOLE_DEVICE_TYPE_USBCDC`

Debug console based on USBCDC.

`DEBUG_CONSOLE_DEVICE_TYPE_FLEXCOMM`

Debug console based on FLEXCOMM.

`DEBUG_CONSOLE_DEVICE_TYPE_IUART`

Debug console based on i.MX UART.

`DEBUG_CONSOLE_DEVICE_TYPE_VUSART`

Debug console based on LPC_VUSART.

`DEBUG_CONSOLE_DEVICE_TYPE_MINI_USART`

Debug console based on LPC_USART.

`DEBUG_CONSOLE_DEVICE_TYPE_SWO`

Debug console based on SWO.

DEBUG_CONSOLE_DEVICE_TYPE_QSCI

Debug console based on QSCI.

MIN(*a*, *b*)

Computes the minimum of *a* and *b*.

MAX(*a*, *b*)

Computes the maximum of *a* and *b*.

UINT16_MAX

Max value of uint16_t type.

UINT32_MAX

Max value of uint32_t type.

USEC_TO_COUNT(*us*, *clockFreqInHz*)

Macro to convert a microsecond period to raw count value

COUNT_TO_USEC(*count*, *clockFreqInHz*)

Macro to convert a raw count value to microsecond

MSEC_TO_COUNT(*ms*, *clockFreqInHz*)

Macro to convert a millisecond period to raw count value

COUNT_TO_MSEC(*count*, *clockFreqInHz*)

Macro to convert a raw count value to millisecond

SDK_ALIGN(*var*, *alignbytes*)

Macro to define a variable with *alignbytes* alignment

AT_NONCACHEABLE_SECTION(*var*)

AT_NONCACHEABLE_SECTION_ALIGN(*var*, *alignbytes*)

AT_NONCACHEABLE_SECTION_INIT(*var*)

AT_NONCACHEABLE_SECTION_ALIGN_INIT(*var*, *alignbytes*)

enum _status_groups

Status group numbers.

Values:

enumerator kStatusGroup_Generic

Group number for generic status codes.

enumerator kStatusGroup_FLASH

Group number for FLASH status codes.

enumerator kStatusGroup_LPSPI

Group number for LPSPI status codes.

enumerator kStatusGroup_FLEXIO_SPI

Group number for FLEXIO SPI status codes.

enumerator kStatusGroup_DSPI

Group number for DSPI status codes.

enumerator kStatusGroup_FLEXIO_UART

Group number for FLEXIO UART status codes.

enumerator kStatusGroup_FLEXIO_I2C

Group number for FLEXIO I2C status codes.

enumerator kStatusGroup_LPI2C
Group number for LPI2C status codes.

enumerator kStatusGroup_UART
Group number for UART status codes.

enumerator kStatusGroup_I2C
Group number for UART status codes.

enumerator kStatusGroup_LPSCI
Group number for LPSCI status codes.

enumerator kStatusGroup_LPUART
Group number for LPUART status codes.

enumerator kStatusGroup_SPI
Group number for SPI status code.

enumerator kStatusGroup_XRDC
Group number for XRDC status code.

enumerator kStatusGroup_SEMA42
Group number for SEMA42 status code.

enumerator kStatusGroup_SDHC
Group number for SDHC status code

enumerator kStatusGroup_SDMMC
Group number for SDMMC status code

enumerator kStatusGroup_SAI
Group number for SAI status code

enumerator kStatusGroup_MCG
Group number for MCG status codes.

enumerator kStatusGroup_SCG
Group number for SCG status codes.

enumerator kStatusGroup_SDSPI
Group number for SDSPI status codes.

enumerator kStatusGroup_FLEXIO_I2S
Group number for FLEXIO I2S status codes

enumerator kStatusGroup_FLEXIO_MCULCD
Group number for FLEXIO LCD status codes

enumerator kStatusGroup_FLASHIAP
Group number for FLASHIAP status codes

enumerator kStatusGroup_FLEXCOMM_I2C
Group number for FLEXCOMM I2C status codes

enumerator kStatusGroup_I2S
Group number for I2S status codes

enumerator kStatusGroup_IUART
Group number for IUART status codes

enumerator kStatusGroup_CSI
Group number for CSI status codes

enumerator kStatusGroup_MIPIDSI
Group number for MIPI DSI status codes

enumerator kStatusGroup_SDRAMC
Group number for SDRAMC status codes.

enumerator kStatusGroup_POWER
Group number for POWER status codes.

enumerator kStatusGroup_ENET
Group number for ENET status codes.

enumerator kStatusGroup_PHY
Group number for PHY status codes.

enumerator kStatusGroup_TRGMUX
Group number for TRGMUX status codes.

enumerator kStatusGroup_SMARTCARD
Group number for SMARTCARD status codes.

enumerator kStatusGroup_LMEM
Group number for LMEM status codes.

enumerator kStatusGroup_QSPI
Group number for QSPI status codes.

enumerator kStatusGroup_DMA
Group number for DMA status codes.

enumerator kStatusGroup_EDMA
Group number for EDMA status codes.

enumerator kStatusGroup_DMAMGR
Group number for DMAMGR status codes.

enumerator kStatusGroup_FLEXCAN
Group number for FlexCAN status codes.

enumerator kStatusGroup_LTC
Group number for LTC status codes.

enumerator kStatusGroup_FLEXIO_CAMERA
Group number for FLEXIO CAMERA status codes.

enumerator kStatusGroup_LPC_SPI
Group number for LPC_SPI status codes.

enumerator kStatusGroup_LPC_USART
Group number for LPC_USART status codes.

enumerator kStatusGroup_DMIC
Group number for DMIC status codes.

enumerator kStatusGroup_SDIF
Group number for SDIF status codes.

enumerator kStatusGroup_SPIFI
Group number for SPIFI status codes.

enumerator kStatusGroup_OTP
Group number for OTP status codes.

enumerator kStatusGroup_MCAN
Group number for MCAN status codes.

enumerator kStatusGroup_CAAM
Group number for CAAM status codes.

enumerator kStatusGroup_ECSPi
Group number for ECSPi status codes.

enumerator kStatusGroup_USDHC
Group number for USDHC status codes.

enumerator kStatusGroup_LPC_I2C
Group number for LPC_I2C status codes.

enumerator kStatusGroup_DCP
Group number for DCP status codes.

enumerator kStatusGroup_MSCAN
Group number for MSCAN status codes.

enumerator kStatusGroup_ESAI
Group number for ESAI status codes.

enumerator kStatusGroup_FLEXSPI
Group number for FLEXSPI status codes.

enumerator kStatusGroup_MMDC
Group number for MMDC status codes.

enumerator kStatusGroup_PDM
Group number for MIC status codes.

enumerator kStatusGroup_SDMA
Group number for SDMA status codes.

enumerator kStatusGroup_ICS
Group number for ICS status codes.

enumerator kStatusGroup_SPDIF
Group number for SPDIF status codes.

enumerator kStatusGroup_LPC_MINISPI
Group number for LPC_MINISPI status codes.

enumerator kStatusGroup_HASHCRYPT
Group number for Hashcrypt status codes

enumerator kStatusGroup_LPC_SPI_SSP
Group number for LPC_SPI_SSP status codes.

enumerator kStatusGroup_I3C
Group number for I3C status codes

enumerator kStatusGroup_LPC_I2C_1
Group number for LPC_I2C_1 status codes.

enumerator kStatusGroup_NOTIFIER
Group number for NOTIFIER status codes.

enumerator kStatusGroup_DebugConsole
Group number for debug console status codes.

enumerator `kStatusGroup_SEMC`
Group number for SEMC status codes.

enumerator `kStatusGroup_ApplicationRangeStart`
Starting number for application groups.

enumerator `kStatusGroup_IAP`
Group number for IAP status codes

enumerator `kStatusGroup_SFA`
Group number for SFA status codes

enumerator `kStatusGroup_SPC`
Group number for SPC status codes.

enumerator `kStatusGroup_PUF`
Group number for PUF status codes.

enumerator `kStatusGroup_TOUCH_PANEL`
Group number for touch panel status codes

enumerator `kStatusGroup_VBAT`
Group number for VBAT status codes

enumerator `kStatusGroup_XSPI`
Group number for XSPI status codes

enumerator `kStatusGroup_PNGDEC`
Group number for PNGDEC status codes

enumerator `kStatusGroup_JPEGDEC`
Group number for JPEGDEC status codes

enumerator `kStatusGroup_AUDMIX`
Group number for AUDMIX status codes

enumerator `kStatusGroup_HAL_GPIO`
Group number for HAL GPIO status codes.

enumerator `kStatusGroup_HAL_UART`
Group number for HAL UART status codes.

enumerator `kStatusGroup_HAL_TIMER`
Group number for HAL TIMER status codes.

enumerator `kStatusGroup_HAL_SPI`
Group number for HAL SPI status codes.

enumerator `kStatusGroup_HAL_I2C`
Group number for HAL I2C status codes.

enumerator `kStatusGroup_HAL_FLASH`
Group number for HAL FLASH status codes.

enumerator `kStatusGroup_HAL_PWM`
Group number for HAL PWM status codes.

enumerator `kStatusGroup_HAL_RNG`
Group number for HAL RNG status codes.

enumerator `kStatusGroup_HAL_I2S`
Group number for HAL I2S status codes.

enumerator kStatusGroup_HAL_ADC_SENSOR
Group number for HAL ADC SENSOR status codes.

enumerator kStatusGroup_TIMERMANAGER
Group number for TiMER MANAGER status codes.

enumerator kStatusGroup_SERIALMANAGER
Group number for SERIAL MANAGER status codes.

enumerator kStatusGroup_LED
Group number for LED status codes.

enumerator kStatusGroup_BUTTON
Group number for BUTTON status codes.

enumerator kStatusGroup_EXTERN_EEPROM
Group number for EXTERN EEPROM status codes.

enumerator kStatusGroup_SHELL
Group number for SHELL status codes.

enumerator kStatusGroup_MEM_MANAGER
Group number for MEM MANAGER status codes.

enumerator kStatusGroup_LIST
Group number for List status codes.

enumerator kStatusGroup_OSA
Group number for OSA status codes.

enumerator kStatusGroup_COMMON_TASK
Group number for Common task status codes.

enumerator kStatusGroup_MSG
Group number for messaging status codes.

enumerator kStatusGroup_SDK_OCOTP
Group number for OCOTP status codes.

enumerator kStatusGroup_SDK_FLEXSPINOR
Group number for FLEXSPINOR status codes.

enumerator kStatusGroup_CODEC
Group number for codec status codes.

enumerator kStatusGroup_ASRC
Group number for codec status ASRC.

enumerator kStatusGroup_OTFAD
Group number for codec status codes.

enumerator kStatusGroup_SDIO SLV
Group number for SDIO SLV status codes.

enumerator kStatusGroup_MECC
Group number for MECC status codes.

enumerator kStatusGroup_ENET_QOS
Group number for ENET_QOS status codes.

enumerator kStatusGroup_LOG
Group number for LOG status codes.

enumerator kStatusGroup_I3CBUS
Group number for I3CBUS status codes.

enumerator kStatusGroup_QSCI
Group number for QSCI status codes.

enumerator kStatusGroup_ELEMU
Group number for ELEMU status codes.

enumerator kStatusGroup_QUEUEDSPI
Group number for QSPI status codes.

enumerator kStatusGroup_POWER_MANAGER
Group number for POWER_MANAGER status codes.

enumerator kStatusGroup_IPED
Group number for IPED status codes.

enumerator kStatusGroup_ELS_PKC
Group number for ELS PKC status codes.

enumerator kStatusGroup_CSS_PKC
Group number for CSS PKC status codes.

enumerator kStatusGroup_HOSTIF
Group number for HOSTIF status codes.

enumerator kStatusGroup_CLIF
Group number for CLIF status codes.

enumerator kStatusGroup_BMA
Group number for BMA status codes.

enumerator kStatusGroup_NETC
Group number for NETC status codes.

enumerator kStatusGroup_ELE
Group number for ELE status codes.

enumerator kStatusGroup_GLIKEY
Group number for GLIKEY status codes.

enumerator kStatusGroup_AON_POWER
Group number for AON_POWER status codes.

enumerator kStatusGroup_AON_COMMON
Group number for AON_COMMON status codes.

enumerator kStatusGroup_ENDAT3
Group number for ENDAT3 status codes.

enumerator kStatusGroup_HIPERFACE
Group number for HIPERFACE status codes.

enumerator kStatusGroup_NPX
Group number for NPX status codes.

enumerator kStatusGroup_ELA_CSEC
Group number for ELA_CSEC status codes.

enumerator kStatusGroup_FLEXIO_T_FORMAT
Group number for T-format status codes.

enumerator kStatusGroup_FLEXIO_A_FORMAT

Group number for A-format status codes.

enumerator kStatusGroup_LPC_QSPI

Group number for LPC QSPI status codes.

Generic status return codes.

Values:

enumerator kStatus_Success

Generic status for Success.

enumerator kStatus_Fail

Generic status for Fail.

enumerator kStatus_ReadOnly

Generic status for read only failure.

enumerator kStatus_OutOfRange

Generic status for out of range access.

enumerator kStatus_InvalidArgument

Generic status for invalid argument check.

enumerator kStatus_Timeout

Generic status for timeout.

enumerator kStatus_NoTransferInProgress

Generic status for no transfer in progress.

enumerator kStatus_Busy

Generic status for module is busy.

enumerator kStatus_NoData

Generic status for no data is found for the operation.

typedef int32_t status_t

Type used for all status and error return values.

uint8_t bool

void *SDK_Malloc(size_t size, size_t alignbytes)

Allocate memory with given alignment and aligned size.

This is provided to support the dynamically allocated memory used in cache-able region.

Parameters

- size – The length required to malloc.
- alignbytes – The alignment size.

Return values

The – allocated memory.

void SDK_Free(void *ptr)

Free memory.

Parameters

- ptr – The memory to be release.

void SDK_DelayAtLeastUs(uint32_t delayTime_us, uint32_t coreClock_Hz)

Delay at least for some time. Please note that, this API uses while loop for delay, different run-time environments make the time not precise, if precise delay count was needed, please implement a new delay function with hardware timer.

Parameters

- delayTime_us – Delay time in unit of microsecond.
- coreClock_Hz – Core clock frequency with Hz.

static inline uint32_t DisableGlobalIRQ(void)

Disable the global IRQ.

static inline void EnableGlobalIRQ(uint32_t irqSts)

Enable the global IRQ.

static inline bool isIRQAllowed(void)

Check if currently core is able to response IRQ.

void SDK_DelayCoreCycles(uint32_t u32Num)

Delay core cycles. Please note that, this API uses software loop for delay, the actual delayed time depends on core clock frequency, where the function is located (ram or flash), flash clock, possible interrupt.

Parameters

- u32Num – Number of core clock cycle which needs to be delayed.

uint32_t SDK_CovertUsToCount(uint32_t u32Us, uint32_t u32Hz)

Covert us to count with fixed-point calculation.

Note: u32Us must not be greater than 4294

Parameters

- u32Us – Time in us
- u32Hz – Clock frequency in Hz

Returns

The count value

uint32_t SDK_CovertCountToUs(uint32_t u32Count, uint32_t u32Hz)

Covert count to us with fixed-point calculation.

Note: u32Hz must not be greater than 429496729UL(0xFFFFFFFFUL/10UL)

Parameters

- u32Count – Count value
- u32Hz – Clock frequency in Hz

Returns

The us value

uint32_t SDK_CovertMsToCount(uint32_t u32Ms, uint32_t u32Hz)

Covert ms to count with fixed-point calculation.

Note: u32Ms must not be greater than 42949UL @ u32Hz = 100M

Parameters

- u32Ms – Time in us
- u32Hz – Clock frequency in Hz

Returns

The count value

uint32_t SDK_CovertCountToMs(uint32_t u32Count, uint32_t u32Hz)

Covert count to ms with fixed-point calculation.

Note: u32Hz must not be greater than 429496729UL(0xFFFFFFFFUL/10UL)

Parameters

- u32Count – Count value
- u32Hz – Clock frequency in Hz

Returns

The us value

void SDK_DelayAtLeastMs(uint32_t delayTime_ms, uint32_t coreClock_Hz)

Delay at least for some time in millisecond unit. Please note that, this API uses while loop for delay, different run-time environments make the time not precise, if precise delay count was needed, please implement a new delay function with hardware timer.

Parameters

- delayTime_ms – Delay time in unit of millisecond.
- coreClock_Hz – Core clock frequency with Hz.

FSL_DRIVER_TRANSFER_DOUBLE_WEAK_IRQ

Macro to use the default weak IRQ handler in drivers.

MAKE_STATUS(group, code)

Construct a status code value from a group and code number.

MAKE_VERSION(major, minor, bugfix)

Construct the version number for drivers.

The driver version is a 32-bit number, for both 32-bit platforms(such as Cortex M) and 16-bit platforms(such as DSC).

Unused	Major Version	Minor Version	Bug Fix
31 25 24	17 16	9 8	0

ARRAY_SIZE(x)

Computes the number of elements in an array.

UINT64_H(X)

Macro to get upper 32 bits of a 64-bit value

UINT64_L(X)

Macro to get lower 32 bits of a 64-bit value

SUPPRESS_FALL_THROUGH_WARNING()

For switch case code block, if case section ends without “break;” statement, there will be fallthrough warning with compiler flag -Wextra or -Wimplicit-fallthrough=n when using armgcc. To suppress this warning, “SUPPRESS_FALL_THROUGH_WARNING();” need to be added at the end of each case section which misses “break;”statement.

true

false

SDK_ISR_EXIT_BARRIER

SDK_DSC_DEFAULT_INT_PRIO

Default DSC interrupt priority number.

SetIRQBasePriority(x)

Set base core IRQ priority, that core will response the interrupt request with priority >= base IRQ priority.

PeriphReadReg(reg)

Read register value.

Example: val = PeriphReadReg(OCCS->OSCTL2);

Parameters

- reg – Register name.

Returns

The value of register.

PeriphWriteReg(reg, data)

Write data to register.

Example: PeriphWriteReg(OCCS->OSCTL2, 0x278U);

Parameters

- reg – Register name.
- data – Data wrote to register.

PeriphSetBits(reg, bitMask)

Set specified bits in register.

Example: PeriphSetBits(OCCS->OSCTL2, 0x12U);

Parameters

- reg – Register name.
- bitMask – Bits mask, set bits will be set in the register.

PeriphClearBits(reg, bitMask)

Clear specified bits in register.

Example: PeriphClearBits(OCCS->OSCTL2, 0x12U);

Parameters

- reg – Register name.
- bitMask – Bits mask, set bits will be cleared in the register.

PeriphInvertBits(reg, bitMask)

Invert specified bits in register.

Example: PeriphInvertBits(OCCS->OSCTL2, 0x12U);

Parameters

- reg – Register name.
- bitMask – Bits mask, set bits will be inverted in the register.

`PeriphGetBits(reg, bitMask)`

Get specified bits in register.

Example: `val = PeriphGetBits(OCCS->OSCTL2, 0x23U);`

Parameters

- `reg` – Register name.
- `bitMask` – Bits mask, specify the getting bits.

Returns

The value of specified bits.

`PeriphWriteBitGroup(reg, bitMask, bitValue)`

Write group of bits to register.

Example: `PeriphWriteBitGroup(OCCS->DIVBY, OCCS_DIVBY_COD_MASK, OCCS_DIVBY_COD(23U));`
`PeriphWriteBitGroup(OCCS->DIVBY, OCCS_DIVBY_COD_MASK | OCCS_DIVBY_PLLDB_MASK, \ OCCS_DIVBY_COD(23U) | OCCS_DIVBY_PLLDB(49U));`

Parameters

- `reg` – Register name.
- `bitMask` – Bits mask, mask of the group of bits.
- `bitValue` – This value will be written into the bit group specified by parameter `bitMask`.

`PeriphSafeClearFlags(reg, allFlagsMask, flagMask)`

Clear (acknowledge) flags which are active-high and are cleared-by-write-one.

This macro is useful when a register is comprised by normal read-write bits and cleared-by-write-one bits. Example: `PeriphSafeClearFlags(PWMA->FAULT[0].FSTS, PWM_FSTS_FFLAG_MASK, PWM_FSTS_FFLAG(2));`

Parameters

- `reg` – Register name.
- `allFlagsMask` – Mask for all flags which are active-high and are cleared-by-write-one.
- `flagMask` – The selected flags(cleared-by-write-one) which are supposed to be cleared.

`PeriphSafeClearBits(reg, allFlagsMask, bitMask)`

Clear selected bits without modifying (acknowledge) bit flags which are active-high and are cleared-by-write-one.

This macro is useful when a register is comprised by normal read-write bits and cleared-by-write-one bits. Example: `PeriphSafeClearBits(PWMA->FAULT[0].FSTS, PWM_FSTS_FFLAG_MASK, PWM_FSTS_FHALF(2));`

Parameters

- `reg` – Register name.
- `allFlagsMask` – Mask for all flags which are active-high and are cleared-by-write-one.
- `bitMask` – The selected bits which are supposed to be cleared.

`PeriphSafeSetBits(reg, allFlagsMask, bitMask)`

Set selected bits without modifying (acknowledge) bit flags which are active-high and are cleared-by-write-one.

This macro is useful when a register is comprised by normal read-write bits and cleared-by-write-one bits. Example: `PeriphSafeSetBits(PWMA->FAULT[0].FSTS, PWM_FSTS_FFLAG_MASK, PWM_FSTS_FHALF(2));`

Parameters

- `reg` – Register name.
- `allFlagsMask` – Mask for all flags which are active-high and are cleared-by-write-one.
- `bitMask` – The selected bits which are supposed to be set.

`PeriphSafeWriteBitGroup(reg, allFlagsMask, bitMask, bitValue)`

Write group of bits without modifying (acknowledge) bit flags which are active-high and are cleared-by-write-one.

This macro is useful when a register is comprised by normal read-write bits and cleared-by-write-one bits. Example: `PeriphSafeWriteBitGroup(PWMA->FAULT[0].FSTS, PWM_FSTS_FFLAG_MASK, PWM_FSTS_FHALF_MASK, PWM_FSTS_FHALF(3U));`
`PeriphSafeWriteBitGroup(PWMA->FAULT[0].FSTS, PWM_FSTS_FFLAG_MASK, PWM_FSTS_FHALF_MASK | PWM_FSTS_FFULL_MASK, \ PWM_FSTS_FHALF(3U) | PWM_FSTS_FFULL(2U));`

Parameters

- `reg` – Register name.
- `allFlagsMask` – Mask for all flags which are active-high and are cleared-by-write-one.
- `bitMask` – Bits mask, mask of the group of bits.
- `bitValue` – This value will be written into the bit group specified by parameter `bitMask`.

`SDK_GET_REGISTER_BYTE_ADDR(ipType, ipBase, regName)`

Get IP register byte address with `uint32_t` type.

This macro is useful when a register byte address is required, especially in SDM mode. Example: `SDK_GET_REGISTER_BYTE_ADDR(ADC_Type, ADC, RSLT[0]);`

Parameters

- `ipType` – IP register mapping struct type.
- `ipBase` – IP instance base pointer, WORD address.
- `regName` – Member register name of IP register mapping struct.

`MSDK_REG_SECURE_ADDR(x)`

`MSDK_REG_NONSECURE_ADDR(x)`

2.43 LPI2C: Low Power Inter-Integrated Circuit Driver

`enum _lpi2c_master_status_flags`

LPI2C master peripheral flags.

The following status register flags can be cleared:

- `kLPI2C_MasterEndOfPacketInterruptFlag`
- `kLPI2C_MasterStopDetectInterruptFlag`
- `kLPI2C_MasterNackDetectInterruptFlag`

- kLPI2C_MasterArbitrationLostInterruptFlag
- kLPI2C_MasterFifoErrInterruptFlag
- kLPI2C_MasterPinLowTimeoutInterruptFlag
- kLPI2C_MasterDataMatchInterruptFlag

All flags except kLPI2C_MasterBusyFlag and kLPI2C_MasterBusBusyFlag can be enabled as interrupts.

Note: These enums are meant to be OR'd together to form a bit mask.

Values:

enumerator kLPI2C_MasterTxReadyInterruptFlag

Transmit data interrupt flag

enumerator kLPI2C_MasterRxReadyInterruptFlag

Receive data interrupt flag

enumerator kLPI2C_MasterEndOfPacketInterruptFlag

End Packet interrupt flag

enumerator kLPI2C_MasterStopDetectInterruptFlag

Stop detect interrupt flag

enumerator kLPI2C_MasterNackDetectInterruptFlag

NACK detect interrupt flag

enumerator kLPI2C_MasterArbitrationLostInterruptFlag

Arbitration lost interrupt flag

enumerator kLPI2C_MasterFifoErrInterruptFlag

FIFO error interrupt flag

enumerator kLPI2C_MasterPinLowTimeoutInterruptFlag

Pin low timeout interrupt flag

enumerator kLPI2C_MasterDataMatchInterruptFlag

Data match interrupt flag

enumerator kLPI2C_MasterBusyFlag

Master busy flag

enumerator kLPI2C_MasterBusBusyFlag

Bus busy flag All flags

enumerator kLPI2C_MasterStatusAllFlags

enumerator kLPI2C_MasterClearInterruptFlags

All flags which are cleared by the driver upon starting a transfer.

enumerator kLPI2C_MasterIrqFlags

IRQ sources enabled by the non-blocking transactional API.

enumerator kLPI2C_MasterErrorInterruptFlags

Errors to check for.

enum _lpi2c_slave_status_flags

LPI2C slave peripheral flags.

The following status register flags can be cleared:

- kLPI2C_SlaveRepeatedStartDetectInterruptFlag
- kLPI2C_SlaveStopDetectInterruptFlag
- kLPI2C_SlaveBitErrInterruptFlag
- kLPI2C_SlaveFifoErrInterruptFlag

All flags except kLPI2C_SlaveBusyFlag and kLPI2C_SlaveBusBusyFlag can be enabled as interrupts.

Note: These enumerations are meant to be OR'd together to form a bit mask.

Values:

enumerator kLPI2C_SlaveTxReadyInterruptFlag

Transmit data interrupt flag

enumerator kLPI2C_SlaveRxReadyInterruptFlag

Receive data interrupt flag

enumerator kLPI2C_SlaveAddressValidInterruptFlag

Address valid interrupt flag

enumerator kLPI2C_SlaveTransmitAckInterruptFlag

Transmit ACK interrupt flag

enumerator kLPI2C_SlaveRepeatedStartDetectInterruptFlag

Repeated start detect interrupt flag

enumerator kLPI2C_SlaveStopDetectInterruptFlag

Stop detect interrupt flag

enumerator kLPI2C_SlaveBitErrInterruptFlag

Bit error interrupt flag

enumerator kLPI2C_SlaveFifoErrInterruptFlag

FIFO error interrupt flag

enumerator kLPI2C_SlaveAddressMatch0InterruptFlag

Address match 0 interrupt flag

enumerator kLPI2C_SlaveAddressMatch1InterruptFlag

Address match 1 interrupt flag

enumerator kLPI2C_SlaveGeneralCallInterruptFlag

General call interrupt flag

enumerator kLPI2C_SlaveSmbusAlertRespInterruptFlag

SMBus alert response interrupt flag

enumerator kLPI2C_SlaveBusyFlag

Master busy flag

enumerator kLPI2C_SlaveBusBusyFlag

Bus busy flag All flags

enumerator kLPI2C_SlaveStatusAllFlags

enumerator kLPI2C_SlaveClearInterruptFlags

All flags which are cleared by the driver upon starting a transfer.

enumerator kLPI2C_SlaveIrqFlags

IRQ sources enabled by the non-blocking transactional API.

enumerator kLPI2C_SlaveErrorInterruptFlags

Errors to check for.

static inline uint16_t LPI2C_MasterGetStatusFlags(LPI2C_Type *base)

Gets the LPI2C master status flags.

A bit mask with the state of all LPI2C master status flags is returned. For each flag, the corresponding bit in the return value is set if the flag is asserted.

See also:

`_lpi2c_master_status_flags`

Parameters

- base – The LPI2C peripheral base address.

Returns

State of the status flags:

- 1: related status flag is set.
- 0: related status flag is not set.

static inline void LPI2C_MasterClearStatusFlags(LPI2C_Type *base, uint16_t u16StatusFlags)

Clears the LPI2C master status flag state.

The following status register flags can be cleared:

- kLPI2C_MasterEndOfPacketInterruptFlag
- kLPI2C_MasterStopDetectInterruptFlag
- kLPI2C_MasterNackDetectInterruptFlag
- kLPI2C_MasterArbitrationLostInterruptFlag
- kLPI2C_MasterFifoErrInterruptFlag
- kLPI2C_MasterPinLowTimeoutInterruptFlag
- kLPI2C_MasterDataMatchInterruptFlag

Attempts to clear other flags has no effect.

See also:

`_lpi2c_master_status_flags`.

Parameters

- base – The LPI2C peripheral base address.
- u16StatusFlags – A bitmask of status flags that are to be cleared. The mask is composed of `_lpi2c_master_status_flags` enumerators OR'd together. You may pass the result of a previous call to `LPI2C_MasterGetStatusFlags()`.

static inline uint16_t LPI2C_SlaveGetStatusFlags(LPI2C_Type *base)

Gets the LPI2C slave status flags.

A bit mask with the state of all LPI2C slave status flags is returned. For each flag, the corresponding bit in the return value is set if the flag is asserted.

See also:

`_lpi2c_slave_status_flags`

Parameters

- `base` – The LPI2C peripheral base address.

Returns

State of the status flags:

- 1: related status flag is set.
- 0: related status flag is not set.

```
static inline void LPI2C_SlaveClearStatusFlags(LPI2C_Type *base, uint16_t u16StatusFlags)
```

Clears the LPI2C status flag state.

The following status register flags can be cleared:

- `kLPI2C_SlaveRepeatedStartDetectInterruptFlag`
- `kLPI2C_SlaveStopDetectInterruptFlag`
- `kLPI2C_SlaveBitErrInterruptFlag`
- `kLPI2C_SlaveFifoErrInterruptFlag`

Attempts to clear other flags has no effect.

See also:

`_lpi2c_slave_status_flags`.

Parameters

- `base` – The LPI2C peripheral base address.
- `u16StatusFlags` – A bitmask of status flags that are to be cleared. The mask is composed of `_lpi2c_slave_status_flags` enumerators OR'd together. You may pass the result of a previous call to `LPI2C_SlaveGetStatusFlags()`.

```
enum _lpi2c_master_pin_config
```

LPI2C pin configuration.

Values:

```
enumerator kLPI2C_2PinOpenDrain
```

LPI2C Configured for 2-pin open drain mode

```
enumerator kLPI2C_2PinOutputOnly
```

LPI2C Configured for 2-pin output only mode (ultra-fast mode)

```
enumerator kLPI2C_2PinPushPull
```

LPI2C Configured for 2-pin push-pull mode

```
enumerator kLPI2C_4PinPushPull
```

LPI2C Configured for 4-pin push-pull mode

```
enumerator kLPI2C_2PinOpenDrainWithSeparateSlave
```

LPI2C Configured for 2-pin open drain mode with separate LPI2C slave

```
enumerator kLPI2C_2PinOutputOnlyWithSeparateSlave
```

LPI2C Configured for 2-pin output only mode(ultra-fast mode) with separate LPI2C slave

enumerator kLPI2C_2PinPushPullWithSeparateSlave
LPI2C Configured for 2-pin push-pull mode with separate LPI2C slave

enumerator kLPI2C_4PinPushPullWithInvertedOutput
LPI2C Configured for 4-pin push-pull mode(inverted outputs)

enum _lpi2c_host_request_source
LPI2C master host request selection.

Values:

enumerator kLPI2C_HostRequestExternalPin
Select the LPI2C_HREQ pin as the host request input

enumerator kLPI2C_HostRequestInputTrigger
Select the input trigger as the host request input

enum _lpi2c_host_request_polarity
LPI2C master host request pin polarity configuration.

Values:

enumerator kLPI2C_HostRequestPinActiveLow
Configure the LPI2C_HREQ pin active low

enumerator kLPI2C_HostRequestPinActiveHigh
Configure the LPI2C_HREQ pin active high

enum _lpi2c_data_match_config_mode
LPI2C master data match configuration modes.

Values:

enumerator kLPI2C_MatchDisabled
LPI2C Match Disabled

enumerator kLPI2C_1stWordEqualsM0OrM1
LPI2C Match Enabled and 1st data word equals MATCH0 OR MATCH1

enumerator kLPI2C_AnyWordEqualsM0OrM1
LPI2C Match Enabled and any data word equals MATCH0 OR MATCH1

enumerator kLPI2C_1stWordEqualsM0And2ndWordEqualsM1
LPI2C Match Enabled and 1st data word equals MATCH0, 2nd data equals MATCH1

enumerator kLPI2C_AnyWordEqualsM0AndNextWordEqualsM1
LPI2C Match Enabled and any data word equals MATCH0, next data equals MATCH1

enumerator kLPI2C_1stWordAndM1EqualsM0AndM1
LPI2C Match Enabled and 1st data word and MATCH0 equals MATCH0 and MATCH1

enumerator kLPI2C_AnyWordAndM1EqualsM0AndM1
LPI2C Match Enabled and any data word and MATCH0 equals MATCH0 and MATCH1

typedef enum _lpi2c_master_pin_config lpi2c_master_pin_config_t
LPI2C pin configuration.

typedef enum _lpi2c_host_request_source lpi2c_host_request_source_t
LPI2C master host request selection.

typedef enum _lpi2c_host_request_polarity lpi2c_host_request_polarity_t
LPI2C master host request pin polarity configuration.

```
typedef enum _lpi2c_data_match_config_mode lpi2c_data_match_config_mode_t
```

LPI2C master data match configuration modes.

```
typedef struct _lpi2c_match_config lpi2c_data_match_config_t
```

LPI2C master data match configuration structure.

```
void LPI2C_MasterSetBaudRate(LPI2C_Type *base, uint32_t u32SrcClockHz, uint32_t  
                             u32BaudRateBps)
```

Sets the I2C bus frequency for master transactions.

The LPI2C master is automatically disabled and re-enabled as necessary to configure the baud rate. Do not call this function during a transfer, or the transfer is aborted.

Note: Please note that the second parameter is the clock frequency of LPI2C module, the third parameter means user configured bus baudrate, this implementation is different from other I2C drivers which use baudrate configuration as second parameter and source clock frequency as third parameter.

Parameters

- base – The LPI2C peripheral base address.
- u32SrcClockHz – LPI2C functional clock frequency in Hertz.
- u32BaudRateBps – Requested bus frequency in Hertz.

```
void LPI2C_MasterSetGlitchFilter(LPI2C_Type *base, uint32_t u32SdaFilterWidthNs, uint32_t  
                                u32SclFilterWidthNs, uint32_t u32SrcClockHz)
```

Sets the LPI2C master glitch filter width.

After the LPI2C module is initialized as master, user can call this function to change the glitch filter width.

Parameters

- base – The LPI2C peripheral base address.
- u32SdaFilterWidthNs – The SDA glitch filter length in nano seconds.
- u32SclFilterWidthNs – The SCL glitch filter length in nano seconds.
- u32SrcClockHz – LPI2C peripheral clock frequency in Hz

```
void LPI2C_MasterSetDataMatch(LPI2C_Type *base, const lpi2c_data_match_config_t *psConfig)
```

Configures LPI2C master data match feature.

Parameters

- base – The LPI2C peripheral base address.
- psConfig – Settings for the data match feature.

```
static inline void LPI2C_MasterReset(LPI2C_Type *base)
```

Performs a software reset.

Restores the LPI2C master peripheral to reset conditions.

Parameters

- base – The LPI2C peripheral base address.

```
static inline void LPI2C_MasterEnable(LPI2C_Type *base, bool bEnable)
```

Enables or disables the LPI2C module as master.

Parameters

- base – The LPI2C peripheral base address.

- `bEnable` – Pass true to enable or false to disable the specified LPI2C as master.

```
static inline void LPI2C_MasterSetWatermarks(LPI2C_Type *base, uint16_t u16TxWords,
                                             uint16_t u16RxWords)
```

Sets the watermarks for LPI2C master FIFOs.

Parameters

- `base` – The LPI2C peripheral base address.
- `u16TxWords` – Transmit FIFO watermark value in words. The `kLPI2C_MasterTxReadyInterruptFlag` flag is set whenever the number of words in the transmit FIFO is equal or less than *u16TxWords*. Writing a value equal or greater than the FIFO size is truncated.
- `u16RxWords` – Receive FIFO watermark value in words. The `kLPI2C_MasterRxReadyInterruptFlag` flag is set whenever the number of words in the receive FIFO is greater than *u16RxWords*. Writing a value equal or greater than the FIFO size is truncated.

```
static inline void LPI2C_MasterGetFifoCounts(LPI2C_Type *base, uint16_t *pu16RxCount,
                                             uint16_t *pu16TxCount)
```

Gets the current number of words in the LPI2C master FIFOs.

Parameters

- `base` – The LPI2C peripheral base address.
- `pu16RxCount` – Pointer through which the current number of words in the transmit FIFO is returned. Pass NULL if this value is not required.
- `pu16TxCount` – Pointer through which the current number of words in the receive FIFO is returned. Pass NULL if this value is not required.

```
enum _lpi2c_slave_address_match
```

LPI2C slave address match options.

Values:

```
enumerator kLPI2C_Match7BitAddress0
```

Match only 7 bit address 0.

```
enumerator kLPI2C_Match10BitAddress0
```

Match only 10 bit address 0.

```
enumerator kLPI2C_Match7BitAddress0Or7BitAddress1
```

Match either 7 bit address 0 or 7 bit address 1.

```
enumerator kLPI2C_Match10BitAddress0Or10BitAddress1
```

Match either 10 bit address 0 or 10 bit address 1.

```
enumerator kLPI2C_Match7BitAddress0Or10BitAddress1
```

Match either 7 bit address 0 or 10 bit address 1.

```
enumerator kLPI2C_Match10BitAddress0Or7BitAddress1
```

Match either 10 bit address 0 or 7 bit address 1.

```
enumerator kLPI2C_Match7BitAddress0Through7BitAddress1
```

Match a range of slave addresses from 7 bit address 0 through 7 bit address 1.

```
enumerator kLPI2C_Match10BitAddress0Through10BitAddress1
```

Match a range of slave addresses from 10 bit address 0 through 10 bit address 1.

```
typedef enum _lpi2c_slave_address_match lpi2c_slave_address_match_t
```

LPI2C slave address match options.

```
void LPI2C_SlaveSetGlitchFilter(LPI2C_Type *base, uint32_t u32SdaFilterWidthNs, uint32_t  
                               u32SclFilterWidthNs, uint32_t u32SrcClockHz)
```

Sets the LPI2C slave glitch filter width.

After the LPI2C module is initialized as slave, user can call this function to change the glitch filter width.

Parameters

- base – The LPI2C peripheral base address.
- u32SdaFilterWidthNs – The SDA glitch filter length in nano seconds.
- u32SclFilterWidthNs – The SCL glitch filter length in nano seconds.
- u32SrcClockHz – LPI2C peripheral clock frequency in Hz

```
void LPI2C_SlaveSetAddressingMode(LPI2C_Type *base, lpi2c_slave_address_match_t  
                                  eAddressMatchMode, uint16_t u16Address0, uint16_t  
                                  u16Address1)
```

Configure the slave addressing mode.

After the LPI2C module is initialized as slave, user can call this function to change the configuration of slave addressing mode.

Parameters

- base – The LPI2C peripheral base address.
- eAddressMatchMode – The slave addressing match mode.
- u16Address0 – LPI2C slave address 0. For 7-bit address low 7-bit is used, for 10-bit address low 10-bit is used.
- u16Address1 – LPI2C slave address 1. For 7-bit address low 7-bit is used, for 10-bit address low 10-bit is used.

```
static inline void LPI2C_SlaveReset(LPI2C_Type *base)
```

Performs a software reset of the LPI2C slave peripheral.

Parameters

- base – The LPI2C peripheral base address.

```
static inline void LPI2C_SlaveEnable(LPI2C_Type *base, bool bEnable)
```

Enables or disables the LPI2C module as slave.

Parameters

- base – The LPI2C peripheral base address.
- bEnable – Pass true to enable or false to disable the specified LPI2C as slave.

```
enum _lpi2c_data_direction
```

Direction of master and slave transfers.

Values:

```
enumerator kLPI2C_Write
```

Master transmit.

```
enumerator kLPI2C_Read
```

Master receive.

```
typedef enum _lpi2c_data_direction lpi2c_data_direction_t
```

Direction of master and slave transfers.

```
status_t LPI2C_MasterCheckAndClearError(LPI2C_Type *base, uint16_t u16Status)
```

```
status_t LPI2C_MasterCheckForBusyBus(LPI2C_Type *base)
```

```
status_t LPI2C_MasterStartInternal(LPI2C_Type *base, uint8_t u8Address, lpi2c_data_direction_t  
eDir, bool bIsRepeatedStart)
```

```
static inline status_t LPI2C_MasterStart(LPI2C_Type *base, uint8_t u8Address,  
lpi2c_data_direction_t eDir)
```

Sends a START signal and slave address on the I2C bus.

This function is used to initiate a new master mode transfer. First, the bus state is checked to ensure that another master is not occupying the bus. Then a START signal is transmitted, followed by the 7-bit address specified in the *address* parameter. Note that this function does not actually wait until the START and address are successfully sent on the bus before returning.

Parameters

- *base* – The LPI2C peripheral base address.
- *u8Address* – 7-bit slave device address, in bits [6:0].
- *eDir* – Master transfer direction, either `kLPI2C_Read` or `kLPI2C_Write`. This parameter is used to set the R/w bit (bit 0) in the transmitted slave address.

Return values

- `kStatus_Success` – START signal and address were successfully enqueued in the transmit FIFO.
- `kStatus_LPI2C_Busy` – Another master is currently utilizing the bus.

```
static inline status_t LPI2C_MasterRepeatedStart(LPI2C_Type *base, uint8_t u8Address,  
lpi2c_data_direction_t eDir)
```

Sends a repeated START signal and slave address on the I2C bus.

This function is used to send a Repeated START signal when a transfer is already in progress. Like `LPI2C_MasterStart()`, it also sends the specified 7-bit address.

Note: This function exists primarily to maintain compatible APIs between LPI2C and I2C drivers, as well as to better document the intent of code that uses these APIs.

Parameters

- *base* – The LPI2C peripheral base address.
- *u8Address* – 7-bit slave device address, in bits [6:0].
- *eDir* – Master transfer direction, either `kLPI2C_Read` or `kLPI2C_Write`. This parameter is used to set the R/w bit (bit 0) in the transmitted slave address.

Return values

- `kStatus_Success` – Repeated START signal and address were successfully enqueued in the transmit FIFO.
- `kStatus_LPI2C_Busy` – Another master is currently utilizing the bus.

```
status_t LPI2C_MasterStop(LPI2C_Type *base)
```

Sends a STOP signal on the I2C bus.

This function does not return until the STOP signal is seen on the bus, or an error occurs.

Parameters

- base – The LPI2C peripheral base address.

Return values

- kStatus_Success – The STOP signal was successfully sent on the bus and the transaction terminated.
- kStatus_LPI2C_Busy – Another master is currently utilizing the bus.
- kStatus_LPI2C_Nak – The slave device sent a NAK in response to a byte.
- kStatus_LPI2C_FifoError – FIFO under run or overrun.
- kStatus_LPI2C_ArbitrationLost – Arbitration lost error.
- kStatus_LPI2C_PinLowTimeout – SCL or SDA were held low longer than the timeout.

status_t LPI2C_MasterSend(LPI2C_Type *base, void *pTxBuff, uint16_t u16TxSize, bool bPecEnable)

Performs a polling send transfer on the I2C bus.

Sends up to *u16TxSize* number of bytes to the previously addressed slave device. The slave may reply with a NAK to any byte in order to terminate the transfer early. If this happens, this function returns kStatus_LPI2C_Nak.

Parameters

- base – The LPI2C peripheral base address.
- pTxBuff – The pointer to the data to be transferred.
- u16TxSize – The length in bytes of the data to be transferred.
- bPecEnable – It decides whether one byte PEC is needed to send.

Return values

- kStatus_Success – Data was sent successfully.
- kStatus_LPI2C_Busy – Another master is currently utilizing the bus.
- kStatus_LPI2C_Nak – The slave device sent a NAK in response to a byte.
- kStatus_LPI2C_FifoError – FIFO under run or over run.
- kStatus_LPI2C_ArbitrationLost – Arbitration lost error.
- kStatus_LPI2C_PinLowTimeout – SCL or SDA were held low longer than the timeout.

status_t LPI2C_MasterReceive(LPI2C_Type *base, void *pRxBuff, uint16_t u16RxSize, bool bPecEnable)

Performs a polling receive transfer on the I2C bus.

Parameters

- base – The LPI2C peripheral base address.
- pRxBuff – The pointer to the data to be transferred.
- u16RxSize – The length in bytes of the data to be transferred.
- bPecEnable – It decides whether one byte PEC is needed to receive.

Return values

- kStatus_Success – Data was received successfully.
- kStatus_LPI2C_Busy – Another master is currently utilizing the bus.

- `kStatus_LPI2C_Nak` – The slave device sent a NAK in response to a byte.
- `kStatus_LPI2C_FifoError` – FIFO under run or overrun.
- `kStatus_LPI2C_ArbitrationLost` – Arbitration lost error.
- `kStatus_LPI2C_PinLowTimeout` – SCL or SDA were held low longer than the timeout.

`enum _lpi2c_master_transfer_control_flags`

Transfer option flags.

Note: These enumerations are intended to be OR'd together to form a bit mask of options for the `_lpi2c_master_transfer::u8ControlFlagMask` field.

Values:

enumerator `kLPI2C_TransferStartStopFlag`

Transfer starts with a start signal, stops with a stop signal.

enumerator `kLPI2C_TransferNoStartFlag`

Don't send a start condition, address, and sub address

enumerator `kLPI2C_TransferRepeatedStartFlag`

Send a repeated start condition

enumerator `kLPI2C_TransferNoStopFlag`

Don't send a stop condition.

`typedef struct _lpi2c_master_transfer lpi2c_master_transfer_t`

`lpi2c_master_transfer_t` forward definition.

`typedef struct _lpi2c_master_transfer_handle lpi2c_master_transfer_handle_t`

`lpi2c_master_transfer_handle_t` forward definition.

`typedef void (*lpi2c_master_transfer_callback_t)(lpi2c_master_transfer_handle_t *psHandle)`

Master completion callback function pointer type.

This callback is used only for the non-blocking master transfer API. Specify the callback you wish to use in the call to `LPI2C_MasterTransferCreateHandle()`.

Param `psHandle`

Pointer to the LPI2C master driver handle.

`status_t LPI2C_MasterTransferBlocking(LPI2C_Type *base, lpi2c_master_transfer_t *psTransfer)`

Performs a master polling transfer on the I2C bus.

Note: The API does not return until the transfer succeeds or fails due to error happens during transfer.

Parameters

- `base` – The LPI2C peripheral base address.
- `psTransfer` – Pointer to the transfer structure.

Return values

- `kStatus_Success` – Data was received successfully.
- `kStatus_LPI2C_Busy` – Another master is currently utilizing the bus.
- `kStatus_LPI2C_Nak` – The slave device sent a NAK in response to a byte.

- `kStatus_LPI2C_FifoError` – FIFO under run or overrun.
- `kStatus_LPI2C_ArbitrationLost` – Arbitration lost error.
- `kStatus_LPI2C_PinLowTimeout` – SCL or SDA were held low longer than the timeout.

```
void LPI2C_MasterTransferCreateHandle(LPI2C_Type *base, lpi2c_master_transfer_handle_t
                                     *psHandle, lpi2c_master_transfer_callback_t
                                     pfCallback, void *pUserData)
```

Creates a new handle for the LPI2C master non-blocking APIs.

The creation of a handle is for use with the non-blocking APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the `LPI2C_MasterTransferAbort()` API shall be called.

Note: The function also enables the NVIC IRQ for the input LPI2C. Need to notice that on some SoCs the LPI2C IRQ is connected to INTMUX, in this case user needs to enable the associated INTMUX IRQ in application.

Parameters

- `base` – The LPI2C peripheral base address.
- `psHandle` – Pointer to the LPI2C master driver handle.
- `pfCallback` – User provided pointer to the asynchronous callback function.
- `pUserData` – User provided pointer to the application callback data.

```
status_t LPI2C_MasterTransferNonBlocking(lpi2c_master_transfer_handle_t *psHandle,
                                         lpi2c_master_transfer_t *psTransfer)
```

Performs a non-blocking transaction on the I2C bus.

Parameters

- `psHandle` – Pointer to the LPI2C master driver handle.
- `psTransfer` – The pointer to the transfer descriptor.

Return values

- `kStatus_Success` – The transaction was started successfully.
- `kStatus_LPI2C_Busy` – Either another master is currently utilizing the bus, or a non-blocking transaction is already in progress.

```
status_t LPI2C_MasterTransferGetCount(lpi2c_master_transfer_handle_t *psHandle, uint16_t
                                     *pu16Count)
```

Returns number of bytes transferred so far.

Parameters

- `psHandle` – Pointer to the LPI2C master driver handle.
- `pu16Count` – Number of bytes transferred so far by the non-blocking transaction.

Return values

- `kStatus_Success` –
- `kStatus_NoTransferInProgress` – There is not a non-blocking transaction currently in progress.

void LPI2C_MasterTransferAbort(*lpi2c_master_transfer_handle_t* *psHandle)

Terminates a non-blocking LPI2C master transmission early.

Note: It is not safe to call this function from an IRQ handler that has a higher priority than the LPI2C peripheral's IRQ priority.

Parameters

- psHandle – Pointer to the LPI2C master driver handle.

Return values

- kStatus_Success – A transaction was successfully aborted.
- kStatus_LPI2C_Idle – There is not a non-blocking transaction currently in progress.

void LPI2C_MasterTransferHandleIRQ(*lpi2c_master_transfer_handle_t* *psHandle)

Reusable routine to handle master interrupts.

Note: This function does not need to be called unless you are reimplementing the non-blocking API's interrupt handler routines to add special functionality.

Parameters

- psHandle – Pointer to the LPI2C master driver handle.

enum *_lpi2c_slave_transfer_event*

Set of events sent to the callback for non blocking slave transfers.

These event enumerations are used for two related purposes. First, a bit mask created by OR'ing together events is passed to LPI2C_SlaveTransferNonBlocking() in order to specify which events to enable. Then, when the slave callback is invoked, it is passed the current event through its *transfer* parameter.

Note: These enumerations are meant to be OR'd together to form a bit mask of events.

Values:

enumerator kLPI2C_SlaveAddressMatchEvent

Received the slave address after a start or repeated start.

enumerator kLPI2C_SlaveTransmitEvent

Callback is requested to provide data to transmit (slave-transmitter role).

enumerator kLPI2C_SlaveReceiveEvent

Callback is requested to provide a buffer in which to place received data (slave-receiver role).

enumerator kLPI2C_SlaveTransmitAckEvent

Callback needs to either transmit an ACK or NACK.

enumerator kLPI2C_SlaveRepeatedStartEvent

A repeated start was detected.

enumerator kLPI2C_SlaveCompletionEvent

A stop was detected, completing the transfer.

enumerator kLPI2C_SlaveAllEvents

Bit mask of all available events.

typedef struct *_lpi2c_slave_transfer* lpi2c_slave_transfer_t

lpi2c_slave_transfer_t forward definition.

typedef struct *_lpi2c_slave_transfer_handle* lpi2c_slave_transfer_handle_t

lpi2c_slave_transfer_handle_t forward definition.

typedef void (*lpi2c_slave_transfer_callback_t)(lpi2c_slave_transfer_handle_t *psHandle)

Slave event callback function pointer type.

This callback is used only for the slave non-blocking transfer API. To install a callback, use the LPI2C_SlaveSetCallback() function after you have created a handle.

Param psHandle

Pointer to the LPI2C slave driver handle.

typedef enum *_lpi2c_slave_transfer_event* lpi2c_slave_transfer_event_t

Set of events sent to the callback for non blocking slave transfers.

These event enumerations are used for two related purposes. First, a bit mask created by OR'ing together events is passed to LPI2C_SlaveTransferNonBlocking() in order to specify which events to enable. Then, when the slave callback is invoked, it is passed the current event through its *transfer* parameter.

Note: These enumerations are meant to be OR'd together to form a bit mask of events.

void LPI2C_SlaveTransferCreateHandle(LPI2C_Type *base, lpi2c_slave_transfer_handle_t *psHandle, lpi2c_slave_transfer_callback_t pfCallback, void *pUserData)

Creates a new handle for the LPI2C slave non-blocking APIs.

The creation of a handle is for use with the non-blocking APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the LPI2C_SlaveTransferAbort() API shall be called.

Note: The function also enables the NVIC IRQ for the input LPI2C. Need to notice that on some SoCs the LPI2C IRQ is connected to INTMUX, in this case user needs to enable the associated INTMUX IRQ in application.

Parameters

- base – The LPI2C peripheral base address.
- psHandle – Pointer to the LPI2C slave driver handle.
- pfCallback – User provided pointer to the asynchronous callback function.
- pUserData – User provided pointer to the application callback data.

status_t LPI2C_SlaveTransferNonBlocking(lpi2c_slave_transfer_handle_t *psHandle, uint8_t u8EventMask)

Starts accepting slave transfers.

Call this API after calling I2C_SlaveInit() and LPI2C_SlaveTransferCreateHandle() to start processing transactions driven by an I2C master. The slave monitors the I2C bus and pass events to the callback that was passed into the call to LPI2C_SlaveTransferCreateHandle(). The callback is always invoked from the interrupt context.

The set of events received by the callback is customizable. To do so, set the *eventMask* parameter to the OR'd combination of *lpi2c_slave_transfer_event_t* enumerators for the events you wish to receive. The *kLPI2C_SlaveTransmitEvent* and *kLPI2C_SlaveReceiveEvent* events are always enabled and do not need to be included in the mask. Alternatively, you can pass 0 to get a default set of only the transmit and receive events that are always enabled. In addition, the *kLPI2C_SlaveAllEvents* constant is provided as a convenient way to enable all events.

Parameters

- *psHandle* – Pointer to *lpi2c_slave_transfer_handle_t* structure which stores the transfer state.
- *u8EventMask* – Bit mask formed by OR'ing together *lpi2c_slave_transfer_event_t* enumerators to specify which events to send to the callback. Other accepted values are 0 to get a default set of only the transmit and receive events, and *kLPI2C_SlaveAllEvents* to enable all events.

Return values

- *kStatus__Success* – Slave transfers were successfully started.
- *kStatus__LPI2C_Busy* – Slave transfers have already been started on this handle.

status_t LPI2C_SlaveTransferGetCount(*lpi2c_slave_transfer_handle_t* **psHandle*, *uint16_t* **pu16Count*)

Gets the slave transfer status during a non-blocking transfer.

Parameters

- *psHandle* – Pointer to *i2c_slave_handle_t* structure.
- *pu16Count* – Pointer to a value to hold the number of bytes transferred. May be NULL if the count is not required.

Return values

- *kStatus__Success* –
- *kStatus__NoTransferInProgress* –

void LPI2C_SlaveTransferAbort(*lpi2c_slave_transfer_handle_t* **psHandle*)

Aborts the slave non-blocking transfers.

Note: This API could be called at any time to stop slave for handling the bus events.

Parameters

- *psHandle* – Pointer to *lpi2c_slave_transfer_handle_t* structure which stores the transfer state.

Return values

- *kStatus__Success* –
- *kStatus__LPI2C_Idle* –

void LPI2C_SlaveTransferHandleIRQ(*lpi2c_slave_transfer_handle_t* **psHandle*)

Reusable routine to handle slave interrupts.

Note: This function does not need to be called unless you are reimplementing the non blocking API's interrupt handler routines to add special functionality.

Parameters

- `psHandle` – Pointer to `lpi2c_slave_transfer_handle_t` structure which stores the transfer state.

`typedef struct _lpi2c_master_config lpi2c_master_config_t`

Structure with settings to initialize the LPI2C master module.

This structure holds configuration settings for the LPI2C peripheral. To initialize this structure to reasonable defaults, call the `LPI2C_MasterGetDefaultConfig()` function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

`typedef struct _lpi2c_slave_config lpi2c_slave_config_t`

Structure with settings to initialize the LPI2C slave module.

This structure holds configuration settings for the LPI2C slave peripheral. To initialize this structure to reasonable defaults, call the `LPI2C_SlaveGetDefaultConfig()` function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

`typedef struct _lpi2c_config lpi2c_config_t`

Structure with settings to initialize the LPI2C module.

This structure holds configuration settings for the LPI2C peripheral. To initialize this structure to reasonable defaults, call the `LPI2C_GetDefaultConfig` function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

`void LPI2C_GetDefaultConfig(lpi2c_config_t *psConfig, uint16_t u16SlaveAddress, uint32_t u32SrcClockHz)`

Provides a default configuration for the LPI2C peripheral, including master and slave.

This is an example:

```
lpi2c_config_t sConfig;
LPI2C_GetDefaultConfig(&sConfig, u16SlaveAddress, u32SrcClockHz);
sConfig.u32BaudRateBps = 100000U;
LPI2C_Init(LPI2C0, &sConfig);
```

After calling this function, you can override any settings in order to customize the configuration, prior to initializing the driver with `LPI2C_Init()`.

Parameters

- `psConfig` – User provided configuration structure for default values. Refer to `lpi2c_config_t`.
- `u16SlaveAddress` – Slave address raw value, driver will shift it.
- `u32SrcClockHz` – Frequency in Hertz of the LPI2C functional clock. Used to calculate the baud rate divisors, filter widths, and timeout periods.

`void LPI2C_Init(LPI2C_Type *base, const lpi2c_config_t *psConfig)`

Initializes the LPI2C peripheral, including master and slave.

This function enables the peripheral clock and initializes the LPI2C peripheral as described by the user provided configuration. A software reset is performed prior to configuration. This function can enable master and slave together. If only want to use one of them, please call `LPI2C_MasterInit` or `LPI2C_SlaveInit`.

Note: If `FSL_SDK_DISABLE_DRIVER_CLOCK_CONTROL` is enabled by user, the init function will not ungate I2C clock source before initialization, to avoid hardfault, user has to manually enable ungate the clock source before calling the API.

Parameters

- `base` – The LPI2C peripheral base address.
- `psConfig` – User provided peripheral configuration. Use `LPI2C_GetDefaultConfig` to get a set of defaults that you can override.

`void LPI2C_Deinit(LPI2C_Type *base)`

Deinitializes the LPI2C peripheral, including master and slave.

This function disables the LPI2C peripheral and gates the clock. It also performs a software reset to restore the peripheral to reset conditions.

Parameters

- `base` – The LPI2C peripheral base address.

`void LPI2C_MasterGetDefaultConfig(lpi2c_master_config_t *psMasterConfig, uint32_t u32SrcClockHz)`

Provides a default configuration for the LPI2C master peripheral.

This is an example:

```
lpi2c_master_config_t sConfig;
LPI2C_MasterGetDefaultConfig(&sConfig, 12000000U);
sConfig.u32BaudRateBps = 100000U;
LPI2C_MasterInit(LPI2C1, &sConfig);
```

After calling this function, you can override any settings in order to customize the configuration, prior to initializing the master driver with `LPI2C_MasterInit()`.

Parameters

- `psMasterConfig` – User provided configuration structure for default values. Refer to `lpi2c_master_config_t`.
- `u32SrcClockHz` – Frequency in Hertz of the LPI2C functional clock. Used to calculate the baud rate divisors, filter widths, and timeout periods.

`void LPI2C_MasterInit(LPI2C_Type *base, const lpi2c_master_config_t *psMasterConfig)`

Initializes the LPI2C master peripheral.

This function enables the peripheral clock and initializes the LPI2C master peripheral as described by the user provided configuration. A software reset is performed prior to configuration. User just needs to call this function to enable LPI2C master if only use I2C master operation.

Note: If `FSL_SDK_DISABLE_DRIVER_CLOCK_CONTROL` is enabled by user, the init function will not ungate I2C clock source before initialization, to avoid hardfault, user has to manually enable ungate the clock source before calling the API.

Parameters

- `base` – The LPI2C peripheral base address.
- `psMasterConfig` – User provided peripheral configuration. Use `LPI2C_MasterGetDefaultConfig()` to get a set of defaults that you can override.

void LPI2C_MasterDeinit(LPI2C_Type *base)

Deinitializes the LPI2C master peripheral.

This function disables the LPI2C master peripheral and gates the clock. It also performs a software reset to restore the peripheral to reset conditions.

Parameters

- base – The LPI2C peripheral base address.

void LPI2C_SlaveGetDefaultConfig(*lpi2c_slave_config_t* *psSlaveConfig, uint16_t u16SlaveAddress, uint32_t u32SrcClockHz)

Provides a default configuration for the LPI2C slave peripheral.

This is an example:

```
lpi2c_slave_config_t sConfig;  
LPI2C_SlaveGetDefaultConfig(&sConfig, u16SlaveAddress, u32SrcClockHz);  
LPI2C_SlaveInit(LPI2C1, &sConfig);
```

After calling this function, override any settings to customize the configuration, prior to initializing the master driver with LPI2C_SlaveInit(). Be sure to override at least the *u8Address0* member of the configuration structure with the desired slave address.

Parameters

- psSlaveConfig – User provided configuration structure that is set to default values. Refer to *lpi2c_slave_config_t*.
- u16SlaveAddress – Slave address raw value, driver will shift it.
- u32SrcClockHz – Frequency in Hertz of the LPI2C functional clock. Used to calculate the filter widths, data valid delay, and clock hold time.

void LPI2C_SlaveInit(LPI2C_Type *base, const *lpi2c_slave_config_t* *psSlaveConfig)

Initializes the LPI2C slave peripheral.

This function enables the peripheral clock and initializes the LPI2C slave peripheral as described by the user provided configuration. User just needs to call this function to enable LPI2C slave if only use I2C slave operation.

Note: If FSL_SDK_DISABLE_DRIVER_CLOCK_CONTROL is enabled by user, the init function will not ungate I2C clock source before initialization, to avoid hardfault, user has to manually enable ungate the clock source before calling the API.

Parameters

- base – The LPI2C peripheral base address.
- psSlaveConfig – User provided peripheral configuration. Use LPI2C_SlaveGetDefaultConfig() to get a set of defaults that you can override.

void LPI2C_SlaveDeinit(LPI2C_Type *base)

Deinitializes the LPI2C slave peripheral.

This function disables the LPI2C slave peripheral and gates the clock. It also performs a software reset to restore the peripheral to reset conditions.

Parameters

- base – The LPI2C peripheral base address.

```
static inline void LPI2C_MasterEnableInterrupts(LPI2C_Type *base, uint16_t u16Interrupts)
```

Enables the LPI2C master interrupt requests.

All flags except kLPI2C_MasterBusyFlag and kLPI2C_MasterBusBusyFlag can be enabled as interrupts.

Parameters

- base – The LPI2C peripheral base address.
- u16Interrupts – Bit mask of interrupts to enable. See `_lpi2c_master_status_flags` for the set of constants that should be OR'd together to form the bit mask.

```
static inline void LPI2C_MasterDisableInterrupts(LPI2C_Type *base, uint16_t u16Interrupts)
```

Disables the LPI2C master interrupt requests.

All flags except kLPI2C_MasterBusyFlag and kLPI2C_MasterBusBusyFlag can be enabled as interrupts.

Parameters

- base – The LPI2C peripheral base address.
- u16Interrupts – Bit mask of interrupts to disable. See `_lpi2c_master_status_flags` for the set of constants that should be OR'd together to form the bit mask.

```
static inline uint16_t LPI2C_MasterGetEnabledInterrupts(LPI2C_Type *base)
```

Returns the set of currently enabled LPI2C master interrupt requests.

Parameters

- base – The LPI2C peripheral base address.

Returns

A bitmask composed of `_lpi2c_master_status_flags` enumerators OR'd together to indicate the set of enabled interrupts.

```
static inline void LPI2C_SlaveEnableInterrupts(LPI2C_Type *base, uint16_t u16Interrupts)
```

Enables the LPI2C slave interrupt requests.

All flags except kLPI2C_SlaveBusyFlag and kLPI2C_SlaveBusBusyFlag can be enabled as interrupts.

Parameters

- base – The LPI2C peripheral base address.
- u16Interrupts – Bit mask of interrupts to enable. See `_lpi2c_slave_status_flags` for the set of constants that should be OR'd together to form the bit mask.

```
static inline void LPI2C_SlaveDisableInterrupts(LPI2C_Type *base, uint16_t u16Interrupts)
```

Disables the LPI2C slave interrupt requests.

All flags except kLPI2C_SlaveBusyFlag and kLPI2C_SlaveBusBusyFlag can be enabled as interrupts.

Parameters

- base – The LPI2C peripheral base address.
- u16Interrupts – Bit mask of interrupts to disable. See `_lpi2c_slave_status_flags` for the set of constants that should be OR'd together to form the bit mask.

```
static inline uint16_t LPI2C_SlaveGetEnabledInterrupts(LPI2C_Type *base)
```

Returns the set of currently enabled LPI2C slave interrupt requests.

Parameters

- base – The LPI2C peripheral base address.

Returns

A bitmask composed of `_lpi2c_slave_status_flags` enumerators OR'd together to indicate the set of enabled interrupts.

```
static inline void LPI2C_MasterEnableDMA(LPI2C_Type *base, bool bEnableTx, bool  
                                         bEnableRx)
```

Enables or disables LPI2C master DMA requests.

Parameters

- base – The LPI2C peripheral base address.
- bEnableTx – Enable flag for transmit DMA request. Pass true for enable, false for disable.
- bEnableRx – Enable flag for receive DMA request. Pass true for enable, false for disable.

```
static inline uint32_t LPI2C_MasterGetTxFifoAddress(LPI2C_Type *base)
```

Gets LPI2C master transmit data register address for DMA transfer.

Parameters

- base – The LPI2C peripheral base address.

Returns

The LPI2C Master Transmit Data Register address.

```
static inline uint32_t LPI2C_MasterGetRxFifoAddress(LPI2C_Type *base)
```

Gets LPI2C master receive data register address for DMA transfer.

Parameters

- base – The LPI2C peripheral base address.

Returns

The LPI2C Master Receive Data Register address.

```
static inline void LPI2C_SlaveEnableDMA(LPI2C_Type *base, bool bEnableAddressValid, bool  
                                         bEnableRx, bool bEnableTx)
```

Enables or disables the LPI2C slave peripheral DMA requests.

Parameters

- base – The LPI2C peripheral base address.
- bEnableAddressValid – Enable flag for the address valid DMA request. Pass true for enable, false for disable. The address valid DMA request is shared with the receive data DMA request.
- bEnableRx – Enable flag for the receive data DMA request. Pass true for enable, false for disable.
- bEnableTx – Enable flag for the transmit data DMA request. Pass true for enable, false for disable.

```
static inline bool LPI2C_SlaveGetBusIdleState(LPI2C_Type *base)
```

Returns whether the bus is idle.

Requires the slave mode to be enabled.

Parameters

- `base` – The LPI2C peripheral base address.

Return values

- `true` – Bus is busy.
- `false` – Bus is idle.

`static inline void LPI2C_SlaveTransmitAck(LPI2C_Type *base, bool bSendAck)`

Transmits either an ACK or NAK on the I2C bus in response to a byte from the master.

Use this function to send an ACK or NAK when the `kLPI2C_SlaveTransmitAckInterruptFlag` is asserted. This only happens if you enable the `sclStall.enableAck` field of the `lpi2c_slave_config_t` configuration structure used to initialize the slave peripheral.

Parameters

- `base` – The LPI2C peripheral base address.
- `bSendAck` – Pass `true` for an ACK or `false` for a NAK.

`static inline uint16_t LPI2C_SlaveGetReceivedAddress(LPI2C_Type *base)`

Returns the slave address sent by the I2C master.

This function should only be called if the `kLPI2C_SlaveAddressValidInterruptFlag` is asserted.

Parameters

- `base` – The LPI2C peripheral base address.

Returns

The 8-bit address matched by the LPI2C slave. Bit 0 contains the R/w direction bit, and the 7-bit slave address is in the upper 7 bits.

`status_t LPI2C_SlaveSend(LPI2C_Type *base, void *pTxBuff, uint16_t u16TxSize, uint16_t *pu16ActualTxSize)`

Performs a polling send transfer on the I2C bus.

Parameters

- `base` – The LPI2C peripheral base address.
- `pTxBuff` – The pointer to the data to be transferred.
- `u16TxSize` – The length in bytes of the data to be transferred.
- `pu16ActualTxSize` –

Returns

Error or success status returned by API.

`status_t LPI2C_SlaveReceive(LPI2C_Type *base, void *pRxBuff, uint16_t u16RxSize, uint16_t *pu16ActualRxSize)`

Performs a polling receive transfer on the I2C bus.

Parameters

- `base` – The LPI2C peripheral base address.
- `pRxBuff` – The pointer to the data to be transferred.
- `u16RxSize` – The length in bytes of the data to be transferred.
- `pu16ActualRxSize` –

Returns

Error or success status returned by API.

FSL_LPI2C_DRIVER_VERSION

LPI2C driver version.

LPI2C status return codes.

Values:

enumerator kStatus_LPI2C_Busy

The master is already performing a transfer.

enumerator kStatus_LPI2C_Idle

The slave driver is idle.

enumerator kStatus_LPI2C_Nak

The slave device sent a NAK in response to a byte.

enumerator kStatus_LPI2C_FifoError

FIFO under run or overrun.

enumerator kStatus_LPI2C_BitError

Transferred bit was not seen on the bus.

enumerator kStatus_LPI2C_ArbitrationLost

Arbitration lost error.

enumerator kStatus_LPI2C_PinLowTimeout

SCL or SDA were held low longer than the timeout.

enumerator kStatus_LPI2C_NoTransferInProgress

Attempt to abort a transfer when one is not in progress.

enumerator kStatus_LPI2C_DmaRequestFail

DMA request failed.

enumerator kStatus_LPI2C_Timeout

Timeout polling status flags.

FSL_SDK_DISABLE_DRIVER_CLOCK_CONTROL

Clock enable/disable controlled by driver or not.

I2C_RETRY_TIMES

Retry times for waiting flag.

I2C_SMBUS_ENABLE

Control whether to use SMBus features.

LPI2C_GET_TRANSFER_COMPLETION_STATUS(psHandle)

LPI2C_GET_TRANSFER_USER_DATA(psHandle)

LPI2C_GET_SLAVE_TRANSFER_EVENT(psHandle)

LPI2C_GET_SLAVE_TRANSFER_DATA_POINTER(psHandle)

LPI2C_GET_SLAVE_TRANSFER_DATASIZE(psHandle)

LPI2C_GET_SLAVE_TRANSFERRED_COUNT(psHandle)

struct `_lpi2c_master_config`

#include <fsl_lpi2c.h> Structure with settings to initialize the LPI2C master module.

This structure holds configuration settings for the LPI2C peripheral. To initialize this structure to reasonable defaults, call the `LPI2C_MasterGetDefaultConfig()` function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

Public Members

bool `bEnableMaster`

Whether to enable master mode.

bool `bEnableDoze`

Whether master is enabled in doze mode.

bool `bDebugEnable`

Enable transfers to continue when halted in debug mode.

bool `bIgnoreAck`

Whether to ignore ACK/NACK.

uint16_t `ePinConfig`

The pin configuration option chosen from `lpi2c_master_pin_config_t`.

struct `_lpi2c_master_config` `hostRequest`

Host request options.

uint32_t `u32SrcClockHz`

Frequency in Hertz of the LPI2C functional clock.

uint32_t `u32BaudRateBps`

Desired baud rate in Hertz.

uint32_t `u32BusIdleTimeoutNs`

Bus idle timeout in nanoseconds. Set to 0 to disable.

uint32_t `u32PinLowTimeoutNs`

Pin low timeout in nanoseconds. Set to 0 to disable.

uint32_t `u32SdaGlitchFilterWidthNs`

Width in nanoseconds of glitch filter on SDA pin. Set to 0 to disable.

uint32_t `u32SclGlitchFilterWidthNs`

Width in nanoseconds of glitch filter on SCL pin. Set to 0 to disable.

struct `_lpi2c_slave_config`

#include <fsl_lpi2c.h> Structure with settings to initialize the LPI2C slave module.

This structure holds configuration settings for the LPI2C slave peripheral. To initialize this structure to reasonable defaults, call the `LPI2C_SlaveGetDefaultConfig()` function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

Public Members

bool `bEnableSlave`

Enable slave mode.

`bool bFilterDozeEnable`
Enable digital glitch filter in doze mode.

`bool bFilterEnable`
Enable digital glitch filter.

`bool bIgnoreAck`
Continue transfers after a NACK is detected.

`bool bEnableGeneralCall`
Enable general call address matching.

`bool bEnableSmbusAlert`
Enable SMBus Alert.

`bool bEnableReceivedAddressRead`
Enable reading the address received address as the first byte of data.

`uint16_t eAddressMatchMode`
Address matching options chosen from `lpi2c_slave_address_match_t`.

`uint16_t u16Address0`
Slave's 7-bit address.

`uint16_t u16Address1`
Alternate slave 7-bit address.

`uint32_t u32SdaGlitchFilterWidthNs`
Width in nanoseconds of the digital filter on the SDA signal.

`uint32_t u32SclGlitchFilterWidthNs`
Width in nanoseconds of the digital filter on the SCL signal.

`uint32_t u32DataValidDelayNs`
Width in nanoseconds of the data valid delay.

`uint32_t u32ClockHoldTimeNs`
Width in nanoseconds of the clock hold time.

`uint32_t u32SrcClockHz`
Frequency in Hertz of the LPI2C functional clock.

`struct _lpi2c_config`

#include <fsl_lpi2c.h> Structure with settings to initialize the LPI2C module.

This structure holds configuration settings for the LPI2C peripheral. To initialize this structure to reasonable defaults, call the `LPI2C_GetDefaultConfig` function and pass a pointer to your configuration structure instance.

The configuration structure can be made constant so it resides in flash.

Public Members

`bool bEnableMaster`
< Master configuration. Whether to enable master mode.

`bool bEnableDoze`
Whether master is enabled in doze mode.

`bool bDebugEnable`
Enable transfers to continue when halted in debug mode.

`bool bMasterIgnoreAck`
Whether to ignore ACK/NACK.

`uint16_t ePinConfig`
The pin configuration option chosen from `lpi2c_master_pin_config_t`.

`struct _lpi2c_config` `hostRequest`
Host request options.

`uint32_t u32BaudRateBps`
Desired baud rate in Hertz.

`uint32_t u32BusIdleTimeoutNs`
Bus idle timeout in nanoseconds. Set to 0 to disable.

`uint32_t u32PinLowTimeoutNs`
Pin low timeout in nanoseconds. Set to 0 to disable.

`uint32_t u32MasterSdaGlitchFilterWidthNs`
Width in nanoseconds of glitch filter on SDA pin. Set to 0 to disable.

`uint32_t u32MasterSclGlitchFilterWidthNs`
Width in nanoseconds of glitch filter on SCL pin. Set to 0 to disable. Slave configuration.

`bool bEnableSlave`
Enable slave mode.

`bool bFilterDozeEnable`
Enable digital glitch filter in doze mode.

`bool bFilterEnable`
Enable digital glitch filter.

`bool bSlaveIgnoreAck`
Continue transfers after a NACK is detected.

`bool bEnableGeneralCall`
Enable general call address matching.

`bool bEnableSmbusAlert`
Enable SMBus Alert.

`bool bEnableReceivedAddressRead`
Enable reading the address received address as the first byte of data.

`uint16_t eAddressMatchMode`
Address matching options chosen from `lpi2c_slave_address_match_t`.

`uint16_t u16Address0`
Slave's 7-bit address.

`uint16_t u16Address1`
Alternate slave 7-bit address.

`uint32_t u32SlaveSdaGlitchFilterWidthNs`
Width in nanoseconds of the digital filter on the SDA signal.

`uint32_t u32SlaveSclGlitchFilterWidthNs`
Width in nanoseconds of the digital filter on the SCL signal.

`uint32_t u32DataValidDelayNs`
Width in nanoseconds of the data valid delay.

uint32_t u32ClockHoldTimeNs

Width in nanoseconds of the clock hold time.

uint32_t u32SrcClockHz

Frequency in Hertz of the LPI2C functional clock.

struct __lpi2c_match_config

#include <fsl_lpi2c.h> LPI2C master data match configuration structure.

Public Members

lpi2c_data_match_config_mode_t eMatchMode

Data match configuration setting.

bool bRxDataMatchOnly

When set to true, received data is ignored until a successful match.

uint8_t u8Match0

Match value 0.

uint8_t u8Match1

Match value 1.

struct __lpi2c_master_transfer

#include <fsl_lpi2c.h> Non-blocking transfer descriptor structure.

This structure is used to pass transaction parameters to the LPI2C_MasterTransferNonBlocking() API.

Public Members

uint8_t u8ControlFlagMask

Bit mask of options for the transfer. See enumeration *__lpi2c_master_transfer_control_flags* for available options. Set to 0 or *kLPI2C_TransferStartStopFlag* for normal transfers.

uint16_t u8SlaveAddress

The 7-bit slave address.

lpi2c_data_direction_t eDirection

Either *kLPI2C_Read* or *kLPI2C_Write*.

uint8_t *pu8Command

Pointer to command code.

uint8_t u8CommandSize

Length of sub address to send in bytes.

void *pData

Pointer to data to transfer.

uint16_t u16DataSize

Number of bytes to transfer.

struct __lpi2c_master_transfer_handle

#include <fsl_lpi2c.h> Driver handle for master non-blocking APIs.

Note: The contents of this structure are private and subject to change.

Public Members

`LPI2C_Type *base`
The peripheral register address base.

`uint8_t u8State`
Transfer state machine current state.

`uint16_t u16RemainingBytes`
Remaining byte count in current state.

`uint8_t *pu8Buf`
Buffer pointer for current state.

`uint16_t u16CommandBuffer[7]`
LPI2C command sequence.

`lpi2c_master_transfer_t sTransfer`
Copy of the current transfer info.

`lpi2c_master_transfer_callback_t pfCompletionCallback`
Callback function pointer.

`status_t completionStatus`
Master transfer complete status indicating how the transfer ends.

`void *pUserData`
Application data passed to callback.

`struct _lpi2c_slave_transfer`
`#include <fsl_lpi2c.h>` LPI2C slave transfer structure.

Public Members

`uint8_t u8EventMask`
Mask of enabled events, set correspond bit if user wants to handle this event.

`lpi2c_slave_transfer_event_t eEvent`
Reason the callback is being invoked `lpi2c_slave_transfer_event_t`.

`uint16_t u16ReceivedAddress`
Matching address send by master.

`uint8_t *pu8Data`
Transfer buffer

`uint16_t u16DataSize`
Transfer size

`status_t completionStatus`
Success or error code describing how the transfer completed. Only applies for `kLPI2C_SlaveCompletionEvent`.

`uint16_t u16TransferredCount`
Number of bytes actually transferred since start or last repeated start.

`struct _lpi2c_slave_transfer_handle`
`#include <fsl_lpi2c.h>` LPI2C slave handle structure.

Note: The contents of this structure are private and subject to change.

Public Members

`LPI2C_Type *base`
The peripheral register address base.

`lpi2c_slave_transfer_t sTransfer`
LPI2C slave transfer copy.

`bool bIsBusy`
Whether transfer is busy.

`bool bWasTransmit`
Whether the last transfer was a transmit.

`uint8_t u8State`
A transfer state maintained during transfer.

`uint16_t u16TransferredCount`
Count of bytes transferred.

`lpi2c_slave_transfer_callback_t pfCallback`
Callback function called at transfer event.

`void *pUserData`
Callback parameter passed to callback.

`struct hostRequest`

Public Members

`bool bEnable`
Whether to enable host request.

`uint16_t eSource`
Host request source chosen from `lpi2c_host_request_source_t`.

`uint16_t ePolarity`
Host request pin polarity chosen from `lpi2c_host_request_polarity_t`.

`struct sSclStall`

Public Members

`bool bEnableAck`
Enables SCL clock stretching during slave-transmit address byte(s) and slave-receiver address and data byte(s) to allow software to write the Transmit ACK Register before the ACK or NACK is transmitted. Clock stretching occurs when transmitting the 9th bit. When `enableAckSCLStall` is enabled, there is no need to set either `enableRxDataSCLStall` or `enableAddressSCLStall`.

`bool bEnableTx`
Enables SCL clock stretching when the transmit data flag is set during a slave-transmit transfer.

`bool bEnableRx`
Enables SCL clock stretching when receive data flag is set during a slave-receive transfer.

`bool bEnableAddress`
Enables SCL clock stretching when the address valid flag is asserted.

`struct hostRequest`

Public Members

bool bEnable

Whether to enable host request.

uint16_t eSource

Host request source chosen from lpi2c_host_request_source_t.

uint16_t ePolarity

Host request pin polarity chosen from lpi2c_host_request_polarity_t.

struct sSclStall

Public Members

bool bEnableAck

Enables SCL clock stretching during slave-transmit address byte(s) and slave-receiver address and data byte(s) to allow software to write the Transmit ACK Register before the ACK or NACK is transmitted. Clock stretching occurs when transmitting the 9th bit. When enableAckSCLStall is enabled, there is no need to set either enableRxDataSCLStall or enableAddressSCLStall.

bool bEnableTx

Enables SCL clock stretching when the transmit data flag is set during a slave-transmit transfer.

bool bEnableRx

Enables SCL clock stretching when receive data flag is set during a slave-receive transfer.

bool bEnableAddress

Enables SCL clock stretching when the address valid flag is asserted.

2.44 The Driver Change Log

2.45 LPI2C_EDMA: EDMA based LPI2C Driver

```
void LPI2C_MasterCreateEDMAHandle(LPI2C_Type *base, lpi2c_master_edma_transfer_handle_t
    *psHandle, lpi2c_master_edma_transfer_callback_t
    pfcallback, void *pUserData, DMA_Type *edmaBase,
    edma_channel_t eEdmaTxChannel, edma_channel_t
    eEdmaRxChannel)
```

Create a new handle for the LPI2C master DMA APIs.

The creation of a handle is for use with the DMA APIs. Once a handle is created, there is not a corresponding destroy handle. If the user wants to terminate a transfer, the LPI2C_MasterTransferAbortEDMA() API shall be called.

For devices where the LPI2C send and receive DMA requests are OR'd together, the *txDma-Handle* parameter is ignored and may be set to NULL.

Parameters

- base – The LPI2C peripheral base address.
- psHandle – Pointer to the LPI2C master driver handle.
- pfcallback – User provided pointer to the asynchronous callback function.

- `pUserData` – User provided pointer to the application callback data.
- `edmaBase` – Edma base address.
- `eEdmaTxChannel` – eDMA channel for master transfer Tx request.
- `eEdmaRxChannel` – eDMA channel for master transfer Rx request.

`status_t LPI2C_MasterTransferEDMA(lpi2c_master_edma_transfer_handle_t *psHandle,
lpi2c_master_transfer_t *psTransfer)`

Performs a non-blocking DMA-based transaction on the I2C bus.

The callback specified when the *handle* was created is invoked when the transaction has completed.

Parameters

- `psHandle` – Pointer to the LPI2C master driver handle.
- `psTransfer` – The pointer to the transfer descriptor.

Return values

- `kStatus_Success` – The transaction was started successfully.
- `kStatus_LPI2C_Busy` – Either another master is currently utilizing the bus, or another DMA transaction is already in progress.

`status_t LPI2C_MasterTransferGetCountEDMA(lpi2c_master_edma_transfer_handle_t *psHandle,
uint16_t *pu16Count)`

Returns number of bytes transferred so far.

Parameters

- `psHandle` – Pointer to the LPI2C master driver handle.
- `pu16Count` – Number of bytes transferred so far by the non-blocking transaction.

Return values

- `kStatus_Success` –
- `kStatus_NoTransferInProgress` – There is not a DMA transaction currently in progress.

`status_t LPI2C_MasterTransferAbortEDMA(lpi2c_master_edma_transfer_handle_t *psHandle)`

Terminates a non-blocking LPI2C master transmission early.

Note: It is not safe to call this function from an IRQ handler that has a higher priority than the eDMA peripheral's IRQ priority.

Parameters

- `psHandle` – Pointer to the LPI2C master driver handle.

Return values

- `kStatus_Success` – A transaction was successfully aborted.
- `kStatus_LPI2C_Idle` – There is not a DMA transaction currently in progress.

`FSL_LPI2C_EDMA_DRIVER_VERSION`

LPI2C EDMA driver version.

`typedef struct lpi2c_master_edma_transfer_handle lpi2c_master_edma_transfer_handle_t`


```
typedef void (*lpi2c_master_edma_transfer_callback_t)(lpi2c_master_edma_transfer_handle_t
*psHandle)
```

Master DMA completion callback function pointer type.

This callback is used only for the non-blocking master transfer API. Specify the callback you wish to use in the call to LPI2C_MasterCreateEDMAHandle().

Param psHandle

Handle associated with the completed transfer.

```
struct _lpi2c_master_edma_transfer_handle
```

#include <fsl_lpi2c_edma.h> Driver handle for master DMA APIs.

Note: The contents of this structure are private and subject to change. This struct address should be sizeof(edma_channel_tcd_t) aligned.

Public Members

edma_channel_tcd_t sRxTcd[1]

TCD for RX EDMA transfer.

edma_channel_tcd_t sTxTcd[3]

TCD for TX EDMA transfer.

LPI2C_Type *base

LPI2C base pointer.

bool bIsBusy

Transfer state machine current state.

uint8_t u8Nbytes

eDMA minor byte transfer count initially configured.

uint16_t u16CommandBuffer[7]

LPI2C command sequence.

lpi2c_master_transfer_t sTransfer

Copy of the current transfer info.

lpi2c_master_edma_transfer_callback_t pfCallback

Callback function pointer.

status_t completionStatus

Either kStatus_Success or an error code describing how the transfer completed.

void *pUserData

Application data passed to callback.

edma_handle_t sRxDmaHandle

Handle for receive DMA channel.

edma_handle_t sTxDmaHandle

Handle for transmit DMA channel.

2.46 LPI2C Peripheral and Driver Overview

2.47 MCM: Miscellaneous Control Module Driver

static inline *mcm_datapath_width_t* MCM_GetDataPathWidth(MCM_Type *base)

Indicates if the datapath is 32 or 64 bits wide.

Parameters

- base – MCM base address.

Returns

The device's datapath width, please refer to *mcm_datapath_width_t*.

static inline *uint16_t* MCM_GetCrossbarSwitchSlaveConfig(MCM_Type *base)

Gets crossbar switch (AXBS) slave configuration that indicates the presence/absence of bus slave connections to the device's crossbar switch.

Parameters

- base – MCM base address.

Returns

Crossbar switch (AXBS) slave configuration, each bit in the return value indicates if there is a corresponding connection to the AXBS slave input port. For example if the result is 0x1, it means a bus slave connection to AXBS input port 0 is present.

static inline *uint16_t* MCM_GetCrossbarSwitchMasterConfig(MCM_Type *base)

Gets crossbar switch (AXBS) master configuration that indicates the presence/absence of bus master connections to the device's crossbar switch.

Parameters

- base – MCM base address.

Returns

Crossbar switch (AXBS) master configuration, each bit in the return value indicates if there is a corresponding connection to the AXBS master input port. For example if the result is 0x1, it means a bus master connection to AXBS input port 0 is present.

static inline void MCM_ClearFlashControllerCache(MCM_Type *base)

Clears Flash Controller Cache, 1 cycle active.

Parameters

- base – MCM base address.

static inline void MCM_DisableFlashControllerDataCaching(MCM_Type *base, bool bDisable)

Disables/Enables flash controller data caching.

Parameters

- base – MCM peripheral base address.
- bDisable – Used to enable/disable flash controller data caching.
 - **true** Disable flash controller data caching.
 - **false** Enable flash controller data caching.

static inline void MCM_DisableFlashControllerInstructionCaching(MCM_Type *base, bool bDisable)

Disables/Enables flash controller instruction caching.

Parameters

- base – MCM peripheral base address.
- bDisable – Used to enable/disable flash controller instruction caching.
 - **true** Disable flash controller instruction caching.

- **false** Enable flash controller instruction caching.

static inline void MCM_DisableFlashControllerCache(MCM_Type *base, bool bDisable)

Disables/Enables flash controller cache.

Parameters

- base – MCM peripheral base address.
- bDisable – Used to enable/disable flash controller cache.
 - **true** Disable flash controller cache.
 - **false** Enable flash controller cache.

static inline void MCM_DisableFlashControllerDataSpeculation(MCM_Type *base, bool bDisable)

Disables/Enables flash controller data speculation.

Parameters

- base – MCM peripheral base address.
- bDisable – Used to enable/disable flash controller data speculation.
 - **true** Disable flash controller data speculation.
 - **false** Enable flash controller data speculation.

static inline void MCM_DisableFlashControllerSpeculation(MCM_Type *base, bool bDisable)

Disables/Enables flash controller speculation.

Parameters

- base – MCM peripheral base address.
- bDisable – Used to enable/disable flash controller speculation.
 - **true** Disable flash controller speculation.
 - **false** Enable flash controller speculation.

static inline void MCM_DisableDSP56800EXCoreInstructions(MCM_Type *base, bool bDisable)

Disables/Enables the instruction support only by DSP56800EX core, the instructions supported only by the DSP56800EX core are the BPSC and 32-bit multiply and MAC instructions.

Parameters

- base – MCM peripheral base address.
- bDisable – Used to enable/disable 32-bit multiply and MAC instructions.
 - **true** BFSC and 32-bit multiply and MAC instructions disabled.
 - **false** BFSC and 32-bit multiply and MAC instructions enabled.

static inline void MCM_DisableCoreReverseCarry(MCM_Type *base, bool bDisable)

Disables/Enables core reverse carry.

Parameters

- base – MCM peripheral base address.
- bDisable – Used to enable/disable reverse carry.
 - **true** Disable bit-reverse addressing mode.
 - **false** Enable bit-reverse addressing mode.

static inline void MCM_DisableDSP56800EXNewShadowRegion(MCM_Type *base, bool bDisable)

Disables/Enables the additional AGU shadow registers on the DSP56800EX core.

Parameters

- `base` – MCM peripheral base address.
- `bDisable` – Used to disable/enable the additional AGU shadow register on the DPS core.
 - **true** Only the AGU shadow registers supported by the DSP56800E core are enabled.
 - **false** The additional AGU shadow registers on the DSP56800EX core are also enabled.

`static inline void MCM_DisableCoreInstructionBuffer(MCM_Type *base, bool bDisable)`
Disables/Enables core instruction buffer.

Parameters

- `base` – MCM peripheral base address.
- `bDisable` – Used to disable/enable core longword instruction buffer.
 - **true** Disable core longword instruction buffer.
 - **false** Enable core longword instruction buffer.

`static inline void MCM_DisableFlashMemoryControllerStall(MCM_Type *base, bool bDisable)`
Disables/Enables the flash memory controller's ability to allow flash memory access to initiate when a flash memory command is executing.

Parameters

- `base` – MCM peripheral base address.
- `bDisable` – Used to disable/enable stall logic.
 - **true** Stall logic is disabled. While a flash memory command is executing, an attempted flash memory access causes a bus error.
 - **false** Stall logic is disabled. While a flash memory command is executing, a flash memory access can occur without causing a bus error. The flash memory command completes execution, and then the flash memory access occurs.

`static inline void MCM_SetAxbsDMAControllerPriority(MCM_Type *base, mcm_axbs_dma_core_priority_t ePriority)`

Sets the priority of the DMA controller in the AXBS crossbar switch arbitration scheme.

Parameters

- `base` – MCM base address.
- `ePriority` – The selected DMA controller priority in Crossbar switch arbitration scheme, please refer to `mcm_axbs_dma_core_priority_t`.

`static inline uint32_t MCM_GetCoreFaultAddr(MCM_Type *base)`
Gets the address of the last core access terminated with an error response.

Parameters

- `base` – MCM base address.

Returns

address of the last core access terminated with an error response.

`void MCM_GetCoreFaultAttribute(MCM_Type *base, mcm_core_fault_attribute_t *psAttribute)`
Gets the processor's attributes of the last faulted core access to the system bus.

Parameters

- `base` – MCM peripheral base address.

- `psAttribute` – The pointer of structure `mcm_core_fault_attribute_t`.

static inline `mcm_last_fault_access_location_t` MCM_GetCoreFaultLocation(MCM_Type *base)

Gets the location of the last captured fault.

Parameters

- `base` – MCM peripheral base address.

Returns

The location of the last captured fault, please refer to `mcm_last_fault_access_location_t`.

static inline `uint32_t` MCM_GetCoreFaultData(MCM_Type *base)

Gets the data associated with the last faulted processor write data access from the device's internal bus.

Parameters

- `base` – MCM base address.

Returns

The data associated with the last faulted processor write data access.

static inline void MCM_EnableCoreFaultInterrupt(MCM_Type *base, bool bEnable)

Enables/Disables core fault error interrupt.

Parameters

- `base` – MCM peripheral base address.
- `bEnable` – Used to enable/disable the core fault error interrupt.
 - **true** Enables core fault error interrupt, so an error interrupt will be generated to the interrupt controller on a faulted system bus cycle.
 - **false** Disables core fault error interrupt, so an error interrupt will not be generated to the interrupt controller on a faulted system bus cycle.

static inline `uint8_t` MCM_GetCoreFaultStatusFlags(MCM_Type *base)

Gets the core fault error status flags, including core fault error interrupt flag and core fault error data lost flag.

Parameters

- `base` – MCM peripheral base address.

Returns

The current status flags, should be the OR'ed value of `_mcm_status_flags`.

static inline void MCM_ClearCoreFaultStatusFlags(MCM_Type *base, `uint8_t` u8StatusFlags)

Clears the core fault error status flags, including core fault error interrupt flag and core fault error data lost flag.

Parameters

- `base` – MCM peripheral base address.
- `u8StatusFlags` – The status flags to be cleared, should be the OR'ed value of `_mcm_status_flags`.

static inline void MCM_EnableResourceProtection(MCM_Type *base, bool bEnable)

Enables/Disables resource protection.

Parameters

- `base` – MCM peripheral base address.
- `bEnable` – Used to enable/disable memory resource protection.

- **true** Enable memory resource protection.
- **false** Disable memory resource protection.

static inline void MCM_LockResourceProtectionRegisters(MCM_Type *base)

Locks the value of the resource protection related registers, after locked the registers' value can not be changed until a system reset.

Parameters

- base – MCM peripheral base address.

status_t MCM_SetResourceProtectionConfig(MCM_Type *base, const
mcm_resource_protection_config_t *psConfig)

Sets the configuration of resource protection, including flash base address, ram base address, etc.

Parameters

- base – MCM peripheral base address.
- psConfig – The pointer of structure mcm_resource_protection_config_t.

Return values

- kStatus_Success – Succeed to setting resource protection related options.
- kStatus_Fail – Fail to set resource protection related options.

static inline uint32_t MCM_GetResourceProtectionIllegalFaultPC(MCM_Type *base)

Gets the 21-bit illegal faulting PC that only for a resource protection fault.

Parameters

- base – MCM peripheral base address.

Returns

The resource protection illegal faulting PC.

static inline bool MCM_IsResourceProtectionIllegalFaultValid(MCM_Type *base)

Indicates whether an resource protection illegal PC fault has occurred.

Parameters

- base – MCM peripheral base address.

Return values

- true – The resource protection illegal PC fault has occurred.
- false – The resource protection illegal PC fault has not occurred.

static inline void MCM_ClearResourceProtectionIllegalFaultValid(MCM_Type *base)

Clears the resource protection illegal fault bit.

Parameters

- base – MCM peripheral base address.

static inline uint32_t MCM_GetResourceProtectionMisalignedFaultPC(MCM_Type *base)

Gets the 21-bit misaligned faulting PC that only for a resource protection fault.

Parameters

- base – MCM peripheral base address.

Returns

The resource protection misaligned faulting PC.

static inline bool MCM_IsResourceProtectionMisalignedFaultValid(MCM_Type *base)

Indicates whether an resource protection misaligned PC fault has occurred.

Parameters

- base – MCM peripheral base address.

Return values

- true – The resource protection misaligned PC fault has occurred.
- false – The resource protection misaligned PC fault has not occurred.

static inline void MCM_ClearResourceProtectionMisalignedFaultValid(MCM_Type *base)

Clears the resource protection misaligned fault bit.

Parameters

- base – MCM peripheral base address.

FSL_MCM_DRIVER_VERSION

MCM driver version.

enum __mcm_status_flags

The enumeration of status flags, including core fault error interrupt flag and core fault error data lost flag.

Values:

enumerator kMCM_CoreFaultErrorInterruptFlag

A bus error has occurred.

enumerator kMCM_CoreFaultErrorDataLostFlag

A bus error has occurred before the previous error condition was cleared.

enum __mcm_datapath_width

The enumeration of datapath width, including 32 bits and 64 bits.

Values:

enumerator kMCM_Datapath32b

Datapath width is 32 bits.

enumerator kMCM_Datapath64b

Datapath width is 64 bits.

enum __mcm_axbs_dma_core_priority

The enumeration of DMA controller priority in the Crossbar switch arbitration scheme.

Values:

enumerator kMCM_AxbsPriorityCoreHigherThanDMA

Fixed-priority arbitration is selected: DSC core has a higher priority than the DMA Controller's priority.

enumerator kMCM_AxbsPriorityCoreDMARoundRobin

Round-robin priority arbitration is selected: DMA Controller and DSC core have equal priority.

enum __mcm_last_fault_access_dir

The enumeration of last faulted core access direction.

Values:

enumerator kMCM_CoreRead

Core read access.

enumerator kMCM_CoreWrite

Core write access.

enum _mcm_last_fault_access_size

The enumeration of last faulted core access size.

Values:

enumerator kMCM_Access8b

Last faulted core access size is 8-bit.

enumerator kMCM_Access16b

Last faulted core access size is 16-bit.

enumerator kMCM_Access32b

Last faulted core access size is 32-bit.

enum _mcm_last_fault_access_type

The enumeration of last faulted core access type.

Values:

enumerator kMCM_AccessInstruction

Last faulted core access is instruction.

enumerator kMCM_AccessData

Last faulted core access is data.

enum _mcm_last_fault_access_location

The enumeration of last captured fault Location.

Values:

enumerator kMCM_ErrOnInstructionBus

Error occurred on M0 (instruction bus).

enumerator kMCM_ErrOnOperandABus

Error occurred on M1 (operand A bus).

enumerator kMCM_ErrOnOperandBBus

Error occurred on M2 (operand B bus).

typedef enum _mcm_datapath_width mcm_datapath_width_t

The enumeration of datapath width, including 32 bits and 64 bits.

typedef enum _mcm_axbs_dma_core_priority mcm_axbs_dma_core_priority_t

The enumeration of DMA controller priority in the Crossbar switch arbitration scheme.

typedef enum _mcm_last_fault_access_dir mcm_last_fault_access_dir_t

The enumeration of last faulted core access direction.

typedef enum _mcm_last_fault_access_size mcm_last_fault_access_size_t

The enumeration of last faulted core access size.

typedef enum _mcm_last_fault_access_type mcm_last_fault_access_type_t

The enumeration of last faulted core access type.

typedef enum _mcm_last_fault_access_location mcm_last_fault_access_location_t

The enumeration of last captured fault Location.

typedef struct _mcm_core_fault_attribute mcm_core_fault_attribute_t

The structure of core fault attributes, contains access type, access size, access direction, etc.

`typedef struct _mcm_resource_protection_config mcm_resource_protection_config_t`

The structure of the resource protection config, the set value can be used only when the resource protection is enabled, and this value can be changed only when the resource protection is disabled.

`struct _mcm_core_fault_attribute`

#include <fsl_mcm.h> The structure of core fault attributes, contains access type, access size, access direction, etc.

Public Members

`mcm_last_fault_access_type_t` eType

Indicates the last faulted core access type, please refer to `mcm_last_fault_access_type_t`.

`uint8_t` bitReserved1

Reserved 1 bit.

`bool` bBufferable

Indicates if last faulted core access was bufferable.

- **true** Last faulted core access is bufferable.
- **false** Last faulted core access is non-bufferable.

`uint8_t` bitReserved2

Reserved 1 bit.

`mcm_last_fault_access_size_t` eSize

Indicates last faulted core access size.

`mcm_last_fault_access_dir_t` eDirection

Indicates the last faulted core access direction.

`struct _mcm_resource_protection_config`

#include <fsl_mcm.h> The structure of the resource protection config, the set value can be used only when the resource protection is enabled, and this value can be changed only when the resource protection is disabled.

Public Members

`bool` bEnableResourceProtection

Enable/Disable resource protection.

- **true** Enable Resource protection.
- **false** Disable Resource protection.

`uint8_t` u8FlashBaseAddress

Flash base address for user region, supports 4 KB granularity.

`uint8_t` u8RamBaseAddress

Program RAM base address for user region, support 256 byte granularity.

`uint32_t` u32BootRomBaseAddress

Boot ROM base address for user region

`uint32_t` u32ResourceProtectionOtherSP

Resource protection other stack pointer.

2.48 The Driver Change Log

2.49 MCM Peripheral and Driver Overview

2.50 OPAMP: Operational Amplifier Driver

`void OPAMP_Init(OPAMP_Type *base, const opamp_config_t *psConfig)`

Initializes the OPAMP module.

This function does initialization when using OPAMP module. The operations are:

- Enable the clock for OPAMP.
- Enable the write protection.
- Enable the load completion interrupt.
- Set configuration register for OPAMP.
- Set Positive channel and Negative channel.
- Set the power mode.
- Set the gain value.
- Set the load mode.
- Enable the OPAMP.

Parameters

- base – OPAMP peripheral base address.
- psConfig – Pointer to configuration structure. See `opamp_config_t`.

`void OPAMP_GetDefaultConfig(opamp_config_t *psConfig)`

Gets default configuration for OPAMP.

The default value:

```
psConfig->bEnableLoadCompletionInterrupt = false;
psConfig->bEnableWriteProtection = false;
psConfig->eLoadMode = kOPAMP_LoadModeDelayLoad;
psConfig->ePowerMode = kOPAMP_PowerModeLowPower;
psConfig->eConfigRegSel = kOPAMP_ConfigRegSelCFG0;

psConfig->sConfigSet0.eWorkMode = kOPAMP_WorkModeBufferMode;
psConfig->sConfigSet0.eNegChannel = kOPAMP_NegChannel0;
psConfig->sConfigSet0.ePosChannel = kOPAMP_PosChannel0;

psConfig->sConfigSet1.eWorkMode = kOPAMP_WorkModeBufferMode;
psConfig->sConfigSet1.eNegChannel = kOPAMP_NegChannel0;
psConfig->sConfigSet1.ePosChannel = kOPAMP_PosChannel0;

psConfig->sConfigSet2.eWorkMode = kOPAMP_WorkModeBufferMode;
psConfig->sConfigSet2.eNegChannel = kOPAMP_NegChannel0;
psConfig->sConfigSet2.ePosChannel = kOPAMP_PosChannel0;

psConfig->sConfigSet3.eWorkMode = kOPAMP_WorkModeBufferMode;
psConfig->sConfigSet3.eNegChannel = kOPAMP_NegChannel0;
psConfig->sConfigSet3.ePosChannel = kOPAMP_PosChannel0;
```

Parameters

- psConfig – Pointer to configuration structure.

void OPAMP_Deinit(OPAMP_Type *base)

De-initializes the OPAMP module.

This function does de-initialization when using OPAMP module. The operations are:

- Disable the OPAMP.
- Disable the clock for OPAMP.

Parameters

- base – OPAMP peripheral base address.

void OPAMP_SetOneConfigSet(OPAMP_Type *base, *opamp_config_set_index_t* eIndex, const *opamp_config_set_t* *psConfigSet)

Sets configuration set.

This function only sets the configuration set, application should call OPAMP_EnableConfigLoad to enable the load after setting all desired configuration sets.

Parameters

- base – OPAMP peripheral base address.
- eIndex – Index of configuration set, please see *opamp_config_set_index_t* for details.
- psConfigSet – Pointer to the configure structure, please see *opamp_config_set_t* for details.

void OPAMP_SetConfigSelection(OPAMP_Type *base, *opamp_config_reg_sel_t* eConfigRegSel)

Changes configuration register selection.

This function can configure the working registers of the software and external signal. When the configuration set is updated using OPAMP_SetOneConfigSet and the external signal is not used, the software working register should also select the corresponding software working register according to the update of the configuration set.

Parameters

- base – OPAMP peripheral base address.
- eConfigRegSel – configuration register selection, please see *opamp_config_reg_sel_t* for details.

static inline void OPAMP_EnableOPAMP(OPAMP_Type *base, bool bEnable)

Enables the OPAMP.

Note: Please use function OPAMP_EnableOPAMP to re-enable the OPAMP if it is disabled. Then load it with function OPAMP_EnableConfigLoad.

Parameters

- base – OPAMP peripheral base address.
- bEnable – Enables/disables the module.

static inline void OPAMP_EnableConfigLoad(OPAMP_Type *base)

Enables the new configuration load.

After configuration load enabled, the new set configuration will be loaded at the time determined by load mode. Application could monitor the load completion by

OPAMP_CheckLoadCompletionFlag or the interrupt. When the load finishes, the configuration load shall be disabled automatically.

Parameters

- base – OPAMP peripheral base address.

```
static inline void OPAMP__DisableWriteProtection(OPAMP_Type *base)
```

Disables write protection.

Write 10b to this field to disable the write protection.

Parameters

- base – OPAMP peripheral base address.

```
static inline void OPAMP__SetPowerMode(OPAMP_Type *base, opamp_power_mode_t  
                                     ePowerMode)
```

Changes the power mode.

Parameters

- base – OPAMP peripheral base address.
- ePowerMode – Power mode, please see opamp_power_mode_t for details.

```
static inline void OPAMP__SetLoadMode(OPAMP_Type *base, opamp_load_mode_t eLoadMode)
```

Changes the load mode.

Parameters

- base – OPAMP peripheral base address.
- eLoadMode – load mode, please see opamp_load_mode_t for details.

```
static inline void OPAMP__EnableLoadCompletionInterrupt(OPAMP_Type *base)
```

Enables load completion interrupt.

Parameters

- base – OPAMP peripheral base address.

```
static inline void OPAMP__DisableLoadCompletionInterrupt(OPAMP_Type *base)
```

Disables load completion interrupt.

Parameters

- base – OPAMP peripheral base address.

```
static inline bool OPAMP__CheckLoadCompletionFlag(OPAMP_Type *base)
```

Checks the configuration load completion flag status.

Parameters

- base – OPAMP peripheral base address.

Returns

Return true if the flag is set, otherwise return false.

```
static inline void OPAMP__ClearLoadCompletionFlag(OPAMP_Type *base)
```

Clears the configuration load completion flag.

Parameters

- base – OPAMP peripheral base address.

```
FSL_OPAMP_DRIVER_VERSION
```

OPAMP driver version.

enum `_opamp_config_reg_sel`

The enumeration lists all options for software controlled opamps and other external signal controlled opamps.

Values:

enumerator `kOPAMP_ConfigRegSelCFG0`

Software work register select CFG0 (internal signal).

enumerator `kOPAMP_ConfigRegSelCFG1`

Software work register select CFG1 (internal signal).

enumerator `kOPAMP_ConfigRegSelCFG2`

Software work register select CFG2 (internal signal).

enumerator `kOPAMP_ConfigRegSelCFG3`

Software work register select CFG3 (internal signal).

enumerator `kOPAMP_ConfigRegSelA1OrA0`

External signal `cfg_sel_a1` or `cfg_sel_a0` selects configuration register.

enumerator `kOPAMP_ConfigRegSelA1OrB0`

External signal `cfg_sel_a1` or `cfg_sel_b0` selects configuration register.

enumerator `kOPAMP_ConfigRegSelA1OrC0`

External signal `cfg_sel_a1` or `cfg_sel_c0` selects configuration register.

enumerator `kOPAMP_configRegSelB1OrA0`

External signal `cfg_sel_b1` or `cfg_sel_a0` selects configuration register.

enumerator `kOPAMP_configRegSelB1OrB0`

External signal `cfg_sel_b1` or `cfg_sel_b0` selects configuration register.

enumerator `kOPAMP_configRegSelB1OrC0`

External signal `cfg_sel_b1` or `cfg_sel_c0` selects configuration register.

enumerator `kOPAMP_ConfigRegSelC1OrA0`

External signal `cfg_sel_c1` or `cfg_sel_a0` selects configuration register.

enumerator `kOPAMP_ConfigRegSelC1OrB0`

External signal `cfg_sel_c1` or `cfg_sel_b0` selects configuration register.

enumerator `kOPAMP_ConfigRegSelC1OrC0`

External signal `cfg_sel_c1` or `cfg_sel_c0` selects configuration register.

enum `_opamp_load_mode`

The enumeration lists the opamp buffer's loading modes, delay loading and immediately loading modes.

Values:

enumerator `kOPAMP_LoadModeDelayLoad`

The buffer registers are loaded when the next configuration is complete, if CTRL[LDOK] is set.

enumerator `kOPAMP_LoadModeImmediatelyLoad`

The buffer register shall be loaded immediately after CTRL[LDOK] is set.

enum `_opamp_power_mode`

The enumeration lists the power modes of the opamp, including low power and high power modes.

Values:

enumerator kOPAMP_PowerModeLowPower

Lower current consumption with slower slew rate and narrower unity gain bandwidth performance.

enumerator kOPAMP_PowerModeHighSpeed

Higher current consumption with higher slew rate and wider unity gain bandwidth performance.

enum _opamp_positive_channel

The enumeration of positive input channel selection.

Values:

enumerator kOPAMP_PosChannel0

Positive channel 0.

enumerator kOPAMP_PosChannel1

Positive channel 1.

enumerator kOPAMP_PosChannel2

Positive channel 2.

enumerator kOPAMP_PosChannel3

Positive channel 3.

enum _opamp_negative_channel

The enumeration of negative input channel selection.

Values:

enumerator kOPAMP_NegChannel0

Negative channel 0.

enumerator kOPAMP_NegChannel1

Negative channel 1.

enumerator kOPAMP_NegChannel2

Negative channel 2.

enumerator kOPAMP_NegChannel3

Negative channel 3.

enum _opamp_config_set_index

The enumeration of configuration set index.

Values:

enumerator kOPAMP_ConfigSet0

Configuration set 0.

enumerator kOPAMP_ConfigSet1

Configuration set 1.

enumerator kOPAMP_ConfigSet2

Configuration set 2.

enumerator kOPAMP_ConfigSet3

Configuration set 3.

enum _opamp_work_mode

The enumeration lists the operating modes of the opamp, including buffer mode, internal gain and external gain mode.

Values:

enumerator `kOPAMP__WorkModeBufferMode`

Buffer mode.

enumerator `kOPAMP__WorkModeInternalGain2X`

Internal gain 2X mode.

enumerator `kOPAMP__WorkModeInternalGain4X`

Internal gain 4X mode.

enumerator `kOPAMP__WorkModeInternalGain8X`

Internal gain 8X mode.

enumerator `kOPAMP__WorkModeInternalGain16X`

Internal gain 16X mode.

enumerator `kOPAMP__WorkModeExternalGain`

External gain mode.

typedef enum `_opamp_config_reg_sel` `opamp_config_reg_sel_t`

The enumeration lists all options for software controlled opamps and other external signal controlled opamps.

typedef enum `_opamp_load_mode` `opamp_load_mode_t`

The enumeration lists the opamp buffer's loading modes, delay loading and immediately loading modes.

typedef enum `_opamp_power_mode` `opamp_power_mode_t`

The enumeration lists the power modes of the opamp, including low power and high power modes.

typedef enum `_opamp_positive_channel` `opamp_positive_channel_t`

The enumeration of positive input channel selection.

typedef enum `_opamp_negative_channel` `opamp_negative_channel_t`

The enumeration of negative input channel selection.

typedef enum `_opamp_config_set_index` `opamp_config_set_index_t`

The enumeration of configuration set index.

typedef enum `_opamp_work_mode` `opamp_work_mode_t`

The enumeration lists the operating modes of the opamp, including buffer mode, internal gain and external gain mode.

typedef struct `_opamp_config_set` `opamp_config_set_t`

Configuration set information.

typedef struct `_opamp_config` `opamp_config_t`

Configuration structure.

struct `_opamp_config_set`

`#include <fsl_opamp.h>` Configuration set information.

Public Members

`opamp_work_mode_t` `eWorkMode`

Opamp work mode.

`opamp_negative_channel_t` `eNegChannel`

Negative channel selection.

opamp_positive_channel_t ePosChannel

Positive channel selection.

struct __opamp_config

#include <fsl_opamp.h> Configuration structure.

Public Members

bool bEnableLoadCompletionInterrupt

Enable load completion interrupt

bool bEnableWriteProtection

Enable write protection.

opamp_load_mode_t eLoadMode

Configuration load mode.

opamp_power_mode_t ePowerMode

Configuration Power mode.

opamp_config_reg_sel_t eConfigRegSel

Selects configuration register.

opamp_config_set_t sConfigSet0

Configuration register set 0.

opamp_config_set_t sConfigSet1

Configuration register set 1.

opamp_config_set_t sConfigSet2

Configuration register set 2.

opamp_config_set_t sConfigSet3

Configuration register set 3.

2.51 The Driver Change Log

2.52 OPAMP Peripheral and Driver Overview

2.53 PIT: Periodic Interrupt Timer (PIT) Driver

void PIT_Init(PIT_Type *base, const *pit_config_t* *psConfig)

Ungates the PIT clock, configures the PIT features. The configurations are:

- Clock source selection for PIT module
- Prescaler configuration to the input clock source
- PIT period interval
- PIT slave mode enable/disable
- Interrupt enable/disable
- PIT timer enable/disable
- Preset Polarity positive edge/negative edge

Note: This API should be called at the beginning of the application using the PIT driver and call PIT_StartTimer() API to start PIT timer.

Parameters

- base – PIT peripheral base address
- psConfig – Pointer to the user's PIT config structure

void PIT_Deinit(PIT_Type *base)

Gates the PIT clock and disables the PIT module.

Parameters

- base – PIT peripheral base address

void PIT_GetDefaultConfig(*pit_config_t* *psConfig)

Fill in the PIT config structure with the default settings.

This function initializes the PIT configuration structure to default values.

```
psConfig->eClockSource = kPIT_CountClockSource0;
psConfig->bEnableTimer = false;
psConfig->bEnableSlaveMode = false;
psConfig->ePrescaler = kPIT_PrescalerDivBy1;
psConfig->bEnableInterrupt = false;
psConfig->u32PeriodCount = 0xFFFFFFFFU;
psConfig->bEnableNegativeEdge = false;
psConfig->sPresetFilter.u16FilterSamplePeriod = 0x0U;
psConfig->sPresetFilter.u16FilterSampleCount = 0x0U;
psConfig->sPresetFilter.bFilterClock = true;
psConfig->sPresetFilter.eFilterPrescalerPeripheral = kPIT_PrescalerDivBy1;
psConfig->sSyncSource.u8StretchCount = 0x0U;
psConfig->sSyncSource.eSyncOutSel = kPIT_Syncout_Default;
```

Parameters

- psConfig – Pointer to user's PIT config structure.

static inline void PIT_EnableSlaveMode(PIT_Type *base, bool bEnable)

Enable/Disable PIT slave mode.

Parameters

- base – PIT peripheral base address
- bEnable – enable/disable slave mode

static inline void PIT_SetTimerPrescaler(PIT_Type *base, *pit_prescaler_value_t* ePrescaler)

Sets the PIT clock prescaler.

Parameters

- base – PIT peripheral base address
- ePrescaler – Timer prescaler value

static inline void PIT_SetTimerPeriod(PIT_Type *base, uint32_t u32PeriodCount)

Sets the timer period in units of count.

Timers begin counting from 0 until it reaches the value set by this function, then it generates an interrupt and counter resumes counting from 0 again.

Note: Users can call the utility macros provided in fsl_common.h to convert to ticks.

Parameters

- base – PIT peripheral base address
- u32PeriodCount – Timer period in units of ticks, use macro definition MSEC_TO_COUNT to convert value in ms to count of ticks, the PIT clock rate is source clock divide prescaler.

```
static inline uint32_t PIT_GetCurrentTimerCount(PIT_Type *base)
```

Reads the current timer counting value.

This function returns the real-time timer counting value, in a range from 0 to a timer period.

Note: Users can call the utility macros provided in fsl_common.h to convert ticks to usec or msec.

Parameters

- base – PIT peripheral base address

Returns

Current timer counting value in ticks, use macro definition COUNT_TO_MSEC to convert value in ticks to count of millisecond, the PIT clock rate is source clock divide prescaler.

```
static inline void PIT_StartTimer(PIT_Type *base)
```

Starts the timer counting.

After calling this function, timers load period value, count down to 0 and then load the respective start value again. Each time a timer reaches 0, it generates a trigger pulse and sets the timeout interrupt flag.

Parameters

- base – PIT peripheral base address

```
static inline void PIT_StopTimer(PIT_Type *base)
```

Stops the timer counting.

This function stops timer counting, and the counter remains at or returns to a 0 value.

Parameters

- base – PIT peripheral base address

```
static inline void PIT_EnableInterrupt(PIT_Type *base)
```

Enables the PIT interrupts.

Parameters

- base – PIT peripheral base address

```
static inline void PIT_DisableInterrupt(PIT_Type *base)
```

Disables the selected PIT interrupts.

Parameters

- base – PIT peripheral base address

```
static inline uint16_t PIT_GetStatusFlags(PIT_Type *base)
```

Gets the PIT status flags.

Parameters

- base – PIT peripheral base address

Returns

The status flags. This is the logical OR of members of the enumeration `_pit_status_flags`

static inline void PIT_ClearStatusFlags(PIT_Type *base)

Clears the PIT status flags.

Parameters

- base – PIT peripheral base address

static inline void PIT_SetPresetFiltConfig(PIT_Type *base, const *pit_config_filt_t* psConfig)

Set FILT configurations.

Parameters

- base – PIT peripheral base address
- psConfig – Pointer to user's PIT FILT config structure

static inline void PIT_SetSyncOutConfig(PIT_Type *base, const *pit_config_ctrl2_t* psConfig)

Set Sync configurations.

Parameters

- base – PIT peripheral base address
- psConfig – Pointer to user's PIT SYNC config structure

FSL_PIT_DRIVER_VERSION

PIT driver version.

enum `_pit_prescaler_value`

PIT clock prescaler values.

Values:

enumerator `kPIT_PrescalerDivBy1`

Clock divided by 1

enumerator `kPIT_PrescalerDivBy2`

Clock divided by 2

enumerator `kPIT_PrescalerDivBy4`

Clock divided by 4

enumerator `kPIT_PrescalerDivBy8`

Clock divided by 8

enumerator `kPIT_PrescalerDivBy16`

Clock divided by 16

enumerator `kPIT_PrescalerDivBy32`

Clock divided by 32

enumerator `kPIT_PrescalerDivBy64`

Clock divided by 64

enumerator `kPIT_PrescalerDivBy128`

Clock divided by 128

enumerator `kPIT_PrescalerDivBy256`

Clock divided by 256

enumerator `kPIT_PrescalerDivBy512`

Clock divided by 512

enumerator kPIT_PrescalerDivBy1024

Clock divided by 1024

enumerator kPIT_PrescalerDivBy2048

Clock divided by 2048

enumerator kPIT_PrescalerDivBy4096

Clock divided by 4096

enumerator kPIT_PrescalerDivBy8192

Clock divided by 8192

enumerator kPIT_PrescalerDivBy16384

Clock divided by 16384

enumerator kPIT_PrescalerDivBy32768

Clock divided by 32768

enum __pit_status_flags

List of PIT status flags.

Values:

enumerator kPIT_Timer_RollOverFlag

Timer roll over flag

enum __pit_syncout_mode

List of SYNC_OUT output mode.

Values:

enumerator kPIT_Syncout_Default

SYNC_OUT takes affect when PIT counter equals to the MODULO value (default)

enumerator kPIT_Syncout_Toggle

SYNC_OUT is in toggle mode

typedef enum __pit_prescaler_value pit_prescaler_value_t

PIT clock prescaler values.

typedef enum __pit_syncout_mode pit_syncout_mode_t

List of SYNC_OUT output mode.

typedef struct __pit_config_filt pit_config_filt_t

PIT FILT configuration structure.

This structure holds the configuration settings for the PIT FILT register. To initialize this structure to reasonable defaults, call the PIT_GetDefaultConfig() function and pass a pointer to your config structure instance.

The configuration structure can be made constant so it resides in flash.

typedef struct __pit_config_ctrl2 pit_config_ctrl2_t

PIT CTRL2 configuration structure.

This structure holds the configuration settings for the PIT CTRL2 register. To initialize this structure to reasonable defaults, call the PIT_GetDefaultConfig() function and pass a pointer to your config structure instance.

The configuration structure can be made constant so it resides in flash.

`typedef struct _pit_config pit_config_t`

PIT configuration structure.

This structure holds the configuration settings for the PIT peripheral. To initialize this structure to reasonable defaults, call the `PIT_GetDefaultConfig()` function and pass a pointer to your config structure instance.

The configuration structure can be made constant so it resides in flash.

`struct __pit_config_filt`

`#include <fsl_pit.h>` PIT FILT configuration structure.

This structure holds the configuration settings for the PIT FILT register. To initialize this structure to reasonable defaults, call the `PIT_GetDefaultConfig()` function and pass a pointer to your config structure instance.

The configuration structure can be made constant so it resides in flash.

Public Members

`bool bFilterClock`

Filter Clock Source selection.

`pit_prescaler_value_t eFilterPrescalerPeripheral`

Sets the peripheral clock prescaler.

`uint8_t u16FilterSampleCount`

Input Filter Sample Count.

`uint8_t u16FilterSamplePeriod`

Input Filter Sample Period.

`struct __pit_config_ctrl2`

`#include <fsl_pit.h>` PIT CTRL2 configuration structure.

This structure holds the configuration settings for the PIT CTRL2 register. To initialize this structure to reasonable defaults, call the `PIT_GetDefaultConfig()` function and pass a pointer to your config structure instance.

The configuration structure can be made constant so it resides in flash.

Public Members

`uint8_t u8StretchCount`

The cycle number to be stretched for SYNC_OUT signal.

`pit_syncout_mode_t eSyncOutSel`

Select the output mode of SYNC_OUT.

`struct __pit_config`

`#include <fsl_pit.h>` PIT configuration structure.

This structure holds the configuration settings for the PIT peripheral. To initialize this structure to reasonable defaults, call the `PIT_GetDefaultConfig()` function and pass a pointer to your config structure instance.

The configuration structure can be made constant so it resides in flash.

Public Members

pit_prescaler_value_t ePrescaler

Clock prescaler value

bool bEnableInterrupt

Enable PIT Roll-Over Interrupt

bool bEnableSlaveMode

Enable the PIT module in slave mode, in which mode the timer will be triggered by master PIT enable.

bool bEnableTimer

PIT timer enable flag, which is false by default

pit_count_clock_source_t eClockSource

Specify the PIT count clock source

uint32_t u32PeriodCount

Timer period in clock cycles, Use macro definition MSEC_TO_COUNT to convert value in ms to count of ticks, the COP clock rate is source clock divide prescaler.

bool bEnableNegativeEdge

choose the polarity of Preset input.

pit_config_filt_t sPresetFilter

Specify the PIT preset filter source

pit_config_ctrl2_t sSyncSource

Specify the PIT Sync source

2.54 The Driver Change Log

2.55 PIT Peripheral and Driver Overview

2.56 PMC: Power Management Controller Driver

static inline void PMC_SetBandgapTrim(PMC_Type *base, uint8_t u8TrimValue)

Sets the trim value of the bandgap reference in the regulator.

Parameters

- base – PMC peripheral base address.
- u8TrimValue – The bandgap's trim value, ranges from 0 to 15.

static inline void PMC_EnableVoltageReferenceBuffer(PMC_Type *base, bool bEnable)

Enables/Disables a buffer that drivers the 1.2V bandgap reference to the ADC.

If the users want to calibrate the ADC using the 1.2V reference voltage, then the voltage reference buffer should be enabled. When ADC calibration is not being performed, the voltage reference buffer should be disabled to save power.

Parameters

- base – PMC peripheral base address.
- bEnable – Used to control the behaviour of voltage reference buffer.
 - **true** Enable voltage reference buffer.

- **false** Disable voltage reference buffer.

static inline void PMC_EnableInterrupts(PMC_Type *base, uint16_t u16Interrupts)

Enables the interrupts, including 2.2V high voltage interrupt, 2.7V/2.65V high voltage interrupt, 2.2V low voltage interrupt, 2.7V/2.65V low voltage interrupt.

Parameters

- base – PMC peripheral base address.
- u16Interrupts – The interrupts to be enabled, should be the OR'ed value of _pmc_interrupt_enable.

static inline void PMC_DisableInterrupts(PMC_Type *base, uint16_t u16Interrupts)

Disables the interrupts, including 2.2V high voltage interrupt, 2.7V/2.65V high voltage interrupt, 2.2V low voltage interrupt, 2.7V/2.65V low voltage interrupt.

Parameters

- base – PMC peripheral base address.
- u16Interrupts – The interrupts to be disabled, should be the OR'ed value of _pmc_interrupt_enable.

static inline uint16_t PMC_GetStatusFlags(PMC_Type *base)

Gets the status flags of PMC module, such as low voltage interrupt flag, small regulator 2.7 active flag, etc.

Parameters

- base – PMC peripheral base address.

Returns

The status flags of PMC module, should be the OR'ed value of _pmc_status_flags.

static inline void PMC_ClearStatusFlags(PMC_Type *base, uint16_t u16StatusFlags)

Clears the status flags of PMC module, only low voltage interrupt flag, sticky 2.7V/2.65V low voltage flag, and sticky 2.2V low voltage flag can be cleared.

Parameters

- base – PMC peripheral base address.
- u16StatusFlags – The status flags to be cleared, should be the OR'ed value of kPMC_LowVoltageInterruptFlag, and kPMC_Sticky2P7VLowVoltageFlag/kPMC_Sticky2P65VLowVoltageFlag, and kPMC_Sticky2P2VLowVoltageFlag,

static inline void PMC_SetVrefTrim(PMC_Type *base, uint16_t u16TrimValue)

Sets the trim value of the Vref reference in the regulator.

Parameters

- base – PMC peripheral base address.
- u16TrimValue – The Vref's trim value, ranges from 0 to 31.

static inline void PMC_SetVcapTrim(PMC_Type *base, uint16_t u16TrimValue)

Sets the trim value of the Vcap reference in the regulator.

Parameters

- base – PMC peripheral base address.
- u16TrimValue – The Vcap's trim value, ranges from 0 to 15.

FSL_PMC_DRIVER_VERSION

PMC driver version.

enum __pmc_interrupt_enable

The enumeration of PMC voltage detection interrupts.

Values:

enumerator kPMC_2P2VLowVoltageInterruptEnable

If the input supply is currently dropped below the 2.2V level, generate the low voltage interrupt.

enumerator kPMC_2P2VHighVoltageInterruptEnable

If the input supply is currently raised above the 2.2V level, generate the low voltage interrupt.

enumerator kPMC_AllInterruptsEnable

enum __pmc_status_flags

The enumeration of PMC status flags.

Values:

enumerator kPMC_SmallRegulator2P7VActiveFlag

The small regulator 2.7V supply is ready to be used.

enumerator kPMC_LowVoltageInterruptFlag

The low voltage interrupt flag, used to indicate whether the low voltage interrupt is asserted.

enumerator kPMC_Sticky2P2VLowVoltageFlag

Input supply has dropped below the 2.2V threshold. This sticky flag indicates that the input supply dropped below the 2.2V level at some point.

enumerator kPMC_2P2VLowVoltageFlag

Input supply is below the 2.2V threshold.

enumerator kPMC_AllStatusFlags

2.57 The Driver Change Log

2.58 PMC Peripheral and Driver Overview

2.59 eFlexPWM: Enhanced Flexible Pulse Width Modulator Driver

void PWM_Init(PWM_Type *base, const *pwm_config_t* *psConfig)

Initialization PWM module with provided structure *pwm_config_t*.

This function can initial one or more submodules of the PWM module.

This examples shows how only initial submodule 0 without fault protection channel.

```
pwm_config_t sPwmConfig = {0};
pwm_sm_config_t sPwmSm0Config;
sPwmConfig.psPwmSubmoduleConfig[0] = &sPwmSm0Config;
PWM_GetSmDefaultConfig(&sPwmSm0Config);
PWM_Init(PWM, sPwmConfig);
```

Note: This API should be called at the beginning of the application using the PWM driver.

Parameters

- base – PWM peripheral base address.
- psConfig – Pointer to PWM module configure structure. See `pwm_config_t`.

void PWM_Deinit(PWM_Type *base)

De-initialization a PWM module.

Parameters

- base – PWM peripheral base address

void PWM_GetSMDefaultConfig(*pwm_sm_config_t* *psConfig)

Gets an default PWM submodule's configuration.

This function fills in the initialization structure member, which can make submodule generate 50% duty cycle center aligned PWM_A/B output.

The default effective values are:

```
psConfig->enableDebugMode = false;
psConfig->enableWaitMode = false;
psConfig->enableRun = false;
psConfig->sCounterConfig.eCountClockSource = kPWM_ClockSrcBusClock;
psConfig->sCounterConfig.eCountClockPrescale = kPWM_ClockPrescaleDivide1;
psConfig->sCounterConfig.eCountInitSource = kPWM_InitOnLocalSync;
psConfig->sReloadConfig.eReloadSignalSelect = kPWM_LocalReloadSignal;
psConfig->sReloadConfig.eLoclReloadEffectTime = kPWM_TakeEffectAtReloadOportunity;
psConfig->sReloadConfig.eLocalReloadOportunity = kPWM_LoadEveryOportunity;
psConfig->sReloadConfig.bEnableFullCycleReloadOportunity = true;
psConfig->sReloadConfig.bEnableHalfCycleReloadOportunity = false;
psConfig->sValRegisterConfig.u16CounterInitialValue = 0xFF00U;
psConfig->sValRegisterConfig.u16ValRegister0 = 0x0U;
psConfig->sValRegisterConfig.u16ValRegister1 = 0x00FFU;
psConfig->sValRegisterConfig.u16ValRegister2 = 0xFF80U;
psConfig->sValRegisterConfig.u16ValRegister3 = 0x80U;
psConfig->sValRegisterConfig.u16ValRegister4 = 0xFF80U;
psConfig->sValRegisterConfig.u16ValRegister5 = 0x80U;
psConfig->sForceConfig.eForceSignalSelect = kPWM_LocalSoftwareForce;
psConfig->sForceConfig.eSoftOutputFor23 = kPWM_SoftwareOutputLow;
psConfig->sForceConfig.eSoftOutputFor45 = kPWM_SoftwareOutputLow;
psConfig->sForceConfig.eForceOutput23 = kPWM_GeneratedPwm;
psConfig->sForceConfig.eForceOutput45 = kPWM_GeneratedPwm;
psConfig->sDeadTimeConfig.eMode = kPWM_Independent;
psConfig->sOutputConfig.ePwmXSignalSelect = kPWM_RawPwmX;
psConfig->sOutputConfig.bEnablePwmXOutput = true;
psConfig->sOutputConfig.bEnablePwmaOutput = true;
psConfig->sOutputConfig.bEnablePwmbOutput = true;
psConfig->sOutputConfig.ePwmXFaultState = kPWM_OutputLowOnFault;
psConfig->sOutputConfig.ePwmaFaultState = kPWM_OutputLowOnFault;
psConfig->sOutputConfig.ePwmbFaultState = kPWM_OutputLowOnFault;
```

Parameters

- psConfig – Pointer to user's PWM submodule config structure. See `pwm_sm_config_t`.

void PWM_GetFaultProtectionDefaultConfig(*pwm_fault_protection_config_t* *psConfig)

Gets an default fault protection channel's configuration.

The default effective values are:

```
psConfig->sFaultInput[i].eFaultActiveLevel = kPWM_Logic0;
psConfig->sFaultInput[i].bEnableAutoFaultClear = true;
psConfig->sFaultInput[i].bEnableFaultFullCycleRecovery = true;
```

Parameters

- psConfig – Pointer to user's PWM fault protection config structure. See `pwm_fault_protection_config_t`.

```
void PWM_SetupSMConfig(PWM_Type *base, pwm_sm_number_t eSubModule, const
                        pwm_sm_config_t *psConfig)
```

Sets up the PWM submodule configure.

Parameters

- base – PWM peripheral base address
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- psConfig – Pointer to submodule configure structure, see `pwm_sm_config_t`.

```
static inline void PWM_SetupCounterConfig(PWM_Type *base, pwm_sm_number_t eSubModule,
                                          const pwm_sm_counter_config_t *psConfig)
```

Sets up the PWM submodule counter configure.

Parameters

- base – PWM peripheral base address
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- psConfig – Pointer to submodule counter configure structure, see `pwm_sm_counter_config_t`.

```
static inline void PWM_SetCounterInitialValue(PWM_Type *base, pwm_sm_number_t
                                              eSubModule, uint16_t u16InitialValue)
```

Sets the PWM submodule counter initial register value.

This function set the INIT register value, the counter will start counting from INIT register value when initial signal assert or software force set. This write value will be loaded into inner set of buffered registers according to reload logic configure.

Parameters

- base – PWM peripheral base address
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- u16InitialValue – The submodule number counter initialize value.

```
static inline void PWM_SetupReloadLogicConfig(PWM_Type *base, pwm_sm_number_t
                                              eSubModule, const
                                              pwm_sm_reload_logic_config_t *psConfig)
```

Sets up the PWM submodule reload logic configure.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- psConfig – Pointer to submodule reload logic configure structure, see `pwm_sm_reload_logic_config_t`.

```
void PWM_GetValueConfig(pwm_sm_value_register_config_t *psConfig,
                       pwm_sm_typical_output_mode_t eTypicalOutputMode, uint16_t
                       u16PwmPeriod, uint16_t u16PwmAPulseWidth, uint16_t
                       u16PwmBPulseWidth)
```

Update PWM submodule compare value configuration according to the typical output mode.

Parameters

- psConfig – See *pwm_sm_config_t*.
- eTypicalOutputMode – Typical PWM_A/B output mode. See *pwm_sm_typical_output_mode_t*.
- u16PwmPeriod – PWM output period value in counter ticks. This value can be got by (main counter clock in Hz) / (wanted PWM signal frequency in Hz).
- u16PwmAPulseWidth – PWM_A pulse width value in counter ticks. Can got by (wanted PWM duty Cycle) * u16PwmPeriod.
- u16PwmBPulseWidth – PWM_B pulse width value in counter ticks. Can got by (wanted PWM duty Cycle) * u16PwmPeriod.

```
static inline void PWM_SetupValRegisterConfig(PWM_Type *base, pwm_sm_number_t
                                             eSubModule, const
                                             pwm_sm_value_register_config_t *psConfig)
```

Sets up the PWM submodule VALn registers logic configure.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see *pwm_sm_number_t*.
- psConfig – Pointer to VALn registers configure structure, see *pwm_sm_value_register_config_t*.

```
static inline void PWM_SetValueRegister(PWM_Type *base, pwm_sm_number_t eSubModule,
                                       pwm_sm_val_register_t eRegister, uint16_t u16Value)
```

Sets the PWM submodule VALn register value.

Note: These write value will be loaded into inner set of buffered registers according to reload logic configure.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see *pwm_sm_number_t*.
- eRegister – Value register index (range in 0~5), see *pwm_sm_val_register_t*.
- u16Value – The value for VALn register.

```
static inline uint16_t PWM_GetValueRegister(PWM_Type *base, pwm_sm_number_t
                                           eSubModule, pwm_sm_val_register_t eRegister)
```

Gets the PWM submodule VALn register value.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see *pwm_sm_number_t*.
- eRegister – Value register index (range in 0~5), see *pwm_sm_val_register_t*.

Returns

The VALn register value.

```
static inline void PWM_SetFracvalRegister(PWM_Type *base, pwm_sm_number_t eSubModule,  
                                         pwm_sm_fracval_register_t eRegister, uint16_t  
                                         u16Value)
```

Sets the PWM submodule fractional value register value.

Note: These write value will be loaded into inner set of buffered registers according to reload logic configure.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- eRegister – Fractional value register index (range in 1~5), see `pwm_sm_val_register_t`.
- u16Value – The value for FRACVALn register.

```
static inline uint16_t PWM_GetFracvalRegister(PWM_Type *base, pwm_sm_number_t  
                                             eSubModule, pwm_sm_fracval_register_t  
                                             eRegister)
```

Sets the PWM submodule fractional value register value.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- eRegister – Fractional value register index (range in 1~5), see `pwm_sm_fracval_register_t`.

Returns

The VALn FRACVALn value.

```
static inline void PWM_SetValueAndFracRegister(PWM_Type *base, pwm_sm_number_t  
                                              eSubModule, pwm_sm_fracval_register_t  
                                              eRegister, uint32_t u32Value)
```

Set submodule register VALx and its FRAC value with 32bit access.

Parameters

- base – PWM peripheral base address.
- eSubModule – Submodule ID.
- eRegister – Fractional value register index (range in 1~5), see `pwm_sm_fracval_register_t`.
- u32Value – 32bit value for VALx and its FRAC. VALx: BIT16~BIT31. FRAC-VALx: BIT11~BIT15. RESERVED: BIT10~BIT0.

```
static inline uint32_t PWM_GetValueAndFracRegister(PWM_Type *base, pwm_sm_number_t  
                                                  eSubModule, pwm_sm_fracval_register_t  
                                                  eRegister)
```

Get submodule register VALx and its FRAC value with 32bit access.

Parameters

- base – PWM peripheral base address.
- eSubModule – Submodule ID.

- `eRegister` – Fractional value register index (range in 1~5), see `pwm_sm_fracval_register_t`.

Returns

The value of submodule register VALx and its FRAC, combined into 32bit.
VALx: BIT16~BIT31. FRACVALx: BIT11~BIT15. RESERVED: BIT10~BIT0.

static inline void PWM_SetPwmLdok(PWM_Type *base, uint16_t u16Mask)

Set the PWM LDOK bit on a single or multiple submodules.

Enable this feature can make buffered CTRL[PRSC] and the INIT, FRACVAL and VAL registers values take effect after next local load signal assert. The timing of take effect can be the next PWM reload or immediately. After loading, MCTRL[LDOK] is automatically cleared and need to enable again before the next register updated.

Note: The VALx, FRACVALx, INIT, and CTRL[PRSC] registers of the corresponding submodule cannot be written while the the corresponding MCTRL[LDOK] bit is set.

Parameters

- `base` – PWM peripheral base address
- `u16Mask` – PWM submodules to set the LDOK bit, Logical OR of `_pwm_sm_enable`.

static inline void PWM_ClearPwmLdok(PWM_Type *base, uint16_t u16Mask)

Clear the PWM LDOK bit on a single or multiple submodules.

Parameters

- `base` – PWM peripheral base address
- `u16Mask` – PWM submodules to clear the LDOK bit, Logical OR of `_pwm_sm_enable`.

static inline void PWM_SetupForceLogicConfig(PWM_Type *base, *pwm_sm_number_t* eSubModule, const *pwm_sm_force_logic_config_t* *psConfig)

brief Sets up the PWM submodule force logic configure.

param `base` PWM peripheral base address. param `eSubModule` PWM submodule number, see `pwm_sm_number_t`. param `psConfig` Poniter to submodule force logic configure structure, see `pwm_sm_force_logic_config_t`.

static inline void PWM_SetSoftwareForce(PWM_Type *base, *pwm_sm_number_t* eSubModule)

Sets up the PWM Sub-Module to trigger a software FORCE_OUT event.

Note: Only works when the CTRL2[FORCE_SEL] select `kPWM_ForceOutOnLocalSoftware`.

Parameters

- `base` – PWM peripheral base address.
- `eSubModule` – PWM submodule number, see `pwm_sm_number_t`.

void PWM_SetupDeadtimeConfig(PWM_Type *base, *pwm_sm_number_t* eSubModule, const *pwm_sm_deadtime_logic_config_t* *psConfig)

Sets up the PWM submodule deadtime logic configure.

Parameters

- `base` – PWM peripheral base address.

- `eSubModule` – PWM submodule number, see `pwm_sm_number_t`.
- `psConfig` – Pointer to deadtime logic configure structure, see `pwm_sm_deadtime_logic_config_t`.

```
static inline uint16_t PWM_GetDeadtimeSampleValue(PWM_Type *base, pwm_sm_number_t
                                                  eSubModule)
```

Get the sampled values of the PWM_X input at the end of each deadtime.

When use PWM_A/B in complementary mode and connect to transistor to controls the output voltage. Need insert deadtime to avoid overlap of conducting interval between the top and bottom transistor. And both transistors in complementary mode are off during deadtime. Then connect the PWM_X input to complementary transistors output, then it sampling input at the end of deadtime 0 for DT[0] and the end of deadtime 1 for DT[1]. Which DT value is not 0 indicates that there is a problem with the corresponding deadtime value. This can help to decide if there need do a deadtime correction for current complementary PWM output.

Parameters

- `base` – PWM peripheral base address
- `eSubModule` – PWM submodule number, see `pwm_sm_number_t`.

Returns

The PWM_X input sampled values.

```
void PWM_SetupFractionalDelayConfig(PWM_Type *base, pwm_sm_number_t eSubModule,
                                   const pwm_sm_fractional_delay_logic_config_t *psConfig)
```

Sets up the PWM submodule fractional delay logic configure.

Note: The fractional delay logic can only be used when the IPBus clock is running at 100 MHz.

Parameters

- `base` – PWM peripheral base address.
- `eSubModule` – PWM submodule number, see `pwm_sm_number_t`.
- `psConfig` – Pointer to fractional delay logic configure structure, see `pwm_sm_fractional_delay_logic_config_t`.

```
void PWM_SetupOutputConfig(PWM_Type *base, pwm_sm_number_t eSubModule, const
                           pwm_sm_output_logic_config_t *psConfig)
```

Sets up the PWM submodule output logic configure.

Parameters

- `base` – PWM peripheral base address.
- `eSubModule` – PWM submodule number, see `pwm_sm_number_t`.
- `psConfig` – Pointer to output logic configure structure, see `pwm_sm_output_logic_config_t`.

```
static inline void PWM_EnableOutput(PWM_Type *base, uint16_t u16SubModules,
                                    pwm_sm_pwm_out_t eOutput)
```

Enables the PWM submodule pin output.

This function handles PWMX_EN/PWMA_EN/PWMB_EN bit filed of OUTEN register, whcih can enable one or more submodule pin in PWMX/A/B.

Parameters

- `base` – PWM peripheral base address
- `u16SubModules` – The submodules that enable `eOutput` output, logical OR of `_pwm_sm_enable`.
- `eOutput` – PWM output pin ID, see `pwm_sm_pwm_out_t`.

```
static inline void PWM_DisableOutput(PWM_Type *base, uint16_t u16SubModules,  
                                     pwm_sm_pwm_out_t eOutput)
```

Disables the PWM submodule pin output.

This function handles `PWMX_EN/PWMA_EN/PWMB_EN` bit filed of `OUTEN` register, whcih can disable one or more submodule pin in `PWMX/A/B`.

Parameters

- `base` – PWM peripheral base address
- `u16SubModules` – The submodules that disable `eOutput` output, logical OR of `_pwm_sm_enable`.
- `eOutput` – PWM output pin ID, see `pwm_sm_pwm_out_t`.

```
static inline void PWM_EnableCombinedOutput(PWM_Type *base, uint16_t u16XSubModules,  
                                           uint16_t u16ASubModules, uint16_t  
                                           u16BSubModules)
```

Enables the PWM pin combination output.

This function handles `PWMX_EN/PWMA_EN/PWMB_EN` bit filed of `OUTEN` register at the same time.

Parameters

- `base` – PWM peripheral base address
- `u16XSubModules` – The submodules that enable `PWMX` output, should be logical OR of `_pwm_sm_enable`.
- `u16ASubModules` – The submodules that enable `PWMA` output, should be logical OR of `_pwm_sm_enable`.
- `u16BSubModules` – The submodules that enable `PWMB` output, should be logical OR of `_pwm_sm_enable`.

```
static inline void PWM_DisableCombinedOutput(PWM_Type *base, uint16_t u16XSubModules,  
                                             uint16_t u16ASubModules, uint16_t  
                                             u16BSubModules)
```

Disables the PWM pin combination output.

This function handles `PWMX_EN/PWMA_EN/PWMB_EN` bit filed of `OUTEN` register at the same time.

Parameters

- `base` – PWM peripheral base address
- `u16XSubModules` – The submodules that disable `PWMX` output, should be logical OR of `_pwm_sm_enable`.
- `u16ASubModules` – The submodules that disable `PWMA` output, should be logical OR of `_pwm_sm_enable`.
- `u16BSubModules` – The submodules that disable `PWMB` output, should be logical OR of `_pwm_sm_enable`.

```
static inline void PWM_MaskOutput(PWM_Type *base, uint16_t u16SubModules,  
                                  pwm_sm_pwm_out_t eOutput)
```

Mask the PWM pin output.

This function handles MASKA/MASKB/MASKX bit field of MASK register, which can mask one or more submodule pin in PWMX/A/B.

Note: The mask bits is buffered and can be updated until a FORCE_OUT event occurs or a software update command.

Parameters

- base – PWM peripheral base address.
- u16SubModules – The submodules that mask eOutput output, logical OR of `_pwm_sm_enable`.
- eOutput – PWM output pin ID, see `pwm_sm_pwm_out_t`.

```
static inline void PWM_UnmaskOutput(PWM_Type *base, uint16_t u16SubModules,  
                                   pwm_sm_pwm_out_t eOutput)
```

Unmask the PWM pin output.

This function handles MASKA/MASKB/MASKX bit field of MASK register, which can mask one or more submodule pin in PWMX/A/B.

Note: The mask bits is buffered and can be updated until a FORCE_OUT event occurs or a software update command.

Parameters

- base – PWM peripheral base address
- u16SubModules – The submodules that unmask eOutput output, logical OR of `_pwm_sm_enable`.
- eOutput – PWM output pin ID, see `pwm_sm_pwm_out_t`.

```
static inline void PWM_MaskCombinedOutput(PWM_Type *base, uint16_t u16XSubModules,  
                                          uint16_t u16ASubModules, uint16_t  
                                          u16BSubModules)
```

Mask the PWM pin combination output.

This function handles MASKA/MASKB/MASKX bit field of MASK register at the same time.

Note: The mask bits is buffered and can be updated until a FORCE_OUT event occurs or a software update command.

Parameters

- base – PWM peripheral base address
- u16XSubModules – The submodules that mask PWMX output, should be logical OR of `_pwm_sm_enable`.
- u16ASubModules – The submodules that mask PWMA output, should be logical OR of `_pwm_sm_enable`.
- u16BSubModules – The submodules that mask PWMB output, should be logical OR of `_pwm_sm_enable`.


```
static inline void PWM_UnmaskCombinedOutput(PWM_Type *base, uint16_t u16XSubModules,
                                           uint16_t u16ASubModules, uint16_t
                                           u16BSubModules)
```

Unmask the PWM pin combination output.

This function handles MASKA/MASKB/MASKX bit field of MASK register at the same time.

Note: The mask bits is buffered and can be updated until a FORCE_OUT event occurs or a software update command.

Parameters

- base – PWM peripheral base address
- u16XSubModules – The submodules that unmask PWMX output, should be logical OR of `_pwm_sm_enable`.
- u16ASubModules – The submodules that unmask PWMA output, should be logical OR of `_pwm_sm_enable`.
- u16BSubModules – The submodules that unmask PWMB output, should be logical OR of `_pwm_sm_enable`.

```
static inline void PWM_UpdateMask(PWM_Type *base, pwm_sm_number_t eSubModule)
```

Update PWM output mask bits immediately with a software command.

Parameters

- base – PWM peripheral base address
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.

```
static inline void PWM_EnablePwmRunInDebug(PWM_Type *base, pwm_sm_number_t
                                           eSubModule, bool bEnable)
```

Enables/Disables the PWM submodule continue to run while the chip is in DEBUG mode.

Parameters

- base – PWM peripheral base address
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- bEnable – Enable the feature or not.
 - **true** Enable load feature.
 - **false** Disable load feature.

```
static inline void PWM_EnablePwmRunInWait(PWM_Type *base, pwm_sm_number_t
                                           eSubModule, bool bEnable)
```

Enables/Disables the PWM submodule continue to run while the chip is in WAIT mode.

Parameters

- base – PWM peripheral base address
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- bEnable – Enable the feature or not.
 - **true** Enable load feature.
 - **false** Disable load feature.

```
static inline void PWM_EnableCounters(PWM_Type *base, uint16_t u16Mask)
```

Starts the PWM submodule counter for a single or multiple submodules.

Sets the Run bit which enables the clocks to the PWM submodule. This function can start multiple submodules at the same time.

Parameters

- base – PWM peripheral base address
- u16Mask – PWM submodules to start run, Logical OR of `_pwm_sm_enable`.

```
static inline void PWM_DisableCounters(PWM_Type *base, uint16_t u16Mask)
```

Stops the PWM counter for a single or multiple submodules.

Clears the Run bit which resets the submodule's counter. This function can stop multiple submodules at the same time.

Parameters

- base – PWM peripheral base address
- u16Mask – PWM submodules to start run, Logical OR of `_pwm_sm_enable`.

```
static inline uint16_t PWM_GetCaptureValue(PWM_Type *base, pwm_sm_number_t  
                                           eSubModule, pwm_sm_input_capture_register_t  
                                           eRegister)
```

Reads PWM submodule input capture value register.

This function read the CVALn register value, stores the value captured from the submodule counter.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- eRegister – PWM submodule input capture value register, see `pwm_sm_input_capture_register_t`.

Returns

The input capture value.

```
static inline uint16_t PWM_GetCaptureValueCycle(PWM_Type *base, pwm_sm_number_t  
                                                eSubModule,  
                                                pwm_sm_input_capture_register_t eRegister)
```

Reads PWM submodule input capture value cycle register.

This function read the CVALnCYC register value, stores the cycle number corresponding to the value captured in CVALn. This register is incremented each time the counter is loaded with the INIT value at the end of a PWM modulo cycle.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- eRegister – PWM submodule input capture value register, see `pwm_sm_input_capture_register_t`.

Returns

The input capture register cycle value.

```
static inline uint16_t PWM_GetCaptureEdgeCounterVaule(PWM_Type *base, pwm_sm_number_t  
                                                      eSubModule,  
                                                      pwm_sm_input_capture_pin_t  
                                                      eInputPin)
```

Reads the PWM submodule input capture logic edge counter value.

Each input capture logic has a edge counter, which counts both the rising and falling edges of the input capture signal and it compare signal can select as input capture trigger source.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- eInputPin – PWM submodule input capture pin number, see `pwm_sm_input_capture_pin_t`.

```
void PWM_SetupInputCaptureConfig(PWM_Type *base, pwm_sm_number_t eSubModule,  
                                pwm_sm_input_capture_pin_t eInputPin, const  
                                pwm_sm_input_capture_config_t *psConfig)
```

Sets up the PWM submodule input capture configure.

Each PWM submodule has 3 pins that can be configured for use as input capture pins. This function sets up the capture parameters for each pin and enables the input capture operation.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- eInputPin – PWM submodule input capture pin number, see `pwm_sm_input_capture_pin_t`.
- psConfig – Pointer to input capture configure structure, see `pwm_sm_input_capture_config_t`.

```
static inline void PWM_EnableInputCapture(PWM_Type *base, pwm_sm_number_t eSubModule,  
                                          pwm_sm_input_capture_pin_t eInputPin)
```

Enables the PWM submodule input capture operation.

Enables input capture operation will start the input capture process. The enable bit is self-cleared when in one shot mode and one or more of the enabled capture circuits has had a capture event.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- eInputPin – PWM submodule input capture pin number, see `pwm_sm_input_capture_pin_t`.

```
static inline void PWM_DisableInputCapture(PWM_Type *base, pwm_sm_number_t  
                                           eSubModule, pwm_sm_input_capture_pin_t  
                                           eInputPin)
```

Disables the PWM submodule input capture operation.

The enable bit can be cleared at any time to disable input capture operation.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see `pwm_sm_number_t`.
- eInputPin – PWM submodule input capture pin number, see `pwm_sm_input_capture_pin_t`.

```
static inline uint16_t PWM_GetInputValue(PWM_Type *base, pwm_sm_number_t eSubModule,  
                                         pwm_sm_input_capture_pin_t eInputPin)
```

Get the logic value currently being driven into the PWM inputs.

Parameters

- base – PWM peripheral base address
- eSubModule – PWM submodule number, see *pwm_sm_number_t*.
- eInputPin – PWM submodule input capture pin number, see *pwm_sm_input_capture_pin_t*.

Returns

The PWM submodule input capture pin logic value.

```
void PWM_SetupFaultProtectionConfig(PWM_Type *base, pwm_fault_protection_channel_t  
                                     eFaultProtection, const pwm_fault_protection_config_t  
                                     *psConfig)
```

Sets up the PWM fault protection channel configure.

Parameters

- base – PWM peripheral base address.
- eFaultProtection – PWM fault protection channel number, see *pwm_fault_protection_channel_t*.
- psConfig – Pointer to fault protection channel configure structure, see *pwm_fault_protection_config_t*.

```
static inline void PWM_SetupSMFaultInputMapping(PWM_Type *base, pwm_sm_number_t  
                                                 eSubModule, pwm_sm_pwm_out_t  
                                                 ePwmOutput, const  
                                                 pwm_sm_fault_input_mapping_t  
                                                 *psMapping)
```

Mapping fault protection channel fault input status to PWM submodule output,.

Note: Each PWM output can be mapping anyone or more fault inputs. The mapped fault protection channel inputs can disable PWM output.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see *pwm_sm_number_t*.
- ePwmOutput – PWM submodule output, see *pwm_sm_pwm_out_t*.
- psMapping – The fault input disable mapping structure, see *pwm_sm_fault_input_mapping_t*.

```
void PWM_SetupDmaConfig(PWM_Type *base, pwm_sm_number_t eSubModule, const  
                        pwm_sm_dma_config_t *psConfig)
```

Sets up the PWM submodule DMA configure.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see *pwm_sm_number_t*.
- psConfig – Pointer to PWM submodule DMA configure, see *pwm_sm_dma_config_t*.

```
static inline void PWM_SetEnabledCaptureDmaSource(PWM_Type *base, pwm_sm_number_t
                                                eSubModule,
                                                pwm_sm_capture_dma_source_t
                                                eCaptureDmaSource)
```

Select the trigger source for enabled capture FIFOs DMA read request.

Note: This function only can be used when the bEnableCaptureDMA be true.

Parameters

- base – PWM peripheral base address.
- eSubModule – PWM submodule number, see pwm_sm_number_t.
- eCaptureDmaSource – The PWM DMA capture source.

```
static inline void PWM_EnableSMInterrupts(PWM_Type *base, pwm_sm_number_t eSubModule,
                                          uint16_t u16Mask)
```

Enables the PWM submodule interrupts according to a provided mask.

This examples shows how to enable VAL 0 compare interrupt and VAL 1 compare interrupt.

```
PWM_EnableSMInterrupts(PWM, kPWM_SubModule0, kPWM_CompareVal0InterruptEnable |
kPWM_CompareVal1InterruptEnable);
```

Parameters

- base – PWM peripheral base address
- eSubModule – PWM submodule number, see pwm_sm_number_t.
- u16Mask – The PWM submodule interrupts to enable. Logical OR of _pwm_sm_interrupt_enable.

```
static inline void PWM_DisbaleSMInterrupts(PWM_Type *base, pwm_sm_number_t eSubModule,
                                           uint16_t u16Mask)
```

Disables the PWM submodule interrupts according to a provided mask.

This examples shows how to disable VAL 0 compare interrupt and VAL 1 compare interrupt.

```
PWM_DisbaleSMInterrupts(PWM, kPWM_SubModule0, kPWM_CompareVal0InterruptEnable |
kPWM_CompareVal1InterruptEnable);
```

Parameters

- base – PWM peripheral base address
- eSubModule – PWM submodule number, see pwm_sm_number_t.
- u16Mask – The PWM submodule interrupts to enable. Logical OR of _pwm_sm_interrupt_enable.

```
static inline void PWM_EnableFaultInterrupts(PWM_Type *base,
                                              pwm_fault_protection_channel_t eFaultProtection,
                                              uint16_t u16Mask)
```

Enables the PWM fault protection channel interrupt according to a provided mask.

This examples shows how to enable fault pin 0 interrupt and fault pin 1 interrupt.

```
PWM_EnableFaultInterrupts(PWM, kPWM_FaultProtection0, kPWM_Fault0InterruptEnable |
kPWM_Fault1InterruptEnable);
```

Parameters

- `base` – PWM peripheral base address
- `eFaultProtection` – PWM fault protection channel number, see `pwm_fault_protection_channel_t`.
- `u16Mask` – The PWM fault protection channel interrupts to enable. Logical OR of `_pwm_fault_protection_interrupt_enable`.

```
static inline void PWM_DisableFaultInterrupts(PWM_Type *base,  
                                              pwm_fault_protection_channel_t  
                                              eFaultProtection, uint16_t u16Mask)
```

Disables the PWM fault protection channel interrupt according to a provided mask.

This examples shows how to disable fault pin 0 interrupt and fault pin 1 interrupt.

```
PWM_DisableFaultInterrupts(PWM, kPWM_FaultProtection0, kPWM_Fault0InterruptEnable |  
kPWM_Fault1InterruptEnable);
```

Parameters

- `base` – PWM peripheral base address
- `eFaultProtection` – PWM fault protection channel number, see `pwm_fault_protection_channel_t`.
- `u16Mask` – The PWM fault protection channel interrupts to disable. Logical OR of `_pwm_fault_protection_interrupt_enable`.

```
static inline uint16_t PWM_GetSMStatusFlags(PWM_Type *base, pwm_sm_number_t  
                                           eSubModule)
```

Gets the PWM submodule status flags.

This examples shows how to check whether the submodule VAL0 compare flag set.

```
if((PWM_GetSMStatusFlags(PWM, kPWM_SubModule0) & kPWM_CompareVal0Flag) != 0U)  
{  
    ...  
}
```

Parameters

- `base` – PWM peripheral base address
- `eSubModule` – PWM submodule number, see `pwm_sm_number_t`.

Returns

The PWM submodule status flags. This is the logical OR of `pwm_sm_status_flags_t`.

```
static inline void PWM_ClearSMStatusFlags(PWM_Type *base, pwm_sm_number_t eSubModule,  
                                          uint16_t u16Mask)
```

Clears the PWM submodule status flags.

This examples shows how to clear the submodule VAL0 compare flag.

```
PWM_ClearSMStatusFlags(PWM, kPWM_SubModule0, kPWM_CompareVal0Flag);
```

Note: The `kPWM_RegUpdatedFlag` can't be cleared by software.

Parameters

- `base` – PWM peripheral base address

- `eSubModule` – PWM submodule number, see `pwm_sm_number_t`.
- `u16Mask` – The status flags to clear. This is the logical OR of `pwm_sm_status_flags_t`.

```
static inline uint16_t PWM_GetFaultStatusFlags(PWM_Type *base,
                                              pwm_fault_protection_channel_t
                                              eFaultProtection)
```

Gets the PWM fault protection status flags.

This examples shows how to check whether the fault protection channel fault input pin 0 set.

```
if((PWM_GetFaultStatusFlags(PWM, kPWM_FaultProtection0) & kPWM_FaultPin0Flag) != 0U)
{
    ...
}
```

Parameters

- `base` – PWM peripheral base address
- `eFaultProtection` – PWM fault protection channel number, see `pwm_fault_protection_channel_t`.

Returns

The PWM fault protection channel status flags. This is the logical OR of `_pwm_fault_protection_status_flags`.

```
static inline void PWM_ClearFaultStatusFlags(PWM_Type *base,
                                             pwm_fault_protection_channel_t eFaultProtection,
                                             uint16_t u16Mask)
```

Clears the PWM fault protection status flags according to a provided mask.

This examples shows how to clear the fault protection channel fault 0 flag.

```
PWM_ClearFaultStatusFlags(PWM, kPWM_FaultProtection0, kPWM_Fault0Flag);
```

Note: The `kPWM_FaultPin0ActiveFlag ~ kPWM_FaultPin3ActiveFlag` can't be cleared by software.

Parameters

- `base` – PWM peripheral base address
- `eFaultProtection` – PWM fault protection channel number, see `pwm_fault_protection_channel_t`.
- `u16Mask` – The PWM fault protection status flags to be clear. Logical OR of `_pwm_fault_protection_status_flags`.

FSL_PWM_DRIVER_VERSION

PWM driver version.

enum `_pwm_sm_number`

The enumeration for PWM submodule number.

Values:

enumerator `kPWM_SubModule0`

PWM Submodule 0

enumerator kPWM__SubModule1
PWM Submodule 1

enumerator kPWM__SubModule2
PWM Submodule 2

enumerator kPWM__SubModule3
PWM Submodule 3

enum __pwm_sm_enable
The enumeration for PWM submodule enable.
Values:

enumerator kPWM__SubModule0Enable
PWM Submodule 0 enable.

enumerator kPWM__SubModule1Enable
PWM Submodule 1 enable.

enumerator kPWM__SubModule2Enable
PWM Submodule 2 enable.

enumerator kPWM__SubModule3Enable
PWM Submodule 3 enable.

enumerator kPWM__ALLSubModuleEnable

enum __pwm_sm_count_clock_source
The enumeration for PWM submodule clock source.
Values:

enumerator kPWM__ClockSrcBusClock
The IPBus clock is used as the source clock

enumerator kPWM__ClockSrcExternalClock
EXT_CLK is used as the source clock

enumerator kPWM__ClockSrcSubmodule0Clock
Clock of the submodule 0 (AUX_CLK) is used as the source clock

enum __pwm_sm_count_clock_prescaler
The enumeration for PWM submodule prescaler factor selection for clock source.
Values:

enumerator kPWM__ClockPrescaleDivide1
PWM submodule clock frequency = fclk/1

enumerator kPWM__ClockPrescaleDivide2
PWM submodule clock frequency = fclk/2

enumerator kPWM__ClockPrescaleDivide4
PWM submodule clock frequency = fclk/4

enumerator kPWM__ClockPrescaleDivide8
PWM submodule clock frequency = fclk/8

enumerator kPWM__ClockPrescaleDivide16
PWM submodule clock frequency = fclk/16

enumerator kPWM__ClockPrescaleDivide32
PWM submodule clock frequency = fclk/32

enumerator kPWM__ClockPrescaleDivide64
PWM submodule clock frequency = fclk/64

enumerator kPWM__ClockPrescaleDivide128
PWM submodule clock frequency = fclk/128

enum __pwm_sm_count_init_source
The enumeration for PWM submodule counter initialization options.
Values:

enumerator kPWM__InitOnLocalSync
Local sync causes initialization

enumerator kPWM__InitOnMasterReload
Master reload from submodule 0 causes initialization

enumerator kPWM__InitOnMasterSync
Master sync from submodule 0 causes initialization

enumerator kPWM__InitOnExtSync
EXT_SYNC causes initialization

enum __pwm_ml2_stretch_count_clock_prescaler
The enumeration for PWM stretch IPBus clock count prescaler for mux0_trig/mux1_trig/out0_trig/out1_trig/pwma_trig/pwmb_trig.
Values:

enumerator kPWM__StretchIPBusClockPrescaler1
Stretch count is zero, no stretch.

enumerator kPWM__StretchIPBusClockPrescaler2
Stretch mux0_trig/mux1_trig/out0_trig/out1_trig/pwma_trig/pwmb_trig for 2 IPBus clock period.

enumerator kPWM__StretchIPBusClockPrescaler4
Stretch mux0_trig/mux1_trig/out0_trig/out1_trig/pwma_trig/pwmb_trig for 4 IPBus clock period.

enumerator kPWM__StretchIPBusClockPrescaler8
Stretch mux0_trig/mux1_trig/out0_trig/out1_trig/pwma_trig/pwmb_trig for 8 IPBus clock period.

enum __pwm_sm_reload_signal_select
The enumeration for PWM submodule local reload take effect timing.
Values:

enumerator kPWM__LocalReloadSignal
The local RELOAD signal is used to reload buffered-registers.

enumerator kPWM__MasterReloadSignal
The master RELOAD signal (from submodule 0) is used to reload buffered-registers (should not be used in submodule 0).

enum __pwm_sm_local_reload_effect_timing
The enumeration for PWM submodule local reload take effect timing.
Values:

enumerator kPWM__TakeEffectAtReloadOpportunity
Buffered-registers reload after one/more reload opportunities, and a load opportunity can generate on a PWM half or/and full cycle.

enumerator kPWM_TakeEffectImmediately

Buffered-registers reload with new values as soon as MCTRL[LDOK] bit is set when choose local reload.

enum _pwm_sm_local_reload_opportunity

The enumeration for PWM submodule reload opportunities selection under kPWM_ReloadWithLocalReloadOpportunity.

Values:

enumerator kPWM_LoadEveryOpportunity

Every PWM submodule reload opportunity

enumerator kPWM_LoadEvery2Opportunity

Every 2 PWM submodule reload opportunities

enumerator kPWM_LoadEvery3Opportunity

Every 3 PWM submodule reload opportunities

enumerator kPWM_LoadEvery4Opportunity

Every 4 PWM submodule reload opportunities

enumerator kPWM_LoadEvery5Opportunity

Every 5 PWM submodule reload opportunities

enumerator kPWM_LoadEvery6Opportunity

Every 6 PWM submodule reload opportunities

enumerator kPWM_LoadEvery7Opportunity

Every 7 PWM submodule reload opportunities

enumerator kPWM_LoadEvery8Opportunity

Every 8 PWM submodule reload opportunities

enumerator kPWM_LoadEvery9Opportunity

Every 9 PWM submodule reload opportunities

enumerator kPWM_LoadEvery10Opportunity

Every 10 PWM submodule reload opportunities

enumerator kPWM_LoadEvery11Opportunity

Every 11 PWM submodule reload opportunities

enumerator kPWM_LoadEvery12Opportunity

Every 12 PWM submodule reload opportunities

enumerator kPWM_LoadEvery13Opportunity

Every 13 PWM submodule reload opportunities

enumerator kPWM_LoadEvery14Opportunity

Every 14 PWM submodule reload opportunities

enumerator kPWM_LoadEvery15Opportunity

Every 15 PWM submodule reload opportunities

enumerator kPWM_LoadEvery16Opportunity

Every 16 PWM submodule reload opportunities

enum _pwm_sm_val_compare_mode

The enumeration for PWM submodule VALn register compare mode.

Values:

enumerator kPWM_CompareOnEqual

The VALn registers and the PWM counter are compared using an “equal to” method.

enumerator kPWM_CompareOnEqualOrGreater

The VALn registers and the PWM counter are compared using an “equal to or greater than” method.

enum _pwm_sm_val_register

The enumeration for PWM submodule VAL registers.

Values:

enumerator kPWM_VAL0

PWM submodule value register 0.

enumerator kPWM_VAL1

PWM submodule value register 1.

enumerator kPWM_VAL2

PWM submodule value register 2.

enumerator kPWM_VAL3

PWM submodule value register 3.

enumerator kPWM_VAL4

PWM submodule value register 4.

enumerator kPWM_VAL5

PWM submodule value register 5.

enum _pwm_sm_force_signal_select

The enumeration for PWM submodule FORCE_OUT source which can trigger force logic output update.

Values:

enumerator kPWM_LocalSoftwareForce

The local software force signal CTRL2[FORCE] is used to force updates.

enumerator kPWM_MasterSoftwareForce

The master software force signal from submodule 0 is used to force updates.

enumerator kPWM_LocalReloadForce

The local reload signal from this submodule is used to force updates without regard to the state of LDOK.

enumerator kPWM_MasterReloadForce

The master reload signal from submodule 0 is used to force updates if LDOK is set, should not be used in submodule 0.

enumerator kPWM_LocalSyncForce

The local sync (VAL1 match event) signal from this submodule is used to force updates.

enumerator kPWM_MasterSyncForce

The master sync signal from submodule0 is used to force updates.

enumerator kPWM_ExternalForceForce

The external force signal EXT_FORCE, from outside the PWM module causes updates.

enumerator kPWM_ExternalSyncForce

The external sync signal EXT_SYNC, from outside the PWM module causes updates.

enum `_pwm_sm_force_deadtime_source`

The enumeration for PWM submodule force out logic output (PWM23 and PWM45) source, which will transfer to output logic when a `FORCE_OUT` signal is asserted.

Values:

enumerator `kPWM_GeneratedPwm`

Generated PWM signal is used as the deadtime logic output.

enumerator `kPWM_InvertedGeneratedPwm`

Inverted PWM signal is used as the deadtime logic output.

enumerator `kPWM_SoftwareControlValue`

Software controlled value is used as the deadtime logic output.

enumerator `kPWM_UseExternal`

`PWM_EXT_A` signal is used as the deadtime logic output.

enum `_pwm_sm_force_software_output_value`

The enumeration for PWM submodule software controlled force out signal value.

Values:

enumerator `kPWM_SoftwareOutputLow`

A logic 0 is supplied to the deadtime generator when chose Software controlled value as output source.

enumerator `kPWM_SoftwareOutputHigh`

A logic 1 is supplied to the deadtime generator when chose Software controlled value as output source.

enum `_pwm_sm_deadtime_logic_mode`

The enumeration for PWM submodule deadtime logic mode, which decide how the dead-time logic process the force logic output signal.

Values:

enumerator `kPWM_Independent`

The PWMA (PWM23) and PWMB (PWM45) signal from force logic transfer to output logic independent.

enumerator `kPWM_IndependentWithDoubleSwitchPwm`

The PWMA (PWM23) and PWMB (PWM45) signals from force logic will XOR first, then the XOR signal transfer to output logic independent.

enumerator `kPWM_IndependentWithSplitDoubleSwitchPwm`

The PWMA (PWM23) and PWMB (PWM45) signals from force_out logic will XOR first, then the XOR signal transfer to output logic independent.

enumerator `kPWM_ComplementaryWithPwmA`

The PWMA (PWM23) signal from force logic will transfer to output logic with complementary mode.

enumerator `kPWM_ComplementaryWithPwmB`

The PWMB (PWM45) signal from force logic will transfer to output logic with complementary mode.

enumerator `kPWM_ComplementaryWithDoubleSwitchPwm`

The PWMA (PWM23) and PWMB (PWM45) signals from force logic will XOR first, then the XOR signal transfer to output logic with complementary mode.

enum `_pwm_sm_fracval_register`

The enumeration for PWM submodule FRACVAL registers.

Values:

enumerator `kPWM_FRACVAL1`

PWM submodule fractional value register 1.

enumerator `kPWM_FRACVAL2`

PWM submodule fractional value register 2.

enumerator `kPWM_FRACVAL3`

PWM submodule fractional value register 3.

enumerator `kPWM_FRACVAL4`

PWM submodule fractional value register 4.

enumerator `kPWM_FRACVAL5`

PWM submodule fractional value register 5.

enum `_pwm_sm_mux_trigger_source`

The enumeration for PWM submodule output logic final trigger output port signal.

Values:

enumerator `kPWM_ActualCompareEvent`

Route the PWM_OUT_TRIG signal (OR of VALx compare signal) to the mux trigger output port.

enumerator `kPWM_PwmOutput`

Route the PWM output (after polarity/mask/enable control) to the mux trigger output port.

enum `_pwm_sm_pwm_output_on_fault`

The enumeration for PWM submodule output logic PWM output fault status.

Values:

enumerator `kPWM_OutputLowOnFault`

The output is forced to logic 0 state prior to consideration of output polarity/mask/enable control during fault conditions and STOP mode.

enumerator `kPWM_OutputHighOnFault`

The output is forced to logic 1 state prior to consideration of output polarity/mask/enable control during fault conditions and STOP mode.

enumerator `kPWM_OutputTristatedOnFault`

The output status be tristated during fault conditions and STOP mode.

enum `_pwm_sm_pwm_x_signal_select`

The enumeration for PWM submodule output logic PwmX signal input source (before output polarity/mask/enable control).

Values:

enumerator `kPWM_RawPwmX`

The PWM_X source is raw Pwm01_fractional_delay signal.

enumerator `kPWM_DoubleSwitch`

The PWM_X source is Pwm23_fractional_delay XOR Pwm23_fractional_delay signal.

enum `_pwm_sm_pwm_out`

The enumeration for PWM submodule PWM output.

Values:

enumerator kPWM_PwmX
The PWM output PWM_X.

enumerator kPWM_PwmB
The PWM output PWM_B.

enumerator kPWM_PwmA
The PWM output PWM_A.

enum __pwm_sm_input_capture_pin
The enumeration for PWM submodule input capture pins.

Values:

enumerator kPWM_InputCapturePwmX
The input capture pin PwmX, need disable PwmX output when enable input capture.

enumerator kPWM_InputCapturePwmA
The input capture pin PwmA, need disable PwmA output when enable input capture.

enumerator kPWM_InputCapturePwmB
The input capture pin PwmB, need disable PwmB output when enable input capture.

enum __pwm_sm_input_capture_source
The enumeration for PWM submodule input capture source.

Values:

enumerator kPWM_RawInput
The capture source is the raw input signal.

enumerator kPWM_InputEdgeCounter
The capture source is edge counter which counts rising and falling edges on the raw input signal.

enum __pwm_sm_input_capture_edge
The enumeration for PWM submodule input capture edge when choose raw input as capture source.

Values:

enumerator kPWM_Noedge
Disabled capture on source falling/falling edge.

enumerator kPWM_FallingEdge
Enable input capture, and capture on source falling edge when chose the raw input signal as capture source.

enumerator kPWM_RisingEdge
Enable input capture, and capture on source rising edge when chose the raw input signal as capture source.

enumerator kPWM_RiseAndFallEdge
Enable input capture, and capture on source rising or falling edge when chose the raw input signal as capture source.

enum __pwm_sm_input_capture_register
The enumeration for PWM submodule input capture value register.

Values:

enumerator kPWM_InpCaptureVal0
Stores the value captured from the submodule counter when the PWM_X circuitry 0 logic capture occurs.

enumerator kPWM_InpCaptureVal1

Stores the value captured from the submodule counter when the PWM_X circuitry 1 logic capture occurs.

enumerator kPWM_InpCaptureVal2

Stores the value captured from the submodule counter when the PWM_A circuitry 0 logic capture occurs.

enumerator kPWM_InpCaptureVal3

Stores the value captured from the submodule counter when the PWM_A circuitry 1 logic capture occurs.

enumerator kPWM_InpCaptureVal4

Stores the value captured from the submodule counter when the PWM_B circuitry 0 logic capture occurs.

enumerator kPWM_InpCaptureVal5

Stores the value captured from the submodule counter when the PWM_B circuitry 1 logic capture occurs.

enum _pwm_sm_input_capture_filter_count

The enumeration for input filter count Represent the number of consecutive samples that must agree prior to the input filter accepting an input transition.

Values:

enumerator kPWM_InputCaptureFilterCount3Samples

3 samples.

enumerator kPWM_InputCaptureFilterCount4Samples

4 samples.

enumerator kPWM_InputCaptureFilterCount5Samples

5 samples.

enumerator kPWM_InputCaptureFilterCount6Samples

6 samples.

enumerator kPWM_InputCaptureFilterCount7Samples

7 samples.

enumerator kPWM_InputCaptureFilterCount8Samples

8 samples.

enumerator kPWM_InputCaptureFilterCount9Samples

9 samples.

enumerator kPWM_InputCaptureFilterCount10Samples

10 samples.

enum _pwm_sm_capture_dma_source

The enumeration for the source which can trigger the DMA read requests for the capture FIFOs.

Values:

enumerator kPWM_FIFOWatermarksORDma

Selected FIFO watermarks are OR'ed together to sets the read DMA request.

enumerator kPWM_FIFOWatermarksANDDMA

Selected FIFO watermarks are AND'ed together to sets the read DMA request.

enumerator kPWM_LocalSyncDma

A local sync (VAL1 match event) sets the read DMA request.

enumerator kPWM_LocalReloadDma

A local reload (STS[RF] being set) sets the read DMA request.

enum __pwm_sm_interrupt_enable

The enumeration for PWM submodule interrupt enable.

Values:

enumerator kPWM_CompareVal0InterruptEnable

PWM submodule VAL0 compare interrupt.

enumerator kPWM_CompareVal1InterruptEnable

PWM submodule VAL1 compare interrupt.

enumerator kPWM_CompareVal2InterruptEnable

PWM submodule VAL2 compare interrupt.

enumerator kPWM_CompareVal3InterruptEnable

PWM submodule VAL3 compare interrupt.

enumerator kPWM_CompareVal4InterruptEnable

PWM submodule VAL4 compare interrupt.

enumerator kPWM_CompareVal5InterruptEnable

PWM submodule VAL5 compare interrupt.

enumerator kPWM_CaptureX0InterruptEnable

PWM submodule capture X0 interrupt.

enumerator kPWM_CaptureX1InterruptEnable

PWM submodule capture X1 interrupt.

enumerator kPWM_CaptureB0InterruptEnable

PWM submodule capture B0 interrupt.

enumerator kPWM_CaptureB1InterruptEnable

PWM submodule capture B1 interrupt.

enumerator kPWM_CaptureA0InterruptEnable

PWM submodule capture A0 interrupt.

enumerator kPWM_CaptureA1InterruptEnable

PWM submodule capture A1 interrupt.

enumerator kPWM_ReloadInterruptEnable

PWM submodule reload interrupt.

enumerator kPWM_ReloadErrorInterruptEnable

PWM submodule reload error interrupt.

enumerator kPWM_ALLSubModuleInterruptEnable

enum __pwm_sm_status_flags

The enumeration for PWM submodule status flags.

Values:

enumerator kPWM_CompareVal0Flag

PWM submodule VAL0 compare flag.

enumerator kPWM_CompareVal1Flag
PWM submodule VAL1 compare flag.

enumerator kPWM_CompareVal2Flag
PWM submodule VAL2 compare flag.

enumerator kPWM_CompareVal3Flag
PWM submodule VAL3 compare flag.

enumerator kPWM_CompareVal4Flag
PWM submodule VAL4 compare flag.

enumerator kPWM_CompareVal5Flag
PWM submodule VAL5 compare flag.

enumerator kPWM_CaptureX0Flag
PWM submodule capture X0 flag.

enumerator kPWM_CaptureX1Flag
PWM submodule capture X1 flag.

enumerator kPWM_CaptureB0Flag
PWM submodule capture B0 flag.

enumerator kPWM_CaptureB1Flag
PWM submodule capture B1 flag.

enumerator kPWM_CaptureA0Flag
PWM submodule capture A0 flag.

enumerator kPWM_CaptureA1Flag
PWM submodule capture A1 flag.

enumerator kPWM_ReloadFlag
PWM submodule reload flag.

enumerator kPWM_ReloadErrorFlag
PWM submodule reload error flag.

enumerator kPWM_RegUpdatedFlag
PWM submodule registers updated flag.

enumerator kPWM_ALLSMStatusFlags

enum __pwm_sm_typical_output_mode

The enumeration for some PWM submodule PWM_A/B typical output mode.

Values:

enumerator kPWM_SignedCenterAligned
Center-aligned PWM with signed compare value.

enumerator kPWM_CenterAligned
Center-aligned PWM with unsigned compare value.

enumerator kPWM_SignedEdgeAligned
Edge-aligned PWM with signed compare value.

enumerator kPWM_EdgeAligned
Edge-aligned PWM with signed compare value.

enum `_pwm_fault_protection_channel`

The enumeration for PWM fault protection channel number.

Values:

enumerator `kPWM_FaultProtection0`

PWM fault protection channel 0

enum `_pwm_fault_protection_interrupt_enable`

The enumeration for PWM module fault protection channel interrupt enable.

Values:

enumerator `kPWM_Fault0InterruptEnable`

Fault protection channel fault 0 interrupt

enumerator `kPWM_Fault1InterruptEnable`

Fault protection channel fault 1 interrupt

enumerator `kPWM_Fault2InterruptEnable`

Fault protection channel fault 2 interrupt

enumerator `kPWM_Fault3InterruptEnable`

Fault protection channel fault 3 interrupt

enumerator `kPWM_ALLfaultInterruptEnable`

enum `_pwm_fault_protection_status_flags`

The enumeration for PWM module fault protection status flags.

Values:

enumerator `kPWM_Fault0Flag`

Fault protection channel fault 0 flag, set within two CPU cycles after a transition to active on the fault input pin 0.

enumerator `kPWM_Fault1Flag`

Fault protection channel fault 1 flag, set within two CPU cycles after a transition to active on the fault input pin 1.

enumerator `kPWM_Fault2Flag`

Fault protection channel fault 2 flag, set within two CPU cycles after a transition to active on the fault input pin 2.

enumerator `kPWM_Fault3Flag`

Fault protection channel fault 3 flag, set within two CPU cycles after a transition to active on the fault input pin 3.

enumerator `kPWM_FaultPin0ActiveFlag`

Fault protection channel fault input pin 0 active flag.

enumerator `kPWM_FaultPin1ActiveFlag`

Fault protection channel fault input pin 1 active flag.

enumerator `kPWM_FaultPin2ActiveFlag`

Fault protection channel fault input pin 2 active flag.

enumerator `kPWM_FaultPin3ActiveFlag`

Fault protection channel fault input pin 3 active flag.

enumerator `kPWM_ALLFaultStatusFlags`

enum `_pwm_fault_active_level`

The enumeration for PWM fault protection channel number.

Values:

enumerator `kPWM_Logic0`

A logic 0 on the fault input indicates a fault condition.

enumerator `kPWM_Logic1`

A logic 0 on the fault input indicates a fault condition.

typedef enum `_pwm_sm_number` `pwm_sm_number_t`

The enumeration for PWM submodule number.

typedef enum `_pwm_sm_count_clock_source` `pwm_sm_count_clock_source_t`

The enumeration for PWM submodule clock source.

typedef enum `_pwm_sm_count_clock_prescaler` `pwm_sm_count_clock_prescaler_t`

The enumeration for PWM submodule prescaler factor selection for clock source.

typedef enum `_pwm_sm_count_init_source` `pwm_sm_count_init_source_t`

The enumeration for PWM submodule counter initialization options.

typedef enum `_pwm_ml2_stretch_count_clock_prescaler`

`pwm_ml2_stretch_count_clock_prescaler_t`

The enumeration for PWM stretch IPBus clock count prescaler for mux0_trig/mux1_trig/out0_trig/out1_trig/pwma_trig/pwmb_trig.

typedef struct `_pwm_sm_counter_config` `pwm_sm_counter_config_t`

The structure for configuring PWM submodule counter logic.

typedef enum `_pwm_sm_reload_signal_select` `pwm_sm_reload_signal_select_t`

The enumeration for PWM submodule local reload take effect timing.

typedef enum `_pwm_sm_local_reload_effect_timing` `pwm_sm_local_reload_effect_timing_t`

The enumeration for PWM submodule local reload take effect timing.

typedef enum `_pwm_sm_local_reload_oportunity` `pwm_sm_local_reload_oportunity_t`

The enumeration for PWM submodule reload opportunities selection under `kPWM_ReloadWithLocalReloadOportunity`.

typedef struct `_pwm_sm_reload_logic_config` `pwm_sm_reload_logic_config_t`

The structure for configuring PWM submodule reload logic.

typedef enum `_pwm_sm_val_compare_mode` `pwm_sm_val_compare_mode_t`

The enumeration for PWM submodule VALn register compare mode.

typedef enum `_pwm_sm_val_register` `pwm_sm_val_register_t`

The enumeration for PWM submodule VAL registers.

typedef struct `_pwm_sm_value_register_config` `pwm_sm_value_register_config_t`

The structure for configuring PWM submodule value registers.

typedef enum `_pwm_sm_force_signal_select` `pwm_sm_force_signal_select_t`

The enumeration for PWM submodule FORCE_OUT source which can trigger force logic output update.

typedef enum `_pwm_sm_force_deadtime_source` `pwm_sm_force_deadtime_source_t`

The enumeration for PWM submodule force out logic output (PWM23 and PWM45) source, which will transfer to output logic when a FORCE_OUT signal is asserted.

typedef enum `_pwm_sm_force_software_output_value` `pwm_sm_force_software_output_value_t`

The enumeration for PWM submodule software controlled force out signal value.

`typedef struct _pwm_sm_force_logic_config pwm_sm_force_logic_config_t`

The structure for configuring PWM submodule force logic.

`typedef enum _pwm_sm_deadtime_logic_mode pwm_sm_deadtime_logic_mode_t`

The enumeration for PWM submodule deadtime logic mode, which decide how the dead-time logic process the force logic output signal.

`typedef struct _pwm_sm_deadtime_value pwm_sm_deadtime_value_t`

The structure of the inserted dead time value, applies only to KPWM_Complementaryxxx mode.

`typedef struct _pwm_sm_deadtime_logic_config pwm_sm_deadtime_logic_config_t`

The structure for configuring PWM submodule force out logic, works on the deadtime logic output.

`typedef enum _pwm_sm_fracval_register pwm_sm_fracval_register_t`

The enumeration for PWM submodule FRACVAL registers.

`typedef struct _pwm_sm_fractional_delay_logic_config pwm_sm_fractional_delay_logic_config_t`

The structure for configuring PWM submodule fractional delay logic, works on the dead-time logic output.

`typedef enum _pwm_sm_mux_trigger_source pwm_sm_mux_trigger_source_t`

The enumeration for PWM submodule output logic final trigger output port signal.

`typedef enum _pwm_sm_pwm_output_on_fault pwm_sm_pwm_output_on_fault_t`

The enumeration for PWM submodule output logic PWM output fault status.

`typedef enum _pwm_sm_pwm_x_signal_select pwm_sm_pwm_x_signal_select_t`

The enumeration for PWM submodule output logic PwmX signal input source (before output polarity/mask/enable control).

`typedef enum _pwm_sm_pwm_out pwm_sm_pwm_out_t`

The enumeration for PWM submodule PWM output.

`typedef struct _pwm_sm_output_logic_config_t pwm_sm_output_logic_config_t`

The structure for configuring PWM submodule output logic.

`typedef enum _pwm_sm_input_capture_pin pwm_sm_input_capture_pin_t`

The enumeration for PWM submodule input capture pins.

`typedef enum _pwm_sm_input_capture_source pwm_sm_input_capture_source_t`

The enumeration for PWM submodule input capture source.

`typedef enum _pwm_sm_input_capture_edge pwm_sm_input_capture_edge_t`

The enumeration for PWM submodule input capture edge when choose raw input as capture source.

`typedef enum _pwm_sm_input_capture_register pwm_sm_input_capture_register_t`

The enumeration for PWM submodule input capture value register.

`typedef enum _pwm_sm_input_capture_filter_count pwm_sm_input_capture_filter_count_t`

The enumeration for input filter count Represent the number of consecutive samples that must agree prior to the input filter accepting an input transition.

`typedef struct _pwm_sm_input_capture_config pwm_sm_input_capture_config_t`

The structure for configuring PWM submodule input capture logic.

Note: When choosing kPWM_InputEdgeCounter as circuit 0/1 capture source, the eCircuit0CaptureEdge and eCircuit1CaptureEdge selected trigger edge will be ignored, but still

need place a value other than kPWM_Noedge in either or both of the eCaptureCircuit0 and/or CaptureCircuit1 fields in order to enable one or both of the capture registers.

typedef enum *_pwm_sm_capture_dma_source* pwm_sm_capture_dma_source_t

The enumeration for the source which can trigger the DMA read requests for the capture FIFOs.

typedef struct *_pwm_sm_capture_dma_config* pwm_sm_capture_dma_config_t

The structure for configuring PWM submodule read capture DMA.

typedef struct *_pwm_sm_dma_config* pwm_sm_dma_config_t

The structure for configuring PWM submodule DMA.

typedef struct *_pwm_sm_fault_input_mapping* pwm_sm_fault_input_mapping_t

The enumeration for PWM submodule output fault enable mask for one fault protection channel.

The structure for configuring PWM submodule fault input disable mapping.

Note: The channel 0 input 0 and channel 1 input 0 are different pins.

Note: Each PWM output can be mapping anyone or more fault inputs. The mapped fault protection channel inputs can disable PWM output.

typedef enum *_pwm_sm_status_flags* pwm_sm_status_flags_t

The enumeration for PWM submodule status flags.

typedef enum *_pwm_sm_typical_output_mode* pwm_sm_typical_output_mode_t

The enumeration for some PWM submodule PWM_A/B typical output mode.

typedef struct *_pwm_sm_config* pwm_sm_config_t

PWM submodule config structure.

This structure holds the configuration settings for the PWM peripheral. To initialize this structure to reasonable defaults, call the PWM_GetDefaultConfig() function and pass a pointer to your config structure instance.

typedef enum *_pwm_fault_protection_channel* pwm_fault_protection_channel_t

The enumeration for PWM fault protection channel number.

typedef enum *_pwm_fault_active_level* pwm_fault_input_active_level_t

The enumeration for PWM fault protection channel number.

typedef struct *_pwm_fault_protection_input_config* pwm_fault_protection_input_config_t

typedef struct *_pwm_fault_protection_config* pwm_fault_protection_config_t

The structure for configuring PWM fault protection channel, a PWM module can have multiple fault protection channels, PWM sub-module can choose to mapping any one or more fault input from fault protection channels.

typedef struct *_pwm_config* pwm_config_t

PWM module config structure which contain submodule config structure pointers and fault protection filter config structure pointers.

Note: Need use submodule structure address to init the structure pointers, when the submodule or fault protection structure pointers is NULL, it will be ignored by PWM_Init API. This can save stack space when only one or two submodules are used.

struct __pwm_sm_counter_config

#include <fsl_pwm.h> The structure for configuring PWM submodule counter logic.

Public Members

pwm_sm_count_clock_source_t eCountClockSource

Configures PWM submodule counter clock source.

pwm_sm_count_clock_prescaler_t eCountClockPrescaler

Configures PWM submodule counter clock source prescaler.

pwm_sm_count_init_source_t eCountInitSource

Configures PWM submodule counter initial source.

bool bEnableForceInitial

Enable force-controlled initialization. The assert FORCE_OUT signal can to initialize the counter without regard to the selected initial source.

uint16_t u16PhaseDelayValue

Defines the delay from the master sync signal of submodule 0 to this submodule counter (the unit of delay is the PWM clock cycle), only works when chose kPWM_InitOnMasterSync as initial source.

struct __pwm_sm_reload_logic_config

#include <fsl_pwm.h> The structure for configuring PWM submodule reload logic.

Public Members

pwm_sm_reload_signal_select_t eReloadSignalSelect

Configures PWM submodule RELOAD signal source to be local reload signal or master reload signal.

pwm_sm_local_reload_effect_timing_t eLoclReloadEffectTime

Configures PWM submodule local reload signal effective timing when choose it as RELOAD signal source.

bool bEnableFullCycleReloadOpportunity

Enable generate a reload opportunity on PWM half cycle (count from INIT value to VAL0).

bool bEnableHalfCycleReloadOpportunity

Enable generate a reload opportunity on PWM full cycle (count from INIT value to VAL1).

pwm_sm_local_reload_opportunity_t eLocalReloadOpportunity

Configures PWM submodule reload frequency when using local reload opportunities mode .

struct __pwm_sm_value_register_config

#include <fsl_pwm.h> The structure for configuring PWM submodule value registers.

Public Members

`uint16_t u16CounterInitialValue`
Configures PWM submodule counter initial value.

`uint16_t u16ValRegister0`
Configures PWM submodule value register 0 (VAL0) value.

`uint16_t u16ValRegister1`
Configures PWM submodule value register 1 (VAL1) value.

`uint16_t u16ValRegister2`
Configures PWM submodule value register 2 (VAL2) value.

`uint16_t u16ValRegister3`
Configures PWM submodule value register 3 (VAL3) value.

`uint16_t u16ValRegister4`
Configures PWM submodule value register 4 (VAL4) value.

`uint16_t u16ValRegister5`
Configures PWM submodule value register 5 (VAL5) value.

`struct __pwm_sm_force_logic_config`
#include <fsl_pwm.h> The structure for configuring PWM submodule force logic.

Public Members

`uint8_t bitPWM23OutputInitialVaule`
Configures PWM submodule compare output x (PwmX) initial value.

`uint8_t bitPWM45OutputInitialVaule`
Configures PWM submodule compare output A (PwmA) initial value.

`uint8_t bitPWMXOutputInitialVaule`
Configures PWM submodule compare output B (PwmB) initial value.

`pwm_sm_force_signal_select_t eForceSignalSelect`
Configures PWM submodule force out select update trigger source.

`pwm_sm_force_software_output_value_t eSoftOutputFor23`
Configures PWM submodule force out PwmA value when select software as output source.

`pwm_sm_force_software_output_value_t eSoftOutputFor45`
Configures PWM submodule force out PwmB value when select software as output source.

`pwm_sm_force_deadtime_source_t eForceOutput23`
Configures the source of Pwm23, which will be force to deadtime logic.

`pwm_sm_force_deadtime_source_t eForceOutput45`
Configures the source of Pwm45, which will be force to deadtime logic.

`struct __pwm_sm_deadtime_value`
#include <fsl_pwm.h> The structure of the inserted dead time value, applies only to KPWM_Complementaryxxx mode.

`struct __pwm_sm_deadtime_logic_config`
#include <fsl_pwm.h> The structure for configuring PWM submodule force out logic, works on the deadtime logic output.

Public Members

pwm_sm_deadtime_logic_mode_t eMode

The mode in which Deadtime logic process the force logic output signal.

pwm_sm_deadtime_value_t sDeadTimeValue0

Control the deadtime during 0 to 1 transitions of the PWM_23 output (assuming normal polarity). When disable fractional delays, the maximum value is 0x7FF which represents 2047 cycles of IP bus cycles. When enable fractional delays, the maximum value is 0xFFFF which represents 2047 31/32 cycles cycles of IP bus cycles.

pwm_sm_deadtime_value_t sDeadTimeValue1

Control the deadtime during 0 to 1 transitions of the PWM_45 output (assuming normal polarity). When disable fractional delays, the maximum value is 0x7FF which represents 2047 cycles of IP bus cycles. When enable fractional delays, the maximum value is 0xFFFF which represents 2047 31/32 cycles cycles of IP bus cycles.

struct *_pwm_sm_fractional_delay_logic_config*

#include <fsl_pwm.h> The structure for configuring PWM submodule fractional delay logic, works on the deadtime logic output.

Public Members

uint8_t bitsFracValue1

Configures PWM submodule compare register VAL1 fractional delay value, the unit is 1/32 IP bus clock.

bool bEnableVal1FractionalDelay

Enable the fractional delay feature of bitsFracValue1.

uint8_t bitsFracValue2

Configures PWM submodule compare register VAL2 fractional delay value, the unit is 1/32 IP bus clock.

uint8_t bitsFracValue3

Configures PWM submodule compare register VAL3 fractional delay value, the unit is 1/32 IP bus clock.

bool bEnableVal23FractionalDelay

Enable the fractional delay feature of bitsFracValue2 and bitsFracValue3.

uint8_t bitsFracValue4

Configures PWM submodule compare register VAL4 fractional delay value, the unit is 1/32 IP bus clock.

uint8_t bitsFracValue5

Configures PWM submodule compare register VAL5 fractional delay value, the unit is 1/32 IP bus clock.

bool bEnableVal45FractionalDelay

Enable the fractional delay feature of bitsFracValue4 and bitsFracValue5.

struct *_pwm_sm_output_logic_config_t*

#include <fsl_pwm.h> The structure for configuring PWM submodule output logic.

Public Members

bool bVal0TriggerEnable

Enable VAL0 register compare event trigger.

`bool bVal1TriggerEnable`

Enable VAL1 register compare event trigger.

`bool bVal2TriggerEnable`

Enable VAL2 register compare event trigger.

`bool bVal3TriggerEnable`

Enable VAL3 register compare event trigger.

`bool bVal4TriggerEnable`

Enable VAL4 register compare event trigger.

`bool bVal5TriggerEnable`

Enable VAL5 register compare event trigger.

`bool bEnableTriggerPostScaler`

True : Trigger outputs are generated only during the final PWM period prior to a reload opportunity, false : Trigger outputs are generated during every PWM period. Configures PWM submodule mux trigger output signal 0 source.

`pwm_sm_mux_trigger_source_t eMuxTrigger0`

Configures PWM submodule mux trigger output signal 1 source.

`pwm_sm_mux_trigger_source_t eMuxTrigger1`

Configures PWM submodule PWM_X output source (before polarity/mask/enable control).

`bool bInvertPwmXOutput`

True : invert PWM_X output, false : no invert PWM_X output.

`bool bInvertPwmaOutput`

True : invert PWM_A output, false : no invert PWM_A output.

`bool bInvertPwmbOutput`

True : invert PWM_B output, false : no invert PWM_B output.

`bool bMaskPwmXOutput`

True : PWM_X output masked, false : PWM_X output normal. Mask bit is buffered, and take effect until FORCE_OUT event or software update command.

`bool bMaskPwmaOutput`

True : PWM_A output masked, false : PWM_A output normal. Mask bit is buffered, and take effect until FORCE_OUT event or software update command.

`bool bMaskPwmbOutput`

True : PWM_B output masked, false : PWM_B output normal. Mask bit is buffered, and take effect until FORCE_OUT event or software update command.

`bool bEnablePwmXOutput`

True : Enable PWM_X output. false : PWM_X is disabled and output is tristated.

`bool bEnablePwmaOutput`

True : Enable PWM_A output. false : PWM_A is disabled and output is tristated.

`bool bEnablePwmbOutput`

True : Enable PWM_B output. false : PWM_B is disabled and output is tristated. Configures PWM submodule PWM_X output during fault status (only works when fault status enable).

`pwm_sm_pwm_output_on_fault_t ePwmxFaultState`

Configures PWM submodule PWM_A output during fault status (only works when fault status enable).

pwm_sm_pwm_output_on_fault_t ePwmaFaultState

Configures PWM submodule PWM_B output during fault status (only works when fault status enable).

struct *_pwm_sm_input_capture_config*

#include <fsl_pwm.h> The structure for configuring PWM submodule input capture logic.

Note: When choosing kPWM_InputEdgeCounter as circuit 0/1 capture source, the eCircuit0CaptureEdge and eCircuit1CaptureEdge selected trigger edge will be ignored, but still need place a value other than kPWM_Noedge in either or both of the eCaptureCircuit0 and/or CaptureCircuit1 fields in order to enable one or both of the capture registers.

Public Members

bool bEnableInputCapture

True: enable the input capture process, false : disable the input capture process.

pwm_sm_input_capture_source_t eInCaptureSource

Configures capture circuit 0/1 input source

pwm_sm_input_capture_edge_t eCircuit0CaptureEdge

Configures which edge causes a capture for capture circuit 0 , will be ignore when use edge counter as capture source.

pwm_sm_input_capture_edge_t eCircuit1CaptureEdge

Configures which edge causes a capture for capture circuit 1 , will be ignore when use edge counter as capture source.

bool bEnableOneShotCapture

True: Enable one-shot capture mode, the bEnableInputCapture will self-cleared when one or more of the enabled capture circuits has had a capture event; false: Capture circuit 0/1 will perform capture continue;

uint8_t bitsCaptureFifoWatermark

Watermark level for circuit 0/1 capture FIFO. The capture flags in the status register will set if the word count in the circuit 0/1 capture FIFO is greater than this watermark level

uint8_t u8EdgeCounterCompareValue

Edge counter compare value, used only if edge counter is used as capture circuit 0/1 input source

uint8_t u8FilterPeriod

Sampling period (in IPBus clock cycles) of the input filter, set to 0 to bypass the filter.

pwm_sm_input_capture_filter_count_t eFilterCount

Filter sample count.

struct *_pwm_sm_capture_dma_config*

#include <fsl_pwm.h> The structure for configuring PWM submodule read capture DMA.

Public Members

bool bEnableCaptureDMA

Enables DMA read requests for the Capture FIFOs.

pwm_sm_capture_dma_source_t eCaptureDMASource

Select the source to enables DMA read requests for the Capture FIFOs. Will be ignored when bEnableCaptureDMA be false.

struct *_pwm_sm_dma_config*

#include <fsl_pwm.h> The structure for configuring PWM submodule DMA.

Public Members

bool bEnableWriteValDMA

STS[RF] set enables DMA write requests for VALx and FRACVALx registers.

bool bEnableReadCaptureX0DMA

STS[CFX0] set enables DMA read requests for Capture X0 FIFO. And X0 FIFO watermark is selected for sCaptureDma pwm_sm_capture_dma_config_t.

bool bEnableReadCaptureX1DMA

STS[CFX1] set enables DMA read requests for Capture X1 FIFO. And X1 FIFO watermark is selected for sCaptureDma pwm_sm_capture_dma_config_t.

bool bEnableReadCaptureA0DMA

STS[CFA0] set enables DMA read requests for Capture A0 FIFO. And A0 FIFO watermark is selected for sCaptureDma pwm_sm_capture_dma_config_t.

bool bEnableReadCaptureA1DMA

STS[CFA1] set enables DMA read requests for Capture A1 FIFO. And A1 FIFO watermark is selected for sCaptureDma pwm_sm_capture_dma_config_t.

bool bEnableReadCaptureB0DMA

STS[CFB0] set enables DMA read requests for Capture B0 FIFO. And B0 FIFO watermark is selected for sCaptureDma pwm_sm_capture_dma_config_t.

bool bEnableReadCaptureB1DMA

STS[CFB1] set enables DMA read requests for Capture B1 FIFO. And B1 FIFO watermark is selected for sCaptureDma pwm_sm_capture_dma_config_t.

pwm_sm_capture_dma_config_t sCaptureDma

DMA read requests for the capture FIFOs configure.

struct *_pwm_sm_fault_input_mapping*

#include <fsl_pwm.h> The enumeration for PWM submodule output fault enable mask for one fault protection channel.

The structure for configuring PWM submodule fault input disable mapping.

Note: The channel 0 input 0 and channel 1 input 0 are different pins.

Note: Each PWM output can be mapping anyone or more fault inputs. The mapped fault protection channel inputs can disable PWM output.

Public Members

bool bFaultInput0Mapping

Mapping fault input 0 (from fault protection channel 0) to PWM output.

`bool bFaultInput1Mapping`
Mapping fault input 1 (from fault protection channel 0) to PWM output.

`bool bFaultInput2Mapping`
Mapping fault input 2 (from fault protection channel 0) to PWM output.

`bool bFaultInput3Mapping`
Mapping fault input 3 (from fault protection channel 0) to PWM output.

`bool bFaultInput4Mapping`
Mapping fault input 4 (from fault protection channel 1) to PWM output.

`bool bFaultInput5Mapping`
Mapping fault input 5 (from fault protection channel 1) to PWM output.

`bool bFaultInput6Mapping`
Mapping fault input 6 (from fault protection channel 1) to PWM output.

`bool bFaultInput7Mapping`
Mapping fault input 7 (from fault protection channel 1) to PWM output.

`struct _pwm_sm_config`

#include <fsl_pwm.h> PWM submodule config structure.

This structure holds the configuration settings for the PWM peripheral. To initialize this structure to reasonable defaults, call the `PWM_GetDefaultConfig()` function and pass a pointer to your config structure instance.

Public Members

`bool enableDebugMode`
true: PWM continues to run in debug mode; false: PWM is paused in debug mode.

`bool enableWaitMode`
true: PWM continues to run in WAIT mode; false: PWM is paused in WAIT mode.

`bool enableRun`
true: PWM submodule is enabled; false: PWM submodule is disabled. Configures submodule value registers compare mode, only can be written one time.

pwm_sm_counter_config_t `sCounterConfig`
Submodule counter logic config.

pwm_sm_reload_logic_config_t `sReloadConfig`
Submodule reload control logic config.

pwm_sm_value_register_config_t `sValRegisterConfig`
Submodule value registers config.

pwm_sm_force_logic_config_t `sForceConfig`
Submodule force out logic config.

pwm_sm_deadtime_logic_config_t `sDeadTimeConfig`
Submodule deadtime logic config.

pwm_sm_fractional_delay_logic_config_t `sFracDelayConfig`
Submodule fractional logic config.

pwm_sm_output_logic_config_t `sOutputConfig`
Submodule output logic config.

pwm_sm_input_capture_config_t sInCaptureConfig[3]

Submodule input capture config for PWM_X/A/B pins.

pwm_sm_dma_config_t sDMAConfig

Submodule DMA config. PWM_X output fault input mapping, determines which fault inputs can disable PWM_X output.

pwm_sm_fault_input_mapping_t sPwmXFaultInputMapping

PWM_A output fault input mapping, determines which fault inputs can disable PWM_A output.

pwm_sm_fault_input_mapping_t sPwmAFaultInputMapping

PWM_B output fault input mapping, determines which fault inputs can disable PWM_B output.

pwm_sm_fault_input_mapping_t sPwmBFaultInputMapping

Submodule interrupt enable mask, logic OR of *_pwm_sm_interrupt_enable*.

pwm_ml2_stretch_count_clock_prescaler_t eStrBusClock

PWM stretch IPBus clock count prescaler.

struct *_pwm_fault_protection_input_config*

#include <fsl_pwm.h>

Public Members

pwm_fault_input_active_level_t eFaultActiveLevel

Select the active logic level of the fault input.

bool bEnableAutoFaultClear

True : Enable automatic fault clearing, fault recovery (PWM outputs can re-enable) occurs when FSTS[FFPINx] is clear , false : Use manual fault clearing, fault recovery (PWM outputs can re-enable) occurs when FSTS[FFLAGx] is manual clear (and FSTS[FFPINx] is clear).

bool bEnableManualFaultClearSafeMode

True : fault recovery (PWM outputs can re-enable) occurs when FSTS[FFLAGx] is manual clear and FSTS[FFPINx] is clear, false : fault recovery (PWM outputs can re-enable) occurs when FSTS[FFLAGx] is manual clear.

bool bEnableFaultFullCycleRecovery

Enable full cycle fault recovery, which make PWM outputs are re-enabled at the start of a half cycle after fault recovery occurs.

bool bEnableFaultHalfCycleRecovery

Enable half cycle fault recovery, which make PWM outputs are re-enabled at the start of a half cycle after fault recovery occurs.

bool bEnableFaultNoCombinationalPath

True : The fault inputs are combined with the filtered and latched fault signals to disable the PWM outputs , false : the filtered and latched fault signals are used to disable the PWM outputs.

bool bEnableFaultInterrupt

Enable the fault input interrupt.

struct *_pwm_fault_protection_config*

#include <fsl_pwm.h> The structure for configuring PWM fault protection channel, a PWM module can have multiple fault protection channels, PWM sub-module can choose to maping any one or more fault input from fault protection channels.

Public Members

bool bEnableFaultGlitchStretch

Fault Glitch Stretch Enable: A logic 1 means that input fault signals will be stretched to at least 2 IPBus clock cycles.

uint8_t bitsFaultFilterCount

Configures PWM fault protection channel fault filter count.

uint8_t u8FaultFilterPeriod

Configures PWM fault protection channel fault filter period, value of 0 will bypass the filter.

struct __pwm_config

#include <fsl_pwm.h> PWM module config structure which contain submodule config structure pointers and fault protection filter config structure pointers.

Note: Need use submodule structure address to init the structure pointers, when the submodule or fault protection structure pointers is NULL, it will be ignored by PWM_Init API. This can save stack space when only one or two submodules are used.

Public Members

pwm_sm_config_t *psPwmSubmoduleConfig[1]

< PWM submodule config. PWM fault protection channel config, will take effect for all submodules.

2.60 The Driver Change Log

2.61 eFlexPWM Peripheral and Driver Overview

2.62 QSCI: Queued Serial Communications Interface Driver

void QSCI_GetDefaultConfig(*qsci_config_t* *psConfig, uint32_t u32BaudRateBps, uint32_t u32SrcClockHz)

Sets the QSCI configuration structure to default values.

The purpose of this API is to initialize the configuration structure to default value for QSCI_Init to use. Use the unchanged structure in QSCI_Init or modify the structure before calling QSCI_Init. This is an example:

```
qsci_config_t sConfig;
QSCI_GetDefaultConfig(&sConfig, 115200, 12000000U);
QSCI_Init(QSCI0, &sConfig);
```

Parameters

- psConfig – Pointer to configuration structure.
- u32BaudRateBps – Baudrate setting.
- u32SrcClockHz – The clock source frequency for QSCI module.

`status_t QSCI_Init(QSCI_Type *base, qsci_config_t *psConfig)`

Initializes the QSCI instance with a user configuration structure.

This function configures the QSCI module with the customized settings. User can configure the configuration structure manually or get the default configuration by using the `QSCI_GetDefaultConfig` function. The example below shows how to use this API to configure QSCI.

```
qsci_config_t sConfig;
QSCI_GetDefaultConfig(&sConfig, 115200, 12000000U);
QSCI_Init(QSCI0, &sConfig);
```

Parameters

- `base` – QSCI peripheral base address.
- `psConfig` – Pointer to the user-defined configuration structure.

Return values

- `kStatus_QSCI_BaudrateNotSupport` – Baudrate is not supported in the current clock source.
- `kStatus_Success` – Set baudrate succeeded.

`void QSCI_Deinit(QSCI_Type *base)`

Deinitializes a QSCI instance.

This function waits for transmitting complete, then disables TX and RX.

Parameters

- `base` – QSCI peripheral base address.

`static inline uint16_t QSCI_GetStatusFlags(QSCI_Type *base)`

Gets QSCI hardware status flags.

Parameters

- `base` – QSCI peripheral base address.

Returns

QSCI status flags, can be a single flag or several flags in `_qsci_status_flags` combined by OR.

`void QSCI_ClearStatusFlags(QSCI_Type *base, uint16_t u16StatusFlags)`

Clears QSCI status flags.

This function clears QSCI status flags. Members in `kQSCI_Group0Flags` can't be cleared by this function, they are cleared or set by hardware.

Parameters

- `base` – QSCI peripheral base address.
- `u16StatusFlags` – The status flag mask, can be a single flag or several flags in `_qsci_status_flags` combined by OR.

`void QSCI_EnableInterrupts(QSCI_Type *base, uint8_t u8Interrupts)`

Enables QSCI interrupts according to the provided mask.

This function enables the QSCI interrupts according to the provided mask. The mask is a logical OR of enumeration members in `_qsci_interrupt_enable`.

Parameters

- `base` – QSCI peripheral base address.

- `u8Interrupts` – The interrupt source mask, can be a single source or several sources in `_qsci_interrupt_enable` combined by OR.

`void QSCI_DisableInterrupts(QSCI_Type *base, uint8_t u8Interrupts)`

Disables QSCI interrupts according to the provided mask.

This function disables the QSCI interrupts according to the provided mask. The mask is a logical OR of enumeration members in `_qsci_interrupt_enable`.

Parameters

- `base` – QSCI peripheral base address.
- `u8Interrupts` – The interrupt source mask, can be a single source or several sources in `_qsci_interrupt_enable` combined by OR.

`uint8_t QSCI_GetEnabledInterrupts(QSCI_Type *base)`

Gets the enabled QSCI interrupts.

This function gets the enabled QSCI interrupts. The enabled interrupts are returned as the logical OR value of the enumerators `_qsci_interrupt_enable`.

Parameters

- `base` – QSCI peripheral base address.

Returns

The interrupt source mask, can be a single source or several sources in `_qsci_interrupt_enable` combined by OR.

`static inline void QSCI_Reset(QSCI_Type *base)`

Sets the QSCI register value to reset value.

Parameters

- `base` – QSCI peripheral base address.

`static inline void QSCI_EnableTx(QSCI_Type *base, bool bEnable)`

Enables or disables the QSCI transmitter.

This function enables or disables the QSCI transmitter.

Parameters

- `base` – QSCI peripheral base address.
- `bEnable` – True to enable, false to disable.

`static inline void QSCI_EnableRx(QSCI_Type *base, bool bEnable)`

Enables or disables the QSCI receiver.

This function enables or disables the QSCI receiver.

Parameters

- `base` – QSCI peripheral base address.
- `bEnable` – True to enable, false to disable.

`static inline void QSCI_EnableStopInWait(QSCI_Type *base, bool bEnable)`

Enables/disables stop in wait.

Parameters

- `base` – QSCI peripheral base address.
- `bEnable` – true to enable, QSCI stops working in wait mode, false to disable, QSCI keeps working in wait mode


```
static inline void QSCI_Enable9bitMode(QSCI_Type *base, bool bEnable)
```

Enables/Disables 9-bit data mode for QSCI.

Parameters

- base – QSCI peripheral base address.
- bEnable – true to enable, false to disable.

```
static inline void QSCI_EnableStandbyMode(QSCI_Type *base, bool bEnable)
```

Enables/Disables standby mode.

When QSCI is in standby mode, further receiver interrupt requests are inhibited waiting to be wake up. The wakeup mode can be configured by QSCI_SetWakeupMode. Hardware wakes the receiver by automatically disabling standby.

Parameters

- base – QSCI peripheral base address.
- bEnable – true to enable, false to disable.

```
static inline void QSCI_EnableLINSlaveMode(QSCI_Type *base, bool bEnable)
```

Enable/Disable LIN slave mode.

If enabled QSCI is in LIN slave mode. When break is detected, the baudrate register is automatically adjusted to match the value measured from the sync character that follows.

Parameters

- base – QSCI peripheral base address.
- bEnable – true to enable, false to disable.

```
static inline void QSCI_EnableStopHold(QSCI_Type *base, bool bEnable)
```

Enable/Disable stop mode hold off.

When enabled, if chip level stop mode occurs and transmitter or receiver is still busy, QSCI will hold off stop mode until both transmitter and receiver are idle.

Parameters

- base – QSCI peripheral base address.
- bEnable – true to enable, false to disable.

```
static inline void QSCI_SetTransferMode(QSCI_Type *base, qsci_transfer_mode_t  
eTransferMode)
```

Sets the QSCI transfer mode.

Parameters

- base – QSCI peripheral base address.
- eTransferMode – The QSCI tx/rx loop mode, kQSCI_Normal to use normal transfer, kQSCI_LoopInternal to let internal tx feed back to rx, kQSCI_SingleWire to use single wire mode using tx pin as tx and rx.

```
static inline void QSCI_SetWakeupMode(QSCI_Type *base, qsci_wakeup_mode_t eWakeupMode)
```

Sets wakeup mode for QSCI.

Parameters

- base – QSCI peripheral base address.
- eWakeupMode – Wakeup mode, kQSCI_WakeupOnIdleLine or kQSCI_WakeupOnAddressMark.

static inline void QSCI_SetPolarityMode(QSCI_Type *base, *qsci_polarity_mode_t* ePolarityMode)
Sets polarity mode for QSCI.

Parameters

- base – QSCI peripheral base address.
- ePolarityMode – Polarity mode, kQSCI_PolarityNormal or kQSCI_PolarityInvert.

static inline void QSCI_SetParityMode(QSCI_Type *base, *qsci_parity_mode_t* eParityMode)
Sets parity mode for QSCI.

Parameters

- base – QSCI peripheral base address.
- eParityMode – Polarity mode, kQSCI_ParityDisabled, kQSCI_ParityEven or kQSCI_ParityOdd.

status_t QSCI_SetBaudRate(QSCI_Type *base, uint32_t u32BaudRateBps, uint32_t u32SrcClockHz)

Sets the QSCI instance baud rate.

This function configures the QSCI module baud rate. This function can be used to update QSCI module baud rate after the QSCI module is initialized by the QSCI_Init.

Parameters

- base – QSCI peripheral base address.
- u32BaudRateBps – QSCI baudrate to be set.
- u32SrcClockHz – QSCI clock source frequency in Hz.

Return values

- kStatus_QSCI_BaudrateNotSupport – Baudrate is not supported in the current clock source.
- kStatus_Success – Set baudrate succeeded.

static inline void QSCI_EnableFifo(QSCI_Type *base, bool bEnable)
Enables/Disables transmitter/receiver FIFO.

Parameters

- base – QSCI peripheral base address.
- bEnable – true to enable, false to disable.

static inline void QSCI_SetTxWaterMark(QSCI_Type *base, *qsci_tx_water_t* eTxFifoWatermark)
Sets transmitter watermark.

Parameters

- base – QSCI peripheral base address.
- eTxFifoWatermark – Tx water mark level.

static inline void QSCI_SetRxWaterMark(QSCI_Type *base, *qsci_rx_water_t* eRxFifoWatermark)
Sets receiver watermark.

Parameters

- base – QSCI peripheral base address.
- eRxFifoWatermark – Rx water mark level.

```
static inline void QSCI_EnableTxDMA(QSCI_Type *base, bool bEnable)
```

Enables or disables the QSCI transmitter DMA request.

This function enables or disables CTRL2[TDE], to generate the DMA requests when Tx data register is empty.

Parameters

- base – QSCI peripheral base address.
- bEnable – True to enable, false to disable.

```
static inline void QSCI_EnableRxDMA(QSCI_Type *base, bool bEnable)
```

Enables or disables the QSCI receiver DMA request.

This function enables or disables CTRL2[RDE], to generate DMA requests when receiver data register is full.

Parameters

- base – QSCI peripheral base address.
- bEnable – True to enable, false to disable.

```
static inline uint32_t QSCI_GetDataRegisterAddress(QSCI_Type *base)
```

Gets the QSCI data register byte address.

This function returns the QSCI data register address, which is mainly used by DMA/eDMA.

Parameters

- base – QSCI peripheral base address.

Returns

QSCI data register byte addresses which are used both by the transmitter and the receiver.

```
static inline void QSCI_WriteByte(QSCI_Type *base, uint8_t u8Data)
```

Writes to the TX register.

This function writes data to the TX register directly. The upper layer must ensure that the TX register is empty or TX FIFO has room before calling this function.

Parameters

- base – QSCI peripheral base address.
- u8Data – The byte to write.

```
static inline void QSCI_SendAddress(QSCI_Type *base, uint8_t u8Address)
```

Sends an address frame in 9-bit data mode.

Parameters

- base – QSCI peripheral base address.
- u8Address – QSCI slave address.

```
static inline uint8_t QSCI_ReadByte(QSCI_Type *base)
```

Reads the RX register directly.

This function reads data from the RX register directly. The upper layer must ensure that the RX register is full or that the TX FIFO has data before calling this function.

Parameters

- base – QSCI peripheral base address.

Returns

The byte read from QSCI data register.

`void QSCI_WriteBlocking(QSCI_Type *base, const uint8_t *pu8Data, uint32_t u32Length)`

Writes TX register using a blocking method.

This function polls the TX register, waits TX register to be empty or TX FIFO have room then writes data to the TX buffer.

Parameters

- `base` – QSCI peripheral base address.
- `pu8Data` – Start address of the data to write.
- `u32Length` – Size of the data to write.

`status_t QSCI_ReadBlocking(QSCI_Type *base, uint8_t *pu8Data, uint32_t u32Length)`

Reads RX data register using a blocking method.

This function polls the RX register, waits RX register to be full or RX FIFO have data, then reads data from the RX register.

Parameters

- `base` – QSCI peripheral base address.
- `pu8Data` – Start address of the buffer to store the received data.
- `u32Length` – Size of the buffer.

Return values

- `kStatus_Fail` – Receiver error occurred while receiving data.
- `kStatus_QSCI_RxHardwareOverrun` – Receiver overrun occurred while receiving data
- `kStatus_QSCI_NoiseError` – Noise error occurred while receiving data
- `kStatus_QSCI_FramingError` – error occurred while receiving data
- `kStatus_QSCI_ParityError` – Parity error occurred while receiving data
- `kStatus_Success` – Successfully received all data.

`static inline void QSCI_SendBreak(QSCI_Type *base)`

Sends one break character (10 or 11 bits of zeroes).

Parameters

- `base` – QSCI peripheral base address.

`void QSCI_TransferCreateHandle(QSCI_Type *base, qsci_transfer_handle_t *psHandle, qsci_transfer_callback_t pfCallback, void *pUserData)`

Initializes the QSCI handle.

This function initializes the QSCI handle which can be used for other QSCI transactional APIs. Usually, for a specified QSCI instance, call this API once to get the initialized handle.

Parameters

- `base` – QSCI peripheral base address.
- `psHandle` – QSCI handle pointer.
- `pfCallback` – The callback function.
- `pUserData` – The parameter of the callback function.

```
void QSCI_TransferStartRingBuffer(qsci_transfer_handle_t *psHandle, uint8_t *pu8RxRingBuffer,  
                                uint16_t u16RxRingBufferSize)
```

Sets up the RX ring buffer.

This function sets up the RX ring buffer to a specific QSCI handle.

When the RX ring buffer is used, data received are stored into the ring buffer even when the user doesn't call the QSCI_TransferReceiveNonBlocking() API. If data is already received in the ring buffer, the user can get the received data from the ring buffer directly.

Note: When using the RX ring buffer, one byte is reserved for internal use. In other words, if ringBufferSize is 32, only 31 bytes are used for saving data.

Parameters

- psHandle – QSCI handle pointer.
- pu8RxRingBuffer – Start address of the ring buffer for background receiving. Pass NULL to disable the ring buffer.
- u16RxRingBufferSize – Size of the ring buffer.

```
void QSCI_TransferStopRingBuffer(qsci_transfer_handle_t *psHandle)
```

Aborts the background transfer and uninstalls the ring buffer.

This function aborts the background transfer and uninstalls the ring buffer.

Parameters

- psHandle – QSCI handle pointer.

```
uint16_t QSCI_TransferGetRxRingBufferLength(qsci_transfer_handle_t *psHandle)
```

Get the ring buffer valid data length.

Parameters

- psHandle – QSCI handle pointer.

Returns

Valid data length in ring buffer.

```
status_t QSCI_TransferSendNonBlocking(qsci_transfer_handle_t *psHandle, qsci_transfer_t  
                                     *psTransfer)
```

Transmits a buffer of data using the interrupt method.

This function sends data using an interrupt method. This is a non-blocking function, which returns directly without waiting for all data to be written to the TX register. When all data is sent out, the QSCI driver calls the callback function and passes the kStatus_QSCI_TxIdle as status parameter.

Parameters

- psHandle – QSCI handle pointer.
- psTransfer – QSCI transfer structure. See qsci_transfer_t.

Return values

- kStatus_Success – Successfully start the data transmission.
- kStatus_QSCI_TxBusy – Previous transmission still not finished; data not all written to TX register yet.

`void QSCI_TransferAbortSend(qsci_transfer_handle_t *psHandle)`

Aborts the interrupt-driven data transmit.

This function aborts the interrupt-driven data sending. The user can get the `remainBytes` to find out how many bytes are not sent out.

Parameters

- `psHandle` – QSCI handle pointer.

`status_t QSCI_TransferGetSendCount(qsci_transfer_handle_t *psHandle, uint32_t *pu32Count)`

Gets the number of bytes sent out to bus.

This function gets the number of bytes sent out to bus by using the interrupt method.

Parameters

- `psHandle` – QSCI handle pointer.
- `pu32Count` – Send bytes count.

Return values

- `kStatus_NoTransferInProgress` – No send in progress.
- `kStatus_Success` – Get successfully through the parameter count;

`status_t QSCI_TransferReceiveNonBlocking(qsci_transfer_handle_t *psHandle, qsci_transfer_t *psTransfer, uint32_t *pu32ReceivedBytes)`

Receives a buffer of data using an interrupt method.

This function receives data using an interrupt method. This is a non-blocking function, which returns without waiting for all data to be received. If the RX ring buffer is used and not empty, the data in the ring buffer is copied and the parameter `pu32ReceivedBytes` shows how many bytes are copied from the ring buffer. After copying, if the data in the ring buffer is not enough to read, the receive request is saved by the QSCI driver. When the new data arrives, the receive request is serviced first. When all data is received, the QSCI driver notifies the upper layer through a callback function and passes the status parameter `kStatus_QSCI_RxIdle`. For example, the upper layer needs 10 bytes but there are only 5 bytes in the ring buffer. The 5 bytes are copied to the `psTransfer->data` and this function returns with the parameter `pu32ReceivedBytes` set to 5. For the left 5 bytes, newly arrived data is saved from the `psTransfer->data[5]`. When 5 bytes are received, the QSCI driver notifies the upper layer. If the RX ring buffer is not enabled, this function enables the RX and RX interrupt to receive data to the `psTransfer->data`. When all data is received, the upper layer is notified.

Parameters

- `psHandle` – QSCI handle pointer.
- `psTransfer` – QSCI transfer structure, see `qsci_transfer_t`.
- `pu32ReceivedBytes` – Bytes received from the ring buffer directly.

Return values

- `kStatus_Success` – Successfully queue the transfer into transmit queue.
- `kStatus_QSCI_RxBusy` – Previous receive request is not finished.

`void QSCI_TransferAbortReceive(qsci_transfer_handle_t *psHandle)`

Aborts the interrupt-driven data receiving.

This function aborts the interrupt-driven data receiving. The user can get the `remainBytes` to know how many bytes are not received yet.

Parameters

- `psHandle` – QSCI handle pointer.

status_t QSCI_TransferGetReceivedCount(*qsci_transfer_handle_t* *psHandle, uint32_t *pu32Count)

Gets the number of bytes that have been received.

This function gets the number of bytes that have been received.

Parameters

- psHandle – QSCI handle pointer.
- pu32Count – Receive bytes count.

Return values

- kStatus_NoTransferInProgress – No receive in progress.
- kStatus_InvalidArgument – Parameter is invalid.
- kStatus_Success – Get successfully through the parameter pu32Count;

FSL_QSCI_DRIVER_VERSION

QSCI driver version.

Status codes for the QSCI driver.

Values:

enumerator kStatus_QSCI_TxBusy

Transmitter is busy.

enumerator kStatus_QSCI_RxBusy

Receiver is busy.

enumerator kStatus_QSCI_TxIdle

Transmitter is idle.

enumerator kStatus_QSCI_RxIdle

Receiver is idle.

enumerator kStatus_QSCI_FlagCannotClearManually

Status flag can't be manually cleared.

enumerator kStatus_QSCI_RxRingBufferOverrun

QSCI RX software ring buffer overrun.

enumerator kStatus_QSCI_RxHardwareOverrun

QSCI receiver hardware overrun.

enumerator kStatus_QSCI_NoiseError

QSCI noise error.

enumerator kStatus_QSCI_FramingError

QSCI framing error.

enumerator kStatus_QSCI_ParityError

QSCI parity error.

enumerator kStatus_QSCI_BaudrateNotSupport

Baudrate is not supported in current clock source

enumerator kStatus_QSCI_IdleLineDetected

QSCI IDLE line detected.

enumerator kStatus_QSCI_Timeout

Timeout happens when waiting for status flags to change.

enum _qsci_status_flags

QSCI hardware status flags.

These enumerations can be ORed together to form bit masks.

Values:

enumerator kQSCI_TxDataRegEmptyFlag

TX data register empty flag.

enumerator kQSCI_TxIdleFlag

Transmission idle flag.

enumerator kQSCI_RxDataRegFullFlag

RX data register full flag.

enumerator kQSCI_RxIdleLineFlag

Rx Idle line flag.

enumerator kQSCI_RxOverrunFlag

RX overrun flag.

enumerator kQSCI_RxNoiseFlag

RX detect noise on Rx input.

enumerator kQSCI_RxFrameErrorFlag

Rx frame error flag, sets if logic 0 was detected for stop bit

enumerator kQSCI_RxParityErrorFlag

Rx parity error if parity enabled, sets upon parity error detection

enumerator kQSCI_RxInputEdgeFlag

RX pin active edge interrupt flag, sets when active edge detected

enumerator kQSCI_LINSyncErrorFlag

Only for LIN mode.

enumerator kQSCI_TxDMARequestFlag

Tx DMA request is ongoing.

enumerator kQSCI_RxDMARequestFlag

Rx DMA request is ongoing.

enumerator kQSCI_RxActiveFlag

enumerator kQSCI_Group0Flags

Members in kQSCI_Group0Flags can't be cleared by QSCI_ClearStatusFlags, they are handled by HW.

enumerator kQSCI_Group1Flags

Whole kQSCI_Group1Flags will be cleared if trying to clear any member in kQSCI_Group1Flags or kQSCI_Group2Flags in the mask.

enumerator kQSCI_Group2Flags

Member in kQSCI_Group2Flags can be cleared individually

enumerator kQSCI_StatusAllFlags

enum _qsci_interrupt_enable

QSCI interrupt enable/disable source.

These enumerations can be ORed together to form bit masks.

Values:

enumerator kQSCI_TxEmptyInterruptEnable
Transmit data register empty interrupt.

enumerator kQSCI_TxIdleInterruptEnable
Transmission idle interrupt.

enumerator kQSCI_RxFullInterruptEnable
Receive data register full interrupt.

enumerator kQSCI_RxErrorInterruptEnable
Receive error interrupt.

enumerator kQSCI_RxInputEdgeInterruptEnable
Receive input edge interrupt.

enumerator kQSCI_RxIdleLineInterruptEnable
Receive idle interrupt.

enumerator kQSCI_AllInterruptEnable

enum _qsci_transfer_mode
QSCI transmitter/receiver loop mode.

Values:

enumerator kQSCI_Normal
Normal mode, 2 signal pins, no loop.

enumerator kQSCI_LoopInternal
Loop mode with internal TXD fed back to RXD.

enumerator kQSCI_SingleWire
Use tx pin as input and output half-duplex transfer.

enum _qsci_data_bit_mode
QSCI data bit count.

Values:

enumerator kQSCI_Data8Bit
1 start bit, 8 data bit, 1 stop bit

enumerator kQSCI_Data9Bit
1 start bit, 9 data bit, 1 stop bit. This mode actually is not supported yet in driver.

enum _qsci_wakeup_mode
QSCI wakeup mode.

Values:

enumerator kQSCI_WakeupOnIdleLine
Idle condition wakes the QSCI module.

enumerator kQSCI_WakeupOnAddressMark
Address mark wakes the QSCI module.

enum _qsci_polarity_mode
QSCI signal polarity mode.

Values:

enumerator kQSCI_PolarityNormal
Normal mode, no inversion.

enumerator kQSCI_PolarityInvert

Invert transmit and receive data bits.

enum _qsci_parity_mode

QSCI parity mode.

Values:

enumerator kQSCI_ParityDisabled

Parity disabled

enumerator kQSCI_ParityEven

Parity enabled, type even, bit setting: PE | PT = 10

enumerator kQSCI_ParityOdd

Parity enabled, type odd, bit setting: PE | PT = 11

enum _qsci_tx_water

QSCI transmitter watermark level.

Values:

enumerator kQSCI_TxWater0Word

Tx interrupt sets when tx fifo empty.

enumerator kQSCI_TxWater1Word

Tx interrupt sets when tx fifo has 1 or few word.

enumerator kQSCI_TxWater2Word

Tx interrupt sets when tx fifo has 2 or few words.

enumerator kQSCI_TxWater3Word

Tx interrupt sets when tx fifo not full.

enum _qsci_rx_water

QSCI receiver watermark level.

Values:

enumerator kQSCI_RxWater1Word

Rx interrupt sets when rx fifo not empty.

enumerator kQSCI_RxWater2Word

Rx interrupt sets when rx fifo has at least 1 word.

enumerator kQSCI_RxWater3Word

Rx interrupt sets when rx fifo has at least 2 words.

enumerator kQSCI_RxWater4Word

Rx interrupt sets when rx fifo full.

typedef enum _qsci_transfer_mode qsci_transfer_mode_t

QSCI transmitter/receiver loop mode.

typedef enum _qsci_data_bit_mode qsci_data_bit_mode_t

QSCI data bit count.

typedef enum _qsci_wakeup_mode qsci_wakeup_mode_t

QSCI wakeup mode.

typedef enum _qsci_polarity_mode qsci_polarity_mode_t

QSCI signal polarity mode.

```
typedef enum _qsci_parity_mode qsci_parity_mode_t
```

QSCI parity mode.

```
typedef enum _qsci_tx_water qsci_tx_water_t
```

QSCI transmitter watermark level.

```
typedef enum _qsci_rx_water qsci_rx_water_t
```

QSCI receiver watermark level.

```
typedef struct _qsci_config qsci_config_t
```

QSCI configuration structure.

```
typedef struct _qsci_transfer_handle_t qsci_transfer_handle_t
```

Forward declaration of the handle typedef .

```
typedef void (*qsci_transfer_callback_t)(qsci_transfer_handle_t *psHandle)
```

QSCI interrupt transfer callback function definition.

Defines the interface of user callback function used in QSCI interrupt transfer using transactional APIs. The callback function shall be defined and declared in application level by user. Before starting QSCI transmitting or receiving by calling QSCI_TransferSendNonBlocking or QSCI_TransferReceiveNonBlocking, call QSCI_TransferCreateHandle to install the user callback. When the transmitting or receiving ends or any bus error like hardware overrun occurs, user callback will be invoked by driver.

Param psHandle

Transfer handle that contains bus status, user data.

```
typedef struct _qsci_transfer qsci_transfer_t
```

QSCI transfer structure.

```
typedef void (*qsci_isr_t)(void *handle)
```

```
qsci_isr_t s_pfQsciIsr
```

```
void *s_psQsciHandles[]
```

```
IRQn_Type const s_eQsciTXIdleIRQs[]
```

```
uint16_t QSCI_GetInstance(QSCI_Type *base)
```

Get the QSCI instance from peripheral base address.

Parameters

- base – QSCI peripheral base address.

Returns

QSCI instance.

```
QSCI_RETRY_TIMES
```

Retry times when checking status flags.

```
QSCI_GET_BUS_STATUS(psHandle)
```

Macros to be used inside user callback.

```
QSCI_GET_TRANSFER_USER_DATA(psHandle)
```

```
struct _qsci_config
```

#include <fsl_qsci.h> QSCI configuration structure.

Public Members

qsci_transfer_mode_t eTransferMode
Transmitter/receiver loop mode.

bool bStopInWaitEnable
Enable/disable module stops working in wait mode.

qsci_data_bit_mode_t eDataBitMode
Number of data bits.

qsci_wakeup_mode_t eWakeupMode
Receiver wakeup mode, idle line or addressmark.

qsci_polarity_mode_t ePolarityMode
Polarity of transmit/receive data.

qsci_parity_mode_t eParityMode
Parity mode, disabled (default), even, odd.

bool bEnableStopHold
Control the stop hold enable.

bool bEnableTx
Enable TX

bool bEnableRx
Enable RX

bool bEnableFifo
Enable Tx/Rx FIFO

bool bEnableTxDMA
Enable Tx DMA

bool bEnableRxDMA
Enable Rx DMA

qsci_tx_water_t eTxFifoWatermark
TX FIFO watermark

qsci_rx_water_t eRxFifoWatermark
RX FIFO watermark

uint8_t u8Interrupts
Mask of QSCI interrupt sources to enable.

uint32_t u32BaudRateBps
QSCI baud rate

uint32_t u32SrcClockHz
The clock source frequency for QSCI module.

struct __qsci_transfer_handle_t
#include <fsl_qsci.h> QSCI transfer handle.

Note: If user wants to use the transactional API to transfer data in interrupt way, one QSCI instance should and can only be allocated one handle.

Note: The handle is maintained by QSCI driver internally, which means the transfer state is retained and user shall not modify its state u8TxState or u8RxState in application level.

If user only wish to use transactional APIs without understanding its mechanism, it is not necessary to understand these members.

Public Members

QSCI_Type *base

QSCI base pointer to the instance belongs to this handle.

uint8_t *pu8TxData

Address of remaining data to send.

volatile uint32_t u32TxRemainingSize

Size of the remaining data to send.

uint32_t u32TxDataSize

Size of the data to send out.

uint8_t *pu8RxData

Address of remaining data to receive.

volatile uint32_t u32RxRemainingSize

Size of the remaining data to receive.

uint32_t u32RxDataSize

Size of the data to receive.

uint8_t *pu8RxRingBuffer

Start address of the receiver ring buffer.

uint16_t u16RxRingBufferSize

Size of the ring buffer.

volatile uint16_t u16RxRingBufferHead

Index for the driver to store received data into ring buffer.

volatile uint16_t u16RxRingBufferTail

Index for the user to get data from the ring buffer.

qsci_transfer_callback_t pfCallback

Callback function.

void *pUserData

QSCI callback function parameter.

volatile uint8_t u8TxState

TX transfer state.

volatile uint8_t u8RxState

RX transfer state

status_t busStatus

QSCI bus status.

struct __qsci_transfer

#include <fsl_qsci.h> QSCI transfer structure.

Public Members

uint8_t *pu8Data

The buffer pointer of data to be transferred.

uint32_t u32DataSize

The byte count to be transferred.

2.63 The Driver Change Log

2.64 QSCI_EDMA: EDMA based QSCI Driver

```
void QSCI_TransferCreateHandleEDMA(QSCI_Type *base, qsci_edma_transfer_handle_t
                                   *psHandle, qsci_edma_transfer_callback_t pfCallback,
                                   void *pUserData, DMA_Type *edmaBase,
                                   edma_channel_t eEdmaTxChannel, edma_channel_t
                                   eEdmaRxChannel)
```

Initializes the QSCI edma handle.

This function initializes the QSCI edma handle which can be used for other QSCI transactional APIs. Usually, for a specified QSCI instance, call this API once to get the initialized handle.

Parameters

- base – QSCI peripheral base address.
- psHandle – Pointer to qsci_edma_transfer_handle_t structure.
- pfCallback – Callback function.
- pUserData – User data.
- edmaBase – Edma base address.
- eEdmaTxChannel – eDMA channel for TX transfer.
- eEdmaRxChannel – eDMA channel for RX transfer.

```
status_t QSCI_TransferSendEDMA(qsci_edma_transfer_handle_t *psHandle, qsci_transfer_t
                               *psTransfer)
```

Initiate data transmit using EDMA.

This function initiates a data transmit process using eDMA. This is a non-blocking function, which returns right away. When all the data is sent, the send callback function is called.

Parameters

- psHandle – QSCI handle pointer.
- psTransfer – QSCI eDMA transfer structure. See qsci_transfer_t.

Return values

- kStatus_Success – if succeed, others failed.
- kStatus_QSCI_TxBusy – Previous transfer on going.
- kStatus_InvalidArgument – Invalid argument.

```
status_t QSCI_TransferReceiveEDMA(qsci_edma_transfer_handle_t *psHandle, qsci_transfer_t
                                *psTransfer)
```

Initiate data receive using EDMA.

This function initiates a data receive process using eDMA. This is a non-blocking function, which returns right away. When all the data is received, the receive callback function is called.

Parameters

- psHandle – Pointer to *qsci_edma_transfer_handle_t* structure.
- psTransfer – QSCI eDMA transfer structure, see *qsci_transfer_t*.

Return values

- kStatus_Success – if succeed, others fail.
- kStatus_QSCI_RxBusy – Previous transfer ongoing.
- kStatus_InvalidArgument – Invalid argument.

```
void QSCI_TransferAbortSendEDMA(qsci_edma_transfer_handle_t *psHandle)
```

Aborts the data transmit process using EDMA.

Parameters

- psHandle – Pointer to *qsci_edma_transfer_handle_t* structure.

```
void QSCI_TransferAbortReceiveEDMA(qsci_edma_transfer_handle_t *psHandle)
```

Aborts the data receive process using EDMA.

Parameters

- psHandle – Pointer to *qsci_edma_transfer_handle_t* structure.

```
status_t QSCI_TransferGetReceivedCountEDMA(qsci_edma_transfer_handle_t *psHandle,
                                           uint32_t *pu32Count)
```

Gets the number of received bytes.

This function gets the number of received bytes.

Parameters

- psHandle – QSCI handle pointer.
- pu32Count – Receive bytes count.

Return values

- kStatus_NoTransferInProgress – No receive in progress.
- kStatus_Success – Get successfully through the parameter count;

```
status_t QSCI_TransferGetSendCountEDMA(qsci_edma_transfer_handle_t *psHandle, uint32_t
                                       *pu32Count)
```

Gets the number of bytes written to the QSCI TX register.

This function gets the number of bytes written to the QSCI TX register by DMA.

Parameters

- psHandle – QSCI handle pointer.
- pu32Count – Send bytes count.

Return values

- kStatus_NoTransferInProgress – No send in progress.
- kStatus_Success – Get successfully through the parameter count;

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QSCI EDMA driver version.

```
typedef struct _qsci_edma_transfer_handle qsci_edma_transfer_handle_t
```

Forward declaration of the qsci edma handle typedef. .

```
typedef void (*qsci_edma_transfer_callback_t)(qsci_edma_transfer_handle_t *psHandle)
```

QSCI edma transfer callback function definition.

Defines the interface of user callback function used in QSCI edma transfer using transactional APIs. The callback function shall be defined and declared in application level by user. Before starting QSCI transmitting or receiving by calling QSCI_TransferSendEDMA or QSCI_TransferReceiveEDMA, call QSCI_TransferCreateHandleEDMA to install the user callback. When the transmitting or receiving ends, user callback will be invoked by driver.

Param psHandle

Transfer handle that contains bus status, user data.

```
struct _qsci_edma_transfer_handle
```

#include <fsl_qsci_edma.h> QSCI edma transfer handle.

This struct address should be sizeof(edma_channel_tcd_t) aligned.

Note: If user wants to use the transactional API to transfer data in edma way, one QSCI instance should and can only be allocated one handle.

Note: The handle is maintained by QSCI driver internally, which means the transfer state is retained and user shall not modify its state u8TxState or u8RxState in application level. If user only wish to use transactional APIs without understanding its mechanism, it is not necessary to understand these members.

Public Members

edma_channel_tcd_t sTxTcd

TCD for EDMA TX transfer.

edma_channel_tcd_t sRxTcd

TCD for EDMA RX transfer.

QSCI_Type *base

Pointer to the QSCI base that belongs to this handle.

qsci_edma_transfer_callback_t pfCallback

Callback function.

uint32_t u32RxDataSizeAll

Size of the data to receive.

uint32_t u32TxDataSizeAll

Size of the data to send out.

edma_handle_t sTxEdmaHandle

The eDMA TX channel used.

edma_handle_t sRxEdmaHandle

The eDMA RX channel used.

volatile uint8_t u8TxState

TX transfer state.

volatile uint8_t u8RxState

RX transfer state

status_t busStatus

QSCI bus status.

void *pUserData

User configurable pointer to any data, function, structure etc that user wish to use in the callback

2.65 QSCI Peripheral and Driver Overview

2.66 QSPI: Queued SPI Driver

void QSPI_MasterInit(QSPI_Type *base, const *qspi_master_config_t* *psConfig)

Initializes the QUEUEDSPI as Master.

Use helper function QSPI_MasterGetDefaultConfig to get ready-to-use structure.

Parameters

- base – QUEUEDSPI peripheral address.
- psConfig – Pointer to the structure *qspi_master_config_t*.

void QSPI_MasterGetDefaultConfig(*qspi_master_config_t* *psConfig, uint32_t u32ClockFreqHz)

Helper function to create ready-to-user maste init structure.

The purpose of this API is to get the configuration structure initialized for the QSPI_MasterInit. Users may use the initialized structure unchanged in the QSPI_MasterInit or modify the structure before calling the QSPI_MasterInit. Example:

```
qspi_master_config_t sMasterConfig;
QSPI_MasterGetDefaultConfig(&sMasterConfig);
```

The default values are: Example:

```
// Parameter provided by user
psConfig->u32BaudRateBps = u32BaudRateBps;
psConfig->u32ClockFrequencyHz = u32ClockFreqHz;
psConfig->eDataWidth = eDataWidth;

// Default configuration
psConfig->eClkPolarity = kQSPI_ClockPolarityActiveRisingEdge;
psConfig->eClkPhase = kQSPI_ClockPhaseSlaveSelectHighBetweenWords;
psConfig->eShiftDirection = kQSPI_MsbFirst;
psConfig->u16DelayBetweenFrameInCLK = 1U;
psConfig->bEnableWiredOrMode = false;
psConfig->bEnableModeFault = false;
psConfig->u8DmaEnableFlags = 0U; // Disable TX/RX Dma
psConfig->bEnableFIFO = false;
psConfig->bEnableStopModeHoldOff = false;
psConfig->u8Interrupts = 0U;
psConfig->bEnableModule = false;
@todo To be added
```

Parameters

- psConfig – pointer to `qspi_master_config_t` structure.
- u32ClockFreqHz – Peripheral clock frequency in Hz

`void QSPI_SlaveInit(QSPI_Type *base, const qspi_slave_config_t *psConfig)`

Initializes the QUEUEDSPI as slave.

Use helper function `QSPI_SlaveGetDefaultConfig` to get ready-to-use structure.

Parameters

- base – QUEUEDSPI peripheral address.
- psConfig – Pointer to the structure `qspi_slave_config_t`.

`void QSPI_SlaveGetDefaultConfig(qspi_slave_config_t *psConfig)`

Set the `qspi_slave_config_t` structure to default values.

The purpose of this API is to get the configuration structure initialized for the `QSPI_SlaveInit`. Users may use the initialized structure unchanged in the `QSPI_SlaveInit` or modify the structure before calling the `QSPI_SlaveInit`. Example:

```
qspi_slave_config_t slaveConfig;  
QSPI_SlaveGetDefaultConfig(&slaveConfig);
```

The default values are: Example:

```
@todo
```

Parameters

- psConfig – Pointer to the `qspi_slave_config_t` structure.

`void QSPI_Deinit(QSPI_Type *base)`

De-initialize the QUEUEDSPI peripheral for either Master or Slave.

Parameters

- base – QUEUEDSPI peripheral address.

`static inline void QSPI_EnableInterrupts(QSPI_Type *base, uint8_t u8Interrupts)`

Enable one or multiple interrupts.

This function enable one or multiple interrupts.

Note: for TX and RX requests, while enabling the interrupt request the DMA request will be disabled as well. Do not use this API while QUEUEDSPI is in running state.

Parameters

- base – QUEUEDSPI peripheral address.
- u8Interrupts – The interrupt mask which is ORed by the `_qspi_interrupt_enable`.

`static inline void QSPI_DisableInterrupts(QSPI_Type *base, uint8_t u8Interrupts)`

Disable one or multiple interrupts.

This function

Parameters

- base – QUEUEDSPI peripheral address.
- u8Interrupts – The interrupt mask which is ORed by the `_qspi_interrupt_enable`.

```
static inline void QSPI_EnableDMA(QSPI_Type *base, uint8_t u8DmaFlags)
```

Enable one or multiple DMA.

Note that if the DMA is enabled for Transmit or Receive, make sure the interrupt is disabled for Transmit or Receive.

Parameters

- base – QUEUEDSPI peripheral address.
- u8DmaFlags – DMA Flags ORed from _qspi_dma_enable_flags.

```
static inline void QSPI_DisableDMA(QSPI_Type *base, uint8_t u8DmaFlags)
```

Enable one or multiple DMA.

Note that if the DMA is enabled for Transmit or Receive, make sure the interrupt is disabled for Transmit or Receive.

Parameters

- base – QUEUEDSPI peripheral address.
- u8DmaFlags – DMA Flags ORed from _qspi_dma_enable_flags.

```
static inline uint32_t QSPI_GetTxRegisterAddress(QSPI_Type *base)
```

Get the QUEUEDSPI transmit data register address for the DMA operation.

Parameters

- base – QUEUEDSPI peripheral address.

Returns

The QUEUEDSPI master PUSHR data register address.

```
static inline uint32_t QSPI_GetRxRegisterAddress(QSPI_Type *base)
```

Get the QUEUEDSPI receive data register address for the DMA operation.

Parameters

- base – QUEUEDSPI peripheral address.

Returns

The QUEUEDSPI POPR data register address.

```
static inline uint16_t QSPI_GetStatusFlags(QSPI_Type *base)
```

Get the QUEUEDSPI status flag state.

Parameters

- base – QUEUEDSPI peripheral address.

Returns

QUEUEDSPI status.

```
static inline void QSPI_ClearStatusFlags(QSPI_Type *base, uint16_t u16StatusFlags)
```

Clear the status flag only for the mode fault.

Clear the status flag only for mode fault.

Note: only kQSPI_ModeFaultFlag can be cleared by this API.

Parameters

- base – QUEUEDSPI peripheral address.
- u16StatusFlags – status flags ORed from _qspi_status_flags

```
static inline void QSPI_Enable(QSPI_Type *base, bool bEnable)
```

Enable or disable the QUEUEDSPI peripheral.

Parameters

- base – QUEUEDSPI peripheral address.
- bEnable – true to enable module, otherwise disable module

```
uint32_t QSPI_MasterSetBaudRate(QSPI_Type *base, uint32_t u32BaudRateBps, uint32_t  
                                u32SrcClockHz)
```

Set the QUEUEDSPI baud rate in bits-per-second.

This function takes in the desired baud rate, calculates the nearest possible baud rate, and returns the calculated baud rate in bits-per-second.

Parameters

- base – QUEUEDSPI peripheral address.
- u32BaudRateBps – The desired baud rate in bits-per-second.
- u32SrcClockHz – Module source input clock in Hertz.

Returns

The actual calculated baud rate.

```
static inline void QSPI_SetMasterSlaveMode(QSPI_Type *base, qspi_master_slave_mode_t  
                                           eMode)
```

Set the QUEUEDSPI as master or slave.

Parameters

- base – QUEUEDSPI peripheral address.
- eMode – Mode setting of type qspi_master_slave_mode_t.

```
static inline bool QSPI_IsMaster(QSPI_Type *base)
```

Return whether the QUEUEDSPI module is in master mode.

Parameters

- base – QUEUEDSPI peripheral address.

Returns

Returns true if the module is in master mode or false if the module is in slave mode.

```
static inline void QSPI_SetDataShiftOrder(QSPI_Type *base, qspi_data_shift_direction_t  
                                           eDataShiftOrder)
```

Set Data Shift Order as MSB first or LSB first.

Parameters

- base – QUEUEDSPI peripheral address.
- eDataShiftOrder – MSB or LSB first from qspi_data_shift_direction_t

```
static inline void QSPI_EnableModeFault(QSPI_Type *base, bool bEnable)
```

Enable/Disable mode fault detection.

If enable, allows the kQSPI_ModeFaultFlag flag to be set. If the kQSPI_ModeFaultFlag flag is set, disable the Mod detection does not clear the flag. If the mod detection is disabled, the level of the SS_B pin does not affect the operation of an enabled SPI configured as a master. If configured as a master and mod fault detection is enabled, a transaction in progress will stop if SS_B goes low. For an enabled SPI configured as a slave, having this feature disabled only prevents the flag from being set. It does not affect any other part of SPI operation

Parameters

- base – QUEUEDSPI peripheral address.
- bEnable – true to enable Mode Fault detection, false to disable

static inline void QSPI_SetClockPolarity(QSPI_Type *base, *qspi_clock_polarity_t* ePolarity)
Set clock polarity.

Note: module shall be disabled before change the polarity by calling QSPI_Enable.

Parameters

- base – QUEUEDSPI peripheral address.
- ePolarity – clock polarity option

static inline void QSPI_SetClockPhase(QSPI_Type *base, *qspi_clock_phase_t* eClockPhase)
Set clock phase.

Configure whether get the Slave Select signal toggle high during 2 data frames. Get the SS toggle high between data frames will lead to SPI to be triggered with transaction for the falling edge of SS signal. Otherwise, the data transaction is started on the first active SCLK edge.

Note: module shall be disabled before change the polarity by calling QSPI_Enable.

Note: Do not use kQSPI_ClockPhaseSlaveSelectHighBetweenWords in DMA mode.

Parameters

- base – QUEUEDSPI peripheral address.
- eClockPhase – Option for clock phase

static inline void QSPI_EnableWiredORMode(QSPI_Type *base, bool bEnable)

Enable/Disable Wired OR mode for SPI pins which means open-drain when enabled and push-pull when disabled.

Parameters

- base – QUEUEDSPI peripheral address.
- bEnable – true to configure SPI pins as open-drain, false to configure as push-pull

static inline void QSPI_SetTransactionDataSize(QSPI_Type *base, *qspi_data_width_t* eDataWidth)
Set the transaction data width.

Parameters

- base – QUEUEDSPI peripheral address.
- eDataWidth – datawidth for bits in each data frame.

static inline void QSPI_MasterSetWaitDelay(QSPI_Type *base, uint16_t
u16WaitDelayInPeriClockCount)

For master mode, set wait delay in clock cycle with delay is set value + 1 peripheral bus clock.

This controls the time between data transactions in master mode. Delay will not be added if no word is waiting for transmitting.

Parameters

- base – QUEUEDSPI peripheral address.
- u16WaitDelayInPeriClockCount – Clock count for the delay during data frames

static inline void QSPI_EnableStopModeHoldOff(QSPI_Type *base, bool bEnable)

Enable/Disable hold off entry to stop mode is a word is being transmitted/received for Master Mode.

When enabled, this bit allows the SPI module to hold off entry to chip level stop mode if a word is being transmitted or received. Stop mode will be entered after the SPI finishes transmitting/receiving. This bit does not allow the SPI to wake the chip from stop mode in any way. The SHEN bit can only delay the entry into stop mode. This bit should not be set in slave mode because the state of SS_B (which would be controlled by an external master device) may cause the logic to hold off stop mode entry forever.

Parameters

- base – QUEUEDSPI peripheral address.
- bEnable – true to enable hold-off entrying stop mode if there is transmitting/receiving

uint32_t QSPI_GetInstance(QSPI_Type *base)

Helper function exported for QSPI DMA driver.

Get the instance index from the base address. User need not understand this function.

Parameters

- base – QUEUEDSPI peripheral address.

Returns

uint32_t Index of the peripheral instance for given base address.

static inline *qspi_ss_data_logic_level_t* QSPI_MasterGetSlaveSelectLogicLevel(QSPI_Type *base)

For master mode, get the SS_B input logic level while true means drive High and false means drive Low.

Get the value to drive on the SS_B pin. This bit is disabled when SSB_AUTO=1 or SSB_STRB=1. Only apply for Master mode.

Parameters

- base – QUEUEDSPI peripheral address.

Returns

true SS_B input level High

Returns

false SS_B input level Low

static inline void QSPI_MasterSetSlaveSelectLogicLevel(QSPI_Type *base,
qspi_ss_data_logic_level_t eLogicLevel)

for master mode, drive Slave Select pin logic high or low

This feature is disabled if Slave Select automatic mode is enabled or Slave Select Strobe feature is enabled

Parameters

- base – QUEUEDSPI peripheral address.
- eLogicLevel – logic level

static inline void QSPI_MasterEnableSlaveSelectOpenDrainMode(QSPI_Type *base, bool bEnable)

For master mode, Enable open drain in SSB pad pin.

Enable it means SS_B is configured for high and low drive. This mode is generally used in single master systems. Disable it means SS_B is configured as an open drain pin (only drives low output level). This mode is useful for multiple master systems

Parameters

- base – QUEUEDSPI peripheral address.
- bEnable – Enable/Disable option.

static inline void QSPI_MasterEnableSlaveSelectAutomaticMode(QSPI_Type *base, bool bEnable)

For master mode, Enable/Disable Slave Select pin automatic mode.

Parameters

- base – QUEUEDSPI peripheral address.
- bEnable – Enable/Disable option.

static inline void QSPI_SetSlaveSelectDirection(QSPI_Type *base, *qspi_ss_direction_t* eDirection)

Set Input/Output mode for SSB signal.

Parameters

- base – QUEUEDSPI peripheral address.
- eDirection – options from *qspi_ss_direction_t*

static inline void QSPI_MasterEnableSlaveSelectStrobe(QSPI_Type *base, bool bEnable)

For master, set strobe mode for SSB signal.

If enabled, Slave select pulse high during data frames irrespective of Clock Phase configuration

Parameters

- base – QUEUEDSPI peripheral address.
- bEnable – Enable/Disable option.

static inline void QSPI_EnableSlaveSelectOverride(QSPI_Type *base, bool bEnable)

Enable / Disable SSB signal from Master/Slave configuration or GPIO pin state.

Parameters

- base – QUEUEDSPI peripheral address.
- bEnable – Enable/Disable option.

void QSPI_SetDummyData(QSPI_Type *base, uint8_t u8DummyData)

Set up the dummy data used when there is not transmit data provided.

Parameters

- base – QUEUEDSPI peripheral address.
- u8DummyData – Data to be transferred when tx buffer is NULL.

uint8_t QSPI_GetDummyData(QSPI_Type *base)

Get the dummy data for each peripheral.

Parameters

- base – QUEUEDSPI peripheral base address.

```
static inline void QSPI_WriteData(QSPI_Type *base, uint16_t data)
```

Write data into the transmit data register without polling the status of shifting.

Parameters

- base – QUEUEDSPI peripheral address.
- data – The data to send.

```
static inline uint16_t QSPI_ReadData(QSPI_Type *base)
```

Read data from the receive data register.

Parameters

- base – QUEUEDSPI peripheral address.

Returns

The data from the receive data register.

```
static inline void QSPI_EnableFifo(QSPI_Type *base, bool bEnable)
```

Enable or disable the QUEUEDSPI FIFOs.

This function allows the caller to disable or enable the TX and RX FIFOs together.

Parameters

- base – QUEUEDSPI peripheral address.
- bEnable – Pass true to enable, pass false to disable

```
static inline uint16_t QSPI_GetTxFIFOCount(QSPI_Type *base)
```

Get TX FIFO level.

This function gets how many words are in the TX FIFO.

Parameters

- base – QUEUEDSPI peripheral address.

Returns

TX FIFO word count.

```
static inline uint16_t QSPI_GetRxFIFOCount(QSPI_Type *base)
```

Get RX FIFO level.

This function gets how many words are in the RX FIFO.

Parameters

- base – QUEUEDSPI peripheral address.

Returns

RX FIFO word count.

```
static inline void QSPI_SetFifoWatermarks(QSPI_Type *base, uint16_t txWatermark, uint16_t rxWatermark)
```

Set the transmit and receive FIFO watermark values.

Parameters

- base – QUEUEDSPI peripheral address.
- txWatermark – The TX FIFO watermark value. Refer to `qspi_txfifo_watermark_t` for available values.
- rxWatermark – The RX FIFO watermark value. Refer to `qspi_rxfifo_watermark_t` for available values.


```
static inline void QSPI_GetFifoWatermarks(QSPI_Type *base, uint8_t *pu8TxWatermark, uint8_t *pu8RxWatermark)
```

Get the transmit and receive FIFO watermark values.

Parameters

- base – QUEUEDSPI peripheral address.
- pu8TxWatermark – The TX FIFO watermark value.
- pu8RxWatermark – The RX FIFO watermark value.

```
static inline void QSPI_EmptyRxFifo(QSPI_Type *base)
```

Empty the QUEUEDSPI RX FIFO.

Parameters

- base – QUEUEDSPI peripheral address.

```
void QSPI_MasterTransferCreateHandle(QSPI_Type *base, qspi_master_transfer_handle_t *psHandle, qspi_master_transfer_callback_t pfCallback, void *pUserData)
```

Initialize the QUEUEDSPI master handle.

This function initializes the QUEUEDSPI handle, which can be used for other QUEUEDSPI transactional APIs. Usually, for a specified QUEUEDSPI instance, call this API once to get the initialized handle.

Note: If only use the QSPI_MasterTransferBlocking, this API is not necessary be called.

Parameters

- base – QUEUEDSPI peripheral address.
- psHandle – QUEUEDSPI handle pointer to qspi_master_transfer_handle_t.
- pfCallback – QUEUEDSPI callback.
- pUserData – Callback function parameter.

```
status_t QSPI_MasterTransferBlocking(QSPI_Type *base, qspi_transfer_t *psXfer)
```

Polling method of QUEUEDSPI master transfer.

This function transfers data using a polling method for master. This is a blocking function, which does not return until all transfers have been completed.

Parameters

- base – QUEUEDSPI peripheral address.
- psXfer – Pointer to the qspi_transfer_t structure.

Returns

status of status_t.

```
status_t QSPI_MasterTransferNonBlocking(qspi_master_transfer_handle_t *psHandle, qspi_transfer_t *psXfer)
```

Interrupt method of QUEUEDSPI master transfer.

This function transfers data using interrupts for master. This is a non-blocking function, which returns right away. When all data is transferred, the callback function is called.

Parameters

- psHandle – QUEUEDSPI handle pointer to qspi_master_transfer_handle_t.
- psXfer – Pointer to the qspi_transfer_t structure.

Returns

status of status_t.

status_t QSPI_MasterTransferGetCount(*qspi_master_transfer_handle_t* *psHandle, uint16_t *pu16Count)

Get the master transfer count.

Parameters

- psHandle – QUEUEDSPI handle pointer to qspi_master_transfer_handle_t.
- pu16Count – The number of bytes transferred by using the non-blocking transaction.

Returns

status of status_t.

void QSPI_MasterTransferAbort(*qspi_master_transfer_handle_t* *psHandle)

Abort a transfer that uses interrupts for master.

Parameters

- psHandle – QUEUEDSPI handle pointer to qspi_master_transfer_handle_t.

void QSPI_MasterTransferHandleIRQ(*qspi_master_transfer_handle_t* *psHandle)

QUEUEDSPI Master IRQ handler function.

This function processes the QUEUEDSPI transmit and receive IRQ.

Parameters

- psHandle – QUEUEDSPI handle pointer to qspi_master_transfer_handle_t.

void QSPI_SlaveTransferCreateHandle(QSPI_Type *base, *qspi_slave_transfer_handle_t* *psHandle, *qspi_slave_transfer_callback_t* pfCallback, void *pUserData)

Initialize the QUEUEDSPI slave handle.

This function initializes the QUEUEDSPI handle, which can be used for other QUEUEDSPI transactional APIs. Usually, for a specified QUEUEDSPI instance, call this API once to get the initialized handle.

Parameters

- base – QUEUEDSPI peripheral base address.
- psHandle – QUEUEDSPI handle pointer to the qspi_slave_transfer_handle_t.
- pfCallback – QUEUEDSPI callback.
- pUserData – Callback function parameter.

status_t QSPI_SlaveTransferNonBlocking(*qspi_slave_transfer_handle_t* *psHandle, *qspi_transfer_t* *psXfer)

Interrupt driven method of QUEUEDSPI slave transfer with completion will be notified by registered callback.

This function transfers data using interrupts for slave. This is a non-blocking function, which returns right away. When all data is transferred, the callback function is called.

Parameters

- psHandle – Pointer to the qspi_slave_transfer_handle_t structure which stores the transfer state.
- psXfer – Pointer to the qspi_transfer_t structure.

Returns

status of status_t.

status_t QSPI_SlaveTransferGetCount(*qspi_slave_transfer_handle_t* *psHandle, uint16_t *pu16Count)

Get the slave transfer count already transmitted/received.

Parameters

- psHandle – Pointer to the *qspi_slave_transfer_handle_t* structure which stores the transfer state.
- pu16Count – The number of bytes transferred by using the non-blocking transaction.

Returns

status of *status_t*.

void QSPI_SlaveTransferAbort(*qspi_slave_transfer_handle_t* *psHandle)

Abort a transaction.

Parameters

- psHandle – Pointer to the *qspi_slave_transfer_handle_t* structure which stores the transfer state.

void QSPI_SlaveTransferHandleIRQ(*qspi_slave_transfer_handle_t* *psHandle)

QUEUEDSPI slave IRQ handler function.

This function processes the QUEUEDSPI transmit and receive IRQ.

Parameters

- psHandle – Pointer to the *qspi_slave_transfer_handle_t* structure which stores the transfer state.

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QSPI_TRANSFER_GET_BASE(handle)

Extract Base Address from handle for master or slave handle.

QSPI_TRANSFER_GET_USER_DATA(handle)

Extract user data from handle for master or slave handle.

Status return code for the QUEUEDSPI driver. Only used in transactional layer in this driver.

.

Values:

enumerator kStatus_QSPI_Busy

QUEUEDSPI transfer is busy.

enumerator kStatus_QSPI_Error

QUEUEDSPI driver error.

enumerator kStatus_QSPI_Idle

QUEUEDSPI is idle.

enumerator kStatus_QSPI_OutOfRange

QUEUEDSPI transfer out of range.

enum *_qspi_status_flags*

QUEUEDSPI peripheral status flags.

Values:

enumerator kQSPI_TxEmptyFlag
Transmitter Empty Flag.

enumerator kQSPI_ModeFaultFlag
Mode Fault Flag.

enumerator kQSPI_RxOverflowFlag
Receiver Overflow Flag.

enumerator kQSPI_RxFullFlag
Receiver Full Flag.

enumerator kQSPI_AllStatusFlags

enum _qspi_interrupt_enable
QUEUEDSPI interrupt source.

Values:

enumerator kQSPI_TxInterruptEnable
SPTE interrupt enable.

enumerator kQSPI_RxInterruptEnable
SPRF interrupt enable.

enumerator kQSPI_RxOverflowInterruptEnable
Bus error interrupt enable.

enumerator kQSPI_AllInterrupts

enum _qspi_ss_direction
options for Slave Select (SSB) signal direction.

Values:

enumerator kQSPI_SlaveSelectDirectionInput
SSB signal as input for slave mode or master mode with Mode fault enabled.

enumerator kQSPI_SlaveSelectDirectionOutput
SSB signal as output.

enum _qspi_ss_data_logic_level
logical level for Slave Select (SSB) signal data

Values:

enumerator kQSPI_SlaveSelectLogicLow
Slave select logic level low

enumerator kQSPI_SlaveSelectLogicHigh
Slave select logic level high

enum _qspi_txfifo_watermark
QUEUEDSPI Transmit FIFO watermark settings.

Values:

enumerator kQSPI_TxFifoWatermarkEmpty
Transmit interrupt active when Tx FIFO is empty

enumerator kQSPI_TxFifoWatermarkOneWord
Transmit interrupt active when Tx FIFO has one or fewer words available

enumerator kQSPI_TxFifoWatermarkTwoWord
Transmit interrupt active when Tx FIFO has two or fewer words available

enumerator kQSPI_TxFifoWatermarkThreeWord

Transmit interrupt active when Tx FIFO has three or fewer words available

enum __qspi_rxfifo_watermark

QUEUEDSPI Receive FIFO watermark settings.

Values:

enumerator kQSPI_RxFifoWatermarkOneWord

Receive interrupt active when Rx FIFO has at least one word used

enumerator kQSPI_RxFifoWatermarkTwoWord

Receive interrupt active when Rx FIFO has at least two words used

enumerator kQSPI_RxFifoWatermarkThreeWord

Receive interrupt active when Rx FIFO has at least three words used

enumerator kQSPI_RxFifowatermarkFull

Receive interrupt active when Rx FIFO is full

enum __qspi_data_width

Transfer data width in each frame.

Values:

enumerator kQSPI_Data2Bits

2 bits data width

enumerator kQSPI_Data3Bits

3 bits data width

enumerator kQSPI_Data4Bits

4 bits data width

enumerator kQSPI_Data5Bits

5 bits data width

enumerator kQSPI_Data6Bits

6 bits data width

enumerator kQSPI_Data7Bits

7 bits data width

enumerator kQSPI_Data8Bits

8 bits data width

enumerator kQSPI_Data9Bits

9 bits data width

enumerator kQSPI_Data10Bits

10 bits data width

enumerator kQSPI_Data11Bits

11 bits data width

enumerator kQSPI_Data12Bits

12 bits data width

enumerator kQSPI_Data13Bits

13 bits data width

enumerator kQSPI_Data14Bits

14 bits data width

enumerator kQSPI_Data15Bits
15 bits data width

enumerator kQSPI_Data16Bits
16 bits data width

enum __qspi_dma_enable_flags
QUEUEDSPI DMA configuration for Transmit and Receive.
Values:

enumerator kQSPI_DmaRx
Receive DMA Enable Flag.

enumerator kQSPI_DmaTx
Transmit DMA Enable Flag.

enum __qspi_master_slave_mode
QUEUEDSPI master or slave mode configuration.
Values:

enumerator kQSPI_Slave
QUEUEDSPI peripheral operates in slave mode.

enumerator kQSPI_Master
QUEUEDSPI peripheral operates in master mode.

enum __qspi_clock_polarity
QUEUEDSPI clock polarity configuration.
Values:

enumerator kQSPI_ClockPolarityActiveRisingEdge
CPOL=0. Active-high QUEUEDSPI clock (idles low), rising edge of SCLK starts transaction.

enumerator kQSPI_ClockPolarityActiveFallingEdge
CPOL=1. Active-low QUEUEDSPI clock (idles high), falling edge of SCLK starts transaction.

enum __qspi_clock_phase
QUEUEDSPI clock phase configuration.
Values:

enumerator kQSPI_ClockPhaseSlaveSelectHighBetweenWords
CPHA=0, Slave Select toggle high during data frames.

enumerator kQSPI_ClockPhaseSlaveSelectLowBetweenWords
CPHA=1, Slave Select keep low during data frames.

enum __qspi_data_shift_direction
QUEUEDSPI data shifter direction options for a given CTAR.
Values:

enumerator kQSPI_MsbFirst
Data transfers start with most significant bit.

enumerator kQSPI_LsbFirst
Data transfers start with least significant bit.

enum `_qspi_pcs_polarity_config`

QUEUEDSPI Peripheral Chip Select Polarity configuration.

Values:

enumerator `kQSPI_PcsActiveHigh`

Pcs Active High (idles low).

enumerator `kQSPI_PcsActiveLow`

Pcs Active Low (idles high).

enum `_qspi_master_transfer_flag`

transaction layer configuration options for each transaction

Values:

enumerator `kQSPI_MasterPCSContinuous`

Indicates whether the PCS signal de-asserts during transfer between frames, note this flag should not be used when CPHA is 0.

enumerator `kQSPI_MasterActiveAfterTransfer`

Indicates whether the PCS signal is active after the last frame transfer, note 1. this flag should not be used when CPHA is 0, 2. this flag can only be used when `kQSPI_MasterPCSContinuous` is used.

enum `_qspi_transfer_state`

QUEUEDSPI transfer state, used internally for transactional layer.

Values:

enumerator `kQSPI_Idle`

Nothing in the transmitter/receiver.

enumerator `kQSPI_Busy`

Transfer queue is not finished.

enumerator `kQSPI_Error`

Transfer error.

typedef enum `_qspi_ss_direction` `qspi_ss_direction_t`

options for Slave Select (SSB) signal direction.

typedef enum `_qspi_ss_data_logic_level` `qspi_ss_data_logic_level_t`

logical level for Slave Select (SSB) signal data

typedef enum `_qspi_txfifo_watermark` `qspi_txfifo_watermark_t`

QUEUEDSPI Transmit FIFO watermark settings.

typedef enum `_qspi_rxfifo_watermark` `qspi_rxfifo_watermark_t`

QUEUEDSPI Receive FIFO watermark settings.

typedef enum `_qspi_data_width` `qspi_data_width_t`

Transfer data width in each frame.

typedef enum `_qspi_master_slave_mode` `qspi_master_slave_mode_t`

QUEUEDSPI master or slave mode configuration.

typedef enum `_qspi_clock_polarity` `qspi_clock_polarity_t`

QUEUEDSPI clock polarity configuration.

typedef enum `_qspi_clock_phase` `qspi_clock_phase_t`

QUEUEDSPI clock phase configuration.

```
typedef enum _qspi_data_shift_direction qspi_data_shift_direction_t
```

QUEUEDSPI data shifter direction options for a given CTAR.

```
typedef struct _qspi_master_config qspi_master_config_t
```

QUEUEDSPI master configuration structure with all master configuration fields covered.

```
typedef struct _qspi_slave_config qspi_slave_config_t
```

QUEUEDSPI slave configuration structure with all slave configuration fields covered.

```
typedef enum _qspi_pcs_polarity_config qspi_pcs_polarity_config_t
```

QUEUEDSPI Peripheral Chip Select Polarity configuration.

```
typedef struct _qspi_transfer qspi_transfer_t
```

QUEUEDSPI master/slave transfer structure.

```
typedef struct _qspi_master_handle qspi_master_transfer_handle_t
```

Forward declaration of the *_qspi_master_handle* typedefs. .

```
typedef void (*qspi_master_transfer_callback_t)(qspi_master_transfer_handle_t *psHandle,  
status_t eCompletionStatus, void *pUserData)
```

Completion callback function pointer type.

Param base

QUEUEDSPI peripheral address.

Param psHandle

Pointer to the handle for the QUEUEDSPI master.

Param eCompletionStatus

Success or error code describing whether the transfer completed.

Param pUserData

Arbitrary pointer-dataSized value passed from the application.

```
typedef struct _qspi_slave_transfer_handle qspi_slave_transfer_handle_t
```

Forward declaration of the *_qspi_slave_transfer_handle* typedefs. .

```
typedef void (*qspi_slave_transfer_callback_t)(qspi_slave_transfer_handle_t *psHandle, status_t  
eCompletionStatus, void *pUserData)
```

Completion callback function pointer type.

Param base

QUEUEDSPI peripheral address.

Param handle

Pointer to the handle for the QUEUEDSPI slave.

Param status

Success or error code describing whether the transfer completed.

Param pUserData

Arbitrary pointer-dataSized value passed from the application.

```
QSPI_DUMMY_DATA
```

User Configuraiton item dummy data filled into Output signal if there is no Tx data.

Dummy data used for Tx if there is no txData.

```
struct _qspi_master_config
```

#include <fsl_queued_spi.h> QUEUEDSPI master configuration structure with all master configuration fields covered.

Public Members

`uint32_t u32BaudRateBps`
Baud Rate for QUEUEDSPI.

`qspi_data_width_t eDataWidth`
Data width in SPI transfer

`qspi_clock_polarity_t eClkPolarity`
Clock polarity.

`qspi_clock_phase_t eClkPhase`
Clock phase.

`qspi_data_shift_direction_t eShiftDirection`
MSB or LSB data shift direction.

`bool bEnableWiredOrMode`
SPI pin configuration, when enabled the SPI pins are configured as open-drain drivers with the pull-ups disabled.

`bool bEnableModeFault`
Enable/Disable mode fault detect for Slave Select Signal

`bool bEnableStrobe`
Enable/Disable strobe between data frames irrespective of clock pahse setting

`bool bEnableSlaveSelAutoMode`
Enable/Disable Slave Select Auto mode.

`bool bEnableSlaveSelOpenDrain`
Enable the open-drain mode of SPI Pins, otherwise Push-Pull

`uint16_t u16DelayBetweenFrameInCLK`
The delay between frame.

`bool bEnableFIFO`
Enable / Disable FIFO for Transmit/Receive

`qspi_txfifo_watermark_t eTxFIFOWatermark`
Watermark config for Transmit FIFO

`qspi_txfifo_watermark_t eRxFIFOWatermark`
Watermark config for Receive FIFO

`bool bEnableModule`
Enable / Disable module

`uint8_t u8Interrupts`
Interrupt enabled ORed from `_qspi_interrupt_enable`

`uint8_t u8DmaEnableFlags`
Configure DMA Enable/Disable for Transmit/Receive

`struct _qspi_slave_config`
`#include <fsl_queued_spi.h>` QUEUEDSPI slave configuration structure with all slave configuration fields covered.

Public Members

`qspi_data_width_t eDataWidth`
Data width in SPI transfer

qspi_clock_polarity_t eClkPolarity

Clock polarity.

qspi_clock_phase_t eClkPhase

Clock phase.

qspi_data_shift_direction_t eShiftDirection

MSB or LSB data shift direction.

bool bEnableWiredOrMode

SPI pin configuration, when enabled the SPI pins are configured as open-drain drivers with the pull-ups disabled.

bool bEnableModeFault

Enable/Disable mode fault detect for Slave Select Signal

bool bEnableSlaveSelOverride

Enable/Disable override Slave Select (SS) signal with Master/Slave Mode config

bool bEnableFIFO

Enable / Disable FIFO for Transmit/Receive

qspi_txfifo_watermark_t eTxFIFOWatermark

Watermark config for Transmit FIFO

qspi_rxfifo_watermark_t eRxFIFOWatermark

Watermark config for Receive FIFO

bool bEnableModule

Enable/Disable Module

uint8_t u8DmaEnableFlags

Configure DMA Enable/Disable for Transmit/Receive

struct __qspi_transfer

#include <fsl_queued_spi.h> QUEUEDSPI master/slave transfer structure.

Public Members

void *pTxData

Transmit buffer.

void *pRxData

Receive buffer.

volatile uint16_t u16DataSize

Transfer bytes.

uint8_t u8ConfigFlags

Transfer configuration flags; set from *__qspi_master_transfer_flag*. This is not used in slave transfer.

struct __qspi_master_handle

#include <fsl_queued_spi.h> QUEUEDSPI master transfer handle structure used for transactional API.

Public Members

QSPI_Type *base

Base address for the QSPI peripheral

qspi_data_width_t eDataWidth

The desired number of bits per frame.

volatile bool bIsPcsActiveAfterTransfer

Indicates whether the PCS signal is active after the last frame transfer, This is not used in slave transfer.

uint8_t *volatile pu8TxData

Send buffer.

uint8_t *volatile pu8RxData

Receive buffer.

volatile uint16_t u16RemainingSendByteCount

A number of bytes remaining to send.

volatile uint16_t u16RemainingReceiveByteCount

A number of bytes remaining to receive.

uint16_t u16TotalByteCount

A number of transfer bytes

volatile uint8_t u8State

QUEUEDSPI transfer state, see *_qspi_transfer_state*.

qspi_master_transfer_callback_t pfCallback

Completion callback.

void *pUserData

Callback user data.

volatile uint16_t u16ErrorCount

Error count for slave transfer, this is not used in master transfer.

2.67 QSPI Peripheral and Driver Overview

2.68 QSPI_EDMA: EDMA based QSPI Driver

FSL_QSPI_EDMA_DRIVER_VERSION

QSPI EDMA driver version.

typedef struct *_qspi_master_edma_handle* qspi_master_edma_handle_t

Forward declaration of the *_qspi_master_edma_handle* typedefs.

typedef struct *_qspi_master_edma_handle* qspi_slave_edma_handle_t

Forward declaration of the *_qspi_master_edma_handle* typedefs.

typedef void (*qspi_edma_transfer_callback_t)(*qspi_master_edma_handle_t* *psHandle, *status_t* eCompletionStatus, void *pUserData)

Completion callback function pointer type.

Param base

QUEUEDSPI peripheral base address.

Param psHandle

Pointer to the handle for the QUEUEDSPI master.

Param eCompletionStatus

Success or error code describing whether the transfer completed.

Param pUserData

Arbitrary pointer-dataSized value passed from the application.

```
void QSPI_MasterTransferCreateHandleEDMA(QSPI_Type *base, qspi_master_edma_handle_t
                                         *psHandle, qspi_edma_transfer_callback_t
                                         pfCallback, void *pUserData, DMA_Type
                                         *psEdmaBase, edma_channel_t eEdmaTxChannel,
                                         edma_channel_t eEdmaRxChannel)
```

Initialize the QUEUEDSPI master EDMA handle.

This function initializes the QUEUEDSPI EDMA master handle which can be used for QUEUEDSPI EDMA master transactional APIs. Usually, for a specified QUEUEDSPI instance, call this API once to get the initialized handle.

Parameters

- base – QUEUEDSPI peripheral base address.
- psHandle – QUEUEDSPI handle pointer to qspi_master_edma_handle_t.
- pfCallback – QUEUEDSPI callback.
- pUserData – callback function parameter.
- psEdmaBase – base address for the EDMA
- eEdmaTxChannel – Channel of the EDMA used for QSPI Tx
- eEdmaRxChannel – Channel of the EDMA used for QSPI Rx

```
status_t QSPI_MasterTransferEDMA(qspi_master_edma_handle_t *psHandle, qspi_transfer_t
                                 *psXfer)
```

EDMA method of QUEUEDSPI master transfer.

This function transfers data using EDMA. This is a non-blocking function, which returns right away. When all data is transferred, the callback function is called.

Note: : The transfer data size should be even, if the transfer data width is larger than 8.

Parameters

- psHandle – pointer to qspi_master_edma_handle_t structure which stores the transfer state.
- psXfer – pointer to qspi_transfer_t structure.

Returns

status of status_t.

```
status_t QSPI_MasterTransferGetCountEDMA(qspi_master_edma_handle_t *psHandle, uint16_t
                                         *pu16Count)
```

Get the master EDMA transfer count.

Parameters

- psHandle – Pointer to the qspi_master_edma_handle_t structure which stores the transfer state.
- pu16Count – The number of bytes transferred by using the EDMA transaction.

Returns

status of status_t.

`void QSPI_MasterTransferAbortEDMA(qspi_master_edma_handle_t *psHandle)`

Abort a transfer that uses EDMA for master.

Parameters

- `psHandle` – Pointer to the `qspi_master_edma_handle_t` structure which stores the transfer state.

`void QSPI_SlaveTransferCreateHandleEDMA(QSPI_Type *base, qspi_slave_edma_handle_t *psHandle, qspi_edma_transfer_callback_t pfCallback, void *pUserData, DMA_Type *psEdmaBase, edma_channel_t eEdmaTxChannel, edma_channel_t eEdmaRxChannel)`

Initialize the QUEUEDSPI slave EDMA handle.

This function initializes the QUEUEDSPI EDMA handle which can be used for other QUEUEDSPI transactional APIs. Usually, for a specified QUEUEDSPI instance, call this API once to get the initialized handle.

Parameters

- `base` – QUEUEDSPI peripheral base address.
- `psHandle` – QUEUEDSPI handle pointer to `qspi_slave_edma_handle_t`.
- `pfCallback` – QUEUEDSPI callback.
- `pUserData` – callback function parameter.
- `psEdmaBase` – base address for the EDMA
- `eEdmaTxChannel` – Channel of the EDMA used for QSPI Tx
- `eEdmaRxChannel` – Channel of the EDMA used for QSPI Rx

`status_t QSPI_SlaveTransferEDMA(qspi_slave_edma_handle_t *psHandle, qspi_transfer_t *psXfer)`

EDMA method of QUEUEDSPI slave transfer.

This function transfers data using EDMA. This is a non-blocking function, which returns right away. When all data is transferred, the callback function is called.

Note: : The transfer data size should be even if the transfer data width is larger than 8.

Parameters

- `psHandle` – pointer to `qspi_slave_edma_handle_t` structure which stores the transfer state.
- `psXfer` – pointer to `qspi_transfer_t` structure.

Returns

status of `status_t`.

`status_t QSPI_SlaveTransferGetCountEDMA(qspi_slave_edma_handle_t *psHandle, uint16_t *pu16Count)`

Get the slave EDMA transfer count.

Parameters

- `psHandle` – Pointer to the `qspi_slave_edma_handle_t` structure which stores the transfer state.
- `pu16Count` – The number of bytes transferred by using the EDMA transaction.

Returns

status of status_t.

void QSPI_SlaveTransferAbortEDMA(*qspi_slave_edma_handle_t* *psHandle)

Abort a transfer that uses EDMA for slave.

Parameters

- psHandle – Pointer to the qspi_slave_edma_handle_t structure which stores the transfer state.

struct __qspi_master_edma_handle

#include <fsl_queued_spi_edma.h> QUEUEDSPI master EDMA transfer handle structure used for transactional API. This struct should be sizeof(edma_channel_tcd_t) aligned.

Public Members

QSPI_Type *base

Base address of the QSPI Peripheral

volatile uint8_t u8State

QUEUEDSPI transfer state , defined in _qspi_transfer_state.

uint16_t u16TotalByteCount

A number of transfer bytes.

qspi_data_width_t eDataWidth

The desired number of bits per frame.

uint16_t u16TxDummyData

Used if txData is NULL.

uint16_t u16RxDummyData

Used if rxData is NULL.

edma_handle_t sTxHandle

edma_handle_t handle point used for transmitting data.

edma_handle_t sRxHandle

edma_handle_t handle point used for receiving data.

bool bIsTxInProgress

Indicates whether the transmit is in progress.

bool bIsRxInProgress

Indicates whether the receive is in progress.

qspi_edma_transfer_callback_t pfCallback

Completion callback.

void *pUserData

Callback user data.

volatile bool bIsPcsActiveAfterTransfer

Indicates whether the PCS signal is active after the last frame transfer, This is not used in slave transfer.

2.69 QTMR: Quad Timer Driver

void QTMR_Init(TMR_Type *base, const *qtmr_config_t* *psConfig)

Initialization Quad Timer module with provided structure.

This function can initial one or more channels of the Quad Timer module.

This examples shows how only initial channel 0.

```
qtmr_config_t sConfig = {0};
qtmr_channel_config_t sChannel0Config;
sConfig.psChannelConfig[0] = &sChannel0Config;
QTMR_GetChannelDefaultConfig(&sChannel0Config);
QTMR_Init(QTMR, sConfig);
```

Note: This API should be called at the beginning of the application using the Quad Timer module.

Parameters

- base – Quad Timer peripheral base address.
- psConfig – Pointer to user's Quad Timer config structure. See *qtmr_config_t*.

void QTMR_Deinit(TMR_Type *base)

De-initialization Quad Timer module.

Parameters

- base – Quad Timer peripheral base address.

void QTMR_GetChannelDefaultConfig(*qtmr_channel_config_t* *psConfig)

Gets an available pre-defined options for Quad Timer channel module's configuration.

This function initializes the channel configuration structure with a free run 16bit timer work setting. The default values are:

```
psConfig->sInputConfig.ePrimarySource = kQTMR_PrimarySrcIPBusClockDivide2;
psConfig->sInputConfig.eSecondarySource = kQTMR_SecondarySrcInputPin0;
psConfig->sInputConfig.eSecondarySourceCaptureMode = kQTMR_SecondarySrcCaptureNoCapture;
psConfig->sInputConfig.bEnableSecondarySrcFaultFunction = false;
psConfig->sInputConfig.eEnableInputInvert = false;
psConfig->sCountConfig.eCountMode = kQTMR_CountPrimarySrcRiseEdge;
psConfig->sCountConfig.eCountLength = kQTMR_CountLengthUntilRollOver;
psConfig->sCountConfig.eCountDir = kQTMR_CountDirectionUp;
psConfig->sCountConfig.eCountTimes = kQTMR_CountTimesRepeat;
psConfig->sCountConfig.eCountLoadMode = kQTMR_CountLoadNormal;
psConfig->sCountConfig.eCountPreload1 = kQTMR_CountPreloadNoLoad;
psConfig->sCountConfig.eCountPreload2 = kQTMR_CountPreloadNoLoad;
psConfig->sOutputConfig.eOutputMode = kQTMR_OutputAssertWhenCountActive;
psConfig->sOutputConfig.eOutputValueOnForce = kQTMR_OutputValueClearOnForce;
psConfig->sOutputConfig.bEnableOutputInvert = false;
psConfig->sOutputConfig.bEnableSwForceOutput = false;
psConfig->sOutputConfig.bEnableOutputPin = false;
psConfig->sCooperationConfig.bEnableMasterReInit = false;
psConfig->sCooperationConfig.bEnableMasterForceOFLAG = false;
psConfig->sCooperationConfig.bEnableMasterMode = false;
psConfig->eDebugMode = kQTMR_DebugRunNormal;
psConfig->u16EnabledInterruptMask = 0x0U;
psConfig->u16EnabledDMAMask = 0x0U;
psConfig->u16Comp1 = 0x0U;
psConfig->u16Comp2 = 0x0U;
psConfig->u16Comp1Preload = 0x0U;
psConfig->u16Comp1Preload = 0x0U;
```

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```
psConfig->u16Load = 0x0U;
psConfig->u16Count = 0x0U;
psConfig->bEnableChannel = false;
```

Parameters

- psConfig – Pointer to user's Quad Timer channel config structure. See `qtmr_channel_config_t`.

```
void QTMR_SetupChannleConfig(TMR_Type *base, qtmr_channel_number_t eChannelNumber,
                             const qtmr_channel_config_t *psConfig)
```

Setup a Quad Timer channel with provided structure.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- psConfig – Pointer to user's Quad Timer channel config structure. See `qtmr_channel_config_t`.

```
static inline void QTMR_SetPrimaryCountSource(TMR_Type *base, qtmr_channel_number_t
                                              eChannelNumber,
                                              qtmr_channel_primary_count_source_t
                                              ePrimarySource)
```

Sets primary input source.

This function select the primary input source, it can select from “input pin 0~3”, “channel output

0~3” and “IP bus clock prescaler”.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- ePrimarySource – The primary input source. See `qtmr_channel_primary_count_source_t`.

```
static inline void QTMR_SetSecondaryCountSource(TMR_Type *base, qtmr_channel_number_t
                                                eChannelNumber,
                                                qtmr_channel_secondary_count_source_t
                                                source)
```

Sets secondary input source.

This function select the secondary input source, it can select from “input pin 0~3”.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- source – The Secondary input source. See `qtmr_channel_secondary_count_source_t`.


```
void QTMR_SetSecondarySourceInputCaptureMode(TMR_Type *base, qtmr_channel_number_t
                                              eChannelNumber,
                                              qtmr_channel_secondary_source_capture_mode_t
                                              eCaptureMode)
```

Sets secondary input capture mode.

This function select the capture mode for secondary input, it can select from “disable capture”, “capture on

rising/falling edge” and “capture on both edges”. Need enable capture mode when input edge interrupt is needed.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- eCaptureMode – The capture mode of secondary input. See `qtmr_channel_secondary_source_capture_mode_t`.

```
static inline void QTMR_EnableSecondarySourceFault(TMR_Type *base, qtmr_channel_number_t
                                                  eChannelNumber, bool bEnable)
```

Enables/Disables secondary input source signal fault feature.

Enable fault feature will make secondary input acts as a fault signal so that the channel output signal (OFLAG) is cleared when the secondary input is set.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- bEnable – Enable the feature or not.
 - **true** Enable secondary source fault feature.
 - **false** Disable secondary source fault feature.

```
static inline void QTMR_EnableInputInvert(TMR_Type *base, qtmr_channel_number_t
                                          eChannelNumber, bool bEnable)
```

Enables/Disables input pin signal polarity invert feature.

This function enables/disables input pin signal polarity invert feature.

Note: Invert feature only affects “input pin 0~3”, and acts on the channel input node, not the input pin, so it only affect current channel and not share by other channel

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- bEnable – Enable the feature or not.
 - **true** Invert input pin signal polarity.
 - **false** No invert for input pin signal polarity.

```
static inline void QTMR_SetInputFilter(TMR_Type *base, qtmr_input_pin_t ePin, uint8_t
                                     u8Count, uint8_t u8Period)
```

Sets input filter for one input pin.

Sets input filter if the input signal is noisy.

Note: The input filter acts on the input pin directly, so the input filter config will affect all channels that select this input pin as source. Turning on the input filter (setting `FILT_PER` to a non-zero value) introduces a latency of $((u8Count + 3) \times u8Period) + 2$ IP bus clock periods.

Parameters

- `base` – Quad Timer peripheral base address.
- `ePin` – Quad Timer input pin number. See `qtmr_input_pin_t`.
- `u8Count` – Range is 0~7, represent the number of consecutive samples that must agree prior to the input filter accepting an input transition. Actual consecutive samples numbers is $(u8Count + 3)$.
- `u8Period` – Represent the sampling period (in IP bus clock cycles) of the input pin signals. Each input is sampled multiple times at the rate specified by this field. If `u8Period` is 0, then the input pin filter is bypassed.

```
static inline uint16_t QTMR_GetInputPinValueInSecondarySource(TMR_Type *base,
                                                             qtmr_channel_number_t
                                                             eChannelNumber)
```

Gets the external input signal value selected via the secondary input source.

This function read the value of the secondary input source, the input pin IPS and filtering have been applied to the read back value.

Parameters

- `base` – Quad Timer peripheral base address.
- `eChannelNumber` – Quad Timer channel number. See `qtmr_channel_number_t`.

Returns

The state of the current state of the external input pin selected via the secondary count source after application of IPS and filtering.

```
void QTMR_SetCountMode(TMR_Type *base, qtmr_channel_number_t eChannelNumber,
                      qtmr_channel_count_mode_t eCountMode)
```

Sets channel count mode.

This function select channel basic count mode which trigger by primary input or/and secondary input events.

Parameters

- `base` – Quad Timer peripheral base address.
- `eChannelNumber` – Quad Timer channel number. See `qtmr_channel_number_t`.
- `eCountMode` – The mode of operation for the count. See `qtmr_channel_count_mode_t`.

```
static inline void QTMR_SetCountLength(TMR_Type *base, qtmr_channel_number_t
                                       eChannelNumber, qtmr_channel_count_length_t
                                       eLength)
```

Sets channel count length.

This function select channel single count length from “until roll over” or “until compare”. “until roll over” means count until 0xFFFF, “until compare” means count until reach COMP1 (for count up) or COMP2 (for count up) value (unless the output signal is in alternating compare mode, this mode make channel use COMP1 and COMP2 alternately).

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- eLength – The channel count length. See `qtmr_channel_count_length_t`.

```
static inline void QTMR_SetCountDirection(TMR_Type *base, qtmr_channel_number_t
                                         eChannelNumber, qtmr_channel_count_direction_t
                                         eDirection)
```

Sets channel count direction.

This function select channel count direction from “count up” or “count down”. Under normal count mode, this function decide the count direction directly, when chose “secondary specifies direction” count mode, count direction decide by “the secondary input level” XOR with “the function selection”.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- eDirection – The channel count direction. See `qtmr_channel_count_direction_t`.

```
static inline qtmr_channel_count_direction_t QTMR_GetCountDirection(TMR_Type *base,
                                                                    qtmr_channel_number_t
                                                                    eChannelNumber)
```

Gets channel count direction.

This function read the channel count direction of the last count during quadrature encoded count mode.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.

Returns

The direction of the last count. Value see `qtmr_channel_count_direction_t`.

```
static inline void QTMR_SetCountTimes(TMR_Type *base, qtmr_channel_number_t
                                       eChannelNumber, qtmr_channel_count_times_t
                                       eTimes)
```

Sets channel count times.

This function select channel count times from “once” or “repeatedly”. If select “once” with “until compare”, channel will stop when reach COMP1 (for count up) or COMP2 (for count up) (unless the output signal is in alternating compare mode, this mode will make channel reaching COMP1, re-initializes then count reaching COMP2, and then stops).

Parameters

- base – Quad Timer peripheral base address.

- `eChannelNumber` – Quad Timer channel number. See `qtmr_channel_number_t`.
- `eTimes` – The channel count times. See `qtmr_channel_count_times_t`.

```
static inline void QTMR_SetCountLoadMode(TMR_Type *base, qtmr_channel_number_t
                                         eChannelNumber,
                                         qtmr_channel_count_load_mode_t eLoadMode)
```

Sets channel count load mode.

This function select channel count re-initialized load mode from “normal” or “alternative”. “normal” means channel counter re-initialized from LOAD register when compare event, “alternative” means channel counter can re-initialized from LOAD (count up) or CMPLD2 (count down) when compare event.

Parameters

- `base` – Quad Timer peripheral base address.
- `eChannelNumber` – Quad Timer channel number. See `qtmr_channel_number_t`.
- `eLoadMode` – The channel count load mode. See `qtmr_channel_count_load_mode_t`.

```
static inline void QTMR_SetCompare1PreloadControl(TMR_Type *base, qtmr_channel_number_t
                                                  eChannelNumber,
                                                  qtmr_channel_count_preload_mode_t
                                                  ePreloadMode)
```

Sets channel preload mode for compare register 1.

This function select channel preload mode for compare register 1. Default the COMP1 register never preload, when enabled, the COMP1 can preload from CMPLD1 register when COMP1 or COMP2 compare event.

Parameters

- `base` – Quad Timer peripheral base address.
- `eChannelNumber` – Quad Timer channel number. See `qtmr_channel_number_t`.
- `ePreloadMode` – The compare register 1 preload mode. See `qtmr_channel_count_preload_mode_t`.

```
static inline void QTMR_SetCompare2PreloadControl(TMR_Type *base, qtmr_channel_number_t
                                                  eChannelNumber,
                                                  qtmr_channel_count_preload_mode_t
                                                  ePreloadMode)
```

Sets channel preload mode for compare register 2.

This function select channel preload mode for compare register 2. Default the COMP2 register never preload, when enabled, the COMP2 can preload from CMPLD2 register when COMP1 or COMP2 compare event.

Parameters

- `base` – Quad Timer peripheral base address.
- `eChannelNumber` – Quad Timer channel number. See `qtmr_channel_number_t`.
- `ePreloadMode` – The compare register 2 preload mode. See `qtmr_channel_count_preload_mode_t`.

```
static inline void QTMR_SetCompare1PreloadValue(TMR_Type *base, qtmr_channel_number_t
                                              eChannelNumber, uint16_t
                                              u16Comp1Preload)
```

Sets channel compare register 1 preload register value.

This function set the CMPLD1 register value. The COMP1 can preload from CMPLD1 register when preload mode is not “never preload”.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- u16Comp1Preload – Value for Channel compare register 1 preload register.

```
static inline void QTMR_SetCompare2PreloadValue(TMR_Type *base, qtmr_channel_number_t
                                              eChannelNumber, uint16_t
                                              u16Comp2Preload)
```

Sets channel compare register 2 preload register value.

This function set the CMPLD2 register value. The COMP2 can preload from CMPLD2 register when preload mode is not “never preload”.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- u16Comp2Preload – Value for Channel compare register 2 preload register.

```
static inline void QTMR_SetLoadValue(TMR_Type *base, qtmr_channel_number_t
                                    eChannelNumber, uint16_t u16Load)
```

Sets channel load register value.

This function set the LOAD register value. The channel will re-initialize the counter value with this register after counter compare or overflow event.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- u16Load – Value used to initialize the counter after counter compare or overflow event.

```
static inline void QTMR_SetCompare1Value(TMR_Type *base, qtmr_channel_number_t
                                         eChannelNumber, uint16_t u16Comp1)
```

Sets channel count compare register 1.

This function set the COMP1 register value. It use to trigger compare event in count up mode or alternating compare mode.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- u16Comp1 – Value for Channel compare register 1.

```
static inline void QTMR_SetCompare2Value(TMR_Type *base, qtmr_channel_number_t
                                         eChannelNumber, uint16_t u16Comp2)
```

Sets channel count compare register 2.

This function set the COMP2 register value. It use to trigger compare event in count down mode or alternating compare mode.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See *qtmr_channel_number_t*.
- u16Comp2 – Value for Channel compare register 2.

```
static inline uint16_t QTMR_ReadCaptureValue(TMR_Type *base, qtmr_channel_number_t
                                              eChannelNumber)
```

Gets channel capture register value.

This function read the CAPT register value, which store the real-time channel counter value when input capture event.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See *qtmr_channel_number_t*.

Returns

The value captured from the channel counter.

```
static inline uint16_t QTMR_GetHoldValue(TMR_Type *base, qtmr_channel_number_t
                                         eChannelNumber)
```

Gets channel hold register value.

This function read the HOLD register value, which stores the channel counter's values of specific channels whenever any of the four channels within a module is read.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See *qtmr_channel_number_t*.

Returns

The channel counter value when any read operation occurs.

```
static inline void QTMR_SetCounterValue(TMR_Type *base, qtmr_channel_number_t
                                         eChannelNumber, uint16_t u16Count)
```

Sets channel counter register value.

This function set the CNTR register value, the channel will start counting based on this value.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See *qtmr_channel_number_t*.
- u16Count – The channel counter initialize value.

```
static inline uint16_t QTMR_GetCounterValue(TMR_Type *base, qtmr_channel_number_t
                                           eChannelNumber)
```

Reads channel counter register value.

This function read the CNTR register value, which stores the channel real-time channel counting value. This read operation will trigger HOLD register update.

Note: User can call the utility macros provided in fsl_common.h to convert ticks to usec or msec.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See qtmr_channel_number_t.

Returns

The real-time channel counter value.

```
static inline void QTMR_SetOutputMode(TMR_Type *base, qtmr_channel_number_t
                                      eChannelNumber, qtmr_channel_output_mode_t
                                      eOutputMode)
```

Sets Channel output signal (OFLAG) work mode.

This function select channel output signal (OFLAG) work mode base on different channel event.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See qtmr_channel_number_t.
- eOutputMode – The mode of operation for the OFLAG output signal. See qtmr_channel_output_mode_t.

```
static inline void QTMR_SetOutputValueOnForce(TMR_Type *base, qtmr_channel_number_t
                                              eChannelNumber,
                                              qtmr_channel_output_value_on_force_t eValue)
```

Sets the value of output signal when a force event occurs.

This function config the value of output signal when a force event occurs. Force events can be a software command or compare event from a master channel.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See qtmr_channel_number_t.
- eValue – The value of output signal when force event occur. See qtmr_channel_output_value_on_force_t.

```
static inline void QTMR_EnableOutputInvert(TMR_Type *base, qtmr_channel_number_t
                                           eChannelNumber, bool bEnable)
```

Enables/Disables output signal polarity invert feature.

This function enables/disables the invert feature of output signal (OFLAG).

Parameters

- base – Quad Timer peripheral base address.

- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- bEnable – Enable the feature or not.
 - **true** Invert output signal polarity.
 - **false** No invert for output signal polarity.

```
static inline void QTMR_EnableSwForceOutput(TMR_Type *base, qtmr_channel_number_t
                                             eChannelNumber)
```

Enables software triggers a FORCE command to output signal.

This function uses a software command to trigger force event, which can force the current value of SCTRL[VAL] bit to be written to the OFLAG output.

Note: This function can be called only if the counter is disabled.

```
QTMR_SetOutputValueOnForce(QTMR, kQTMR_Channel0, kQTMR_OutputValueSetOnForce);
QTMR_EnableSwForceOutput(QTMR, kQTMR_Channel0);
```

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.

```
static inline void QTMR_EnableOutputPin(TMR_Type *base, qtmr_channel_number_t
                                         eChannelNumber, bool bEnable)
```

Enables/Disables output signal (OFLAG) drive on the external pin feature.

This function enables/disables output signal (OFLAG) drive on the external pin feature.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- bEnable – Enable the feature or not.
 - **true** The output signal is driven on the external pin.
 - **false** The external pin is configured as an input.

```
static inline void QTMR_EnableMasterMode(TMR_Type *base, qtmr_channel_number_t
                                          eChannelNumber, bool bEnable)
```

Enables/Disables channel master mode.

This function enables/disables channel master mode.

Note: Master channel can broadcast compare event to all channels within the module to re-initialize channel and/or force channel output signal.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- bEnable – Enable the feature or not.

- **true** Enables channel master mode.
- **false** Disables channel master mode.

```
static inline void QTMR_EnableMasterForceOFLAG(TMR_Type *base, qtmr_channel_number_t
                                              eChannelNumber, bool bEnable)
```

Enables/Disables force the channel output signal (OFLAG) state by master channel compare event.

This function enables/disables the compare event from master channel within the same module to force the state of this channel OFLAG output signal.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- bEnable – Enable the feature or not.
 - **true** Enables OFLAG state to be forced by master channel compare event.
 - **false** Disables OFLAG state to be forced by master channel compare event.

```
static inline void QTMR_EnableMasterReInit(TMR_Type *base, qtmr_channel_number_t
                                           eChannelNumber, bool bEnable)
```

Enables/Disables channel be re-initialized by master channel compare event feature.

This function enables/disables the compare event from master channel within the same module to force the re-initialization of this channel.

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.
- bEnable – Enable the feature or not.
 - **true** Enables channel be re-initialized by master channel compare event.
 - **false** Disables channel be re-initialized by master channel compare event.

```
static inline void QTMR_EnableDma(TMR_Type *base, qtmr_channel_number_t
                                 eChannelNumber, uint16_t u16Mask)
```

Enables the Quad Timer DMA request according to a provided mask.

This function enables the Quad Timer DMA request according to a provided mask. The mask is a logical OR of enumerators members. See `_qtmr_channel_dma_enable`. This examples shows how to enable compare 1 register preload DMA request and compare 2 register preload DMA request.

```
QTMR_EnableDma((QTMR, kQTMR_Channel0, kQTMR_Compare1PreloadDmaEnable | kQTMR_
↪ Compare2PreloadDmaEnable);
```

Parameters

- base – Quad Timer peripheral base address.
- eChannelNumber – Quad Timer channel number. See `qtmr_channel_number_t`.

- `u16Mask` – The QTMR DMA requests to enable. Logical OR of `_qtmr_channel_dma_enable`.

```
static inline void QTMR_DisableDma(TMR_Type *base, qtmr_channel_number_t
                                eChannelNumber, uint16_t u16Mask)
```

Disables the Quad Timer DMA request according to a provided mask.

This function disables the Quad Timer DMA request according to a provided mask. The mask is a logical OR of enumerators members. See `_qtmr_channel_dma_enable`. This examples shows how to disable compare 1 register preload DMA request and compare 2 register preload DMA request.

```
QTMR_DisableDma((QTMR, kQTMR_Channel0, kQTMR_Compare1PreloadDmaEnable | kQTMR_
↳ Compare2PreloadDmaEnable);
```

Parameters

- `base` – Quad Timer peripheral base address.
- `eChannelNumber` – Quad Timer channel number. See `qtmr_channel_number_t`.
- `u16Mask` – The QTMR DMA requests to disable. Logical OR of `_qtmr_channel_dma_enable`.

```
static inline void QTMR_EnableInterrupts(TMR_Type *base, qtmr_channel_number_t
                                        eChannelNumber, uint16_t u16Mask)
```

Enables the Quad Timer interrupts according to a provided mask.

This function enables the Quad Timer interrupts according to a provided mask. The mask is a logical OR of enumerators members. See `_qtmr_channel_interrupt_enable`. This examples shows how to enable compare 1 interrupt and compare 2 interrupt.

```
QTMR_EnableInterrupts((QTMR, kQTMR_Channel0, kQTMR_Compare1InterruptEnable |
↳ kQTMR_Compare2InterruptEnable);
```

Parameters

- `base` – Quad Timer peripheral base address.
- `eChannelNumber` – Quad Timer channel number. See `qtmr_channel_number_t`.
- `u16Mask` – The QTMR DMA interrupts to enable. Logical OR of `_qtmr_channel_interrupt_enable`.

```
static inline void QTMR_DisableInterrupts(TMR_Type *base, qtmr_channel_number_t
                                         eChannelNumber, uint16_t u16Mask)
```

Disables the Quad Timer interrupts according to a provided mask.

This function disables the Quad Timer interrupts according to a provided mask. The mask is a logical OR of enumerators members. See `_qtmr_channel_interrupt_enable`. This examples shows how to disable compare 1 interrupt and compare 2 interrupt.

```
QTMR_DisableInterrupts((QTMR, kQTMR_Channel0, kQTMR_Compare1InterruptEnable |
↳ kQTMR_Compare2InterruptEnable);
```

Parameters

- `base` – Quad Timer peripheral base address.
- `eChannelNumber` – Quad Timer channel number. See `qtmr_channel_number_t`.

- `u16Mask` – The QTMR DMA interrupts to disable. Logical OR of `_qtmr_channel_interrupt_enable`.

```
static inline uint16_t QTMR_GetStatusFlags(TMR_Type *base, qtmr_channel_number_t
                                         eChannelNumber)
```

Gets the Quad Timer status flags.

This function gets all QTMR channel status flags. The flags are returned as the logical OR value of the enumerators `_qtmr_channel_status_flags`. To check for a specific status, compare the return value with enumerators in the `_qtmr_channel_status_flags`. For example, to check whether the compare flag set.

```
if((QTMR_GetStatusFlags(QTMR, kQTMR_Channel0) & kQTMR_CompareFlag) != 0U)
{
    ...
}
```

Parameters

- `base` – Quad Timer peripheral base address.
- `eChannelNumber` – Quad Timer channel number. See `qtmr_channel_number_t`.

Returns

The QTMR status flags which is the logical OR of the enumerators `_qtmr_channel_status_flags`.

```
static inline void QTMR_ClearStatusFlags(TMR_Type *base, qtmr_channel_number_t
                                         eChannelNumber, uint16_t u16Mask)
```

Clears the Quad Timer status flags.

This function clears QTMR channel status flags with a provide mask. The mask is a logical OR of enumerators `_qtmr_channel_status_flags`. This examples shows how to clear compare 1 flag and compare 2 flag.

```
QTMR_ClearStatusFlags((QTMR, kQTMR_Channel0, kQTMR_Compare1Flag | kQTMR_
↳ Compare2Flag);
```

Parameters

- `base` – Quad Timer peripheral base address
- `eChannelNumber` – Quad Timer channel number. See `qtmr_channel_number_t`
- `u16Mask` – The QTMR status flags to clear. Logical OR of `_qtmr_channel_status_flags`

```
static inline void QTMR_SetDebugActions(TMR_Type *base, qtmr_channel_number_t
                                         eChannelNumber, qtmr_channel_debug_action_t
                                         eDebugMode)
```

Sets channel debug actions.

This function selects the certain actions which will perform when the chip entering debug mode.

Parameters

- `base` – Quad Timer peripheral base address.
- `eChannelNumber` – Quad Timer channel number. See `qtmr_channel_number_t`.

- `eDebugMode` – The Quad Timer channel actions in response to the chip entering debug mode. See `qtmr_channel_debug_action_t`.

`static inline void QTMR_EnableChannels(TMR_Type *base, uint16_t u16Mask)`

Enables the Quad Timer channels according to a provided mask.

This function enables the Quad Timer channels according to a provided mask. The mask is a logical OR of enumerators `_qtmr_channel_enable`. This examples shows how to enable channel 0 and channel 1.

```
QTMR_EnableChannels(QTMR, kQTMR_Channel0Enable | kQTMR_Channel1Enable);
```

Note: If one channel has effective count mode, it will start its counter as soon as the channel be enabled.

Parameters

- `base` – Quad Timer peripheral base address.
- `u16Mask` – The QTMR channels to enable. Logical OR of `_qtmr_channel_enable`.

`static inline void QTMR_DisableChannels(TMR_Type *base, uint16_t u16Mask)`

Disables the Quad Timer channels according to a provided mask.

This function disables the Quad Timer channels according to a provided mask. The mask is a logical OR of enumerators `_qtmr_channel_enable`. This examples shows how to disable channel 0 and channel 1.

```
QTMR_DisableChannels(QTMR, kQTMR_Channel0Enable | kQTMR_Channel1Enable);
```

Parameters

- `base` – Quad Timer peripheral base address.
- `u16Mask` – The QTMR channels to enable. Logical OR of `_qtmr_channel_enable`.

`static inline uint32_t TMR_GetCaptureRegAddr(TMR_Type *base, qtmr_channel_number_t nChannel)`

Gets the TMR capture register address. This API is used to provide the transfer address for TMR capture transfer.

Parameters

- `base` – TMR base pointer
- `nChannel` – Quad Timer channel number. See `qtmr_channel_number_t`.

Returns

capture register address

`FSL_QTMR_DRIVER_VERSION`

QTMR driver version.

`enum _qtmr_input_pin`

The enumeration for Quad Timer module input pin source.

Values:

enumerator `kQTMR_InputPin0`

Quad Timer input pin 0.

enumerator kQTMR_InputPin1

Quad Timer input pin 1.

enumerator kQTMR_InputPin2

Quad Timer input pin 2.

enumerator kQTMR_InputPin3

Quad Timer input pin 3.

enum __qtmr_channel_number

The enumeration for Quad Timer module channel number.

Values:

enumerator kQTMR_Channel0

Quad Timer Channel 0.

enumerator kQTMR_Channel1

Quad Timer Channel 1.

enumerator kQTMR_Channel2

Quad Timer Channel 2.

enumerator kQTMR_Channel3

Quad Timer Channel 3.

enum __qtmr_channel_primary_count_source

The enumeration for Quad Timer channel primary input source.

Values:

enumerator kQTMR_PrimarySrcInputPin0

Quad Timer input pin 0.

enumerator kQTMR_PrimarySrcInputPin1

Quad Timer input pin 1.

enumerator kQTMR_PrimarySrcInputPin2

Quad Timer input pin 2.

enumerator kQTMR_PrimarySrcInputPin3

Quad Timer input pin 3.

enumerator kQTMR_PrimarySrcChannel0Output

Quad Timer channel 0 output.

enumerator kQTMR_PrimarySrcChannel1Output

Quad Timer channel 1 output.

enumerator kQTMR_PrimarySrcChannel2Output

Quad Timer channel 2 output.

enumerator kQTMR_PrimarySrcChannel3Output

Quad Timer channel 3 output.

enumerator kQTMR_PrimarySrcIPBusClockDivide1

IP bus clock divide by 1.

enumerator kQTMR_PrimarySrcIPBusClockDivide2

IP bus clock divide by 2.

enumerator kQTMR_PrimarySrcIPBusClockDivide4

IP bus clock divide by 4.

enumerator kQTMR_PrimarySrcIPBusClockDivide8

IP bus clock divide by 8.

enumerator kQTMR_PrimarySrcIPBusClockDivide16

IP bus clock divide by 16.

enumerator kQTMR_PrimarySrcIPBusClockDivide32

IP bus clock divide by 32.

enumerator kQTMR_PrimarySrcIPBusClockDivide64

IP bus clock divide by 64.

enumerator kQTMR_PrimarySrcIPBusClockDivide128

IP bus clock divide by 128.

enum _qtmr_channel_secondary_count_source

The enumeration for Quad Timer channel secondary input source.

Values:

enumerator kQTMR_SecondarySrcInputPin0

Quad Timer input pin 0.

enumerator kQTMR_SecondarySrcInputPin1

Quad Timer input pin 1.

enumerator kQTMR_SecondarySrcInputPin2

Quad Timer input pin 2.

enumerator kQTMR_SecondarySrcInputPin3

Quad Timer input pin 3.

enum _qtmr_channel_secondary_source_capture_mode

The enumeration for Quad Timer channel secondary input source capture mode.

Values:

enumerator kQTMR_SecondarySrcCaptureNoCapture

Secondary source capture is disabled.

enumerator kQTMR_SecondarySrcCaptureRisingEdge

Secondary source capture on rising edge.

enumerator kQTMR_SecondarySrcCaptureFallingEdge

Secondary source capture on falling edge.

enumerator kQTMR_SecondarySrcCaptureRisingAndFallingEdge

Secondary source capture on both edges.

enumerator kQTMR_SecondarySrcCaptureRisingEdgeWithReload

Secondary source capture on rising edge while cause the channel to be reloaded.

enumerator kQTMR_SecondarySrcCaptureFallingEdgeWithReload

Secondary source capture on falling edge while cause the channel to be reloaded.

enumerator kQTMR_SecondarySrcCaptureRisingAndFallingEdgeWithReload

Secondary source capture on both edges while cause the channel to be reloaded.

enum _qtmr_channel_count_mode

The enumeration for Quad Timer channel count mode.

When “channel output 0~3” or “IP bus clock prescaler” is chosen, active edge is the rising edge. When “input pin 0~3” is chosen, active edge and active level is determined by input invert feature (IPS). Disable input invert feature means active edge is rising edge, active

level is high level, enable input invert feature means active edge is falling edge, active level is low level.

Values:

enumerator kQTMR_CountNoOperation

No operation.

enumerator kQTMR_CountPrimarySrcRiseEdge

Count active edge of primary input source.

enumerator kQTMR_CountPrimarySrcRiseAndFallEdge

Count rising and falling edges of primary input source.

enumerator kQTMR_CountPrimarySrcRiseEdgeSecondarySrcInHigh

Count active edge of primary input source when secondary input is at a active level.

enumerator kQTMR_CountPrimarySecondarySrcInQuadDecode

Quadrature count mode, uses primary and secondary sources.

enumerator kQTMR_CountPrimarySrcRiseEdgeSecondarySrcDir

Count active edge of primary input source; secondary input source specifies count direction.

enumerator kQTMR_CountPrimarySrcRiseEdgeSecondarySrcRiseEdgeTrig

The active edge of secondary input source triggers count active edge of primary input source, and the channel counter will stop upon receiving a second trigger event while it's still counting from the first trigger event.

enumerator kQTMR_CountCascadeWithOtherChannel

Cascaded count mode, the channel will count as compare events occur in the selected source channel (use a special high-speed signal path rather than the OFLAG output signal). The active edge of secondary input source triggers count active edge of primary input source, and the channel counter will re-initialized upon receiving a second trigger event while it's still counting from the first trigger event.

enumerator kQTMR_CountPrimarySrcRiseEdgeSecondarySrcRiseEdgeTrigWithReInit

enum __qtmr_channel_count_length

The enumeration for Quad Timer channel count length.

Values:

enumerator kQTMR_CountLengthUntilRollOver

Count until roll over at \$FFFF.

enumerator kQTMR_CountLengthUntilCompare

Count until compare.

enum __qtmr_channel_count_direction

The enumeration for Quad Timer channel count direction.

Values:

enumerator kQTMR_CountDirectionUp

Count direction up.

enumerator kQTMR_CountDirectionDown

Count direction down.

enum __qtmr_channel_count_times

The enumeration for Quad Timer channel count times.

Values:

enumerator kQTMR_CountTimesRepeat
Count repeatedly.

enumerator kQTMR_CountTimesOnce
Count time once.

enum _qtmr_channel_count_load_mode
The enumeration for Quad Timer channel count load mode.

Values:

enumerator kQTMR_CountLoadNormal
Count can be re-initialized only with the LOAD register when match event occurs.

enumerator kQTMR_CountLoadAlternative
Channel can be re-initialized with the LOAD register when count up and a match with COMP1 occurs, or with CMPLD2 register when count down and a match with COMP2 occurs.

enum _qtmr_channel_count_preload_mode
The enumeration for Quad Timer channel COMP1 & COMP2 preload mode.

Values:

enumerator kQTMR_CountPreloadNoLoad
Not load CMPLDn into COMPn register when compare event occurs.

enumerator kQTMR_CountPreloadOnComp1CompareEvent
Load CMPLDn register into COMPn when occurs a successful comparison of channel counter value and the COMP1 register.

enumerator kQTMR_CountPreloadOnComp2CompareEvent
Load CMPLDn register into COMPn when occurs a successful comparison of channel counter value and the COMP2 register.

enum _qtmr_channel_output_mode
The enumeration for Quad Timer channel output signal (OFLAG signal) work mode.

Values:

enumerator kQTMR_OutputAssertWhenCountActive
OFLAG output assert while counter is active.

enumerator kQTMR_OutputClearOnCompare
OFLAG output clear on successful compare.

enumerator kQTMR_OutputSetOnCompare
OFLAG output set on successful compare.

enumerator kQTMR_OutputToggleOnCompare
OFLAG output toggle on successful compare.

enumerator kQTMR_OutputToggleOnAltCompareReg
OFLAG output toggle using alternating compare registers.

enumerator kQTMR_OutputSetOnCompareClearOnSecSrcActiveEdge
OFLAG output set on compare, clear on secondary source input edge.

enumerator kQTMR_OutputSetOnCompareClearOnCountRoll
OFLAG output set on compare, clear on counter rollover.

enumerator kQTMR_OutputGateClockOutWhenCountActive
OFLAG output gated while count is active.

enum _qtmr_qtmr_channel_output_value_on_force

The enumeration for Quad Timer channel output signal (OFLAG) value on force event occur.

Values:

enumerator kQTMR__OutputValueClearOnForce

OFLAG output clear (low) when software triggers a FORCE command or master channel force the OFLAG (EEOF need set).

enumerator kQTMR__OutputValueSetOnForce

OFLAG output set (high) when software triggers a FORCE command or master channel force the OFLAG (EEOF need set).

enum _qtmr_channel_debug_action

The enumeration for Quad Timer channel run options when the chip entering debug mode.

Values:

enumerator kQTMR__DebugRunNormal

Continue with normal operation.

enumerator kQTMR__DebugHaltCounter

Halt counter.

enumerator kQTMR__DebugForceOutToZero

Force output to logic 0.

enumerator kQTMR__DebugHaltCountForceOutZero

Halt counter and force output to logic 0.

enum _qtmr_channel_interrupt_enable

The enumeration for Quad Timer channel interrupts.

Values:

enumerator kQTMR__CompareInterruptEnable

Compare interrupt.

enumerator kQTMR__Compare1InterruptEnable

Compare 1 interrupt.

enumerator kQTMR__Compare2InterruptEnable

Compare 2 interrupt.

enumerator kQTMR__OverflowInterruptEnable

Timer overflow interrupt.

enumerator kQTMR__EdgeInterruptEnable

Input edge interrupt.

enumerator kQTMR__ALLInterruptEnable

enum _qtmr_channel_status_flags

The enumeration for Quad Timer channel work status.

Values:

enumerator kQTMR__CompareFlag

Compare flag.

enumerator kQTMR__Compare1Flag

Compare 1 flag.

enumerator kQTMR_Compare2Flag

Compare 2 flag.

enumerator kQTMR_OverflowFlag

Timer overflow flag.

enumerator kQTMR_EdgeFlag

Input edge flag.

enumerator kQTMR_StatusAllFlags

enum __qtmr_channel_enable

The enumeration for Quad Timer channel enable.

Values:

enumerator kQTMR_Channel0Enable

Channel 0 enable.

enumerator kQTMR_Channel1Enable

Channel 1 enable.

enumerator kQTMR_Channel2Enable

Channel 2 enable.

enumerator kQTMR_Channel3Enable

Channel 3 enable.

enumerator kQTMR_ALLChannelEnable

enum __qtmr_channel_dma_enable

The enumeration for Quad Timer channel DMA trigger source.

Values:

enumerator kQTMR_InputEdgeFlagDmaEnable

Input edge flag setting will trigger DMA read request for CAPT register.

enumerator kQTMR_Compare1PreloadDmaEnable

Channel load CMPLD1 register into COMP1 will trigger DMA write request for CMPLD1.

enumerator kQTMR_Compare2PreloadDmaEnable

Channel load CMPLD2 register into COMP2 will trigger DMA write request for CMPLD2.

enumerator kQTMR_AllDMAEnable

typedef enum __qtmr_input_pin qtmr_input_pin_t

The enumeration for Quad Timer module input pin source.

typedef enum __qtmr_channel_number qtmr_channel_number_t

The enumeration for Quad Timer module channel number.

typedef enum __qtmr_channel_primary_count_source qtmr_channel_primary_count_source_t

The enumeration for Quad Timer channel primary input source.

typedef enum __qtmr_channel_secondary_count_source qtmr_channel_secondary_count_source_t

The enumeration for Quad Timer channel secondary input source.

typedef enum __qtmr_channel_secondary_source_capture_mode

qtmr_channel_secondary_source_capture_mode_t

The enumeration for Quad Timer channel secondary input source capture mode.

```
typedef enum _qtmr_channel_count_mode qtmr_channel_count_mode_t
```

The enumeration for Quad Timer channel count mode.

When “channel output 0~3” or “IP bus clock prescaler” is chosen, active edge is the rising edge. When “input pin 0~3” is chosen, active edge and active level is determined by input invert feature (IPS). Disable input invert feature means active edge is rising edge, active level is high level, enable input invert feature means active edge is falling edge, active level is low level.

```
typedef enum _qtmr_channel_count_length qtmr_channel_count_length_t
```

The enumeration for Quad Timer channel count length.

```
typedef enum _qtmr_channel_count_direction qtmr_channel_count_direction_t
```

The enumeration for Quad Timer channel count direction.

```
typedef enum _qtmr_channel_count_times qtmr_channel_count_times_t
```

The enumeration for Quad Timer channel count times.

```
typedef enum _qtmr_channel_count_load_mode qtmr_channel_count_load_mode_t
```

The enumeration for Quad Timer channel count load mode.

```
typedef enum _qtmr_channel_count_preload_mode qtmr_channel_count_preload_mode_t
```

The enumeration for Quad Timer channel COMP1 & COMP2 preload mode.

```
typedef enum _qtmr_channel_output_mode qtmr_channel_output_mode_t
```

The enumeration for Quad Timer channel output signal (OFLAG signal) work mode.

```
typedef enum _qtmr_qtmr_channel_output_value_on_force
```

```
qtmr_channel_output_value_on_force_t
```

The enumeration for Quad Timer channel output signal (OFLAG) value on force event occur.

```
typedef enum _qtmr_channel_debug_action qtmr_channel_debug_action_t
```

The enumeration for Quad Timer channel run options when the chip entering debug mode.

```
typedef struct _qtmr_channel_input_config qtmr_channel_input_config_t
```

The structure for configuring Quad Timer channel input signal.

```
typedef struct _qtmr_channel_count_config qtmr_channel_count_config_t
```

The structure for configuring Quad Timer channel counting behaviors.

```
typedef struct _qtmr_channel_output_config qtmr_channel_output_config_t
```

The structure for configuring Quad Timer channel output signal (OFLAG).

```
typedef struct _qtmr_channel_cooperation_config qtmr_channel_cooperation_config_t
```

The structure for configuring Quad Timer channel cooperation mode with other channels.

```
typedef struct _qtmr_channel_config qtmr_channel_config_t
```

Quad Timer channel configuration covering all channel configurable fields.

```
typedef struct _qtmr_input_pin_filter_config qtmr_input_pin_filter_config_t
```

The structure for configuring Quad Timer module input pin filter.

```
typedef struct _qtmr_config qtmr_config_t
```

Quad Timer module configuration which contain channel config structure pointers and input pin filter config structure pointers.

Note: Need use channel structure address to init the structure pointers, when the channel or input pin structure pointers is NULL, it will be ignored by QTMR_Init API. This can save stack space when only one or two channels are used.

```
struct _qtmr_channel_input_config
```

#include <fsl_qtmr.h> The structure for configuring Quad Timer channel input signal.

Public Members

qtmr_channel_primary_count_source_t ePrimarySource

Specify the primary input source.

qtmr_channel_secondary_count_source_t eSecondarySource

Specify the secondary input source.

bool bEnableSecondarySrcFaultFunction

true: The selected secondary input acts as a fault signal which can clear the channel output signal when it is set, false: Fault function disabled.

bool eEnableInputInvert

true: Invert input signal value when select input pin as primary or/and secondary input source false: no operation.

struct *_qtmr_channel_count_config*

#include <fsl_qtmr.h> The structure for configuring Quad Timer channel counting behaviors.

Public Members

qtmr_channel_count_mode_t eCountMode

Configures channel count mode.

qtmr_channel_count_length_t eCountLength

Configures channel count length.

qtmr_channel_count_direction_t eCountDir

Configures channel count direction.

qtmr_channel_count_times_t eCountTimes

Configures channel count times.

qtmr_channel_count_load_mode_t eCountLoadMode

Configures channel count load mode.

struct *_qtmr_channel_output_config*

#include <fsl_qtmr.h> The structure for configuring Quad Timer channel output signal (OFLAG).

Public Members

qtmr_channel_output_mode_t eOutputMode

Configures channel output signal work mode.

qtmr_channel_output_value_on_force_t eOutputValueOnForce

The value of output signal when force event occur.

bool bEnableOutputInvert

True: the polarity of output signal will be inverted, false: The output signal is not inverted.

bool bEnableSwForceOutput

True: forces the current value of eOFLAGValueOnForce to output signal. false: no operation.

bool bEnableOutputPin

True: the output signal is driven on the external pin. false: the external pin is configured as an input.

struct `_qtmr_channel_cooperation_config`

#include <fsl_qtmr.h> The structure for configuring Quad Timer channel cooperation mode with other channels.

Public Members

bool `bEnableMasterReInit`

true: Master channel within the module can re-initialize this channel when it has a compare event, false: no operation.

bool `bEnableMasterForceOFLAG`

true: Master channel within the module can force this channel OFLAG signal when it has a compare event, false: no operation.

bool `bEnableMasterMode`

true: This channel is configured as mater channel, it can broadcast compare event to all channels within the module to re-initialize channel and/or force channel output signal, false: no operation.

struct `_qtmr_channel_config`

#include <fsl_qtmr.h> Quad Timer channel configuration covering all channel configurable fields.

Public Members

qtmr_channel_input_config_t `sInputConfig`

Configures channel input signal.

qtmr_channel_count_config_t `sCountConfig`

Configures channel count work mode.

qtmr_channel_output_config_t `sOutputConfig`

Configures channel output signal (OFLAG) work mode.

qtmr_channel_debug_action_t `eDebugMode`

Configures channel operation in chip debug mode.

uint16_t `u16EnabledInterruptMask`

The mask of the interrupts to be enabled, should be the OR'ed of `_qtmr_channel_interrupt_enable`.

uint16_t `u16EnabledDMAMask`

The mask of the interrupts to be enabled, should be the OR'ed of `_qtmr_channel_dma_enable`.

uint16_t `u16Comp1`

Value for Channel compare register 1.

uint16_t `u16Comp2`

Value for Channel compare register 2.

uint16_t `u16Comp1Preload`

Value for Channel compare 1 preload register.

uint16_t `u16Comp2Preload`

Value for Channel compare 2 preload register.

uint16_t `u16Load`

Value for Channel load register.

uint16_t u16Count

Value for Channel counter value register.

bool bEnableChannel

True: enable the channel prescaler (if it is being used) and counter false: disable channel.

struct __qtmr_input_pin_filter_config

#include <fsl_qtmr.h> The structure for configuring Quad Timer module input pin filter.

Public Members

uint8_t u8Period

Value for input filter sample period.

uint8_t u8Count

Value for input filter sample count (sample count = count +3).

struct __qtmr_config

#include <fsl_qtmr.h> Quad Timer module configuration which contain channel config structure pointers and input pin filter config structure pointers.

Note: Need use channel structure address to init the structure pointers, when the channel or input pin structure pointers is NULL, it will be ignored by QTMR_Init API. This can save stack space when only one or two channels are used.

2.70 The Driver Change Log

2.71 QTMR Peripheral and Driver Overview

2.72 The Driver Change Log

2.73 SIM: System Integration Module Driver

FSL_SIM_DRIVER_VERSION

SIM driver version.

2.74 The Driver Change Log

static inline void SIM_SetWaitModeOperation(SIM_Type *base, sim_wait_mode_operation_t eOperation)

Sets the operation of wait mode, enable/disable the entry of wait mode.

Parameters

- base – SIM peripheral base address.
- eOperation – Used to enable/disable the wait mode, please refer to sim_wait_mode_operation_t.

```
static inline void SIM_SetStopModeOperation(SIM_Type *base, sim_stop_mode_operation_t  
                                             eOperation)
```

Sets the operation of stop mode, enable/disable the entry of stop mode.

Parameters

- base – SIM peripheral base address.
- eOperation – Used to enable/disable the stop mode, please refer to `sim_stop_mode_operation_t`.

```
static inline void SIM_EnterLPMode(SIM_Type *base)
```

Enters into LPMode when the advanced power mode is enabled(register FOPT[1] bit is set).

Note: Please make sure the power mode register is not set as write protected before invoking this function.

Note: This function is useful only when the FTFE module's FOPT[0] bit is set(advanced power mode is enabled).

Parameters

- base – SIM peripheral base address.

```
static inline void SIM_ExitLPMode(SIM_Type *base)
```

Exits from LPMode when the advanced power mode is enabled(register FOPT[1] bit is set).

Note: Please make sure the power mode register is not set as write protected before invoking this function.

Note: This function is useful only when the FTFE module's FOPT[0] bit is set(advanced power mode is enabled).

Parameters

- base – SIM peripheral base address.

```
static inline void SIM_EnterVLPMMode(SIM_Type *base)
```

Enters into VLPMMode when the advanced power mode is enabled(register FOPT[1] bit is set).

Note: Please make sure the power mode register is not set as write protected before invoking this function. If both set to enter LPMode and VLPMMode, the VLPMMode has higher priority.

Note: This function is useful only when the FTFE module's FOPT[0] bit is set(advanced power mode is enabled).

Parameters

- base – SIM peripheral base address.

static inline void SIM_ExitVLPMMode(SIM_Type *base)

Exits from VLPMMode when the advanced power mode is enabled(register FOPT[1] bit is set).

Note: Please make sure the power mode register is not set as write protected before invoking this function.

Note: This function is useful only when the FTFE module's FOPT[0] bit is set(advanced power mode is enabled).

Parameters

- base – SIM peripheral base address.

static inline bool SIM_IsInLPMode(SIM_Type *base)

Indicates whether the chip is in LPMode when the advanced power mode is enabled(register FOPT[1] bit is set).

Note: This function is useful only when the FTFE module's FOPT[0] bit is set(advanced power mode is enabled).

Parameters

- base – SIM peripheral base address.

Return values

- true – The chip is in LPMode.
- false – The chip is not in LPMode.

static inline bool SIM_IsInVLPMMode(SIM_Type *base)

Indicates whether the chip is in VLPMMode when the advanced power mode is enabled(register FOPT[1] bit is set).

Note: This function is useful only when the FTFE module's FOPT[0] bit is set(advanced power mode is enabled).

Parameters

- base – SIM peripheral base address.

Return values

- true – The chip is in VLPMMode.
- false – The chip is not in VLPMMode.

static inline void SIM_TriggerSoftwareReset(SIM_Type *base)

Triggers the software reset for device.

Parameters

- base – SIM base address.

static inline uint16_t SIM_GetResetStatusFlags(SIM_Type *base)

Gets the cause of the most recent reset.

Note: At any given time, the only one reset source is indicated. When multiple reset source assert simultaneously, the reset source with the highest precedence is indicated. The precedence from highest to lowest is POR, external reset, COP loss of reference reset, COP CPU time-out reset, software reset, COP window time-out reset. The POR is always set during a power-on reset. However, POR is cleared and the external reset is set if the external reset pin is asserted or remains asserted after the power-on reset has de-asserted.

Parameters

- base – SIM peripheral base address.

Returns

The current reset status flags, should be the OR'ed value of `_sim_reset_status_flags`.

```
static inline void SIM_TriggerPeripheralSoftwareReset(SIM_Type *base,
                                                    sim_swReset_peri_index_t ePeriIndex)
```

Triggers the software reset of specific peripheral.

Parameters

- base – SIM peripheral base address.
- ePeriIndex – The index of the peripheral to be reset.

```
static inline void SIM_EnableResetPadCellInputFilter(SIM_Type *base, bool bEnable)
```

Enables/Disables the input filter on external reset padcell.

If the input filter is enabled, the filter will remove transient signals on the input at the expense of an increased input delay.

Note: If the input filter is enabled, the filter will affect all input functions supported by that padcell, including GPIO.

Parameters

- base – SIM peripheral base address.
- bEnable – Used to control the behaviour of input filter.
 - **true** Enable the input filter on external input padcell.
 - **false** Disable the input filter on external input padcell.

```
static inline void SIM_SetInternalPeriInput(SIM_Type *base, sim_internal_peri_index_t eIndex,
                                           sim_internal_peri_input_t eInput)
```

Sets internal peripheral inputs, some peripheral inputs have the ability to be connected to either XBAR outputs or GPIO.

Parameters

- base – SIM base address.
- eIndex – The internal peripherals that supply multi-inputs.
- eInput – The specific input that connected to the selected internal peripheral.

```
static inline void SIM_SetXbarInputAdcTmrSelection(SIM_Type *base,
                                                    sim_xbar_input_adc_tmr_index_t eIndex,
                                                    sim_xbar_input_adc_tmr_selection_t eSelection)
```

Selects the Xbar input from ADC and TMR A/B.

Parameters

- base – SIM base address.
- eIndex – SIM ADC and TMR select register field index.
- eSelection – Xbar input ADC and TMR selection.

```
static inline void SIM_XBARInputFilter(SIM_Type *base, sim_xbar_input_t eXbarInput, uint8_t  
                                     u8SamplePeriod, sim_xbar_filter_count_t eCount)
```

Sets XBAR input filter period and count.

Parameters

- base – SIM peripheral base address.
- eXbarInput – XBAR input index.
- u8SamplePeriod – XBAR input filter sample period, in unit of 1 IP bus clock. u8SamplePeriod must be range in 0~31, where 0 means filter disabled.
- eCount – Count for filter, which means eCount consecutive samples must agree to be accepted as transition.

```
static inline void SIM_SetSmallRegulator1P2VControlMode(SIM_Type *base,  
                                                         sim_small_regulator_1P2V_control_mode_t  
                                                         eControlMode)
```

Sets the control mode of small regulator 1.2V supply, the available control modes are normal mode, standby mode, etc.

Note: This function is useful only when the flash module's FOPT[0] bit is 0.

Parameters

- base – SIM peripheral base address.
- eControlMode – The control mode to be set, please refer to *sim_small_regulator_1P2V_control_mode_t*.

```
static inline void SIM_SetSmallRegulator2P7VControlMode(SIM_Type *base,  
                                                         sim_small_regulator_2P7V_control_mode_t  
                                                         eControlMode)
```

Sets the control mode of small regulator 2.7 supply, the available control modes are normal mode, standby mode, etc.

Note: This function is useful only when the flash module's FOPT[0] bit is 0.

Parameters

- base – SIM peripheral base address.
- eControlMode – The control mode to be set, please refer to *sim_small_regulator_2P7V_control_mode_t*.

```
static inline void SIM_SetLargeRegulatorControlMode(SIM_Type *base,  
                                                     sim_large_regulator_control_mode_t  
                                                     eControlMode)
```

Sets the control mode of large regulator, the available control mode are normal mode, standby mode, etc.

Note: This function is useful only when the flash module's FOPT[0] bit is 0.

Parameters

- base – SIM peripheral base address.
- eControlMode – The control mode to be set, please refer to `sim_large_regulator_control_mode_t`.

```
static inline void SIM_SetRegisterProtectionMode(SIM_Type *base,  
                                                sim_write_protection_module_t eModule,  
                                                sim_write_protection_mode_t eMode)
```

Sets the write protection mode of the selected register.

Parameters

- base – SIM peripheral base address.
- eModule – The module to be set, please refer to `sim_write_protection_module_t`.
- eMode – The specific write protection mode to be set, please refer to `sim_write_protection_mode_t`.

```
static inline uint32_t SIM_GetJTAGID(SIM_Type *base)
```

Gets JTAG ID, the JTAG ID is 32bits width.

Parameters

- base – SIM base address.

Returns

The 32bits width JTAG ID.

```
static inline void SIM_SetIOShortAddressValue(SIM_Type *base, uint32_t  
                                              u32IOShortAddressValue)
```

Sets the I/O short address location value which specifies the memory referenced through the I/O short address mode.

The I/O short address mode allows the instruction to specify the lower 6 bits of the address. And the upper 18 bits of the address can be controlled by invoking this function.

Note: The pipeline delay between setting the related register set and using short I/O addressing with the new value is five cycles.

Parameters

- base – SIM base address.
- u32IOShortAddressValue – The value of I/O short address location, this address value should be 24 bits width.

```
static inline uint16_t SIM_GetSoftwareControlData(SIM_Type *base,  
                                                  sim_software_ctrl_register_index_t  
                                                  eIndex)
```

Gets the software control data by the software control register index.

Parameters

- base – SIM base address.
- eIndex – SIM software control register index.

Returns

Software control registers value.

```
static inline void SIM_SetSoftwareControlData(SIM_Type *base,  
                                             sim_software_ctrl_register_index_t eIndex,  
                                             uint16_t u16Value)
```

Sets the software control data by the software control register index, the data is for general-purpose use by software.

Parameters

- base – SIM base address.
- eIndex – SIM software control register index.
- u16Value – Software control registers value.

```
static inline void SIM_SetOnCEClockOperationMode(SIM_Type *base,  
                                                sim_onceclk_operation_mode_t  
                                                eOperationMode)
```

Sets the operation mode of the OnCE clock, the available operation modes are always enabled and enabled when the core TAP is enabled.

Parameters

- base – SIM peripheral base address.
- eOperationMode – The operation mode of OnCE clock, please refer to `sim_onceclk_operation_mode_t`.

```
static inline void SIM_SetDMAOperationMode(SIM_Type *base, sim_dma_operation_mode_t  
                                           eOperationMode)
```

Sets the operation mode of DMA, such as disabled, enabled in run mode only, etc.

Parameters

- base – SIM peripheral base address.
- eOperationMode – The operation mode to be set, please refer to `sim_dma_operation_mode_t`.

```
static inline void SIM_SetLPI2C0TriggerSelection(SIM_Type *base, sim_lpi2c_trigger_selection_t  
                                                eTriggerSelection)
```

Sets the trigger selection of lpi2c0, the available selections are master trigger and slave trigger.

This function can be used to selection the LPI2C0 output trigger. If selected as master trigger, the LPI2C0 master will generate an output trigger that can be connected to other peripherals on the device. If selected as slave trigger, the LPI2C0 slave will generate an output trigger that can be connected to other peripherals on the device.

Parameters

- base – SIM peripheral base address.
- eTriggerSelection – The trigger selection to set, please refer to `sim_lpi2c_trigger_selection_t`.

```
static inline sim_device_operate_mode_t SIM_GetDeviceOperateMode(SIM_Type *base)
```

Gets device currently operate mode, the possible result is normal operate mode or fast operate mode.

Parameters

- base – SIM peripheral base address.

Returns

Current device's operate mode.

static inline void SIM_EnableADCScanControlReorder(SIM_Type *base, bool bEnable)

Enables/Disables the ADC scan control register reorder feature.

Parameters

- base – SIM peripheral base address.
- bEnable – Used to control the ADC scan control register reorder feature.
 - **true** Enable the re-ordering of ADC scan control bits.
 - **false** ADC scan control register works in normal order.

static inline void SIM_SetMasterPIT(SIM_Type *base, sim_master_pit_selection_t eMasterPit)

Sets master programmable interval timer.

Parameters

- base – SIM peripheral base address.
- eMasterPit – The master PIT to be selected, please refer to `sim_master_pit_selection_t`.

enum _sim_reset_status_flags

The enumeration of system reset status flags, such as power on reset, software reset, etc.

Values:

enumerator kSIM_PowerONResetFlag

The Power on reset caused the most recent reset.

enumerator kSIM_ExternalResetFlag

The external reset caused the most recent reset, that means the external reset pin was asserted or remained asserted after the power-on reset de-asserted.

enumerator kSIM_COPLossOfReferenceResetFlag

The computer operating properly module signaled a loss of reference clock reset caused the most recent reset.

enumerator kSIM_COPCPUTimeOutResetFlag

The computer operating properly module signaled a CPU time-out reset caused the most recent reset.

enumerator kSIM_SoftwareResetFlag

The previous system reset occurred as a result of a software reset

enumerator kSIM_COPWindowTimeOutResetFlag

The previous system reset occurred as a result of a cop_window reset.

enum _sim_stop_mode_operation

The enumeration of stop mode operation can be used to enable/disable stop mode enter.

Values:

enumerator kSIM_STOPInstructionEnterStopMode

Stop mode is entered when the DSC core executes a STOP instruction.

enumerator kSIM_STOPInstructionNotEnterStopMode

The DSC core STOP instruction does not cause entry into stop mode.

enumerator kSIM_STOPInstructionEnterStopModeWriteProtect

Stop mode is entered when the DSC core executes a STOP instruction, and the related register bit field is write protected until the next reset.

enumerator kSIM_STOPInstructionNotEnterStopModeWriteProtect

The DSC core STOP instruction does not cause entry into stop mode, and the related register bit field is write protected until the next reset.

enum _sim_wait_mode_operation

The enumeration of wait mode operation can be used to enable/disable wait mode enter.

Values:

enumerator kSIM_WAITInstructionEnterWaitMode

Wait mode is entered when the DSC core executes a WAIT instruction.

enumerator kSIM_WAITInstructionNotEnterWaitMode

The DSC core WAIT instruction does not cause entry into wait mode.

enumerator kSIM_WAITInstructionEnterWaitModeWriteProtect

Wait mode is entered when the DSC core executes a WAIT instruction, and the related register bit field is write protected until the next reset.

enumerator kSIM_WAITInstructionNotEnterWaitModeWriteProtect

The DSC core WAIT instruction does not cause entry into wait mode, and the related register bit field is write protected until the next reset.

enum _sim_onceclk_operation_mode

The enumeration of OnCE clock operation mode, such as enabled when core TAP is enabled and always enabled.

Values:

enumerator kSIM_OnCEClkEnabledWhenCoreTapEnabled

The OnCE clock to the DSC core is enabled when the core TAP is enabled.

enumerator kSIM_OnCEClkAlwaysEnabled

The OnCE clock to the DSC core is always enabled.

enum _sim_dma_operation_mode

The enumeration of dma operation mode, this enumeration can be used to disable/enable DMA module in different power modes.

Values:

enumerator kSIM_DMADisable

DMA module is disabled.

enumerator kSIM_DMAEnableAtRunModeOnly

DMA module is enabled in run mode only.

enumerator kSIM_DMAEnableAtRunModeWaitMode

DMA module is enabled in run and wait modes only.

enumerator kSIM_DMAEnableAtAllPowerModes

DMA module is enabled in all power modes.

enumerator kSIM_DMADisableWriteProtect

DMA module is disabled and the related register bit field is write protected until the next reset.

enumerator kSIM_DMAEnableAtRunModeOnlyWriteProtect

DMA module is enabled in run mode only and the related bit field is write protected until the next reset.

enumerator kSIM_DMAEnableAtRunModeWaitModeWriteProtect

DMA module is enabled in run and wait modes only and the related register bit field is write protected until the next reset.

enumerator kSIM_DMAEnableAtAllPowerModesWriteProtect

DMA module is enabled in all low power modes and the related register bit field is write protected until the next reset.

enum _sim_small_regulator_1P2V_control_mode

The enumeration of small regulator 1P2V control mode, such as normal mode and standby mode.

Values:

enumerator kSIM_SmallRegulator1P2VInNormalMode

Small regulator 1.2V supply placed in normal mode.

enumerator kSIM_SmallRegulator1P2VInStandbyMode

Small regulator 1.2V supply placed in standby mode.

enumerator kSIM_SmallRegulator1P2VInNormalModeWriteProtect

Small regulator 1.2V supply placed in normal mode, and the related register bit field is write protected until the next reset.

enumerator kSIM_SmallRegulator1P2VInStandbyModeWriteProtect

Small regulator 1.2V supply placed in standby mode, and the related register bit field is write protected until the next reset.

enum _sim_small_regulator_2P7V_control_mode

The enumeration of small regulator 2P7V control mode, such as normal mode, standby mode, powerdown mode, etc.

Values:

enumerator kSIM_SmallRegulator2P7VInNormalMode

Small regulator 2.7V supply placed in normal mode.

enumerator kSIM_SmallRegulator2P7VInStandbyMode

Small regulator 2.7V supply placed in standby mode.

enumerator kSIM_SmallRegulator2P7VInPowerdownMode

Small regulator 2.7V supply placed in powerdown mode.

enumerator kSIM_SmallRegulator2P7VInNormalModeWriteProtect

Small regulator 2.7V supply placed in normal mode and the related bit field is write protected until chip reset.

enumerator kSIM_SmallRegulator2P7VInStandbyModeWriteProtect

Small regulator 2.7V supply placed in standby mode and the related bit field is write protected until chip reset.

enumerator kSIM_SmallRegulator2P7VInPowerdownModeWriteProtect

Small regulator placed in powerdown mode and the related bit field is write protected until chip reset.

enum _sim_large_regulator_control_mode

The enumeration of large regulator control mode, such as normal mode, standby mode.

Values:

enumerator kSIM_LargeRegulatorInNormalMode

Large regulator placed in normal mode.

enumerator kSIM_LargeRegulatorInStandbyMode

Large regulator placed in standby mode.

enumerator kSIM_LargeRegulatorInNormalModeWriteProtect

Large regulator placed in normal mode, and the related register bit field is write protected until chip reset.

enumerator kSIM_LargeRegulatorInStandbyModeWriteProtect

Large regulator placed in standby mode, and the related register bit field is write protected until chip reset.

enum _sim_write_protection_module

The enumeration of modules that support various protection mode.

Values:

enumerator kSIM_GPIOInternalPeripheralSelectProtection

Used to control the protection mode GPSn and IPSn registers in the SIM, all XBAR, EVTG, GPIO_n_PER, GPIO_n_PPMODE, GPIO_n_DRIVE.

enumerator kSIM_PeripheralClockEnableProtection

Used to control the protection mode of PCEn, SDn, PSWRn, and PCR register.

enumerator kSIM_GPIOPortDPProtection

Used to control the protection mode of GPIO_D_PER, GPIO_D_PPMODE, and GPIO_D_DRIVE register.

enumerator kSIM_PowerModeControlWriteProtection

Used to control the protection mode of the PWRMODE register.

enum _sim_write_protection_mode

The enumeration of write protection mode, such as write protection off, write protection on, etc.

Values:

enumerator kSIM_WriteProtectionOff

Write protection off.

enumerator kSIM_WriteProtectionOn

Write protection on.

enumerator kSIM_WriteProtectionOffAndLocked

Write protection off and locked until chip reset.

enumerator kSIM_WriteProtectionOnAndLocked

Write protection on and locked until chip reset.

enum _sim_lpi2c_trigger_selection

The enumeration of lpi2c trigger selection, including slave trigger and master trigger.

Values:

enumerator kSIM_Lpi2cSlaveTrigger

Selects slave trigger.

enumerator kSIM_Lpi2cMasterTrigger

Selects master trigger.

enum _sim_device_operate_mode

The enumeration of device operate mode, including normal mode and fast mode.

Values:

enumerator kSIM_NormalOperateMode

Device in normal operating mode, core:bus:flash frequency as 2:2:1

enumerator kSIM_FastOperateMode

Device in fast operate mode, core:bus:flash frequency as 4:4:1

enum _sim_master_pit_selection

The enumeration of master pit.

Values:

enumerator kSIM_PIT0MasterPIT1Slave

PIT0 is master PIT and PIT1 is slave PIT.

enumerator kSIM_PIT1MasterPIT0Slave

PIT0 is master PIT and PIT1 is slave PIT.

enum _sim_xbar_input

The enumeration of XBAR input.

Values:

enumerator kSIM_XBARInput2

XBAR Input 2.

enumerator kSIM_XBARInput3

XBAR Input 3.

enumerator kSIM_XBARInput4

XBAR Input 4.

enumerator kSIM_XBARInput5

XBAR Input 5.

enumerator kSIM_XBARInput6

XBAR Input 6.

enumerator kSIM_XBARInput7

XBAR Input 7.

enumerator kSIM_XBARInput8

XBAR Input 8.

enumerator kSIM_XBARInput9

XBAR Input 9.

enum _sim_xbar_filter_count

The enumeration of XBAR filter count.

Values:

enumerator kSIM_XBARFilter3Count

3 consecutive sample must agree.

enumerator kSIM_XBARFilter4Count

4 consecutive sample must agree.

enumerator kSIM_XBARFilter5Count

5 consecutive sample must agree.

enumerator kSIM_XBARFilter6Count

6 consecutive sample must agree.

enumerator kSIM_XBARFilter7Count

7 consecutive sample must agree.

enumerator kSIM_XBARFilter8Count

8 consecutive sample must agree.

enumerator kSIM_XBARFilter9Count

9 consecutive sample must agree.

enumerator kSIM_XBARFilter10Count

10 consecutive sample must agree.

typedef enum *_sim_stop_mode_operation* sim_stop_mode_operation_t

The enumeration of stop mode operation can be used to enable/disable stop mode enter.

typedef enum *_sim_wait_mode_operation* sim_wait_mode_operation_t

The enumeration of wait mode operation can be used to enable/disable wait mode enter.

typedef enum *_sim_onceclk_operation_mode* sim_onceclk_operation_mode_t

The enumeration of OnCE clock operation mode, such as enabled when core TAP is enabled and always enabled.

typedef enum *_sim_dma_operation_mode* sim_dma_operation_mode_t

The enumeration of dma operation mode, this enumeration can be used to disable/enable DMA module in different power modes.

typedef enum *_sim_small_regulator_1P2V_control_mode*

sim_small_regulator_1P2V_control_mode_t

The enumeration of small regulator 1P2V control mode, such as normal mode and standby mode.

typedef enum *_sim_small_regulator_2P7V_control_mode*

sim_small_regulator_2P7V_control_mode_t

The enumeration of small regulator 2P7V control mode, such as normal mode, standby mode, powerdown mode, etc.

typedef enum *_sim_large_regulator_control_mode* sim_large_regulator_control_mode_t

The enumeration of large regulator control mode, such as normal mode, standby mode.

typedef enum *_sim_write_protection_module* sim_write_protection_module_t

The enumeration of modules that support various protection mode.

typedef enum *_sim_write_protection_mode* sim_write_protection_mode_t

The enumeration of write protection mode, such as write protection off, write protection on, etc.

typedef enum *_sim_lpi2c_trigger_selection* sim_lpi2c_trigger_selection_t

The enumeration of lpi2c trigger selection, including slave trigger and master trigger.

typedef enum *_sim_device_operate_mode* sim_device_operate_mode_t

The enumeration of device operate mode, including normal mode and fast mode.

typedef enum *_sim_master_pit_selection* sim_master_pit_selection_t

The enumeration of master pit.

typedef enum *_sim_xbar_input* sim_xbar_input_t

The enumeration of XBAR input.

typedef enum *_sim_xbar_filter_count* sim_xbar_filter_count_t

The enumeration of XBAR filter count.

FSL_COMPONENT_ID

SIM_RESET_STATUS_MASK

The macro of REST status bit field mask.

`SIM_PWR_SR27_CONTROL_MODE_MASK`

The definition of the short regulator control mode bit field mask.

`SIM_PWR_SR27_CONTROL_MODE_SHIFT`

The definition of the short regulator control mode bit field shift.

`SIM_PWR_SR27_CONTROL_MODE(x)`

The macro that can be used to set the bit field of PWR register's short regulator bit field.

`SIM_PROT_BIT_FIELD_MASK(moduleName)`

The definition of the PORT register bit field mask.

`SIM_PORT_SET_MODE_PROTECTION_MODE(moduleName, protectionMode)`

The macro that can be used to set module's protection mode.

`SIM_XBAR_FILTER_REG_INDEX(xbarInput)`

The definition of the XBAR_FLTx register index.

`SIM_XBAR_FILTER_BIT_SHIFT(xbarInput)`

The definition of the XBAR_FLTx register bit field shift.

`SIM_XBAR_FILTER_BIT_MASK(xbarInput)`

The definition of the XBAR_FLTx register bit field mask.

2.75 SIM Peripheral and Driver Overview

2.76 XBAR: Inter-Peripheral Crossbar Switch Driver

`void XBARA_Init(XBARA_Type *base)`

Initializes the XBARA module.

This function un-gates the XBARA clock.

Parameters

- `base` – XBARA peripheral address.

`void XBARA_Deinit(XBARA_Type *base)`

Shuts down the XBARA module.

This function disables XBARA clock.

Parameters

- `base` – XBARA peripheral address.

`static inline void XBARA_SetSignalsConnection(XBARA_Type *base, xbar_input_signal_t eInput, xbar_output_signal_t eOutput)`

Sets a connection between the selected XBARA_IN[*] input and the XBARA_OUT[*] output signal.

This function connects the XBARA input to the selected XBARA output. If more than one XBARA module is available, only the inputs and outputs from the same module can be connected.

Example:

```
XBARA_SetSignalsConnection(XBARA, kXBARA_InputPIT_TRG0, kXBARA_
↪OutputDMAMUX18);
```

Parameters

- base – XBARA peripheral address.
- eInput – XBARA input signal.
- eOutput – XBARA output signal.

```
static inline void XBARA_SetActiveEdgeDetectMode(XBARA_Type *base, xbar_output_signal_t
                                                eOutput, xbara_active_edge_t
                                                eActiveEdgeMode)
```

Sets active edge detection mode for the XBARA_OUT[*] output signal.

Parameters

- base – XBARA peripheral address.
- eOutput – XBARA output signal.
- eActiveEdgeMode – Active edge mode.

```
static inline void XBARA_SetInterruptDMARequestMode(XBARA_Type *base,
                                                    xbar_output_signal_t eOutput,
                                                    xbara_request_t eRequest)
```

Sets DMA, Interrupt or disabled request generation mode for the XBARA_OUT[*] output signal.

Parameters

- base – XBARA peripheral address.
- eOutput – XBARA output signal.
- eRequest – Request type.

```
void XBARA_SetOutputSignalConfig(XBARA_Type *base, xbar_output_signal_t eOutput, const
                                xbara_control_config_t *psControlConfig)
```

Configures the XBARA output signal edge detection and interrupt/dma features.

This function configures an XBARA control register. The active edge detection and the DMA/IRQ function on the corresponding XBARA output can be set.

Example:

```
xbara_control_config_t userConfig;
userConfig.activeEdge = kXBARA_EdgeRising;
userConfig.requestType = kXBARA_RequestInterruptEnable;
XBARA_SetOutputSignalConfig(XBARA, kXBARA_OutputDMAMUX18, &userConfig);
```

Note: Only a subset of the XBARA output signal can be called with this API. On debug mode code will check whether the output signal eOutput satisfy the requirement.

Parameters

- base – XBARA peripheral address.
- eOutput – XBARA output number.
- psControlConfig – Pointer to structure that keeps configuration of control register.

```
uint16_t XBARA_GetStatusFlags(XBARA_Type *base)
```

Gets the active edge detection status for all XBAR output signal supporting this feature.

This function gets the active edge detect status of all XBARA_OUTs. If the active edge occurs, the return value is asserted. When the interrupt or the DMA functionality is enabled for

the XBARA_OUTx, this field is 1 when the interrupt or DMA request is asserted and 0 when the interrupt or DMA request has been cleared.

Parameters

- base – XBARA peripheral address.

Returns

ORed value from all status flag from xbara_status_flag_t.

```
static inline void XBARA_ClearStatusFlags(XBARA_Type *base, uint16_t u16Flags)
```

Clear the edge detection status flags of relative mask.

Parameters

- base – XBARA peripheral address.
- u16Flags – status flags composed from ORed xbara_status_flag_t indicating flags to be cleared.

```
FSL_XBAR_DRIVER_VERSION
```

XBAR driver version.

```
enum __xbara_active_edge
```

XBARA active edge for detection.

Values:

```
enumerator kXBARA_EdgeNone
```

Edge detection status bit never asserts.

```
enumerator kXBARA_EdgeRising
```

Edge detection status bit asserts on rising edges.

```
enumerator kXBARA_EdgeFalling
```

Edge detection status bit asserts on falling edges.

```
enumerator kXBARA_EdgeRisingAndFalling
```

Edge detection status bit asserts on rising and falling edges.

```
enum __xbara_request
```

XBARA DMA and interrupt configurations. Note it only apply for a subset of XBARA output signal.

Values:

```
enumerator kXBARA_RequestDisable
```

Interrupt and DMA are disabled.

```
enumerator kXBARA_RequestDMAEnable
```

DMA enabled, interrupt disabled.

```
enumerator kXBARA_RequestInterruptEnable
```

Interrupt enabled, DMA disabled.

```
enum __xbara_status_flag
```

XBARA status flags.

This provides constants for the XBARA status flags for use in the XBARA functions. The enumerator value is designed to make sure Flags in same register can be created with register value to write/read register.

Values:

```
enumerator kXBARA_EdgeDetectionOut0Flag
```

XBAR_OUT0 active edge interrupt flag, sets when active edge detected.

enumerator kXBARA_EdgeDetectionOut1Flag

XBAR_OUT1 active edge interrupt flag, sets when active edge detected.

enumerator kXBARA_EdgeDetectionOut2Flag

XBAR_OUT2 active edge interrupt flag, sets when active edge detected.

enumerator kXBARA_EdgeDetectionOut3Flag

XBAR_OUT3 active edge interrupt flag, sets when active edge detected.

enumerator kXBARA_AllStatusFlags

typedef enum *_xbara_active_edge* xbara_active_edge_t

XBARA active edge for detection.

typedef enum *_xbara_request* xbara_request_t

XBARA DMA and interrupt configurations. Note it only apply for a subset of XBARA output signal.

typedef enum *_xbara_status_flag* xbara_status_flag_t

XBARA status flags.

This provides constants for the XBARA status flags for use in the XBARA functions. The enumerator value is designed to make sure Flags in same register can be created with register value to write/read register.

typedef struct *_xbara_control_config* xbara_control_config_t

Defines the configuration structure of the XBARA control register.

This structure keeps the configuration of XBARA control register for one output. Control registers are available only for a few outputs. Not every XBARA module has control registers.

XBARA_SELx(base, output)

Macro function to extract the XBAR select register address for a given xbar output signal.

XBARA_CTRLx(base, output)

Macro function to extract the XBAR Ctrl register address for a given xbar output signal.

XBARA_SELx_SELn_SHIFT(output)

Macro function to get SELn field shift in XBARA_SELx register for a given output signal.

XBARA_SELx_SELn_MASK(output)

Macro function to get SELn field mask in XBARA_SELx register for a given output signal.

XBARA_SELx_SELn(output, input_signal)

Macro function to create SELn field value in XBARA_SELx register for given output signal and input signal value input_signal, see xbar_input_signal_t.

XBARA_CTRLx_DIENn_MASK(output)

Macro function to get DIENn field mask in XBARA_CTRLx register for a given output signal.

XBARA_CTRLx_DIENn_SHIFT(output)

Macro function to get DIENn field shift in XBARA_CTRLx register for a given output signal.

XBARA_CTRLx_DIENn(output, x)

Macro function to create DIENn field value in XBARA_CTRLx register for given output signal and DMA/Interrupt mode x, see xbara_request_t.

XBARA_CTRLx_EDGEn_MASK(output)

Macro function to get EDGEn field mask in XBARA_CTRLx register for a given output signal.

XBARA_CTRLx_EDGEn_SHIFT(output)

Macro function to get EDGEn field shift in XBARA_CTRLx register for a given output signal.

`XBARA_CTRLx_EDGEn(output, x)`

Macro function to create EDGEn field value in XBARA_CTRLx register for given output signal and edge mode x, see `xbara_active_edge_t`.

`XBARA_CTRLx_STS_MASK`

Macro value for the Status bits in CTRL register.

`struct __xbara_control_config`

#include <fsl_xbara.h> Defines the configuration structure of the XBARA control register.

This structure keeps the configuration of XBARA control register for one output. Control registers are available only for a few outputs. Not every XBARA module has control registers.

Public Members

`xbara_active_edge_t eActiveEdge`

Active edge to be detected.

`xbara_request_t eRequestType`

Selects DMA/Interrupt request.

2.77 The Driver Change Log

2.78 XBAR Peripheral and Driver Overview

Chapter 3

Middleware

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