
i.MX53 SABRE TABLET Linux Reference Manual

Part Number: 924-76374
Rev. 1
05/2011



How to Reach Us:

Home Page:

www.freescale.com

Web Support:

<http://www.freescale.com/support>

USA/Europe or Locations Not Listed:

Freescale Semiconductor, Inc.
Technical Information Center, EL516
2100 East Elliot Road
Tempe, Arizona 85284
1-800-521-6274 or
+1-480-768-2130
www.freescale.com/support

Europe, Middle East, and Africa:

Freescale Halbleiter Deutschland GmbH
Technical Information Center
Schatzbogen 7
81829 Muenchen, Germany
+44 1296 380 456 (English)
+46 8 52200080 (English)
+49 89 92103 559 (German)
+33 1 69 35 48 48 (French)
www.freescale.com/support

Japan:

Freescale Semiconductor Japan Ltd.
Headquarters
ARCO Tower 15F
1-8-1, Shimo-Meguro, Meguro-ku
Tokyo 153-0064
Japan
0120 191014 or
+81 3 5437 9125
support.japan@freescale.com

Asia/Pacific:

Freescale Semiconductor China Ltd.
Exchange Building 23F
No. 118 Jianguo Road
Chaoyang District
Beijing 100022
China
+86 10 5879 8000
support.asia@freescale.com

For Literature Requests Only:

Freescale Semiconductor
Literature Distribution Center
1-800 441-2447 or
+1-303-675-2140
Fax: +1-303-675-2150
LDCForFreescaleSemiconductor@hibbertgroup.com

Information in this document is provided solely to enable system and software implementers to use Freescale Semiconductor products. There are no express or implied copyright licenses granted hereunder to design or fabricate any integrated circuits or integrated circuits based on the information in this document.

Freescale Semiconductor reserves the right to make changes without further notice to any products herein. Freescale Semiconductor makes no warranty, representation or guarantee regarding the suitability of its products for any particular purpose, nor does Freescale Semiconductor assume any liability arising out of the application or use of any product or circuit, and specifically disclaims any and all liability, including without limitation consequential or incidental damages. "Typical" parameters which may be provided in Freescale Semiconductor data sheets and/or specifications can and do vary in different applications and actual performance may vary over time. All operating parameters, including "Typicals" must be validated for each customer application by customer's technical experts. Freescale Semiconductor does not convey any license under its patent rights nor the rights of others. Freescale Semiconductor products are not designed, intended, or authorized for use as components in systems intended for surgical implant into the body, or other applications intended to support or sustain life, or for any other application in which the failure of the Freescale Semiconductor product could create a situation where personal injury or death may occur. Should Buyer purchase or use Freescale Semiconductor products for any such unintended or unauthorized application, Buyer shall indemnify and hold Freescale Semiconductor and its officers, employees, subsidiaries, affiliates, and distributors harmless against all claims, costs, damages, and expenses, and reasonable attorney fees arising out of, directly or indirectly, any claim of personal injury or death associated with such unintended or unauthorized use, even if such claim alleges that Freescale Semiconductor was negligent regarding the design or manufacture of the part.

Freescale and the Freescale logo are trademarks or registered trademarks of Freescale Semiconductor, Inc. in the U.S. and other countries. All other product or service names are the property of their respective owners.

© Freescale Semiconductor, Inc., 2004-2011. All rights reserved.



Contents

Paragraph Number	Title	Page Number
About This Book		
Audience	xxi	
Conventions	xxi	
Definitions, Acronyms, and Abbreviations	xxi	
Suggested Reading	xxiv	
Chapter 1		
Introduction		
1.1	Software Base	6-1
1.2	Features	6-2
Chapter 2		
Machine Specific Layer (MSL)		
2.1	Interrupts	7-1
2.1.1	Interrupt Hardware Operation.....	7-1
2.1.2	Interrupt Software Operation	7-2
2.1.3	Interrupt Features	7-2
2.1.4	Interrupt Source Code Structure	7-2
2.1.5	Interrupt Programming Interface	7-2
2.2	Timer	7-3
2.2.1	Timer Hardware Operation	7-3
2.2.2	Timer Software Operation	7-3
2.2.3	Timer Features	7-3
2.2.4	Timer Source Code Structure.....	7-4
2.3	Memory Map	7-4
2.3.1	Memory Map Hardware Operation.....	7-4
2.3.2	Memory Map Software Operation.....	7-4
2.3.3	Memory Map Features.....	7-4
2.3.4	Memory Map Source Code Structure	7-4
2.3.5	Memory Map Programming Interface	7-4
2.4	IOMUX	7-5
2.4.1	IOMUX Hardware Operation	7-5
2.4.2	IOMUX Software Operation	7-5
2.4.3	IOMUX Features	7-5
2.4.4	IOMUX Source Code Structure.....	7-6
2.4.5	IOMUX Programming Interface.....	7-6
2.5	General Purpose Input/Output (GPIO)	7-6
2.5.1	GPIO Software Operation.....	7-6

Contents

Paragraph Number	Title	Page Number
2.5.1.1	API for GPIO	7-6
2.5.2	GPIO Features.....	7-7
2.5.3	GPIO Source Code Structure.....	7-7
2.5.4	GPIO Programming Interface.....	7-7

Chapter 3 Smart Direct Memory Access (SDMA) API

3.1	Overview.....	8-1
3.2	Hardware Operation.....	8-1
3.3	Software Operation.....	8-1
3.4	Source Code Structure.....	8-3
3.5	Menu Configuration Options.....	8-3
3.6	Programming Interface.....	8-4
3.7	Usage Example.....	8-4

Chapter 4 Universal Asynchronous Receiver/Transmitter (UART) Driver

4.1	Hardware Operation.....	9-1
4.2	Software Operation.....	9-2
4.3	Driver Features.....	9-2
4.4	Source Code Structure.....	9-3
4.5	Configuration.....	9-3
4.5.1	Menu Configuration Options.....	9-3
4.5.2	Source Code Configuration Options.....	9-4
4.5.2.1	Chip Configuration Options.....	9-4
4.5.2.2	Board Configuration Options.....	9-4
4.6	Programming Interface.....	9-4
4.7	Interrupt Requirements.....	9-4

Chapter 5 DA9053 PMIC Driver

5.1	Hardware information.....	10-1
5.2	Software Drivers.....	10-1
5.3	Source code structure.....	10-2
5.4	Menu Configuration Options.....	10-2

Chapter 6 ARC USB Driver

Contents

Paragraph Number	Title	Page Number
6.1	Architectural Overview.....	11-2
6.2	Hardware Operation.....	11-2
6.3	Software Operation.....	11-2
6.4	Driver Features.....	11-3
6.5	Source Code Structure.....	11-4
6.6	Menu Configuration Options.....	11-5
6.7	Programming Interface.....	11-6
6.8	Default USB Settings.....	11-7
6.9	USB Wakeup usage.....	11-7
6.9.1	How to enable usb wakeup system ability.....	11-7
6.9.2	What kinds of wakeup event usb support.....	11-7
6.9.3	How to close the usb child device power.....	11-8

Chapter 7 Image Processing Unit (IPU) Drivers

7.1	Hardware Operation.....	12-2
7.2	Software Operation.....	12-2
7.2.1	IPU Frame Buffer Drivers Overview.....	12-3
7.2.1.1	IPU Frame Buffer Hardware Operation.....	12-4
7.2.1.2	IPU Frame Buffer Software Operation.....	12-4
7.2.1.3	Synchronous Frame Buffer Driver.....	12-4
7.3	Source Code Structure.....	12-6
7.4	Menu Configuration Options.....	12-7
7.5	Programming Interface.....	12-9

Chapter 8 HDMI Driver

8.1	Hardware Operation.....	13-1
8.2 Software Operation	13-1
8.3	Source Code Structure.....	13-2
8.4	Linux Menu Configuration Options.....	13-2

Chapter 9 MXC DDC Driver

9.1	MXC DDC Driver Overview.....	14-1
9.1.1	Hardware Operation.....	14-1
9.1.2 Software Operation	14-1
9.2	Source Code Structure Configuration.....	14-1

Contents

Paragraph Number	Title	Page Number
9.3	Driver Configuration.....	14-2
Chapter 10 i.MX5 Dual Display		
10.1	Hardware Operation.....	15-1
10.2	Software Operation.....	15-1
10.3	Examples.....	15-3
Chapter 11 Video for Linux Two (V4L2) Driver		
11.1	V4L2 Capture Device.....	16-2
11.1.1	V4L2 Capture IOCTLs.....	16-2
11.1.2	Use of the V4L2 Capture APIs.....	16-4
11.2	V4L2 Output Device.....	16-5
11.2.1	V4L2 Output IOCTLs.....	16-5
11.2.2	Use of the V4L2 Output APIs.....	16-6
11.3	Source Code Structure.....	16-6
11.4	Menu Configuration Options.....	16-7
11.5	V4L2 Programming Interface.....	16-7
Chapter 12 Graphics Processing Unit (GPU)		
12.1	Driver Features.....	17-1
12.2	Hardware Operation.....	17-1
12.3	Software Operation.....	17-1
12.4	Source Code Structure.....	17-1
12.5	API References.....	17-2
12.6	Menu Configuration Options.....	17-2
Chapter 13 X Windows Acceleration		
13.1	Hardware Operation.....	18-1
13.2	Software Operation.....	18-1
13.2.1	X Windows Acceleration Architecture.....	18-1
13.2.2	i.MX X Driver Details.....	18-3
13.2.3	libz160 Details.....	18-4
13.2.4	EGL-X Details.....	18-4

Contents

Paragraph Number	Title	Page Number
13.2.5	The xorg.conf File for i.MX X Driver	18-5
13.2.6	Setup X Windows Acceleration	18-6

Chapter 14 Video Processing Unit (VPU) Driver

14.1	Hardware Operation	19-1
14.2	Software Operation	19-2
14.3	Source Code Structure	19-3
14.4	Menu Configuration Options	19-4
14.5	Programming Interface	19-4
14.6	Defining an Application	19-5

Chapter 15 Low-level Power Management (PM) Driver

15.1	Hardware Operation	20-1
15.2	Software Operation	20-1
15.3	Source Code Structure	20-2
15.4	Menu Configuration Options	20-2
15.5	Programming Interface	20-2

Chapter 16 Dynamic Voltage Frequency Scaling (DVFS) Driver

16.1	Hardware Operation	21-1
16.2	Software Operation	21-1
16.3	Source Code Structure	21-1
16.4	Menu Configuration Options	21-2
16.4.1	Board Configuration Options	21-2

Chapter 17 CPU Frequency Scaling (CPUFREQ) Driver

17.1	Software Operation	22-1
17.2	Source Code Structure	22-1
17.3	Menu Configuration Options	22-2
17.3.1	Board Configuration Options	22-2

Chapter 18 Software Based Peripheral Domain Frequency Scaling

Contents

Paragraph Number	Title	Page Number
18.1	Software based Bus Frequency Scaling.....	23-1
18.1.1	Low Power Audio Playback Mode (LPAPM)	23-1
18.1.2	Medium Frequency Setpoint.....	23-2
18.1.3	High Frequency Setpoint	23-2
18.2	Source Code Structure	23-2
18.3	Menu Configuration Options	23-2
18.3.1	Board Configuration Options.....	23-2

Chapter 19 MAX17085 charger Driver

19.1	Overview.....	24-1
19.1.1	Hardware Operation.....	24-1
19.1.2 Software Operation	24-1
19.2	Source Code Structure Configuration.....	24-2
19.3	Driver Configuration.....	24-2

Chapter 20 ISL29023 Ambient Light Sensor Driver

20.1	ISL29023 Features	25-1
20.2	Driver Requirements.....	25-1
20.3	Driver Architecture	25-1
20.4	Driver Source Code Structure.....	25-2
20.5	Driver Configuration.....	25-2

Chapter 21 Advanced Linux Sound Architecture (ALSA) System on a Chip (ASoC) Sound Driver

21.1	SoC Sound Card.....	26-1
21.1.1	Stereo Codec Features	26-2
21.1.2	Sound Card Information	26-2
21.2	ASoC Driver Source Architecture	26-2
21.3	Menu Configuration Options	26-4
21.4	Hardware Operation.....	26-4
21.4.1	Stereo Audio Codec	26-4
21.5	Software Operation	26-5
21.5.1	Sound Card Registration.....	26-5
21.5.2	Device Open	26-5
21.6	Platform Data.....	26-6

Contents

Paragraph Number	Title	Page Number
Chapter 22		
The Sony/Philips Digital Interface (S/PDIF) Driver		
22.1	S/PDIF Overview	27-1
22.1.1	Hardware Overview	27-1
22.1.2	Software Overview	27-2
22.1.3	The ASoC layer	27-2
22.2	S/PDIF Tx Driver.....	27-2
22.2.1	Driver Design.....	27-3
22.2.2	Provided User Interface	27-4
22.3	Interrupts and Exceptions	27-4
22.4	Source Code Structure	27-4
22.5	Menu Configuration Options	27-4
22.6	Platform Data	27-5
Chapter 23		
Asynchronous Sample Rate Converter (ASRC) Driver		
23.1	Hardware Operation.....	28-1
23.2	Software Operation	28-1
23.2.1	Sequence for Memory to ASRC to Memory	28-2
23.2.2	Sequence for Memory to ASRC to Peripheral.....	28-3
23.3	Source Code Structure	28-3
23.3.1	Linux Menu Configuration Options	28-3
23.4	Platform Data	28-3
23.5	Programming Interface (Exported API and IOCTLs)	28-3
Chapter 24		
SPI NOR Flash Memory Technology Device (MTD) Driver		
24.1	Hardware Operation.....	29-1
24.2	Software Operation	29-2
24.3	Driver Features	29-2
24.4	Source Code Structure	29-2
24.5	Menu Configuration Options	29-3
Chapter 25		
SATA Driver		
25.1	Hardware Operation.....	30-1
25.2	Software Operation	30-1

Contents

Paragraph Number	Title	Page Number
25.3	Source Code Structure Configuration.....	30-1
25.4	Linux Menu Configuration Options	30-1
25.5	Board Configuration Options.....	30-1
25.6	Programming Interface	30-2
25.7	Usage Example	30-2
25.8	Usage Example	30-3
25.9	SATA temperature monitor	30-3

Chapter 26 MMC/SD/SDIO Host Driver

26.1	Hardware Operation.....	31-1
26.2	Software Operation	31-2
26.3	Driver Features	31-3
26.4	Source Code Structure	31-4
26.5	Menu Configuration Options	31-4
26.6	Platform Data	31-4
26.7	How to add a SDHC slot support.....	31-5
26.8	Programming Interface	31-5

Chapter 27 Symmetric/Asymmetric Hashing and Random Accelerator (Sahara) Drivers

27.1	Overview.....	32-1
27.2	Software Operation	32-1
27.2.1	API Notes.....	32-1
27.2.2	Architecture	32-1
27.2.2.1	Registration List.....	32-2
27.2.2.2	Command Queue	32-2
27.2.2.3	Result Pools	32-3
27.2.2.4	Sahara Hardware.....	32-3
27.2.2.5	Initialize and Cleanup.....	32-3
27.2.2.6	Sahara Public Interface	32-4
27.2.2.7	UM Extension.....	32-4
27.2.2.8	Access Grant.....	32-4
27.2.2.9	Command.....	32-5
27.2.2.10	Translator	32-6
27.2.2.11	Polling and Interrupts	32-6
27.2.2.12	Completion Notification	32-6
27.2.2.13	Get Results.....	32-7
27.3	Driver Features	32-7

Contents

Paragraph Number	Title	Page Number
27.4	Source Code Structure	32-7
27.5	Menu Configuration Options	32-9
27.6	Programming Interface	32-9
27.7	Interrupt Requirements	32-9

Chapter 28 Security Drivers

28.1	Hardware Overview	33-1
28.1.1	Boot Security	33-1
28.1.2	Secure RAM	33-2
28.1.3	KEM.....	33-2
28.1.4	Zeroizable Memory.....	33-2
28.1.5	Security Key Interface Module.....	33-3
28.1.6	Secure Memory Controller	33-3
28.1.7	Security Monitor	33-3
28.1.8	Secure State Controller	33-4
28.1.9	Security Policy	33-5
28.1.10	Algorithm Integrity Checker (AIC)	33-5
28.1.11	Secure Timer	33-5
28.1.12	Debug Detector	33-5
28.2	Software Operation	33-5
28.2.1	SCC Common Software Operations	33-5
28.3	Driver Features	33-6
28.4	Source Code Structure	33-6
28.5	Menu Configuration Options	33-6

Chapter 29 Fast Ethernet Controller (FEC) Driver

29.1	Hardware Operation.....	34-1
29.2	Software Operation	34-3
29.3	Source Code Structure	34-3
29.4	Menu Configuration Options	34-3
29.5	Programming Interface	34-4
29.5.1	Device-Specific Defines	34-4
29.5.2	Getting a MAC Address	34-5

Chapter 30 Inter-IC (I2C) Driver

Contents

Paragraph Number	Title	Page Number
30.1	I2C Bus Driver Overview	35-1
30.2	I2C Device Driver Overview	35-1
30.3	Hardware Operation.....	35-1
30.4	Software Operation.....	35-2
30.4.1	I2C Bus Driver Software Operation	35-2
30.4.2	I2C Device Driver Software Operation	35-2
30.5	Driver Features	35-3
30.6	Source Code Structure	35-3
30.7	Menu Configuration Options	35-3
30.8	Programming Interface	35-3
30.9	Interrupt Requirements	35-3

Chapter 31 Configurable Serial Peripheral Interface (CSPI) Driver

31.1	Hardware Operation.....	36-1
31.2	Software Operation.....	36-1
31.2.1	SPI Sub-System in Linux.....	36-1
31.2.2	Software Limitations.....	36-3
31.2.3	Standard Operations.....	36-3
31.2.4	CSPI Synchronous Operation	36-4
31.3	Driver Features	36-4
31.4	Source Code Structure	36-4
31.5	Menu Configuration Options	36-4
31.6	Programming Interface	36-5
31.7	Interrupt Requirements	36-5

Chapter 32 Secure Real Time Clock (SRTC) Driver

32.1	Hardware Operation.....	37-1
32.2	Software Operation.....	37-1
32.2.1	IOCTL.....	37-1
32.2.2	Keep Alive in the Power Off State	37-2
32.3	Driver Features	37-2
32.4	Source Code Structure	37-2
32.5	Menu Configuration Options	37-3

Chapter 33 Watchdog (WDOG) Driver

Contents

Paragraph Number	Title	Page Number
33.1	Hardware Operation.....	38-1
33.2	Software Operation.....	38-1
33.3	Generic WDOG Driver.....	38-1
33.3.1	Driver Features.....	38-1
33.3.2	Menu Configuration Options.....	38-1
33.3.3	Source Code Structure.....	38-2
33.3.4	Programming Interface.....	38-2

Chapter 34 Touch Screen (P1003) Driver

34.1	Driver Overview.....	39-1
34.2	Hardware Operation.....	39-1
34.3	Software Operation.....	39-1
34.4	Source Code Structure.....	39-1
34.5	Linux Menu Configuration Options.....	39-1
34.6	I2C slave address.....	39-1
34.7	Capacitive calibration for mass production.....	39-1

Chapter 35 Touch Screen (eGalax) Driver

35.1	Driver Overview.....	40-1
35.2	Hardware Operation.....	40-1
35.3	Software Operation.....	40-1
35.4	Source Code Structure.....	40-1
35.5	Linux Menu Configuration Options.....	40-1
35.6	I2C slave address.....	40-1
35.7	Enable in Ubuntu.....	40-1

Chapter 36 Capacitive Touch Button(MPR121) Driver

36.1	Driver Overview.....	41-1
36.2	Hardware Operation.....	41-1
36.3	Software Operation.....	41-1
36.4	Source Code Structure.....	41-1
36.5	Linux Menu Configuration Options.....	41-1
36.6	I2C slave address.....	41-1
36.7	Setting of platform data.....	41-2

Contents

Paragraph Number	Title	Page Number
Chapter 37 MMA8451 Accelerometer Driver		
37.1	MMA8451 Features	42-1
37.2	Driver Requirements	42-1
37.3	Driver Architecture	42-1
37.4	Driver Source Code Structure	42-1
37.5	Driver Configuration.....	42-2
Chapter 38 MAG3110 Magnetometer Driver		
38.1	MAG3110 Features.....	43-1
38.2	Driver Requirements	43-1
38.3	Driver Architecture	43-1
38.4	Driver Source Code Structure	43-2
38.5	Driver Configuration.....	43-2
Chapter 39 AR6003 WiFi		
39.1	Hardware Operation.....	44-1
39.2	Software Operation	44-1
39.3	Driver features	44-1
39.4	Source Code Structure	44-1
39.5	Linux Menu Configuration Options	44-2
Chapter 40 AR3001 Bluetooth		
40.1	Hardware Operation.....	45-1
40.2	Software Operation	45-1
40.3	Source Code Structure	45-1
40.4	UART related config.....	45-1
40.5	Linux Menu Configuration Options	45-2
40.6	To run AR3001 under ubuntu	45-2
Chapter 41 Pulse-Width Modulator (PWM) Driver		
41.1	Hardware Operation.....	46-1

Contents

Paragraph Number	Title	Page Number
41.2	Clocks	46-2
41.3	Software Operation	46-2
41.4	Driver Features	46-3
41.5	Source Code Structure	46-3
41.6	Menu Configuration Options	46-3

Chapter 42 OProfile

42.1	Overview	47-1
42.2	Features	47-1
42.3	Hardware Operation	47-1
42.4	Software Operation	47-2
42.4.1	Architecture Specific Components	47-2
42.4.2	oprofilefs Pseudo Filesystem	47-2
42.4.3	Generic Kernel Driver	47-2
42.4.4	OProfile Daemon	47-2
42.4.5	Post Profiling Tools	47-3
42.5	Requirements	47-3
42.6	Source Code Structure	47-3
42.7	Menu Configuration Options	47-4
42.8	Programming Interface	47-4
42.9	Interrupt Requirements	47-4
42.10	Example Software Configuration	47-4



Contents

**Paragraph
Number**

Title

**Page
Number**

Tables

Table Number	Title	Page Number
1-1	Linux BSP Supported Features	6-2
2-1	Interrupt Files	7-2
2-2	Memory Map Files	7-4
2-3	IOMUX Files	7-6
2-4	GPIO Files.....	7-7
3-1	SDMA Channel Usage.....	8-2
3-2	SDMA API Source Files.....	8-3
3-3	SDMA Script Files.....	8-3
4-1	UART Driver Files.....	9-3
4-2	UART Global Header Files.....	9-3
4-3	UART Interrupt Requirements.....	9-4
5-1	DA9053 PMIC Driver Source Files.....	10-2
6-1	USB Driver Files.....	11-4
6-2	USB Platform Source Files	11-4
6-3	USB Platform Header Files.....	11-4
6-4	USB Common Platform Files	11-5
6-5	Default USB Settings	11-7
7-1	IPU Driver Files	12-6
7-2	IPU Global Header Files	12-6
8-1	Camera File List.....	13-2
9-1	MXC DDC Driver Source File	14-1
10-1	External Display Devices for i.MX53 TABLET Platform.....	15-1
11-1	V2L2 Driver Files	16-6
12-1	GPU Driver Files	17-2
14-1	VPU Driver Files	19-3
14-2	VPU Library Files.....	19-4
14-3	VPU firmware Files	19-4
15-1	Low Power Modes	20-1
15-2	PM Driver Files.....	20-2
16-1	DVFS Driver Files	21-1
17-1	CPUFREQ Driver Files	22-2
18-1	Bus Frequency Scaling Driver Files	23-2
19-1	MAX17085 charger Driver Source File.....	24-2
20-1	Driver Source Code Structure File.....	25-2
21-1	Stereo Codec SoC Driver Files	26-4
22-1	S/PDIF Driver Files	27-4
23-1	ASRC Source File List.....	28-3
23-2	ASRC Exported Functions.....	28-4
24-1	SPI NOR MTD Driver Files	29-2
26-1	eSDHC Driver Files MMC/SD Driver Files.....	31-4
27-1	Blocking/Non-Blocking Definitions	32-5

Tables

Table Number	Title	Page Number
27-2	Sahara Source Files	32-8
27-3	Sahara Header Files	32-8
28-1	SCCDriver Files	33-6
29-1	Pin Usage in MII and SNI Modes	34-1
29-2	FEC Driver Files	34-3
30-1	I2C Bus Driver Files	35-3
30-2	I2C Interrupt Requirements	35-3
31-1	CSPI Driver Files	36-4
31-2	CSPI Interrupt Requirements	36-5
32-1	RTC Driver Files	37-3
33-1	WDOG Driver Files	38-2
34-1	TouchScreen Driver File List	39-1
35-1	TouchScreen Driver File List	40-1
36-1	Button Driver File List	41-1
37-1	Driver Source Code Structure File	42-2
38-1	Driver Source Code Structure File	43-2
41-1	PWM Driver Summary	46-2
41-2	PWM Driver Files	46-3
42-1	OProfile Source Files	47-3

Figures

Figure Number	Title	Page Number
3-1	SDMA Block Diagram.....	8-2
6-1	USB Block Diagram	11-2
7-1	IPU Module Overview	12-2
7-2	Graphics/Video Drivers Software Interaction.....	12-3
11-1	Video4Linux2 Capture API Interaction	16-4
13-1	X Window Acceleration Block Diagram	18-2
14-1	VPU Hardware Data Flow	19-2
20-1	Driver Architecture	25-2
21-1	ALSA SoC Software Architecture	26-1
21-2	ALSA Soc Source File Relationship	26-3
22-1	S/PDIF Transceiver Data Interface Block Diagram.....	27-1
23-1	Audio Driver Interactions	28-2
24-1	Components of a Flash-Based File System.....	29-2
26-1	MMC Drivers Layering	31-3
27-1	Sahara Architecture Overview	32-2
28-1	Secure RAM Block Diagram	33-2
28-2	Security Monitor Block Diagram.....	33-4
28-3	Secure State Controller State Diagram.....	33-4
31-1	SPI Subsystem.....	36-2
31-2	Layering of SPI Drivers in SPI Subsystem.....	36-2
31-3	CSPI Synchronous Operation	36-4
37-1	Driver Architecture	42-1
38-1	Driver Architecture	43-1
41-1	PWM Block Diagram.....	46-1



Figures

**Figure
Number**

Title

**Page
Number**

About This Book

The Linux Board Support Package (BSP) represents a porting of the Linux Operating System (OS) to the i.MX processors and its associated reference boards. The BSP supports many hardware features on the platforms and most of the Linux OS features that are not dependent on any specific hardware feature.

Audience

This document is targeted to individuals who will port the i.MX Linux BSP to customer-specific products. The audience is expected to have a working knowledge of the Linux 2.6 kernel internals, driver models, and i.MX processors.

Conventions

This document uses the following notational conventions:

- `Courier monospaced type` indicate commands, command parameters, code examples, and file and directory names.
- *Italic* type indicates replaceable command or function parameters.
- **Bold** type indicates function names.

Definitions, Acronyms, and Abbreviations

The following table defines the acronyms and abbreviations used in this document.

Definitions and Acronyms

Term	Definition
ADC	Asynchronous Display Controller
address translation	Address conversion from virtual domain to physical domain
API	Application Programming Interface
ARM®	Advanced RISC Machines processor architecture
AUDMUX	Digital audio MUX—provides a programmable interconnection for voice, audio, and synchronous data routing between host serial interfaces and peripheral serial interfaces
BCD	Binary Coded Decimal
bus	A path between several devices through data lines
bus load	The percentage of time a bus is busy
CODEC	Coder/decoder or compression/decompression algorithm—used to encode and decode (or compress and decompress) various types of data
CPU	Central Processing Unit—generic term used to describe a processing core
CRC	Cyclic Redundancy Check—Bit error protection method for data communication
CSI	Camera Sensor Interface
DFS	Dynamic Frequency Scaling

Definitions and Acronyms (continued)

Term	Definition
DMA	Direct Memory Access—an independent block that can initiate memory-to-memory data transfers
DPM	Dynamic Power Management
DRAM	Dynamic Random Access Memory
DVFS	Dynamic Voltage Frequency Scaling
EMI	External Memory Interface—controls all IC external memory accesses (read/write/erase/program) from all the masters in the system
Endian	Refers to byte ordering of data in memory. Little endian means that the least significant byte of the data is stored in a lower address than the most significant byte. In big endian, the order of the bytes is reversed
EPIT	Enhanced Periodic Interrupt Timer—a 32-bit set and forget timer capable of providing precise interrupts at regular intervals with minimal processor intervention
FCS	Frame Checker Sequence
FIFO	First In First Out
FIPS	Federal Information Processing Standards—United States Government technical standards published by the National Institute of Standards and Technology (NIST). NIST develops FIPS when there are compelling Federal government requirements such as for security and interoperability but no acceptable industry standards
FIPS-140	Security requirements for cryptographic modules—Federal Information Processing Standard 140-2(FIPS 140-2) is a standard that describes US Federal government requirements that IT products should meet for Sensitive, but Unclassified (SBU) use
Flash	A non-volatile storage device similar to EEPROM, where erasing can be done only in blocks or the entire chip.
Flash path	Path within ROM bootstrap pointing to an executable Flash application
Flush	Procedure to reach cache coherency. Refers to removing a data line from cache. This process includes cleaning the line, invalidating its VBR and resetting the tag valid indicator. The flush is triggered by a software command
GPIO	General Purpose Input/Output
hash	Hash values are produced to access secure data. A hash value (or simply hash), also called a message digest, is a number generated from a string of text. The hash is substantially smaller than the text itself, and is generated by a formula in such a way that it is extremely unlikely that some other text produces the same hash value.
I/O	Input/Output
ICE	In-Circuit Emulation
IP	Intellectual Property
IPU	Image Processing Unit —supports video and graphics processing functions and provides an interface to video/still image sensors and displays
IrDA	Infrared Data Association—a nonprofit organization whose goal is to develop globally adopted specifications for infrared wireless communication
ISR	Interrupt Service Routine
JTAG	JTAG (IEEE Standard 1149.1) A standard specifying how to control and monitor the pins of compliant devices on a printed circuit board
Kill	Abort a memory access
KPP	KeyPad Port—16-bit peripheral used as a keypad matrix interface or as general purpose input/output (I/O)

Definitions and Acronyms (continued)

Term	Definition
line	Refers to a unit of information in the cache that is associated with a tag
LRU	Least Recently Used—a policy for line replacement in the cache
MMU	Memory Management Unit—a component responsible for memory protection and address translation
MPEG	Moving Picture Experts Group—an ISO committee that generates standards for digital video compression and audio. It is also the name of the algorithms used to compress moving pictures and video
MPEG standards	Several standards of compression for moving pictures and video: <ul style="list-style-type: none"> • MPEG-1 is optimized for CD-ROM and is the basis for MP3 • MPEG-2 is defined for broadcast video in applications such as digital television set-top boxes and DVD • MPEG-3 was merged into MPEG-2 • MPEG-4 is a standard for low-bandwidth video telephony and multimedia on the World-Wide Web
MQSPI	Multiple Queue Serial Peripheral Interface—used to perform serial programming operations necessary to configure radio subsystems and selected peripherals
MSHC	Memory Stick Host Controller
NAND Flash	Flash ROM technology—NAND Flash architecture is one of two flash technologies (the other being NOR) used in memory cards such as the Compact Flash cards. NAND is best suited to flash devices requiring high capacity data storage. NAND flash devices offer storage space up to 512-Mbyte and offers faster erase, write, and read capabilities over NOR architecture
NOR Flash	See NAND Flash
PCMCIA	Personal Computer Memory Card International Association—a multi-company organization that has developed a standard for small, credit card-sized devices, called PC Cards. There are three types of PCMCIA cards that have the same rectangular size (85.6 by 54 millimeters), but different widths
physical address	The address by which the memory in the system is physically accessed
PLL	Phase Locked Loop—an electronic circuit controlling an oscillator so that it maintains a constant phase angle (a lock) on the frequency of an input, or reference, signal
RAM	Random Access Memory
RAM path	Path within ROM bootstrap leading to the downloading and the execution of a RAM application
RGB	The RGB color model is based on the additive model in which Red, Green, and Blue light are combined to create other colors. The abbreviation RGB comes from the three primary colors in additive light models
RGBA	RGBA color space stands for Red Green Blue Alpha. The alpha channel is the transparency channel, and is unique to this color space. RGBA, like RGB, is an additive color space, so the more of a color placed, the lighter the picture gets. PNG is the best known image format that uses the RGBA color space
RNGA	Random Number Generator Accelerator—a security hardware module that produces 32-bit pseudo random numbers as part of the security module
ROM	Read Only Memory
ROM bootstrap	Internal boot code encompassing the main boot flow as well as exception vectors
RTIC	Real-Time Integrity Checker—a security hardware module
SCC	SeCurity Controller—a security hardware module
SDMA	Smart Direct Memory Access

Definitions and Acronyms (continued)

Term	Definition
SDRAM	Synchronous Dynamic Random Access Memory
SoC	System on a Chip
SPBA	Shared Peripheral Bus Arbiter—a three-to-one IP-Bus arbiter, with a resource-locking mechanism
SPI	Serial Peripheral Interface—a full-duplex synchronous serial interface for connecting low-/medium-bandwidth external devices using four wires. SPI devices communicate using a master/slave relationship over two data lines and two control lines: <i>Also see SS, SCLK, MISO, and MOSI</i>
SRAM	Static Random Access Memory
SSI	Synchronous-Serial Interface—standardized interface for serial data transfer
TBD	To Be Determined
UART	Universal Asynchronous Receiver/Transmitter—asynchronous serial communication to external devices
UID	Unique ID—a field in the processor and CSF identifying a device or group of devices
USB	Universal Serial Bus—an external bus standard that supports high speed data transfers. The USB 1.1 specification supports data transfer rates of up to 12 Mb/s and USB 2.0 has a maximum transfer rate of 480 Mbps. A single USB port can be used to connect up to 127 peripheral devices, such as mice, modems, and keyboards. USB also supports Plug-and-Play installation and hot plugging
USBOTG	USB On The Go—an extension of the USB 2.0 specification for connecting peripheral devices to each other. USBOTG devices, also known as dual-role peripherals, can act as limited hosts or peripherals themselves depending on how the cables are connected to the devices, and they also can connect to a host PC
word	A group of bits comprising 32-bits

Suggested Reading

The following documents contain information that supplements this guide:

- i.MX53 Multimedia Applications Processor Reference Manual

Chapter 1

Introduction

The i.MX family Linux Board Support Package (BSP) supports the Linux Operating System (OS) on the following processor:

- i.MX53 Applications Processor

The purpose of this software package is to support Linux on the i.MX family of Integrated Circuits (ICs) and their associated platforms (SABRE Tablet). It provides the necessary software to interface the standard open-source Linux kernel to the i.MX hardware. The goal is to enable Freescale customers to rapidly build products based on i.MX devices that use the Linux OS.

The BSP is not a platform or product reference implementation. It does not contain all of the product-specific drivers, hardware-independent software stacks, Graphical User Interface (GUI) components, Java Virtual Machine (JVM), and applications required for a product. Some of these are made available in their original open-source form as part of the base kernel.

The BSP is not intended to be used for silicon verification. While it can play a role in this, the BSP functionality and the tests run on the BSP do not have sufficient coverage to replace traditional silicon verification test suites.

1.1 Software Base

The i.MX BSP is based on version 2.6.35 of the Linux kernel from the official Linux kernel web site (<http://www.kernel.org>). It is enhanced with the features provided by Freescale.

1.2 Features

Table 1-1 describes the features supported by the Linux BSP for specific platforms.

Table 1-1. Linux BSP Supported Features

Feature	Description	Chapter Source	Applicable Platform
Machine Specific Layer			
MSL	<p>Machine Specific Layer (MSL) supports interrupts, Timer, Memory Map, GPIO/IOMUX, SPBA, SDMA.</p> <ul style="list-style-type: none"> • Interrupts (AITC/AVIC): The Linux kernel contains common ARM code for handling interrupts. The MSL contains platform-specific implementations of functions for interfacing the Linux kernel to the interrupt controller. • Timer (GPT): The General Purpose Timer (GPT) is set up to generate an interrupt as programmed to provide OS ticks. Linux facilitates timer use through various functions for timing delays, measurement, events, alarms, high resolution timer features, and so on. Linux defines the MSL timer API required for the OS-tick timer and does not expose it beyond the kernel tick implementation. • GPIO/EDIO/IOMUX: The GPIO and EDIO components in the MSL provide an abstraction layer between the various drivers and the configuration and utilization of the system, including GPIO, IOMUX, and external board I/O. The IO software module is board-specific, and resides in the MSL layer as a self-contained set of files. I/O configuration changes are centralized in the GPIO module so that changes are not required in the various drivers. • SPBA: The Shared Peripheral Bus Arbiter (SPBA) provides an arbitration mechanism among multiple masters to allow access to the shared peripherals. The SPBA implementation under MSL defines the API to allow different masters to take or release ownership of a shared peripheral. 	Chapter 2, “Machine Specific Layer (MSL)”	All
SDMA API	<p>The Smart Direct Memory Access (SDMA) API driver controls the SDMA hardware. It provides an API to other drivers for transferring data between MCU, DSP and peripherals. The SDMA controller is responsible for transferring data between the MCU memory space, peripherals, and the DSP memory space. The SDMA API allows other drivers to initialize the scripts, pass parameters and control their execution. SDMA is based on a microRISC engine that runs channel-specific scripts.</p>	Chapter 3, “Smart Direct Memory Access (SDMA) API”	i.MX53

Table 1-1. Linux BSP Supported Features (continued)

Feature	Description	Chapter Source	Applicable Platform
Power Management Drivers			
Low-level PM Drivers	The low-level power management driver is responsible for implementing hardware-specific operations to meet power requirements and also to conserve power on the development platforms. Driver implementations are often different for different platforms. It is used by the DPM layer.	Chapter 15, “Low-level Power Management (PM) Driver”	i.MX53
CPU Frequency Scaling	The CPU frequency scaling device driver allows the clock speed of the CPUs to be changed on the fly.	Chapter 17, “CPU Frequency Scaling (CPUFREQ) Driver”	i.MX53
DVFS	The Dynamic Voltage Frequency Scaling (DVFS) device driver allows simple dynamic voltage frequency scaling. The frequency of the core clock domain and the voltage of the core power domain can be changed on the fly with all modules continuing their normal operations.	Chapter 16, “Dynamic Voltage Frequency Scaling (DVFS) Driver”	i.MX53
Multimedia Drivers			
IPU	The Image Processing Unit (IPU) is designed to support video and graphics processing functions and to interface with video/still image sensors and displays. The IPU driver is a self-contained driver module in the Linux kernel. It contains a custom kernel-level API to manipulate logical channels. A logical channel represents a complete IPU processing flow. The IPU driver includes a frame buffer driver, a V4L2 device driver, and low-level IPU drivers.	Chapter 7, “Image Processing Unit (IPU) Drivers”	i.MX53
TVE	This driver provides the support of i.MX TVE modules.	Chapter 8, “TV encoder (TVE) Driver”	i.MX53
VGA	This driver provides the support of i.MX VGA module.	Chapter 9, “TVE-VGA Driver”	i.MX53
HDMI	This driver provides the support of SII902x HDMI chip.	Chapter 8, “HDMI Driver”	i.MX53
Dual Display	This chapter introduces the basic information about dual display	Chapter 10, “i.MX5 Dual Display”	i.MX53
V4L2 Output	The Video for Linux 2 (V4L2) output driver uses the IPU post-processing functions for video output. The driver implements the standard V4L2 API for output devices.	Chapter 11, “Video for Linux Two (V4L2) Driver”	i.MX53
VPU	The Video Processing Unit (VPU) is a multi-standard video decoder and encoder that can perform decoding and encoding of various video formats.	Chapter 14, “Video Processing Unit (VPU) Driver”	i.MX53
AMD GPU	The Graphics Processing Unit (GPU) is a graphics accelerator targeting embedded 2D/3D graphics applications.	Chapter 12, “Graphics Processing Unit (GPU)”	i.MX53

Table 1-1. Linux BSP Supported Features (continued)

Feature	Description	Chapter Source	Applicable Platform
Sound Drivers			
ALSA Sound	The Advanced Linux Sound Architecture (ALSA) is a sound driver that provides ALSA and OSS compatible applications with the means to perform audio playback and recording functions. ALSA has a user-space component called ALSALib that can extend the features of audio hardware by emulating the same in software (user space), such as resampling, software mixing, snooping, and so on. The ASoC Sound driver supports stereo codec playback and capture through SSI.	Chapter 21, “Advanced Linux Sound Architecture (ALSA) System on a Chip (ASoC) Sound Driver”	i.MX53
S/PDIF	The S/PDIF driver is designed under the Linux ALSA subsystem. It implements one playback device for Tx and one capture device for Rx.	Chapter 22, “The Sony/Philips Digital Interface (S/PDIF) Driver”	i.MX53
Memory Drivers			
SATA	The SATA AHCI driver is based on the LIBATA layer of the block device infrastructure of the Linux kernel	Chapter 25, “SATA Driver”	i.MX53
Input Device Drivers			
Networking Drivers			
FEC	The FEC Driver performs the full set of IEEE 802.3/Ethernet CSMA/CD media access control and channel interface functions. The FEC requires an external interface adaptor and transceiver function to complete the interface to the Ethernet media. It supports half or full-duplex operation on 10 Mbps- or 100 Mbps-related Ethernet networks.	Chapter 29, “Fast Ethernet Controller (FEC) Driver”	i.MX53
Bus Drivers			
I ² C	The I ² C bus driver is a low-level interface that is used to interface with the I ² C bus. This driver is invoked by the I ² C chip driver; it is not exposed to the user space. The standard Linux kernel contains a core I ² C module that is used by the chip driver to access the bus driver to transfer data over the I ² C bus. This bus driver supports: <ul style="list-style-type: none"> • Compatibility with the I²C bus standard • Bit rates up to 400 Kbps • Standard I²C master mode • Power management features by suspending and resuming I²C. 	Chapter 30, “Inter-IC (I2C) Driver”	i.MX53
CSPI	The low-level Configurable Serial Peripheral Interface (CSPI) driver interfaces a custom, kernel-space API to both CSPI modules. It supports the following features: <ul style="list-style-type: none"> • Interrupt-driven transmit/receive of SPI frames • Multi-client management • Priority management between clients • SPI device configuration per client 	Chapter 31, “Configurable Serial Peripheral Interface (CSPI) Driver”	i.MX53

Table 1-1. Linux BSP Supported Features (continued)

Feature	Description	Chapter Source	Applicable Platform
MMC/SD/SDIO - eSDHC	The MMC/SD/SDIO Host driver implements the standard Linux driver interface to eSDHC.	Chapter 26, "MMC/SD/SDIO Host Driver"	i.MX53
UART Drivers			
MXC UART	The Universal Asynchronous Receiver/Transmitter (UART) driver interfaces the Linux serial driver API to all of the UART ports. A kernel configuration parameter gives the user the ability to choose the UART driver and also to choose whether the UART should be used as the system console.	Chapter 4, "Universal Asynchronous Receiver/Transmitter (UART) Driver"	i.MX53
General Drivers			
USB	The USB driver implements a standard Linux driver interface to the ARC USB-OTG controller.	Chapter 6, "ARC USB Driver"	i.MX53
SRTC	The SRTC driver is designed to support MXC Secure RTC module to keep the time and date	Chapter 32, "Secure Real Time Clock (SRTC) Driver"	i.MX53
WatchDog	The Watchdog Timer module protects against system failures by providing an escape from unexpected hang or infinite loop situations or programming errors. This WDOG implements the following features: <ul style="list-style-type: none"> • Generates a reset signal if it is enabled but not serviced within a predefined time-out value • Does not generate a reset signal if it is serviced within a predefined time-out value 	Chapter 33, "Watchdog (WDOG) Driver"	i.MX53
MXC PWM driver	The MXC PWM driver provides the interfaces to access MXC PWM signals	Chapter 41, "Pulse-Width Modulator (PWM) Driver"	i.MX53
Bootloaders			
uBoot	uBoot is an open source boot loader.	See uBoot User guide.	i.MX53
GUI			
OProfile	OProfile is a system-wide profiler for Linux systems, capable of profiling all running code at low overhead.	Chapter 42, "OProfile"	i.MX53

Chapter 2

Machine Specific Layer (MSL)

The Machine Specific Layer (MSL) provides the Linux kernel with the following machine-dependent components:

- Interrupts including GPIO
- Timer
- Memory map
- General Purpose Input/Output (GPIO) including IOMUX
- Smart Direct Memory Access (SDMA)
- Direct Memory Access (DMA)

These modules are normally available in the following directory:

```
<ltib_dir>/rpm/BUILD/linux/arch/arm/mach-mx5 for MX5 platform
```

The header files are implemented under the following directory:

```
<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc/include/mach
```

The MSL layer contains not only the modules common to all the boards using the same processor, such as the interrupts and timer, but it also contains modules specific to each board, such as the memory map. The following sections describe the basic hardware and software operation and the software interfaces for MSL modules. First, the common modules, such as Interrupts and Timer are discussed. Next, the board-specific modules, such as Memory Map and General Purpose Input/Output (GPIO) (including IOMUX) are detailed. Because of the complexity of the SDMA module, its design is explained in [Chapter 3, “Smart Direct Memory Access \(SDMA\) API.”](#)

Each of the following sections contains an overview of the hardware operation. For more information, see the corresponding device documentation.

2.1 Interrupts

The following sections explain the hardware and software operation of interrupts on the device.

2.1.1 Interrupt Hardware Operation

The Interrupt Controller controls and prioritizes a maximum of 128 internal and external interrupt sources. Each source can be enabled or disabled by configuring the Interrupt Enable Register or using the Interrupt Enable/Disable Number Registers. When an interrupt source is enabled and the corresponding interrupt source is asserted, the Interrupt Controller asserts a normal or a fast interrupt request depending on the associated Interrupt Type Register setting.

Interrupt Controller registers can only be accessed in supervisor mode. The Interrupt Controller interrupt requests are prioritized in the order of fast interrupts, and normal interrupts in order of highest priority level, then highest source number with the same priority. There are sixteen normal interrupt levels for all interrupt sources, with level zero being the lowest priority. The interrupt levels are configurable through

eight normal interrupt priority level registers. Those registers, along with the Normal Interrupt Mask Register, support software-controlled priority levels for normal interrupts and priority masking.

2.1.2 Interrupt Software Operation

For ARM-based processors, normal interrupt and fast interrupt are two different exception types. The exception vector addresses can be configured to start at low address (0x0) or high address (0xFFFF0000). The ARM Linux implementation chooses the high vector address model.

The following file has a description of the ARM interrupt architecture.

```
<ltib_dir>/rpm/BUILD/linux/Documentation/arm/Interrupts
```

The software provides a processor-specific interrupt structure with callback functions defined in the `irq_chip` structure and exports one initialization function, which is called during system startup.

2.1.3 Interrupt Features

The interrupt implementation supports the following features:

- Interrupt Controller interrupt disable and enable
- Functions required by the Linux interrupt architecture as defined in the standard ARM interrupt source code (mainly the `<ltib_dir>/rpm/BUILD/linux/arch/arm/kernel/irq.c` file)

2.1.4 Interrupt Source Code Structure

The interrupt module is implemented in the following file:

```
<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc/tzic.c
```

There are also two header files (located in the include directory specified at the beginning of this chapter):

```
hardware.h  
irqs.h
```

Table 2-1 lists the source files for interrupts.

Table 2-1. Interrupt Files

File	Description
hardware.h	Register descriptions
irqs.h	Declarations for number of interrupts supported
tzic.c	Actual interrupt functions for TZIC modules

2.1.5 Interrupt Programming Interface

The machine-specific interrupt implementation exports a single function. This function initializes the Interrupt Controller hardware and registers functions for interrupt enable and disable from each interrupt source. This is done with the global structure `irq_desc` of type `struct irq_desc`. After the initialization,

the interrupt can be used by the drivers through the `request_irq()` function to register device-specific interrupt handlers.

In addition to the native interrupt lines supported from the Interrupt Controller, the number of interrupts is also expanded to support GPIO interrupt. This allows drivers to use the standard interrupt interface supported by ARM Linux, such as the `request_irq()` and `free_irq()` functions.

2.2 Timer

The Linux kernel relies on the underlying hardware to provide support for both the system timer (which generates periodic interrupts) and the dynamic timers (to schedule events). After the system timer interrupt occurs, it does the following:

- Updates the system uptime
- Updates the time of day
- Reschedules a new process if the current process has exhausted its time slice
- Runs any dynamic timers that have expired
- Updates resource usage and processor time statistics

The timer hardware on most i.MX platforms consists of either Enhanced Periodic Interrupt Timer (EPIT) or general purpose timer (GPT) or both. GPT is configured to generate a periodic interrupt at a certain interval (every 10 ms) and is used by the Linux kernel.

2.2.1 Timer Hardware Operation

The General Purpose Timer (GPT) has a 32 bit up-counter. The timer counter value can be captured in a register using an event on an external pin. The capture trigger can be programmed to be a rising or falling edge. The GPT can also generate an event on `ipp_do_cmpout` pins, or can produce an interrupt when the timer reaches a programmed value. It has a 12-bit prescaler providing a programmable clock frequency derived from multiple clock sources.

2.2.2 Timer Software Operation

The timer software implementation provides an initialization function that initializes the GPT with the proper clock source, interrupt mode and interrupt interval. The timer then registers its interrupt service routine and starts timing. The interrupt service routine is required to service the OS for the purposes mentioned in [Section 2.2, “Timer.”](#) Another function provides the time elapsed as the last timer interrupt.

2.2.3 Timer Features

The timer implementation supports the following features:

- Functions required by Linux to provide the system timer and dynamic timers.
- Generates an interrupt every 10 ms.

2.2.4 Timer Source Code Structure

The timer module is implemented in the `arch/arm/plat-mxc/time.c` file.

2.3 Memory Map

A predefined virtual-to-physical memory map table is required for the device drivers to access to the device registers since the Linux kernel is running under the virtual address space with the Memory Management Unit (MMU) enabled.

2.3.1 Memory Map Hardware Operation

The MMU, as part of the ARM core, provides the virtual to physical address mapping defined by the page table. For more information, see the *ARM Technical Reference Manual (TRM)* from ARM Limited.

2.3.2 Memory Map Software Operation

A table mapping the virtual memory to physical memory is implemented for i.MX platforms as defined in the `<ltib_dir>/rpm/BUILD/linux/arch/arm/mach-mx5/mm.c` file.

2.3.3 Memory Map Features

The Memory Map implementation programs the Memory Map module to creates the physical to virtual memory map for all the I/O modules.

2.3.4 Memory Map Source Code Structure

The Memory Map module implementation is in `mm.c` under the platform-specific MSL directory. The `hardware.h` header file is used to provide macros for all the IO module physical and virtual base addresses and physical to virtual mapping macros. All of the memory map source code is in the in the following directories:

```
<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc/include/mach  
<ltib_dir>/rpm/BUILD/linux/arch/arm/mach-mx5
```

Table 2-2 lists the source file for the memory map.

Table 2-2. Memory Map Files

File	Description
<code>mm.c</code>	Memory map definition file

2.3.5 Memory Map Programming Interface

The Memory Map is implemented in the `mm.c` file to provide the map between physical and virtual addresses. It defines an initialization function to be called during system startup.

2.4 IOMUX

The limited number of pins of highly integrated processors can have multiple purposes. The IOMUX module controls a pin usage so that the same pin can be configured for different purposes and can be used by different modules. This is a common way to reduce the pin count while meeting the requirements from various customers. Platforms that do not have the IOMUX hardware module can do pin muxing through the GPIO module.

The IOMUX module provides the multiplexing control so that each pin may be configured either as a functional pin or as a GPIO pin. A functional pin can be subdivided into either a primary function or alternate functions. The pin operation is controlled by a specific hardware module. A GPIO pin, is controlled by the user through software with further configuration through the GPIO module. For example, the `UART1_TXD` pin might have the following functions:

- `UART1_TXD`—internal UART1 Transmit Data. This is the primary function of this pin.
- `GPIO6 [6]`—alternate mode 1
- `USBPHY1_DATAOUT [14]`—alternate mode 7

If the hardware modes are chosen at the system integration level, this pin is dedicated only to that purpose and cannot be changed by software. Otherwise, the IOMUX module needs to be configured to serve a particular purpose that is dictated by the system (board) design. If the pin is connected to an external UART transceiver and therefore to be used as the UART data transmit signal, it should be configured as the primary function. If the pin is connected to an external Ethernet controller for interrupting the ARM core, then it should be configured as GPIO input pin with interrupt enabled. Again, be aware that the software does not have control over what function a pin should have. The software only configures pin usage according to the system design.

2.4.1 IOMUX Hardware Operation

The IOMUX controller registers are briefly described here. For detailed information, refer to the pin multiplexing section of the IC Reference Manual.

- `SW_MUX_CTL`—Selects the primary or alternate function of a pin. Also enables loopback mode when applicable.
- `SW_SELECT_INPUT`—Controls pin input path. This register is only required when multiple pads drive the same internal port.
- `SW_PAD_CTL`—Control pad slew rate, driver strength, pull-up/down resistance, and so on.

2.4.2 IOMUX Software Operation

The IOMUX software implementation provides an API to set up pin functionality and pad features.

2.4.3 IOMUX Features

The IOMUX implementation programs the IOMUX module to configure the pins that are supported by the hardware.

2.4.4 IOMUX Source Code Structure

Table 2-3 lists the source files for the IOMUX module. The files are in the directory:

<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc

Table 2-3. IOMUX Files

File	Description
iomux-v3.c	IOMUX function implementation
include/mach/iomux-mx53.h	Pin definitions in the iomux pins

2.4.5 IOMUX Programming Interface

The IOMUX API is in arch/arm/plat-mxc/include/mach/iomux-v3.h. Read the comments at the head of this file to understand the iomux scheme.

2.5 General Purpose Input/Output (GPIO)

The GPIO module provides general-purpose pins that can be configured as either inputs or outputs. When configured as an output, the pin state (high or low) can be controlled by writing to an internal register. When configured as an input, the pin input state can be read from an internal register.

2.5.1 GPIO Software Operation

The general purpose input/output (GPIO) module provides an API to configure the i.MX processor external pins and a central place to control the GPIO interrupts.

The GPIO utility functions should be called to configure a pin instead of directly accessing the GPIO registers. The GPIO interrupt implementation contains functions, such as the interrupt service routine (ISR) registration/un-registration and ISR dispatching once an interrupt occurs. All driver-specific GPIO setup functions should be made during device initialization in the MSL layer to provide better portability and maintainability. This GPIO interrupt is initialized automatically during the system startup.

If a pin is configured as GPIO by the IOMUX, the state of the pin should also be set since it is not initialized by a dedicated hardware module.

2.5.1.1 API for GPIO

The GPIO implementation supports the following features:

- An API for registering an interrupt service routine to a GPIO interrupt. This is made possible as the number of interrupts defined by `NR_IRQS` is expanded to accommodate all the possible GPIO pins that are capable of generating interrupts. The macro `IOMUX_TO_IRQ_V3()` or `gpio_to_irq()` is used to convert GPIO pin to irq number,
- Functions to set an IOMUX pin, named `mx53_iomux_v3_setup_pad()`. If a pin is used as GPIO, another set of request/free function calls are provided, named `gpio_request()` and `gpio_free()`. The user should check the return value of the request calls to see if the pin has already been

reserved before modifying the pin state. The free function calls should be made when the pin is not needed. Furthermore, functions `gpio_direction_input()` and `gpio_direction_output()` are provided to set GPIO when it's used as input or output. See the API document and `Documentation/gpio.txt` for more details.

2.5.2 GPIO Features

This GPIO implementation supports the following features:

- Implements the functions for accessing the GPIO hardware modules
- Provides a way to control GPIO signal direction and GPIO interrupts

2.5.3 GPIO Source Code Structure

GPIO driver is implemented based on general gpiolib framework. The MSL-layer codes defines and registers `gpio_chip` instances for each bank of on-chip GPIOs, in the following files, located in the directories indicated at the beginning of this chapter:

Table 2-4. GPIO Files

File	Description
<code>gpio.h</code>	GPIO public header file
<code>gpio.c</code>	Function implementation

2.5.4 GPIO Programming Interface

For more information, see the API documents and `Documentation/gpio.txt` for the programming interface.

Chapter 3

Smart Direct Memory Access (SDMA) API

3.1 Overview

The Smart Direct Memory Access (SDMA) API driver controls the SDMA hardware. It provides an API to other drivers for transferring data between MCU memory space and the peripherals. It supports the following features:

- Loading channel scripts from the MCU memory space into SDMA internal RAM
- Loading context parameters of the scripts
- Loading buffer descriptor parameters of the scripts
- Controlling execution of the scripts
- Callback mechanism at the end of script execution

3.2 Hardware Operation

The SDMA controller is responsible for transferring data between the MCU memory space and peripherals and includes the following features.

- Multi-channel DMA supporting up to 32 time-division multiplexed DMA channels
- Powered by a 16-bit Instruction-Set microRISC engine
- Each channel executes specific script
- Very fast context-switching with two-level priority based preemptive multi-tasking
- 4 Kbytes ROM containing startup scripts (that is, boot code) and other common utilities that can be referenced by RAM-located scripts
- 8 Kbyte RAM area is divided into a processor context area and a code space area used to store channel scripts that are downloaded from the system memory.

3.3 Software Operation

The driver provides an API for other drivers to control SDMA channels. SDMA channels run dedicated scripts, according to peripheral and transfer types. The SDMA API driver is responsible for loading the scripts into SDMA memory, initializing the channel descriptors, and controlling the buffer descriptors and SDMA registers.

Complete support for SDMA is provided in three layers (see [Figure](#)):

- I.API
- Linux DMA API
- TTY driver or DMA-capable drivers, such as ATA, SSI and the UART driver.

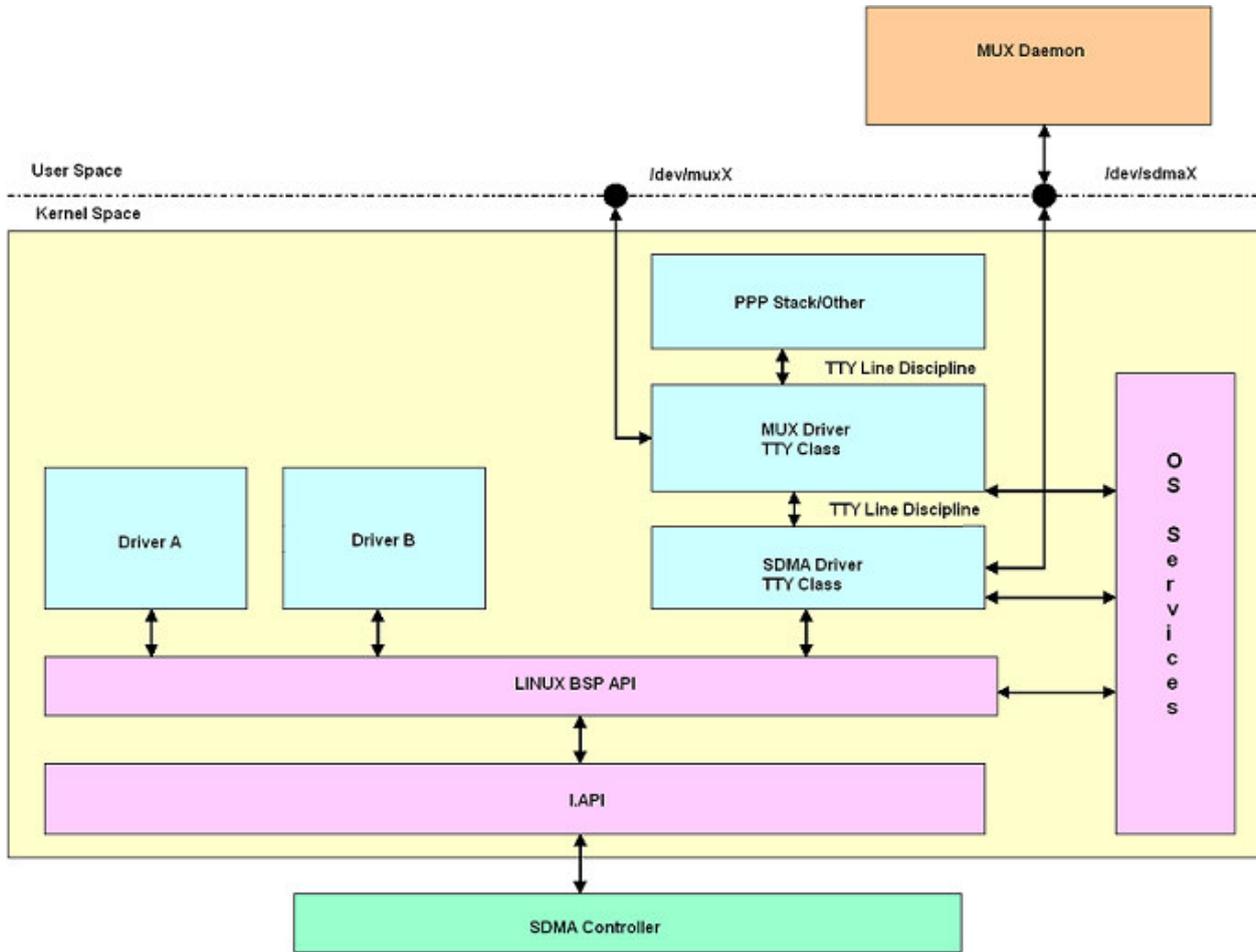


Figure 3-1. SDMA Block Diagram

The first two layers are part of the MSL and customized for each platform. I.API is the lowest layer and it interfaces with the Linux DMA API with the SDMA controller. The Linux DMA API interfaces other drivers (for example, MMC/SD, Sound) with the SDMA controller through the I.API.

Table 3-1 provides a list of drivers that use SDMA and the number of SDMA physical channels used by each driver. A driver can specify the SDMA channel number that it wishes to use (static channel allocation) or can have the SDMA driver provide a free SDMA channel for the driver to use (dynamic channel allocation). For dynamic channel allocation, the list of SDMA channels is scanned from channel 32 to channel 1. On finding a free channel, that channel is allocated for the requested DMA transfers.

Table 3-1. SDMA Channel Usage

Driver Name	Number of SDMA Channels	SDMA Channel Used
SDMA CMD	1	Static Channel allocation—uses SDMA channels 0
SSI	2 per device	Dynamic channel allocation

Table 3-1. SDMA Channel Usage (continued)

Driver Name	Number of SDMA Channels	SDMA Channel Used
UART	2 per device	Dynamic channel allocation
SPDIF	2 per device	Dynamic channel allocation

3.4 Source Code Structure

The source file, `sdma.h` (header file for SDMA API) is available in the directory

`<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc/include/mach.`

Table 3-2 shows the source files available in the directory,

`<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc/sdma.`

Table 3-2. SDMA API Source Files

File	Description
<code>sdma.c</code>	SDMA API functions
<code>sdma_malloc.c</code>	SDMA functions to get memory that allows DMA
<code>iapi/</code>	iAPI source files

Table 3-3 shows the header files available in the directory,

`<ltib_dir>/rpm/BUILD/linux/arch/arm/mach-mx5/.`

Table 3-3. SDMA Script Files

File	Description
<code>sdma_script_code_mx53.h</code>	SDMA RAM scripts

3.5 Menu Configuration Options

The following Linux kernel configuration option is provided for this module. To get to this options, use the `./ltib -c` command when located in the `<ltib_dir>`. On the screen displayed, select **Configure the Kernel** and exit. When the next screen appears, select the following option to enable this module:

- `CONFIG_MXC_SDMA_API`—This is the configuration option for the SDMA API driver. In `menuconfig`, this option is available under System type > Freescale MXC implementations > MX5x Options: > Use SDMA API. By default, this option is Y.
- `CONFIG_SDMA_IRAM`—This is the configuration option to support Internal RAM as SDMA buffer or control structures. This option is available under System type > Freescale MXC implementations > MX5x Options > Use Internal RAM for SDMA transfer.

3.6 Programming Interface

The module implements custom API and partially standard DMA API. Custom API is needed for supporting non-standard DMA features such as loading scripts, interrupts handling and DVFS control. Standard API is supported partially. It can be used along with custom API functions only. Refer to the API document for more information on the functions implemented in the driver (in the doxygen folder of the documentation package).

3.7 Usage Example

Refer to one of the drivers from [Table 3-1](#) that uses the SDMA API driver for a usage example.

Chapter 4

Universal Asynchronous Receiver/Transmitter (UART) Driver

The low-level UART driver interfaces the Linux serial driver API to all the UART ports. It has the following features:

- Interrupt-driven and SDMA-driven transmit/receive of characters
- Standard Linux baud rates up to 4 Mbps
- Transmit and receive characters with 7-bit and 8-bit character lengths
- Transmits one or two stop bits
- Supports `TIOCMGET` IOCTL to read the modem control lines. Only supports the constants `TIOCM_CTS` and `TIOCM_CAR`, plus `TIOCM_RI` in DTE mode only
- Supports `TIOCMSET` IOCTL to set the modem control lines. Supports the constants `TIOCM_RTS` and `TIOCM_DTR` only
- Odd and even parity
- XON/XOFF software flow control. Serial communication using software flow control is reliable when communication speeds are not too high and the probability of buffer overruns is minimal
- CTS/RTS hardware flow control—both interrupt-driven software-controlled hardware flow and hardware-driven hardware-controlled flow
- Send and receive break characters through the standard Linux serial API
- Recognizes frame and parity errors
- Ability to ignore characters with break, parity and frame errors
- Get and set UART port information through the `TIOCGSSERIAL` and `TIOCSSERIAL` TTY IOCTL. Some programs like `setserial` and `dip` use this feature to make sure that the baud rate was set properly and to get general information on the device. The UART type should be set to 52 as defined in the `serial_core.h` header file.
- Serial IrDA
- Power management feature by suspending and resuming the URT ports
- Standard TTY layer IOCTL calls

All the UART ports can be accessed through the device files `/dev/ttymx0` through `/dev/ttymx4`, where `/dev/ttymx0` refers to UART 1. Autobaud detection is not supported.

4.1 Hardware Operation

Refer to the *i.MX53 Multimedia Applications Processor Reference Manual* to determine the number of UART modules available in the device. Each UART hardware port is capable of standard RS-232 serial communication and has support for IrDA 1.0. Each UART contains a 32-byte transmitter FIFO and a 32-half-word deep receiver FIFO. Each UART also supports a variety of maskable interrupts when the data level in each FIFO reaches a programmed threshold level and when there is a change in state in the modem signals. Each UART can be programmed to be in DCE or DTE mode.

4.2 Software Operation

The Linux OS contains a core UART driver that manages many of the serial operations that are common across UART drivers for various platforms. The low-level UART driver is responsible for supplying information such as the UART port information and a set of control functions to this core UART driver. These functions are implemented as a low-level interface between the Linux OS and the UART hardware. They cannot be called from other drivers or from a user application. The control functions used to control the hardware are passed to the core driver through a structure called `uart_ops`, and the port information is passed through a structure called `uart_port`. The low level driver is also responsible for handling the various interrupts for the UART ports, and providing console support if necessary.

Each UART can be configured to use DMA for the data transfer. These configuration options are provided in the `mxc_uart.h` header file. The user can specify the size of the DMA receive buffer. The minimum size of this buffer is 512 bytes. The size should be a multiple of 256. The driver breaks the DMA receive buffer into smaller sub-buffers of 256 bytes and registers these buffers with the DMA system. The DMA transmit buffer size is fixed at 1024 bytes. The size is limited by the size of the Linux UART transmit buffer (1024).

The driver requests two DMA channels for the UARTs that need DMA transfer. On a receive transaction, the driver copies the data from the DMA receive buffer to the TTY Flip Buffer.

While using DMA to transmit, the driver copies the data from the UART transmit buffer to the DMA transmit buffer and sends this buffer to the DMA system. The user should use hardware-driven hardware flow control when using DMA data transfer. For more information, see the Linux documentation on the serial driver in the kernel source tree.

The low-level driver supports both interrupt-driven software-controlled hardware flow control and hardware-driven hardware flow control. The hardware flow control method can be configured using the options provided in the header file. The user has the capability to de-assert the CTS line using the available IOCTL calls. If the user wishes to assert the CTS line, then control is transferred back to the receiver, as long as the driver has been configured to use hardware-driven hardware flow control.

4.3 Driver Features

The UART driver supports the following features:

- Baud rates up to 4 Mbps
- Recognizes frame and parity errors only in interrupt-driven mode; does not recognize these errors in DMA-driven mode
- Sends, receives, and appropriately handles break characters
- Recognizes the modem control signals
- Ignores characters with frame, parity, and break errors if requested to do so
- Implements support for software and hardware flow control (software-controlled and hardware-controlled)
- Get and set the UART port information; certain flow control count information is not available in hardware-driven hardware flow control mode
- Implements support for Serial IrDA

- Power management
- Interrupt-driven and DMA-driven data transfer

4.4 Source Code Structure

Table 4-1 shows the UART driver source files that are available in the directory:

<ltib_dir>/rpm/BUILD/linux/drivers/serial.

Table 4-1. UART Driver Files

File	Description
mxc_uart.c	Low level driver
serial_core.c	Core driver that is included as part of standard Linux
mxc_uart_reg.h	Register values
mxc_uart_early.c	Source file to support early serial console for UART

Table 4-2 shows the header files associated with the UART driver.

Table 4-2. UART Global Header Files

File	Description
<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc/include/mach/mxc_uart.h	UART header that contains UART configuration data structure definitions

The source files, `serial.c` and `serial.h`, are associated with the UART driver that is available in the directory: <ltib_dir>/rpm/BUILD/linux/arch/arm/mach-mx5. The source file contains UART configuration data and calls to register the device with the platform bus.

4.5 Configuration

This section discusses configuration options associated with Linux, chip configuration options, and board configuration options.

4.5.1 Menu Configuration Options

The following Linux kernel configuration options are provided for this module. To get to these options, use the `./ltib -c` command when located in the <ltib_dir>. On the screen displayed, select **Configure the Kernel** and exit. When the next screen appears, select the following options to enable this module:

- `CONFIG_SERIAL_MXC`—Used for the UART driver for the UART ports. In menuconfig, this option is available under
Device Drivers > Character devices > Serial drivers > MXC Internal serial port support.
By default, this option is Y.
- `CONFIG_SERIAL_MXC_CONSOLE`—Chooses the Internal UART to bring up the system console. This option is dependent on the `CONFIG_SERIAL_MXC` option. In the menuconfig this option is available under

Universal Asynchronous Receiver/Transmitter (UART) Driver

Device Drivers > Character devices > Serial drivers > MXC Internal serial port support > Support for console on a MXC/MX27/MX21 Internal serial port.

By default, this option is Y.

4.5.2 Source Code Configuration Options

This section details the chip configuration options and board configuration options.

4.5.2.1 Chip Configuration Options

The chip-specific configuration options are provided in

`<ltib_dir>/rpm/BUILD/linux/arch/arm/mach-mx5/serial.c`

4.5.2.2 Board Configuration Options

For *i.MX53*, the board specific configuration options for the driver is set within

`<ltib_dir>/rpm/BUILD/linux/arch/arm/mach-mx5/serial.h`

4.6 Programming Interface

The UART driver implements all the methods required by the Linux serial API to interface with the UART port. The driver implements and provides a set of control methods to the Linux core UART driver. For more information about the methods implemented in the driver, see the API document.

4.7 Interrupt Requirements

The UART driver interface generates many kinds of interrupts. The highest interrupt rate is associated with transmit and receive interrupt.

The system requirements are listed in [Table 4-3](#).

Table 4-3. UART Interrupt Requirements

Parameter	Equation	Typical	Worst Case
Rate	$(\text{BaudRate}/(10)) * (1/\text{Rxtl} + 1/(32-\text{Txtl}))$	5952/sec	300000/sec
Latency	$320/\text{BaudRate}$	5.6 ms	213.33 μs

The baud rate is set in the `mxuart_set_termios` function. The typical values are based on a baud rate of 57600 with a receiver trigger level (Rxtl) of one and a transmitter trigger level (Tctl) of two. The worst case is based on a baud rate of 1.5 Mbps (maximum supported by the UART interface) with an Rxtl of one and a Tctl of 31. There is also an undetermined number of handshaking interrupts that are generated but the rates should be an order of magnitude lower.

Chapter 5

DA9053 PMIC Driver

The DA9053 PMIC driver for Linux provides support for controlling the PMIC multi-function device. This device drivers contain a core MFD (multi-function device) protocol driver and a set of sub device drivers.

5.1 Hardware information

The DA9053 PMIC provides SPI/I2C bus and a dedicated IRQ line to communicate with the host CPU. The main features including:

- Switched DC/USB Charger with power path management
- 4 Buck Converters (3 have DVS)
- 10 Programmable LDO
- Low power Backup Charger
- 32 kHz RTC Oscillator
- 10 channel General Purpose ADC with touch screen interface
- High voltage white LED driver
- 16 bit GPIO bus
- Dual serial control interfaces
- Unique USB supply detection and charge current selection

See DA9053 specs for more details.

5.2 Software Drivers

The PMIC driver implements a MFD class device driver for register access and event notifications. Each sub module is registered as a sub-device of the MFD core device and implemented under different driver model classes.

The DA9053 driver is intergrated from the Dialog-LKML-Source-Code.tar.gz release from Dialog. Inc.

- Porting and intergration are done for different MX53 board powered by DA9053.

Two suspend solutions are provided which are dependent on HW signal connections:

- A software suspend solution can be deployed for DA9053 suspend operation. It is implemented via a standalone polling-mode i2c interface to preset the voltage of DA9053 deep sleep mode. It also issues the DEEP_SLEEP command to DA9053. See the implementation “da9053_suspend_cmd_sw” under arch/arm/mach-mx5/pm_da9053.c. With this solution, only power key which is connected to NONKEY_KEEP_ACT signal can wakeup the system.
- A hardware suspend solution can be deployed for DA9053 suspend operation. See the function “da9053_suspend_cmd_hw” under arch/arm/mach-mx5/pm_da9053.c for the details. For HW solution, please ensure the right DA9053 chip is used. With this solution, all CPU interrupts can be used as wakeup resources.

5.3 Source code structure

Table 5-1 lists the source files for DA9053 PMIC driver:

Table 5-1. DA9053 PMIC Driver Source Files

Directory	File	Description
include/linux/mfd/da9052/	*.h	header files for mfd sub-devices
drivers/gpio/	da9052-gpio.c	driver source for DA9053 gpio
drivers/hwmon/	da9052-adc.c	driver source for DA9053 adc
drivers/input/misc/	da9052_onkey.c	driver source for DA9053 power key
drivers/input/touchscreen/	da9052_tsi.c	driver source for DA9053 touch screen
drivers/leds/	leds-da9052.c	driver source for DA9053 led
drivers/mfd/	da9052-core.c da9052-i2c.c da9052-spi.c	driver source for DA9053 core
drivers/power/	da9052-battery.c	driver source for DA9053 battery charger
drivers/regulator/	da9052-regulator.c	driver source for DA9053 regulator
drivers/rtc/	rtc-da9052.c	driver source for DA9053 RTC
drivers/video/backlight/	da9052_bl.c	driver source for DA9053 backlight
drivers/watchdog/	da9052_wdt.c	driver source for DA9053 watchdog
arch/arm/mach-mx5/	pm_da9053.c	suspend routine for DA9053

Note: The source get from Dialog is upgraded from the DA9052 driver code. So the device naming is remained as DA9052.

5.4 Menu Configuration Options

To get to the PMIC device driver, use the command `./ltib -c` when located in the `<ltib dir>`. In the screen displayed, select **Configure Kernel** and exit. When the next screen appears, select the following options to enable the PMIC device driver.

To enable: Dialog DA9052 with SPI/I2C

select: PMIC_DA9052

Depends on: MFD_SUPPORT [=y] && SPI_MASTER [=y] && I2C [=y]=y [=y]

Location:

-> Device Drivers

-> Multifunction device drivers (MFD_SUPPORT [=y])

Selects: MFD_CORE [=y]

To enable: Dialog DA9052 GPIO

Depends on: GPIOLIB [=y] && PMIC_DA9052 [=y]

Location:

-> Device Drivers

-> GPIO Support (GPIOLIB [=y])

select: DA9052_GPIO_ENABLE

To enable: Dialog DA9052 WLED

select: BACKLIGHT_DA9052

Depends on: HAS_IOMEM [=y] && BACKLIGHT_LCD_SUPPORT [=y] && BACKLIGHT_CLASS_DEVICE [=y] && PMIC_DA9052 [=y]

Location:

-> Device Drivers

-> Graphics support

-> Backlight & LCD device support (BACKLIGHT_LCD_SUPPORT [=y])

-> Lowlevel Backlight controls (BACKLIGHT_CLASS_DEVICE [=y])

To enable: Dialog DA9052 TSI

select: TOUCHSCREEN_DA9052

Depends on: !S390 [=S390] && INPUT [=y] && INPUT_TOUCHSCREEN [=y] && PMIC_DA9052 [=y]

Location:

-> Device Drivers

-> Input device support

-> Generic input layer (needed for keyboard, mouse, ...) (INPUT [=y])

-> Touchscreens (INPUT_TOUCHSCREEN [=y])

To enable: Dialog DA9052 Battery

select: BATTERY_DA9052

Depends on: POWER_SUPPLY [=y] && PMIC_DA9052 [=y]

DA9053 PMIC Driver

Location:

-> Device Drivers

-> Power supply class support (POWER_SUPPLY [=y])

To enable: Dialog DA9052 HWMon

select: SENSORS_DA9052

Depends on: HWMON [=y] && PMIC_DA9052 [=y]

Location:

-> Device Drivers

-> Hardware Monitoring support (HWMON [=y])

To enable: Dialog DA9052 regulators

select: REGULATOR_DA9052

Depends on: REGULATOR [=y] && PMIC_DA9052 [=y]

Location:

-> Device Drivers

-> Voltage and Current Regulator Support (REGULATOR [=y])

To enable: Dialog DA9052 RTC

select: RTC_DRV_DA9052

Depends on: RTC_CLASS [=y] && PMIC_DA9052 [=y]

Location:

-> Device Drivers

-> Real Time Clock (RTC_CLASS [=y])

To enable: Dialog DA9052 Onkey

select: INPUT_DA9052_ONKEY

Depends on: INPUT [=y] && INPUT_MISC [=y] && PMIC_DA9052 [=y]

Location:

-> Device Drivers

-> Input device support

-> Generic input layer (needed for keyboard, mouse, ...) (INPUT [=y])

-> Miscellaneous devices (INPUT_MISC [=y])

To enable: Dialog DA9052 LEDs

select: LEDS_DA9052

Depends on: NEW_LEDS [=y] && LEDS_CLASS [=y] && PMIC_DA9052 [=y]

Location:

-> Device Drivers

-> LED Support (NEW_LEDS [=y])

-> LED Class Support (LEDS_CLASS [=y])

To enable: Dialog DA9052 Watchdog

select: DA9052_WATCHDOG

Depends on: WATCHDOG [=y] && PMIC_DA9052 [=y]

Location:

-> Device Drivers

-> Watchdog Timer Support (WATCHDOG [=y])

Chapter 6

ARC USB Driver

The universal serial bus (USB) driver implements a standard Linux driver interface to the ARC USB-HS OTG controller. The USB provides a universal link that can be used across a wide range of PC-to-peripheral interconnects. It supports plug-and-play, port expansion, and any new USB peripheral that uses the same type of port.

The ARC USB controller is enhanced host controller interface (EHCI) compliant. This USB driver has the following features:

- High Speed/Full Speed Host Only core (HOST1)
- High speed and Full Speed OTG core
- Host mode—Supports HID (Human Interface Devices), MSC (Mass Storage Class), and PTP (Still Image) drivers
- Peripheral mode—Supports MSC, and CDC (Communication Devices Class) drivers
- Embedded DMA controller

6.1 Architectural Overview

A USB host system is composed of a number of hardware and software layers. Figure 6-1 shows a conceptual block diagram of the building block layers in a host system that support USB 2.0.

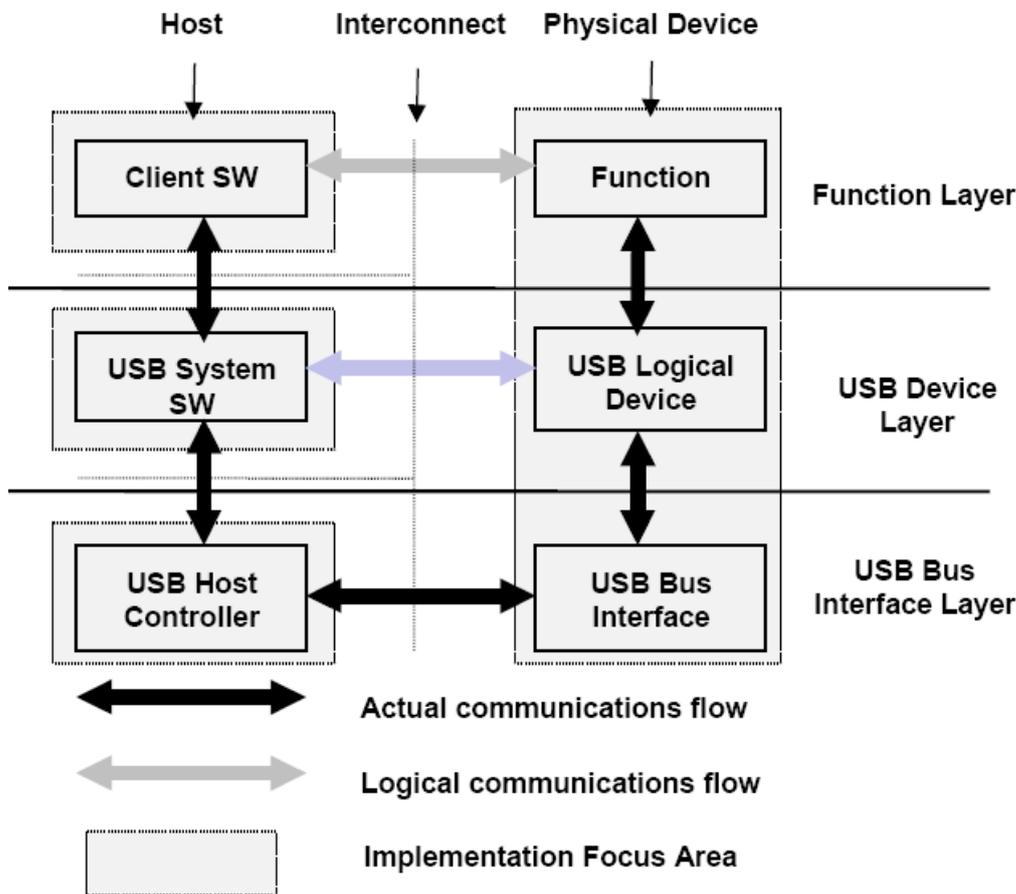


Figure 6-1. USB Block Diagram

6.2 Hardware Operation

For information on hardware operations, refer to the EHCI spec.ehci-r10.pdf available at <http://www.usb.org/developers/docs/>.

6.3 Software Operation

The Linux OS contains a USB driver, which implements the USB protocols. For the USB host, it only implements the hardware specified initialization functions. For the USB peripheral, it implements the gadget framework.

```
static struct usb_ep_ops fsl_ep_ops = {
    .enable = fsl_ep_enable,
    .disable = fsl_ep_disable,
    .alloc_request = fsl_alloc_request,
    .free_request = fsl_free_request,
}
```

```

        .queue = fsl_ep_queue,
        .dequeue = fsl_ep_dequeue,
        .set_halt = fsl_ep_set_halt,
        .fifo_status = arcotg_fifo_status,
        .fifo_flush = fsl_ep_fifo_flush,          /* flush fifo */
    };
static struct usb_gadget_ops fsl_gadget_ops = {
    .get_frame = fsl_get_frame,
    .wakeup = fsl_wakeup,
/*
    .set_selfpowered = fsl_set_selfpowered, */ /* Always selfpowered */
    .vbus_session = fsl_vbus_session,
    .vbus_draw = fsl_vbus_draw,
    .pullup = fsl_pullup,
};

```

- `fsl_ep_enable`—configures an endpoint making it usable
- `fsl_ep_disable`—specifies an endpoint is no longer usable
- `fsl_alloc_request`—allocates a request object to use with this endpoint
- `fsl_free_request`—frees a request object
- `arcotg_ep_queue`—queues (submits) an I/O request to an endpoint
- `arcotg_ep_dequeue`—dequeues (cancels, unlinks) an I/O request from an endpoint
- `arcotg_ep_set_halt`—sets the endpoint halt feature
- `arcotg_fifo_status`—get the total number of bytes to be moved with this transfer descriptor

For OTG, an OTG finish state machine (FSM) is implemented.

6.4 Driver Features

The USB stack supports the following features:

- USB device mode
- Mass storage device profile—subclass 8-1 (RBC set)
- USB host mode
- HID host profile—subclasses 3-1-1 and 3-1-2. (USB mouse and keyboard)
- Mass storage host profile—subclass 8-1
- Ethernet USB profile—subclass 2
- DC PTP transfer

6.5 Source Code Structure

Table 6-1 shows the source files available in the source directory,

<ltib_dir>/rpm/BUILD/linux/drivers/usb.

Table 6-1. USB Driver Files

File	Description
host/ehci-hcd.c	Host driver source file
host/ehci-arc.c	Host driver source file
host/ehci-mem-iram.c	Host driver source file for IRAM support
host/ehci-hub.c	Hub driver source file
host/ehci-mem.c	Memory management for host driver data structures
host/ehci-q.c	EHCI host queue manipulation
host/ehci-q-iram.c	Host driver source file for IRAM support
gadget/arcotg_udc.c	Peripheral driver source file
gadget/arcotg_udc.h	USB peripheral/endpoint management registers
otg/fsl_otg.c	OTG driver source file
otg/fsl_otg.h	OTG driver header file
otg/otg_fsm.c	OTG FSM implement source file
otg/otg_fsm.h	OTG FSM header file
gadget/fsl_updater.c	FSL manufacture tool usb char driver source file
gadget/fsl_updater.h	FSL manufacture tool usb char driver header file

Table 6-2 shows the platform related source files.

Table 6-2. USB Platform Source Files

File	Description
arch/arm/plat-mxc/include/mach/arc_otg.h	USB register define
include/linux/fsl_devices.h	FSL USB specific structures and enums

Table 6-3 shows the platform-related source files in the directory:

<ltib_dir>/rpm/BUILD/linux/arch/arm/mach-mx5/

Table 6-3. USB Platform Header Files

File	Description
usb_dr.c	Platform-related initialization
usb_h1.c	Platform-related initialization

Table 6-4 shows the common platform source files in the directory:

<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc.

Table 6-4. USB Common Platform Files

File	Description
utmixc.c	Internal UTMI transceiver driver
usb_common.c	Common platform related part of USB driver
usb_wakeup.c	Handle usb wakeup events

6.6 Menu Configuration Options

The following Linux kernel configuration options are provided for this module. To get to these options, use the `./ltib -c` command when located in the <ltib_dir>. On the screen displayed, select **Configure the Kernel** and exit. When the next screen appears, select the following options to enable this module:

- **CONFIG_USB**—Build support for USB
- **CONFIG_USB_EHCI_HCD**—Build support for USB host driver. In menuconfig, this option is available under Device drivers > USB support > EHCI HCD (USB 2.0) support.
By default, this option is Y.
- **CONFIG_USB_EHCI_ARC**—Build support for selecting the ARC EHCI host. In menuconfig, this option is available under Device drivers > USB support > Support for Freescale controller.
By default, this option is Y.
- **CONFIG_USB_EHCI_ARC_OTG**—Build support for selecting the ARC EHCI OTG host. In menuconfig, this option is available under Device drivers > USB support > EHCI HCD (USB 2.0) support > Support for DR host port on Freescale controller.
By default, this option is Y.
- **CONFIG_USB_STATIC_IRAM**—Build support for selecting the IRAM usage for host. In menuconfig, this option is available under Device drivers > USB support > Use IRAM for USB.
By default, this option is N.
- **CONFIG_USB_EHCI_ROOT_HUB_TT**—Some EHCI chips have vendor-specific extensions to integrate transaction translators, so that no OHCI or UHCI companion controller is needed. In menuconfig, this option is available under Device drivers > USB support > Root Hub Transaction Translators.
By default, this option is Y selected by `USB_EHCI_ARC` && `USB_EHCI_HCD`.
- **CONFIG_USB_STORAGE**—Build support for USB mass storage devices. In menuconfig, this option is available under Device drivers > USB support > USB Mass Storage support.
By default, this option is Y.

- **CONFIG_USB_HID**—Build support for all USB HID devices. In menuconfig, this option is available under
Device drivers > HID Devices > USB Human Interface Device (full HID) support.
By default, this option is Y.
- **CONFIG_USB_GADGET**—Build support for USB gadget. In menuconfig, this option is available under
Device drivers > USB support > USB Gadget Support.
By default, this option is M.
- **CONFIG_USB_GADGET_ARC**—Build support for ARC USB gadget. In menuconfig, this option is available under
Device drivers > USB support > USB Gadget Support > USB Peripheral Controller (Freescale USB Device Controller).
By default, this option is Y.
- **CONFIG_USB_OTG**—OTG Support, support dual role with ID pin detection.
By default, this option is Y.
- **CONFIG_USB_ETH**—Build support for Ethernet gadget. In menuconfig, this option is available under
Device drivers > USB support > USB Gadget Support > Ethernet Gadget (with CDC Ethernet Support).
By default, this option is M.
- **CONFIG_USB_ETH_RNDIS**—Build support for Ethernet RNDIS protocol. In menuconfig, this option is available under
Device drivers > USB support > USB Gadget Support > Ethernet Gadget (with CDC Ethernet Support) > RNDIS support.
By default, this option is Y.
- **CONFIG_USB_FILE_STORAGE**—Build support for Mass Storage gadget. In menuconfig, this option is available under
Device drivers > USB support > USB Gadget Support > File-backed Storage Gadget.
By default, this option is M.
- **CONFIG_USB_G_SERIAL**—Build support for ACM gadget. In menuconfig, this option is available under
Device drivers > USB support > USB Gadget Support > Serial Gadget (with CDC ACM support).
By default, this option is M.

6.7 Programming Interface

This driver implements all the functions that are required by the USB bus protocol to interface with the i.MX USB ports. See the *BSP API* document, for more information.

6.8 Default USB Settings

Table 6-5 shows the default USB settings.

By default, both usb device and host function are build-in kernel, otg port is used for device mode, and host 1 is used for host mode.

6.9 USB Wakeup usage

6.9.1 How to enable usb wakeup system ability

For otg port:

```
echo enabled > /sys/devices/platform/fsl-usb2-otg/power/wakeup
```

For device-only port:

```
echo enabled > /sys/devices/platform/fsl-usb2-udc/power/wakeup
```

For host-only port:

```
echo enabled > /sys/devices/platform/fsl-ehci.x/power/wakeup
(x is the port num)
```

For usb child device

```
echo enabled > /sys/bus/usb/devices/1-1/power/wakeup
```

6.9.2 What kinds of wakeup event usb support

Take USBOTG port as the example.

Device mode wakeup:

- connect wakeup: when usb line connects to usb port, the other port is connected to PC (Wakeup signal: vbus change)

```
echo enabled > /sys/devices/platform/fsl-usb2-otg/power/wakeup
```

Host mode wakeup:

- connect wakeup: when usb device connects to host port (Wakeup signal: ID/(dm/dp) change)

```
echo enabled > /sys/devices/platform/fsl-usb2-otg/power/wakeup
```

- disconnect wakeup: when usb device disconnects to host port (Wakeup signal: ID/(dm/dp) change)

```
echo enabled > /sys/devices/platform/fsl-usb2-otg/power/wakeup
```

- remote wakeup: press usb device (such as press usb key at usb keyboard) when usb device connects to host port (Wakeup signal: ID/(dm/dp) change):

```
echo enabled > /sys/devices/platform/fsl-usb2-otg/power/wakeup
echo enabled > /sys/bus/usb/devices/1-1/power/wakeup
```

NOTE: For the hub on board, it needs to enable hub's wakeup first. for remote wakeup, it needs to do below three steps:

```
echo enabled > /sys/devices/platform/fsl-usb2-otg/power/wakeup (enable the roothub's
wakeup)
echo enabled > /sys/bus/usb/devices/1-1/power/wakeup (enable the second level hub's
wakeup)
(1-1 is the hub name)
```

```
echo enabled > /sys/bus/usb/devices/1-1.1/power/wakeup (enable the usb device's wakeup,
that device connects at second level hub)
(1-1.1 is the usb device name)
```

6.9.3 How to close the usb child device power

```
echo auto > /sys/bus/usb/devices/1-1/power/control
echo auto > /sys/bus/usb/devices/1-1.1/power/control (If there is a hub at usb device)
```

Chapter 7

Image Processing Unit (IPU) Drivers

The image processing unit (IPU) is designed to support video and graphics processing functions and to interface with video and still image sensors and displays. The IPU driver provides a kernel-level API to manipulate logical channels. A logical channel represents a complete IPU processing flow. For example, a complete IPU processing flow (logical channel) might consist of reading a YUV buffer from memory, performing post-processing, and writing an RGB buffer to memory. A logical channel maps one to three IDMA channels and maps to either zero or one IC tasks. A logical channel can have one input, one output, and one secondary input IDMA channel. The IPU API consists of a set of common functions for all channels. Its functions are to initialize channels, set up buffers, enable and disable channels, link channels for auto frame synchronization, and set up interrupts.

Typical logical channels include:

- CSI direct to memory
- CSI to viewfinder pre-processing to memory
- Memory to viewfinder pre-processing to memory
- Memory to viewfinder rotation to memory
- Previous field channel of memory to video deinterlacing and viewfinder pre-processing to memory
- Current field channel of memory to video deinterlacing and viewfinder pre-processing to memory
- Next field channel of memory to video deinterlacing and viewfinder pre-processing to memory
- CSI to encoder pre-processing to memory
- Memory to encoder pre-processing to memory
- Memory to encoder rotation to memory
- Memory to post-processing to memory
- Memory to post-processing rotation to memory
- Memory to synchronous frame buffer background
- Memory to synchronous frame buffer foreground
- Memory to synchronous frame buffer DC
- Memory to synchronous frame buffer mask

The IPU API has some additional functions that are not common across all channels, and are specific to an IPU sub-module. The types of functions for the IPU sub-modules are as follows:

- Synchronous frame buffer functions
 - Panel interface initialization
 - Set foreground positions
 - Set local/global alpha and color key
 - Set gamma
- CSI functions
 - Sensor interface initialization

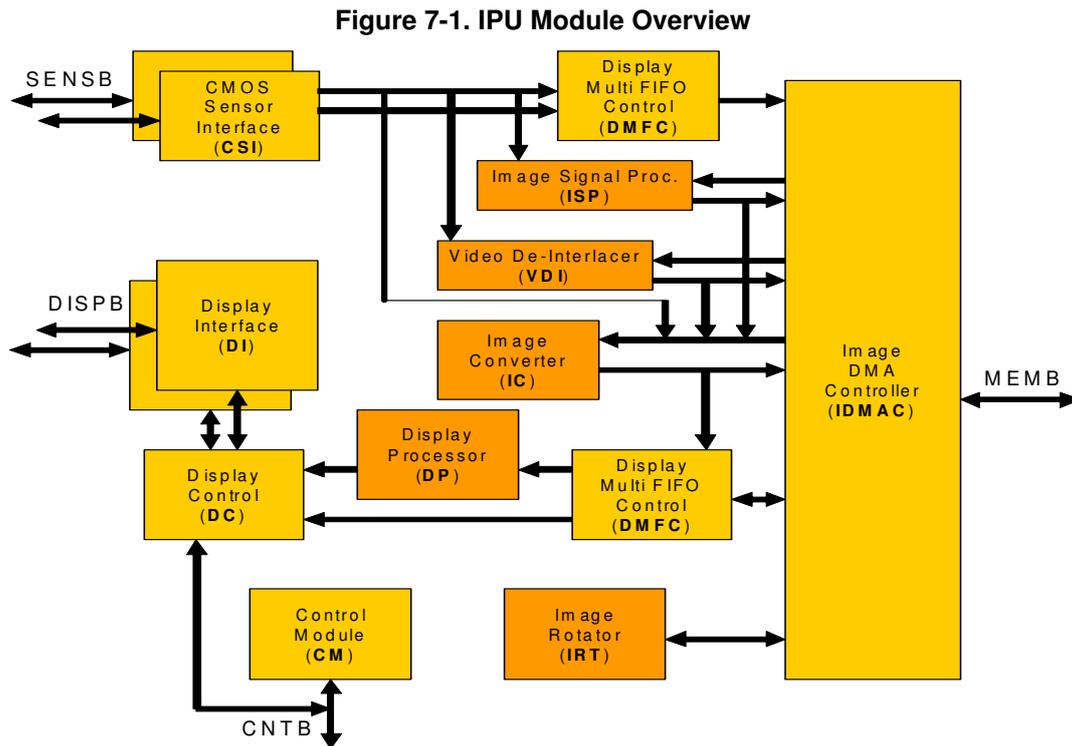
Image Processing Unit (IPU) Drivers

- Set sensor clock
- Set capture size

The higher level drivers are responsible for memory allocation, chaining of channels, and providing user-level API.

7.1 Hardware Operation

The detailed hardware operation of the IPU is discussed in the *MCIMX53 Multimedia Applications Processor Reference Manual (MCIMX53RM)*. Figure 7-3 shows the IPU hardware modules.

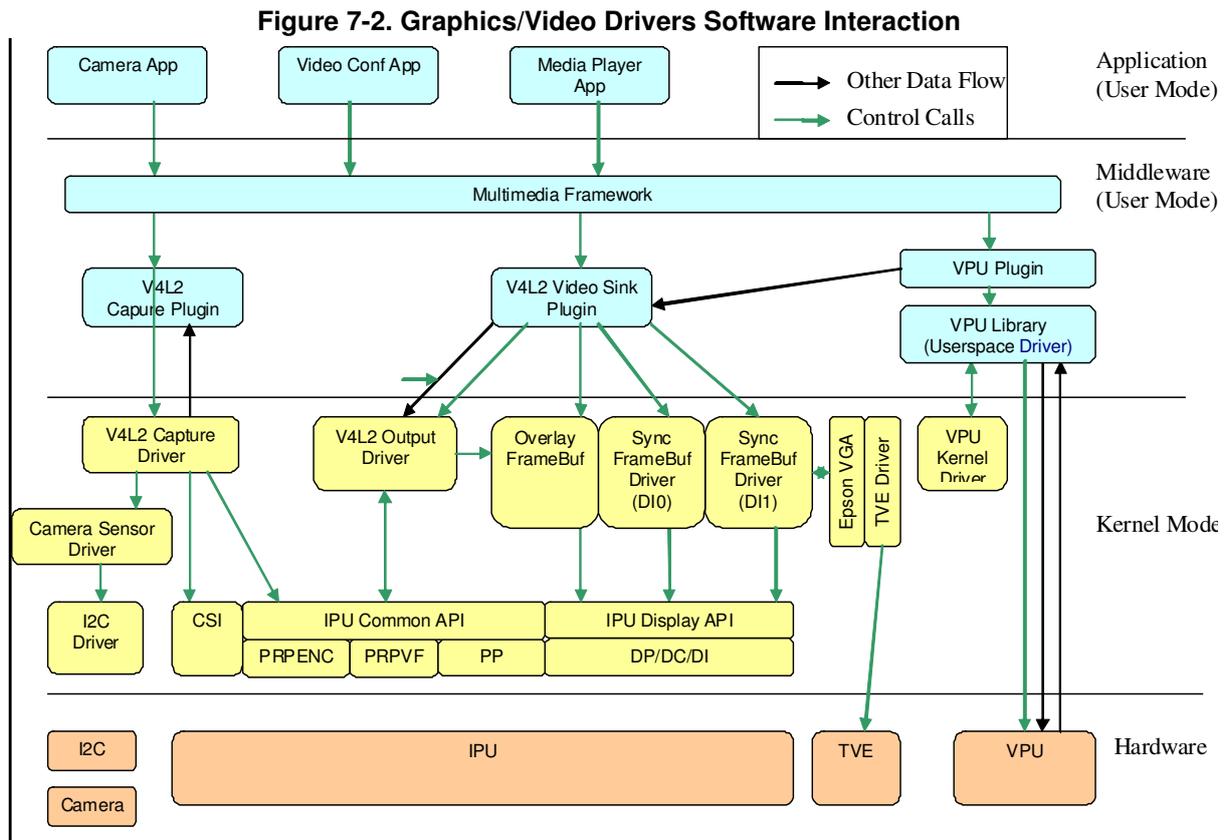


7.2 Software Operation

The IPU driver is a self-contained driver module in the Linux kernel. It consists of a custom kernel-level API for the following blocks:

- Synchronous frame buffer driver
- Display Interface (DI)
- Display Processor (DP)
- Image DMA Controller (IDMAC)
- CMOS Sensor Interface (CSI)
- Image Converter (IC)

Figure 7-2 shows the interaction between the different graphics/video drivers and the IPU.



The IPU drivers are sub-divided as follows:

- Device drivers—include the frame buffer driver for the synchronous frame buffer, the frame buffer driver for the displays, V4L2 capture drivers for IPU pre-processing, and the V4L2 output driver for IPU post-processing. The frame buffer device drivers are available in the `<ltib_dir>/rpm/BUILD/linux/drivers/video/mxc` directory of the Linux kernel. The V4L2 device drivers are available in the `<ltib_dir>/rpm/BUILD/linux/drivers/media/video` directory of the Linux kernel.
- Low-level library routines—interface to the IPU hardware registers. They take input from the high-level device drivers and communicate with the IPU hardware. The low-level libraries are available in the `<ltib_dir>/rpm/BUILD/linux/drivers/mxc/ipu3` directory of the Linux kernel.

7.2.1 IPU Frame Buffer Drivers Overview

The frame buffer device provides an abstraction for the graphics hardware. It represents the frame buffer video hardware, and allows application software to access the graphics hardware through a well-defined interface, so that the software is not required to know anything about the low-level hardware registers.

The driver is enabled by selecting the frame buffer option under the graphics parameters in the kernel configuration. To supplement the frame buffer driver, the kernel builder may also include support for fonts and a startup logo. This device depends on the virtual terminal (VT) console to switch from serial to graphics mode. The device is accessed through special device nodes, located in the `/dev` directory, as `/dev/fb*`. `fb0` is generally the primary frame buffer.

Other than the physical memory allocation and LCD panel configuration, the common kernel video API is utilized for setting colors, palette registration, image blitting, and memory mapping. The IPU reads the raw pixel data from the frame buffer memory and sends it to the panel for display.

7.2.1.1 IPU Frame Buffer Hardware Operation

The frame buffer interacts with the IPU hardware driver module.

7.2.1.2 IPU Frame Buffer Software Operation

A frame buffer device is a memory device, such as `/dev/mem`, and it has features similar to a memory device. Users can read it, write to it, seek to some location in it, and `mmap()` it (the main use). The difference is that the memory that appears in the special file is not the whole memory, but the frame buffer of some video hardware.

`/dev/fb*` also interacts with several IOCTLs, which allows users to query and set information about the hardware. The color map is also handled through IOCTLs. For more information on what IOCTLs exist and which data structures they use, see `<ltib_dir>/rpm/BUILD/linux/include/linux/fb.h`. The following are a few of the IOCTLs functions:

- Request general information about the hardware, such as name, organization of the screen memory (planes, packed pixels, and so on), and address and length of the screen memory.
- Request and change variable information about the hardware, such as visible and virtual geometry, depth, color map format, timing, and so on. The driver suggests values to meet the hardware capabilities (the hardware returns `EINVAL` if that is not possible) if this information is changed.
- Get and set parts of the color map. Communication is 16 bits-per-pixel (values for red, green, blue, transparency) to support all existing hardware. The driver does all the calculations required to apply the options to the hardware (round to fewer bits, possibly discard transparency value).

The hardware abstraction makes the implementation of application programs easier and more portable. The only thing that must be built into the application programs is the screen organization (bitplanes or chunky pixels, and so on), because it works on the frame buffer image data directly.

The MXC frame buffer driver (`<ltib_dir>/rpm/BUILD/linux/drivers/video/mxc/mxc_ipuv3_fb.c`) interacts closely with the generic Linux frame buffer driver (`<ltib_dir>/rpm/BUILD/linux/drivers/video/fbmem.c`).

7.2.1.3 Synchronous Frame Buffer Driver

The synchronous frame buffer screen driver implements a Linux standard frame buffer driver API for synchronous LCD panels or those without memory. The synchronous frame buffer screen driver is the top level kernel video driver that interacts with kernel and user level applications. This is enabled by selecting

the Synchronous Panel Frame buffer option under the graphics support device drivers in the kernel configuration. To supplement the frame buffer driver, the kernel builder may also include support for fonts and a startup logo. This depends on the VT console for switching from serial to graphics mode.

Except for physical memory allocation and LCD panel configuration, the common kernel video API is utilized for setting colors, palette registration, image blitting and memory mapping. The IPU reads the raw pixel data from the frame buffer memory and sends it to the panel for display.

The frame buffer driver supports different panels as a kernel configuration option. Support for new panels can be added by defining new values for a structure of panel settings.

The frame buffer interacts with the IPU driver using custom APIs that allow:

- Initialization of panel interface settings
- Initialization of IPU channel settings for LCD refresh
- Changing the frame buffer address for double buffering support

The following features are supported:

- Configurable screen resolution
- Configurable RGB 16, 24 or 32 bits per pixel frame buffer
- Configurable panel interface signal timings and polarities
- Palette/color conversion management
- Power management
- LCD power off/on

User applications utilize the generic video API (the standard Linux frame buffer driver API) to perform functions with the frame buffer. These include the following:

- Obtaining screen information, such as the resolution or scan length
- Allocating user space memory using `mmap` for performing direct blitting operations

A second frame buffer driver supports a second video/graphics plane.

7.3 Source Code Structure

Table 7-1 lists the source files associated with the IPU, Sensor, V4L2, and Panel drivers. These files are available in the following directories:

```
<ltib_dir>/rpm/BUILD/linux/drivers/mxc/ipu3
<ltib_dir>/rpm/BUILD/linux/drivers/video/mxc
<ltib_dir>/rpm/BUILD/linux/drivers/media/video/mxc
<ltib_dir>/rpm/BUILD/linux/drivers/video/backlight
```

Table 7-1. IPU Driver Files

File	Description
ipu_capture.c	Asynchronous frame buffer configuration driver
ipu_common.c	Configuration functions for asynchronous and synchronous frame buffers
ipu_device.c	IPU driver device interface and fops functions
ipu_disp.c	IPU display functions
ipu_ic.c	IPU library functions
ipu_calc_stripes_sizes.c	Multi-stripes method functions for ipu_ic.c
mxcpuv3_fb.c	Driver for synchronous frame buffer
mxcfb_epson_vga.c	Driver for synchronous framebuffer for VGA
mxcfb_claa_wvga.c	Driver for synchronous frame buffer for WVGA
mxcfb_modedb.c	Parameter settings for Framebuffer devices
ldb.c	Driver for synchronous frame buffer for on chip LVDS
tve.c	Driver for synchronous frame buffer for on chip TVE
mxcfb_sii9022.c	Driver for synchronous frame buffer for HDMI chip sii9022
mxcfb_seiko_wvga.c	Driver for synchronous frame buffer for Seiko WVGA
mxcp_edid.c	Driver for EDID

Table 7-2 lists the global header files associated with the IPU and Panel drivers. These files are available in the following directories:

```
<ltib_dir>/rpm/BUILD/linux/drivers/mxc/ipu3/
<ltib_dir>/rpm/BUILD/linux/include/linux/
<ltib_dir>/rpm/BUILD/linux/drivers/media/video/mxc/
```

Table 7-2. IPU Global Header Files

File	Description
ipu_param_mem.h	Helper functions for IPU parameter memory access
ipu_priv.h	Header file for Pre-processing drivers
ipu_regs.h	IPU register definitions
mxcfb.h	Header file for the synchronous framebuffer driver
ipu.h	Header file for ipu basic driver

7.4 Menu Configuration Options

The following Linux kernel configuration options are provided for the IPU module. To get to these options use the command `./ltib -c` when located in the `<ltib dir>`. On the screen displayed, select **Configure the kernel** and exit. When the next screen appears select the options to configure.

- CONFIG_MXC_IPU**—Includes support for the Image Processing Unit. In menuconfig, this option is available under:

Device Drivers > MXC support drivers > Image Processing Unit Driver

By default, this option is Y for all architectures.

If ARCH_MX37 or ARCH_MX5 is true, CONFIG_MXC_IPU_V3 will be set, otherwise, CONFIG_MXC_IPU_V1 will be set.
- CONFIG_MXC_CAMERA_MICRON_111**—Option for both the Micron mt9v111 sensor driver and the use case driver. This option is dependent on the MXC_IPU option. In menuconfig, this option is available under:

Device Drivers > Multimedia devices > Video capture adapters > MXC Video For Linux Camera > MXC Camera/V4L2 PRP Features support > Micron mt9v111 Camera support

Only one sensor should be installed at a time.
- CONFIG_MXC_CAMERA_OV2640**—Option for both the OV2640 sensor driver and the use case driver. This option is dependent on the MXC_IPU option. In menuconfig, this option is available under:

Device Drivers > Multimedia devices > Video capture adapters > MXC Video For Linux Camera > MXC Camera/V4L2 PRP Features support > OmniVision ov2640 camera support

Only one sensor should be installed at a time.
- CONFIG_MXC_CAMERA_OV3640**—Option for both the OV3640 sensor driver and the use case driver. This option is dependent on the MXC_IPU option. In menuconfig, this option is available under:

Device Drivers > Multimedia devices > Video capture adapters > MXC Video For Linux Camera > MXC Camera/V4L2 PRP Features support > OmniVision ov3640 camera support

Only one sensor should be installed at a time.
- CONFIG_MXC_IPU_PRP_VF_SDC**—Option for the IPU (here the > symbols illustrates data flow direction between HW blocks):

CSI > IC > MEM MEM > IC (PRP VF) > MEM

Use case driver for dumb sensor or

CSI > IC (PRP VF) > MEM

for smart sensors. In menuconfig, this option is available under:

Multimedia devices > Video capture adapters > MXC Video For Linux Camera > MXC Camera/V4L2 PRP Features support > Pre-Processor VF SDC library

By default, this option is M for all.
- CONFIG_MXC_IPU_PRP_ENC**—Option for the IPU:

Use case driver for dumb sensors

CSI > IC > MEM MEM > IC (PRP ENC) > MEM

or for smart sensors

CSI > IC(PRP ENC) > MEM.

In menuconfig, this option is available under:

Device Drivers > Multimedia Devices > Video capture adapters > MXC Video For Linux Camera > MXC Camera/V4L2 PRP Features support > Pre-processor Encoder library

By default, this option is set to M for all.

- **CONFIG_VIDEO_MXC_CAMERA**—This is configuration option for V4L2 capture Driver. This option is dependent on the following expression:

`VIDEO_DEV && MXC_IPU && MXC_IPU_PRP_VF_SDC && MXC_IPU_PRP_ENC`

In menuconfig, this option is available under:

Device Drivers > Multimedia devices > Video capture adapters > MXC Video For Linux Camera

By default, this option is M for all.

- **CONFIG_VIDEO_MXC_OUTPUT**—This is configuration option for V4L2 output Driver. This option is dependent on `VIDEO_DEV && MXC_IPU` option. In menuconfig, this option is available under:

Device Drivers > Multimedia devices > Video capture adapters > MXC Video for Linux Video Output

By default, this option is Y for all.

- **CONFIG_FB**—This is the configuration option to include frame buffer support in the Linux kernel. In menuconfig, this option is available under:

Device Drivers > Graphics support > Support for frame buffer devices

By default, this option is Y for all architectures.

- **CONFIG_FB_MXC**—This is the configuration option for the MXC Frame buffer driver. This option is dependent on the `CONFIG_FB` option. In menuconfig, this option is available under:

Device Drivers > Graphics support > MXC Framebuffer support

By default, this option is Y for all architectures.

- **CONFIG_FB_MXC_SYNC_PANEL**—This is the configuration option that chooses the synchronous panel framebuffer. This option is dependent on the `CONFIG_FB_MXC` option. In menuconfig, this option is available under:

Device Drivers > Graphics support > MXC Framebuffer support > Synchronous Panel Framebuffer

By default this option is Y for all architectures.

- **CONFIG_FB_MXC_EPSON_VGA_SYNC_PANEL**—This is the configuration option that chooses the Epson VGA panel. This option is dependent on `CONFIG_FB_MXC_SYNC_PANEL` option. In menuconfig, this option is available under:

Device Drivers > Graphics support > MXC Framebuffer support > Synchronous Panel Framebuffer > Epson VGA Panel

- **CONFIG_FB_MXC_TVOUT_TVE** —This configuration option selects the TVOUT encoder on MX5x chip. This option is dependent on `CONFIG_FB_MXC_SYNC_PANEL` and `CONFIG_MXC_IPU_V3` option. In menuconfig, this option is available under:

Device Drivers > Graphics support > MXC Framebuffer support > Synchronous Panel Framebuffer > MXC TVE TV Out Encoder

- **CONFIG_FB_MXC_LDB** —This configuration option selects the LVDS module on iMX53 chip. This option is dependent on **CONFIG_FB_MXC_SYNC_PANEL** and **CONFIG_MXC_IPU_V3** option. In menuconfig, this option is available under:
Device Drivers > Graphics support > MXC Framebuffer support > Synchronous Panel Framebuffer > MXC LDB
- **CONFIG_FB_MXC_CLAA_WVGA_SYNC_PANEL** —This is the configuration option that chooses the CLAA WVGA panel. This option is dependent on **CONFIG_FB_MXC_SYNC_PANEL** option. In menuconfig, this option is available under:
Device Drivers > Graphics support > MXC Framebuffer support > Synchronous Panel Framebuffer > CLAA WVGA Panel.
- **CONFIG_FB_MXC_SEIKO_WVGA_SYNC_PANEL** —This is the configuration option that chooses the SEIKO WVGA panel. This option is dependent on **CONFIG_FB_MXC_SYNC_PANEL** option. In menuconfig, this option is available under:
Device Drivers > Graphics support > MXC Framebuffer support > Synchronous Panel Framebuffer > SEIKO WVGA Panel.
- **CONFIG_FB_MXC_SII9022** —This configuration option selects the SII9022 HDMI chip. This option is dependent on **CONFIG_FB_MXC_SYNC_PANEL** option. In menuconfig, this option is available under:
Device Drivers > Graphics support > MXC Framebuffer support > Synchronous Panel Framebuffer > Si Image SII9022 DVI/HDMI Interface Chip
- **CONFIG_FB_MXC_CH7026** —This configuration option selects the CH7026 VGA interface chip. This option is dependent on the **CONFIG_FB_MXC_SYNC_PANEL** option. In menuconfig, this option is available under:
Device Drivers > Graphics support > MXC Framebuffer support > Synchronous Panel Framebuffer > Chrontel CH7026 VGA Interface Chip
- **CONFIG_FB_MXC_TVOUT_CH7024** —This configuration option selects the CH7024 TVOUT encoder. This option is dependent on the **CONFIG_FB_MXC_SYNC_PANEL** option. In menuconfig, this option is available under:
Device Drivers > Graphics support > MXC Framebuffer support > Synchronous Panel Framebuffer > CH7024 TV Out Encoder

7.5 Programming Interface

For more information, see the *API Documents* for the programming interface.

Chapter 8

HDMI Driver

The HDMI module is supported by a SII902x chip on board or a daughter card, it supports:

- HDMI video output
- Display device EDID fetching
- HDMI audio output

Refer to SII902x's datasheet for detail information.

8.1 Hardware Operation

Normally, the SII902x chip connects with

- IPUv3 DI port for display support
- SoC SPDIF port for audio support
- I2C bus for setup operation and EDID fetching
- A cable detection interrupt line

8.2 Software Operation

The HDMI driver is implemented based on a fb client driver, it mainly contains:

- A fb event notifier callback
- A delay workqueue based on interrupt serves for cable detection and EDID fetching

In fb event notifier callback:

- An event as FB_EVENT_MODE_CHANGE will setup SII902x video and audio parameters
- An event as FB_EVENT_BLANK will be responsible for SII902x power on/off

For cable detection and EDID fetching:

- An irq handler -- sii902x_detect_handler() is registered
- A delay workqueue will be scheduled when interrupt occurs
- Workqueue callback function -- det_worker() will trigger EDID fetching
- A sysfs node -- /sys/devices/platform/sii9022.0/cable_state is provided to show cable state
- An uevent with EVENT=plugin or EVENT=plugout will send out after hdmi cable plugin/out

8.3 Source Code Structure

Table 8-1 lists the TVE driver source files available in the `<ltib_dir>/rpm/BUILD/linux/drivers/video/mxc` directory.

Table 8-1. Camera File List

File	Description
<code>mxcfb_sii902x.c</code>	HDMI Sii902x driver implementation

8.4 Linux Menu Configuration Options

The Linux kernel configuration option, `CONFIG_FB_MXC_SII902X`, is provided for the module. This is the configuration option for the HDMI SII902x driver. In `menuconfig`, this option is available under

Device Drivers > Graphics support > Si Image SII9022 DVI/HDMI Interface Chip

This option is dependent on the support Synchronous Panel Framebuffer and IPUv3 option. By default, this option is Y.

Chapter 9

MXC DDC Driver

The mxc DDC driver is a common EDID fetch driver based on I2C bus.

9.1 MXC DDC Driver Overview

The MAX DDC driver is an I2C based driver. It provides a detection method for DDC device cable. After the cable is detected, the EDID will be fetched through I2C bus. Then the video modes are parsed into the fb info struct which is attached to this DDC driver.

9.1.1 Hardware Operation

One pin provides the interrupt for the cable detection.

When the cable is plugged into, a serial of I2C operation is triggered to read the EDID data from DDC address.

9.1.2 Software Operation

The cable plugin interrupt handler will trigger one delayed work, which will fetch the EDID data through I2C, then parsing EDID to video modes, attached fb info then will reload these video modes into its modelist.

The fb info should be attached through fb notifier.

Uevent will be sent out to user space when cable plugin/pluginout.

Cable state can be checked under:

```
/sys/devices/platform/mxc_ddc.0/cable_state
```

Attached fb name could be checked under:

```
/sys/devices/platform/mxc_ddc.0/fb_name
```

EDID data could be checked under:

```
/sys/devices/platform/mxc_ddc.0/edid
```

A command line option 'ddc' could enable mxc ddc feature.

9.2 Source Code Structure Configuration

[Table 9-1](#) describes the source files associated with the MXC DDC driver, which are available in the directory `<ltib_dir>/rpm/BUILD/linux/drivers/video/mxc`.

Table 9-1. MXC DDC Driver Source File

File	Description
mxc_edid.c	Source file for MXC DDC driver

9.3 Driver Configuration

This module can be selected using the ltib menu options.

To get to enable the MXC DDC driver use the command `./ltib -c` when located in the `<ltib dir>`. On the screen displayed, select **Configure the kernel** and exit. When the next screen appears select the following options to enable the MXC DDC driver.

- Device Drivers > Graphics support > Support for frame buffer devices >
— Chooses Enable Video Mode Handling Helpers

Chapter 10

i.MX5 Dual Display

This section describes how to setup dual-display on i.MX53 TABLET platform.

10.1 Hardware Operation

i.MX53 multimedia application processes incorporate the Image Processing Unit (IPUv3) hardware image processing accelerator. There are two Display Interfaces (DI) within IPUv3, which provide connection to external display devices and related devices. The external display devices can be a LCD display panel, which connects with DI directly. The related devices may be embedded in chip or integrated on EVK boards. TV Encoder (TVE) is the only embedded device which connects with DI1 in i.MX53 chips.

i.MX53 chips embed the LVDS Display Bridge (LDB) module so that external display devices with LVDS interfaces can be connected with the chips directly. TVE is only supported in i.MX53 TO2 chips. There is a connector on i.MX53 TABLET platform which leads the legacy parallel signals of DI0 out so that a LCD display panel can be connected to it directly or a connected DVI convertor can provide an interface for a DVI monitor. One HDMI chip is integrated in i.MX53 TABLET platform.

As there are two DIs within IPUv3, we can support dual-display feature, that is, each of the two DIs can support an external display device simultaneously. As long as the hardware bandwidth is not exceeded, i.MX53 TABLET platform can drive every possible dual-display feature provided by the board design.

Table 10-1 shows all the external display devices that can be connected with i.MX53 TABLET platform.

Table 10-1. External Display Devices for i.MX53 TABLET Platform

EVK Platform	DI Number	External Display Device
i.MX53 TABLET	0	1) DVI daughter card 2) CLAA-WVGA display panel 3) HDMI interface (driven by HDMI transmitter on board)
	1	1) LVDS display panel (driven by LDB)

For the detailed information about the external display devices, see the relevant board schematics.

10.2 Software Operation

The user should setup a correct bootup command line if he or she wants to enable dual-display feature. The user may follow these steps to set the bootup command line for display related options:

1. Add 'tve', 'vga', 'ldb' or 'hdmi' to bootup command line if the use case involves TVE, VGA, LDB or HDMI, otherwise, the options should not be added.
2. Add 'di1_primary' to bootup command line if the device connected with DI1 is the primary device, that is, /dev/fb0 will be mapped to this device after the system boots up. If the device connected with DI0 is the primary device, no specific option is needed.

i.MX5 Dual Display

3. Add 'di0_primary' to bootup command line if the device connected with DI0 is the primary device, that is, /dev/fb0 will be mapped to this device after the system boots up. If the device connected with DI0 is the primary device, no specific option is needed
4. For each of the devices connected with DI, provide a specific video mode in bootup command line in this format: video=mxcdixfb:DI_pixel_format, video_mode,bpp=bits_per_pixel_of_frame_buffer.

The 'x' stands for DI number.

The 'DI_pixel_format' stands for the output pixel format of the related DI. Usually, 'RGB565' is used for CLAA WVGA LCD display panel, 'RGB24' is used for DVI monitor.

The 'bits_per_pixel_of_frame_buffer' stands for the pixel format of the related framebuffer.

The 'video_mode' can be found here:

1. DVI connector: The video mode is in this format:
`<xres>x<yres> [M] [-<bpp>] [@<refresh>`
with <xres>, <yres>, <bpp> and <refresh> decimal numbers and <name> a string. If 'M' is present after yres (and before refresh/bpp if present), the framebuffer driver will compute the timings using VESA(tm) Coordinated Video Timings (CVT).

Note, if the display resolution is 720P, then '720P60' should be used as 'video_mode', and if the display resolution is UXGA, then 'UXGA' should be used as 'video_mode'.

2. LVDS display panel: Use 'XGA' for XGA LVDS display panel and use '1080P60' for 1080P LVDS display panel.
3. CLAA WVGA LCD display panel: Use 'CLAA-WVGA'.
4. SEIKO WVGA LCD display panel: Use 'SEIKO-WVGA'
5. TV: Use 'TV-1080P60' for 1080P60 TVout, use 'TV-1080P30' for 1080P30 TVout, use 'TV-1080P25' for 1080P25 TVout, use 'TV-1080P24' for 1080P24 TVout, use 'TV-1080I60' for 1080I60 TVout, use 'TV-1080I50' for 1080I50 TVout, use 'TV-720P60' for 720P60 TVout, use 'TV-720P30' for 720P30 TVout, use 'TV-PAL' for PAL TVout and use 'TV-NTSC' for NTSC TVout.
- 6.

As the primary display device will be unblanked automatically after the system boots up but the secondary is still blank, the user needs to unblank the secondary by himself or herself either with framebuffer ioctlr or command line. Here is the command line the user may use on PDK to unblank the secondary display device in an ordinary case:

```
echo 0 > /sys/class/graphics/fb1/blank
```

The user may also switch the primary display device and secondary display device by command lines on PDK. For example, fb0 is the primary device's framebuffer and fb1 is the secondary device's framebuffer. To switch the primary display device and secondary display device, the user may use these command lines:

1. echo 1 > /sys/class/graphics/fb0/blank
2. echo 1 > /sys/class/graphics/fb1/blank
3. echo 1 > /sys/class/graphics/fb2/blank
4. echo 1-layer-fb > /sys/class/graphics/fb0/fsl_disp_property

5. `echo 0 > /sys/class/graphics/fb0/blank`
6. `echo 0 > /sys/class/graphics/fb1/blank`

To switch them back, the user may use these command lines:

1. `echo 1 > /sys/class/graphics/fb0/blank`
2. `echo 1 > /sys/class/graphics/fb1/blank`
3. `echo 1 > /sys/class/graphics/fb2/blank`
4. `echo 1-layer-fb > /sys/class/graphics/fb1/fsl_disp_property`
5. `echo 0 > /sys/class/graphics/fb0/blank`
6. `echo 0 > /sys/class/graphics/fb1/blank`

10.3 Examples

Examples for i.MX53 TABLET platform:

7. DI0:HDMI monitor, DI1:XGA LVDS display panel (primary)

```
video=mxcdi0fb:RGB24,1024x768M@60 hdmi video=mxcdi1fb:RGB666,XGA di1_primary ldb=di1
```


Chapter 11

Video for Linux Two (V4L2) Driver

The Video for Linux Two (V4L2) drivers are plug-ins to the V4L2 framework that enable support for camera and preprocessing functions, as well as video and post-processing functions. The V4L2 camera driver implements support for all camera related functions. The V4L2 capture device takes incoming video images, either from a camera or a stream, and manipulates them. The output device takes video and manipulates it, then sends it to a display or similar device. The V4L2 Linux standard API specification is available at <http://v4l2spec.bytesex.org/spec/>.

The features supported by the V4L2 driver are as follows:

- Direct preview and output to SDC foreground overlay plane (with no processor intervention and synchronized to LCD refresh)
- Direct preview to graphics frame buffer (with no processor intervention, but not synchronized to LCD refresh)
- Color keying or alpha blending of frame buffer and overlay planes
- Simultaneous preview and capture
- Streaming (queued) capture from IPU encoding channel
- Direct (raw Bayer) still capture (sensor dependent)
- Programmable pixel format, size, frame rate for preview and capture
- Programmable rotation and flipping using custom API
- RGB 16-bit, 24-bit, and 32-bit preview formats
- Raw Bayer (still only, sensor dependent), RGB 16, 24, and 32-bit, YUV 4:2:0 and 4:2:2 planar, YUV 4:2:2 interleaved, and JPEG formats for capture
- Control of sensor properties including exposure, white-balance, brightness, contrast, and so on
- Plug-in of different sensor drivers
- Linking post-processing resize and CSC, rotation, and display IPU channels with no ARM processing of intermediate steps
- Streaming (queued) input buffer
- Double buffering of overlay and intermediate (rotation) buffers
- Configurable 3+ buffering of input buffers
- Programmable input and output pixel format and size
- Programmable scaling and frame rate
- RGB 16, 24, and 32-bit, YUV 4:2:0 and 4:2:2 planar, and YUV 4:2:2 interleaved input formats
- TV output

The driver implements the standard V4L2 API for capture, output, and overlay devices. The command `modprobe mxc_v4l2_capture` must be run before using these functions.

11.1 V4L2 Capture Device

The V4L2 capture device includes two interfaces:

- Capture interface—uses IPU pre-processing ENC channels to record the YCrCb video stream
- Overlay interface—uses the IPU pre-processing VF channels to display the preview video to the SDC foreground panel without ARM processor interaction.

V4L2 capture support can be selected during kernel configuration. The driver includes two layers. The top layer is the common Video for Linux driver, which contains chain buffer management, stream API and other `ioctl` interfaces. The files for this device are located in

`<ltib_dir>/rpm/BUILD/linux/drivers/media/video/mxc/capture/`.

The V4L2 capture device driver is in the `mxc_v4l2_capture.c` file. The lowest layer is in the `ipu_prp_enc.c` file.

This code (`ipu_prp_enc.c`) interfaces with the IPU ENC hardware, `ipu_prp_vf_sdc_bg.c` interfaces with the IPU VF hardware, and `ipu_still.c` interfaces with the IPU CSI hardware. Sensor frame rate control is handled by `VIDIOC_S_PARM` `ioctl`. Before the frame rate is set, the sensor turns on the AE and AWB turn on. The frame rate may change depending on light sensor samples.

Drivers for specific cameras can be found in

`<ltib_dir>/rpm/BUILD/linux/drivers/media/video/mxc/capture/`

11.1.1 V4L2 Capture IOCTLs

Currently, the memory map stream API is supported. Supported V4L2 IOCTLs include the following:

- `VIDIOC_QUERYCAP`
- `VIDIOC_G_FMT`
- `VIDIOC_S_FMT`
- `VIDIOC_REQBUFS`
- `VIDIOC_QUERYBUF`
- `VIDIOC_QBUF`
- `VIDIOC_DQBUF`
- `VIDIOC_STREAMON`
- `VIDIOC_STREAMOFF`
- `VIDIOC_OVERLAY`
- `VIDIOC_G_FBUF`
- `VIDIOC_S_FBUF`
- `VIDIOC_G_CTRL`
- `VIDIOC_S_CTRL`
- `VIDIOC_CROPCAP`
- `VIDIOC_G_CROP`
- `VIDIOC_S_CROP`

- VIDIOC_S_PARM
- VIDIOC_G_PARM
- VIDIOC_ENUMSTD
- VIDIOC_G_STD
- VIDIOC_S_STD
- VIDIOC_ENUMOUTPUT
- VIDIOC_G_OUTPUT
- VIDIOC_S_OUTPUT

V4L2 control code has been extended to provide support for rotation. The ID is V4L2_CID_PRIVATE_BASE. Supported values include:

- 0—Normal operation
- 1—Vertical flip
- 2—Horizontal flip
- 3—180° rotation
- 4—90° rotation clockwise
- 5—90° rotation clockwise and vertical flip
- 6—90° rotation clockwise and horizontal flip
- 7—90° rotation counter-clockwise

Figure 11-1 shows a block diagram of V4L2 Capture API interaction.

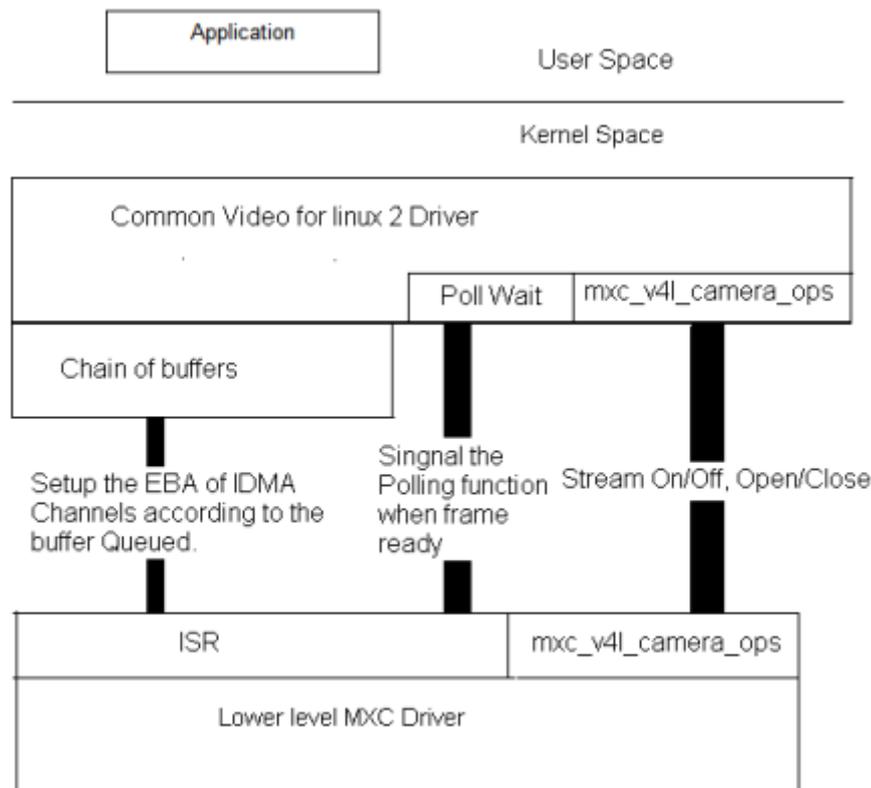


Figure 11-1. Video4Linux2 Capture API Interaction

11.1.2 Use of the V4L2 Capture APIs

This section describes a sample V4L2 capture process. The application completes the following steps:

1. Sets the capture pixel format and size by IOCTL VIDIOC_S_FMT.
2. Sets the control information by IOCTL VIDIOC_S_CTRL for rotation usage.
3. Requests a buffer using IOCTL VIDIOC_REQBUFS. The common V4L2 driver creates a chain of buffers (currently the maximum number of frames is 3).
4. Memory maps the buffer to its user space.
5. Queues buffers using the IOCTL command VIDIOC_QBUF.
6. Starts the stream using the IOCTL VIDIOC_STREAMON. This IOCTL enables the IPU tasks and the IDMA channels. When the processing is completed for a frame, the driver switches to the buffer that is queued for the next frame. The driver also signals the semaphore to indicate that a buffer is ready.
7. Takes the buffer from the queue using the IOCTL VIDIOC_DQBUF. This IOCTL blocks until it has been signaled by the ISR driver.
8. Stores the buffer to a YCrCb file.
9. Replaces the buffer in the queue of the V4L2 driver by executing VIDIOC_QBUF again.

For the V4L2 still image capture process, the application completes the following steps:

1. Sets the capture pixel format and size by executing the IOCTL VIDIOC_S_FMT.
2. Reads one frame still image with YUV422.

For the V4L2 overlay support use case, the application completes the following steps:

1. Sets the overlay window by IOCTL VIDIOC_S_FMT.
2. Turns on overlay task by IOCTL VIDIOC_OVERLAY.
3. Turns off overlay task by IOCTL VIDIOC_OVERLAY.

11.2 V4L2 Output Device

The V4L2 output driver uses the IPU post-processing functions for video output. The driver implements the standard V4L2 API for output devices. V4L2 output device support can be selected during kernel configuration. The driver is available at

`<ltib_dir>/rpm/BUILD/linux/drivers/media/video/mxc/output/mxc_v4l2_output.c.`

11.2.1 V4L2 Output IOCTLs

Currently, the memory map stream API is supported. Supported V4L2 IOCTLs include the following:

- VIDIOC_QUERYCAP
- VIDIOC_REQBUFS
- VIDIOC_G_FMT
- VIDIOC_S_FMT
- VIDIOC_QUERYBUF
- VIDIOC_QBUF
- VIDIOC_DQBUF
- VIDIOC_STREAMON
- VIDIOC_STREAMOFF
- VIDIOC_G_CTRL
- VIDIOC_S_CTRL
- VIDIOC_CROPCAP
- VIDIOC_G_CROP
- VIDIOC_S_CROP
- VIDIOC_S_PARM
- VIDIOC_G_PARM

The V4L2 control code has been extended to provide support for rotation. For this use, the ID is V4L2_CID_PRIVATE_BASE. Supported values include the following:

- 0—Normal operation
- 1—Vertical flip
- 2—Horizontal flip

Video for Linux Two (V4L2) Driver

- 3—Horizontal and vertical flip
- 4—90° rotation
- 5—90° rotation and vertical flip
- 6—90° rotation and horizontal flip
- 7—90° rotation with horizontal and vertical flip

11.2.2 Use of the V4L2 Output APIs

This section describes a sample V4L2 capture process that uses the V4L2 output APIs. The application completes the following steps:

1. Sets the capture pixel format and size using IOCTL VIDIOC_S_FMT.
2. Sets the control information using IOCTL VIDIOC_S_CTRL, for rotation.
3. Requests a buffer using IOCTL VIDIOC_REQBUFS. The common V4L2 driver creates a chain of buffers (currently the maximum number of frames is 3).
4. Memory maps the buffer to its user space.
5. Executes the IOCTL VIDIOC_DQBUF.
6. Passes the data that requires post-processing to the buffer.
7. Queues the buffer using the IOCTL command VIDIOC_QBUF.
8. Starts the stream by executing IOCTL VIDIOC_STREAMON.
9. VIDIOC_STREAMON and VIDIOC_OVERLAY cannot be enabled simultaneously.

11.3 Source Code Structure

Table 11-1 lists the source and header files associated with the V4L2 drivers. These files are available in the following directory:

```
<ltib_dir>/rpm/BUILD/linux/drivers/media/video/mxc
```

Table 11-1. V2L2 Driver Files

File	Description
capture/mxc_v4l2_capture.c	V4L2 capture device driver
output/mxc_v4l2_output.c	V4L2 output device driver
capture/mxc_v4l2_capture.h	Header file for V4L2 capture device driver
output/mxc_v4l2_output.h	Header file for V4L2 output device driver
capture/ipu_prp_enc.c	Pre-processing encoder driver
capture/ipu_prp_vf_adc.c	Pre-processing view finder (asynchronous) driver
capture/ipu_prp_vf_sdc.c	Pre-processing view finder (synchronous foreground) driver
capture/ipu_prp_vf_sdc_bg.c	Pre-processing view finder (synchronous background) driver
capture/ipu_still.c	Pre-processing still image capture driver

Drivers for specific cameras can be found in

```
<ltib_dir>/rpm/BUILD/linux/drivers/media/video/mxc/capture/
```

11.4 Menu Configuration Options

The Linux kernel configuration options are provided in the chapter on the IPU module. See [Section 7.4](#), “Menu Configuration Options.”

11.5 V4L2 Programming Interface

For more information, see the *V4L2 Specification* and the *API Documents* for the programming interface. The API Specification is available at <http://v4l2spec.bytesex.org/spec/>.

Chapter 12

Graphics Processing Unit (GPU)

The Graphics Processing Unit (GPU) is a graphics accelerator targeting embedded 2D/3D graphics applications. The GPU3D (3D graphics processing unit) is based on the AMD Z430 core, which is an embedded engine that accelerates user level graphics APIs (Application Programming Interface) such as OpenGL ES 1.1 and 2.0. The GPU2D (2D graphics processing unit) is based on the AMD Z160 core, which is an embedded 2D and vector graphics accelerator targeting the OpenVG 1.1 graphics API and feature set. The GPU driver kernel module source is in kernel source tree, but the libs are delivered as binary only.

12.1 Driver Features

The GPU driver enables this board to provide the following software and hardware support:

- EGL (EGL™ is an interface between Khronos rendering APIs such as OpenGL ES or OpenVG and the underlying native platform window system) 1.3 API defined by Khronos Group
- OpenGL ES (OpenGL® ES is a royalty-free, cross-platform API for full-function 2D and 3D graphics on embedded systems) 1.1 API defined by Khronos Group
- OpenGL ES 2.0 API defined by Khronos Group
- OpenVG (OpenVG™ is a royalty-free, cross-platform API that provides a low-level hardware acceleration interface for vector graphics libraries such as Flash and SVG) 1.1 API defined by Khronos Group

12.2 Hardware Operation

Refer to the GPU chapter in the *SOC Reference Manual* for detailed hardware operation and programming information.

12.3 Software Operation

The GPU driver is divided into two layers. The first layer is running in kernel mode and acts as the base driver for the whole stack. This layer provides the essential hardware access, device management, memory management, command stream management, context management and power management. The second layer is running in user mode, implementing the stack logic and providing the following APIs to the upper layer applications:

- OpenGL ES 1.1 and 2.0 API
- EGL 1.3 API
- OpenVG 1.1 API

12.4 Source Code Structure

Table 12-1 lists GPU driver kernel module source structure:

```
<ltib_dir>/rpm/BUILD/linux/drivers/mxc/amd-gpu
```

Table 12-1. GPU Driver Files

File	Description
Kconfig Makefile	kernel configure file and makefile
include	header files
common	common and core code
os	os specific code
platform	platform specific code

12.5 API References

Refer to the following web sites for detailed specifications:

- OpenGL ES 1.1 and 2.0 API: <http://www.khronos.org/opengles/>
- EGL 1.3 API: <http://www.khronos.org/egl/>
- OpenVG 1.1 API: <http://www.khronos.org/openvg/>

12.6 Menu Configuration Options

The following Linux kernel configurations are provided for GPU driver:

- CONFIG_MXC_AMD_GPU —Configuration option for GPU driver. In the menuconfig this option is available under Device Drivers > MXC support drivers > MXC GPU support > MXC GPU support.

To get to the GPU library package in LTIB, use the command `./ltib -c` when located in the `<ltib dir>`. On the screen displayed, select **Configure the kernel** and select “Device Drivers” > “MXC support drivers” > “MXC GPU support” > “MXC GPU support” and exit. When the next screen appears select the following options to enable the GPU driver:

- Package list > amd-gpu-bin-mx51
This package provides proprietary binary kernel modules, libraries, and test code built from the GPU for framebuffer
- Package list > amd-gpu-x11-bin-mx51
This package provides proprietary binary kernel modules, libraries, and test code built from the GPU for X-Window

Chapter 13

X Windows Acceleration

X Windows is a portable, client-server based, graphics display system. X Windows can run with a default frame buffer driver which handles all drawing operations to the main display. Since there is a 2D GPU (graphics processing unit) available, then some of the drawing operations can be accelerated. High level X Windows operations may get decomposed into many low level drawing operations where these low level operations are accelerated for X Windows.

13.1 Hardware Operation

X Windows acceleration utilizes the 2D GPU which is discussed in the [Chapter 12, “Graphics Processing Unit \(GPU\)”](#). Acceleration is also dependent on the frame buffer memory.

13.2 Software Operation

X Windows acceleration is supported for X.org X Server version 1.7.6 and some later versions supporting the EXA interface version 2.5.

The following list summarizes the types of operations that are accelerated for X Windows. All operations involve frame buffer memory which may be onscreen or offscreen:

- Solid fill of a rectangle
- Copy of a rectangle with same pixel format with possible source-target rectangle overlap
- Copy of a rectangle supporting most XRender compositing operations with these options:
 - Pixel format conversion
 - Repeating pattern source
 - Porter-Duff blending of source with target
 - Source alpha masking

The following list includes additional features supported as part of the X Windows acceleration:

- Allocation of X pixmaps directly in frame buffer memory
- EGL swap buffers where the EGL window surface is an X window
- X window can be composited into an X pixmap which can be used directly as any EGL surface

13.2.1 X Windows Acceleration Architecture

The following block diagram shows the components that are involved in the acceleration of X Windows:

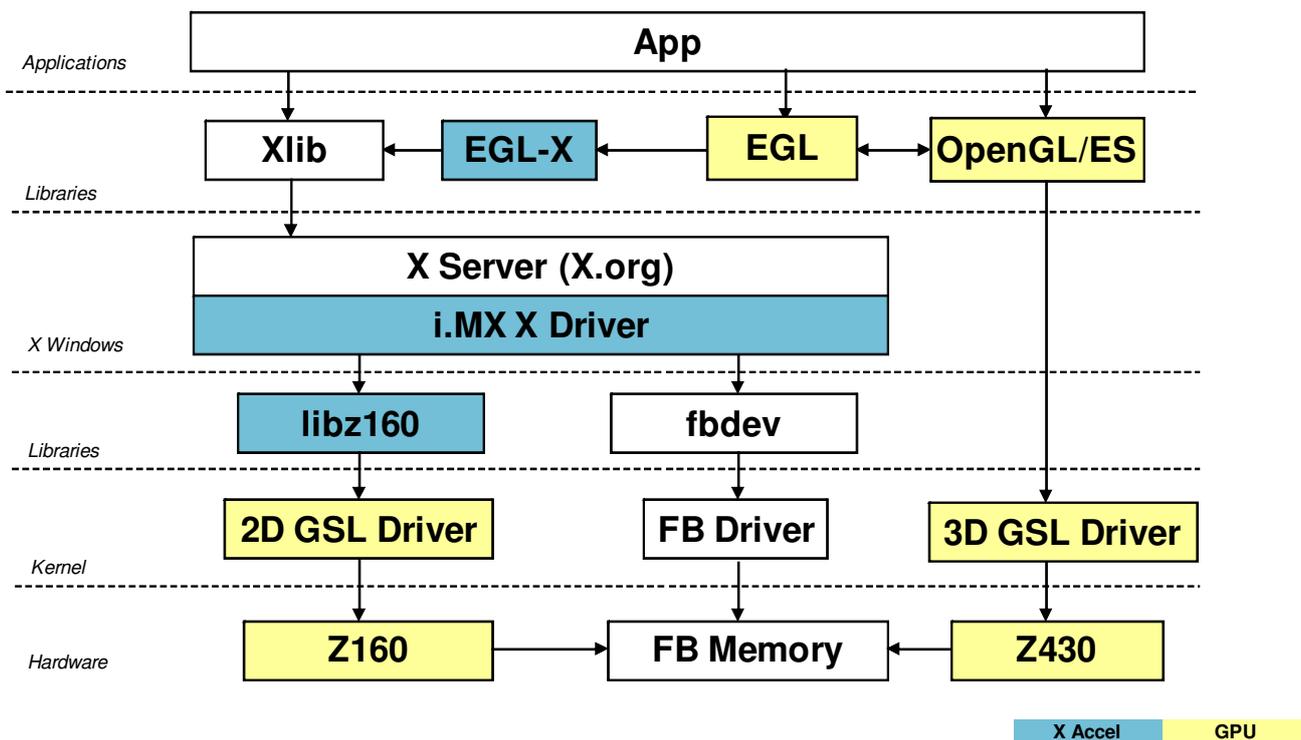


Figure 13-1. X Window Acceleration Block Diagram

The components shown in yellow are those provided as part of the 2D/3D GPU driver support which includes OpenGL/ES and EGL. The components shown in white are the standard components in the X Windows system without acceleration. The components shown in blue are those added to support X Windows acceleration and briefly described here.

The **i.MX X Driver** library module (`imx-drv.so`) is loaded by the X server and contains the high level implementation of the X Windows acceleration interface for i.MX platforms containing the Z160 2D GPU core. The entire linearly contiguous frame buffer memory in `/dev/fb0` is used for allocating pixmaps for X both onscreen and offscreen. The driver supports a custom X extension which allows X clients to query the GPU address of any X pixmap stored in frame buffer memory.

The **libz160** library module (`libz160.so`) contains the register level programming interface to the Z160 GPU module. This includes the storing of register programming commands into packets which can be streamed to the device. The functions in the libz160 library are called by the i.MX X Driver code.

The **EGL-X** library module (`libEGL.so`) contains the X Windows implementation of the low level EGL platform-specific support functions. This allows X window and X pixmap objects to be used as EGL window and pixmap surfaces. The EGL-X library uses Xlib function calls in its implementation along with the i.MX X Driver module's X extension for querying the GPU address of X pixmaps stored in frame buffer memory.

13.2.2 i.MX X Driver Details

The i.MX X Driver, referred to as `imx-drv`, implements the EXA interface of the X server in providing acceleration. The following list describes details particular to this implementation:

- The implementation builds upon the source from the `fbdev` frame buffer driver for X so that it can be the fallback when the acceleration is disabled.
- The implementation is based on X server EXA version 2.5.0.
- The EXA solid fill operation is accelerated, except for source/target drawables containing less than 150 pixels in which case fallback is to software rendering.
- The EXA copy operation is accelerated, except for source/target drawables containing less than 150 pixels in which case fallback is to software rendering.
- For EXA solid fill and copy operations, only solid plane masks and only `GXcopy` raster-op operations are accelerated.
- EXA composite allows for many options and combinations of source/mask/target for rendering. Most of the (commonly used) EXA composite operations are accelerated.

The following types of EXA composite operations are accelerated;

- Simple source composite with target
- Simple source-in-mask composite with target
- Constant source (with or without alpha mask) composite with target
- Repeating pattern source (with or without alpha mask) composite with target
- Operations for source/target drawables containing at least 150 pixels
- Only these blending functions: `SOURCE`, `OVER`, `IN`, `IN-REVERSE`, `OUT-REVERSE`, and `ADD` (some of these are needed to support component-alpha blending which is accelerate)

In general, the following types of (less commonly used) EXA composite operations are **not** accelerated:

- Transformed (that is, scaled, rotated) sources and masks
- Gradient sources
- Alpha masks with repeating patterns
- The implementation handles all pixmap allocation for X through the EXA callback interface. A first attempt is made to allocate the memory where it can be accessed by a physical GPU address. This attempt can fail if there is insufficient GPU accessible memory remaining, but it can also fail when the bits per pixel being requested for the pixmap is less than 8. If the attempt to allocate from the GPU accessible memory fails, then the memory is allocated from the system. If the pixmap memory is allocated from the system, then this pixmap cannot be involved in a GPU accelerated option. The number of pitch bytes used to access the pixmap memory may be different depending on whether it was allocated from GPU accessible memory or from the system.
- Once the memory for an X pixmap has been allocated, whether it is from GPU accessible memory or from the system, the pixmap is locked and can never migrate to the other type of memory. Pixmap migration from GPU accessible memory to system memory is not necessary since a system virtual address is always available for GPU accessible memory. Pixmap migration from system memory to GPU accessible memory is not currently implemented, but would only help in

situations where there was insufficient GPU accessible memory at initial allocation but more memory becomes available (through de-allocation) at a later time.

- The GPU accessible memory pitch (horizontal) alignment for the Z430 is 32 pixels while the buffer pitch alignment for the Z160 is 4 bytes. Because the memory for X pixmaps can be allocated from GPU accessible memory and these X pixmaps could be used in EGL for OpenGL/ES drawing operations (using the Z430), the pitch alignment requirement is set conservatively for the Z430. There is also a 32-pixel vertical alignment requirement (for the Z430) and a 4096-byte address offset alignment requirement (for the Z160) also for GPU accessible memory.
- All of the memory allocated for `/dev/fb0` is made available to an internal linear offscreen memory manager based on the one used in EXA. The portion of this memory beyond the screen memory is available for allocation of X pixmap where this memory area is GPU accessible. The amount of memory allocated to `/dev/fb0` needs to be several MB more than the amount needed for the screen. The actual amount needed depends on the number of X windows and pixmaps used, possible usage of X pixmaps as texture, and whether X windows are using the XComposite extension.
- An X extension is provided so that X clients can query the physical GPU address associated with an X pixmap, if that X pixmap was allocated in the GPU accessible memory.

13.2.3 libz160 Details

The `libz160` library module provides an API for user space programs to perform 2D accelerated graphics operations using the Z160. The following list describes details particular to this implementation:

- The API was originally developed to provide the separation of functionality needed by the EXA implementation in the i.MX X Driver.
- The packet streaming is provided by the 2D GPU driver support command stream interface (CSI) library (`libcsi.a`) which is statically linked into this `libz160` library module.
- The kernel support for the 2D GPU driver is provided by the `gsl_kmod` kernel device module

13.2.4 EGL-X Details

The EGL-X library implements the low level EGL interface when used in the X Windows system. The following list describes details particular to this implementation:

- The `eglDisplay` native display type is “Display*” in X Windows.
- The `eglWindowSurface` native window surface type is “Window” in X Windows.
- The `eglPixmapSurface` native pixmap surface type is “Pixmap” in X Windows.
- When an `eglWindowSurface` is created, the back buffers used for double-buffering can have different representations from the window surface (based on the selected `eglConfig`). An attempt is made to create each back buffer using the representation which provides the most efficient blit of the back buffer contents to the window surface when `eglSwapBuffers` is called. Each back buffer is allocated separately using the following approach:
 - Create an X pixmap of the necessary size. Use the X extension for the i.MX X Driver module to query the physical frame buffer address for this X pixmap if it was allocated in the offscreen frame buffer memory.

- If the X pixmap is in the offscreen frame buffer memory then consider the following.
 - If the pixel format of the back buffer matches that of the window, then the `XCopyArea` function is used to blit the back buffer to the window.
 - If the pixel format of the back buffer does **not** match that of the window, then the `XRenderComposite` function is used to convert and blit the back buffer to the window.
- If the X pixmap is **not** in the offscreen frame buffer memory, then a back buffer is allocated from the GSL memory pool and mapped to an `XImage`.
 - If the pixel format of the back buffer matches that of the window, then the `XPutImage` function is used to blit the back buffer to the window.
 - If the pixel format of the back buffer does **not** match that of the window, then the `XPutImage` function is used to first blit the back buffer to the X pixmap (to get image transferred to X server without format conversion) and then the `XRenderComposite` function is used to convert and blit the X pixmap to the window.

13.2.5 The `xorg.conf` File for i.MX X Driver

The `/etc/X11/xorg.conf` file must be properly configured to use the i.MX X Driver. This configuration appears in a “Device” section of the file which contains some required entries and some entries that are optional. The following example shows a preferred configuration for using the i.MX X Driver:

```
Section "Device"
    Identifier      "i.MX Accelerated Framebuffer Device"
    Driver          "imx"
    Option          "fbdev" "/dev/fb0"
    Option          "NoAccel" "false"
    Option          "AccelMethod" "EXA"
    Option          "EXANoComposite" "false"
    Option          "EXANoUploadToScreen" "false"
    Option          "EXANoDownloadFromToScreen" "false"
EndSection
```

Each entry recognized by the i.MX X Driver is described as follows.

```
Identifier "i.MX Accelerated Framebuffer Device"
```

This mandatory entry specifies the unique name to associate with this graphics device. This is what ties a specific graphics card to a screen. This string must match the `Device` identifier string in a `Screen` section of the `xorg.conf` file. For example:

```
Section "Screen"
    Identifier "Default Screen"
    Device "i.MX Accelerated Framebuffer Device"
    <other entries>
EndSection
```

Driver "imx"

This mandatory entry specifies the name of this loadable i.MX X driver.

Option "fbdev" "string"

This mandatory entry specifies the path for the frame buffer device to use.

Option "NoAccel" boolean

Disables GPU acceleration of all rendering operations. Default: off.

Option "AccelMethod" boolean

Method of X server interface to use for acceleration. Only supported value is "EXA" so any other value specified disables acceleration. Default: "EXA".

Option "EXANoComposite" boolean

Disables acceleration of the EXA Composite operation which is the basic interface in EXA to support the X Render extension. This is not related to the X Composite extension. Default: off.

Option "EXANoUploadToScreen" boolean

Disables acceleration of uploading pixmap data to the frame buffer. Default: off.

Option "EXANoDownloadFromScreen" boolean

Disables acceleration of downloading of pixmap data from the frame buffer. Default: off.

13.2.6 Setup X Windows Acceleration

- Verify that the following packages are available and installed:

`libz160-bin_<bsp-version>_armel.deb`

This package contains the `libz160.so` library module and installs it in the `/usr/lib` folder.

`amd-gpu-x11-bin-mx51_<bsp-version>_armel.deb`

This package contains the `libEGL.so` library module and installs it in the `/usr/lib` folder.

`xserver-xorg-video-imx_<bsp-version>_armel.deb`

This package contains the `imx-dev.so` driver module for X acceleration and installs it in the folder with all the other X.org driver modules.

- Verify that the device file `/dev/gsl_kmod` is present.
- Verify that the file `/etc/X11/xorg.conf` contains the correct entries as described in the previous section.

There are a few ways to verify that X Windows acceleration is indeed operating given that the above steps have been performed.

1. Verify that the device file `/dev/gsl_kmod` is present.
2. Examine the file `/var/log/Xorg.0.log` and confirm that the following lines are present:

```
(II) EXA(0): Using custom EXA
```

```
(II) IMX(0): IMX EXA acceleration setup successful
```

3. In the same `/var/log/Xorg.0.log` file, search for a line similar to the following:

```
(II) IMX(0): Offscreen pixmap area of 15062K bytes
```

This indicates the number of bytes available for X pixmaps that can be allocated in the off-screen frame buffer memory. The size indicated here is about 15MB of available memory, but this is just an example.

Chapter 14

Video Processing Unit (VPU) Driver

14.1 Hardware Operation

The VPU hardware performs all of the codec computation and most of the bitstream parsing/packeting. Therefore, the software takes advantage of less control and effort to implement a complex and efficient multimedia codec system.

The VPU hardware data flow is shown in the MPEG4 decoder example in [Figure 14-1](#).

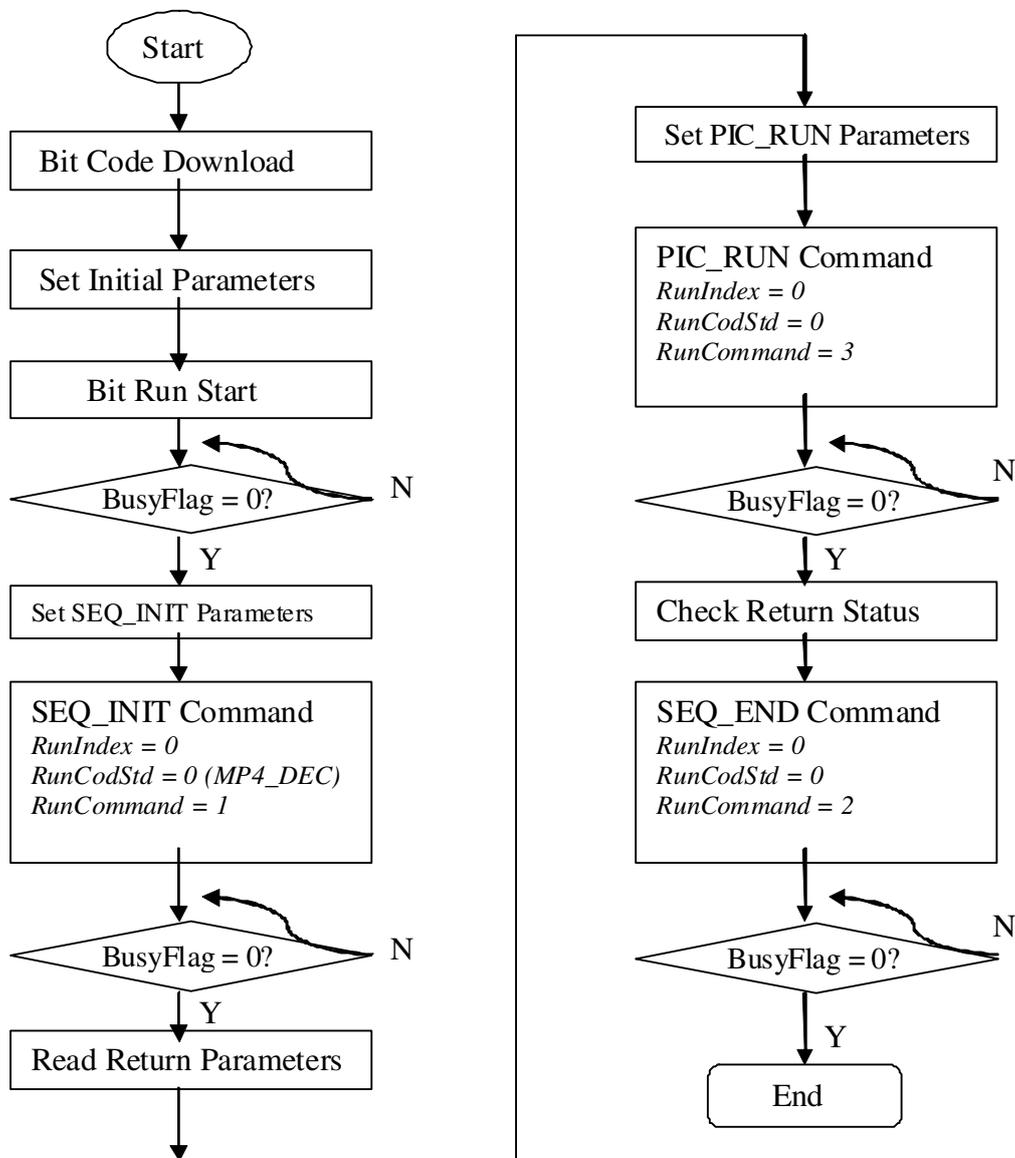


Figure 14-1. VPU Hardware Data Flow

14.2 Software Operation

The VPU software can be divided into two parts: the kernel driver and the user-space library as well as the application in user space. The kernel driver takes responsibility for system control and reserving resources (memory/IRQ). It provides an IOCTL interface for the application layer in user-space as a path to access system resources. The application in user-space calls related IOCTLs and codec library functions to implement a complex codec system.

The VPU kernel driver include the following functions:

- Module initialization—Initializes the module with the device specific structure
- Device initialization—Initializes the VPU clock and hardware, and request the IRQ
- Interrupt servicing routine—Supports events that one frame has been finished
- File operation routines— Provides the following interfaces to user space
 - File open
 - File release
 - File synchronization
 - File IOCTL to provide interface for memory allocating and releasing
 - Memory map for register and memory accessing in user space
- Device Shutdown—Shutowns the VPU clock and hardware, and release the IRQ

The VPU user space driver has the following functions:

- Codec lib
 - Downloads executable bitcode for hardware
 - Initializes codec system
 - Sets codec system configuration
 - Controls codec system by command
 - Reports codec status and result
- System I/O operation
 - Requests and frees memory
 - Maps and unmaps memory/register to user space
 - Device management

14.3 Source Code Structure

Table 14-1 lists the kernel space source files available in the following directories:

```
<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc/include/mach/
<ltib_dir>/rpm/BUILD/linux/drivers/mxc/vpu/
```

Table 14-1. VPU Driver Files

File	Description
mxv_vpu.h	Header file defining IOCTLs and memory structures
mxv_vpu.c	Device management and file operation interface implementation

Table 14-2 lists the user-space library source files available in the <ltib_dir>/rpm/BUILD/imx-lib-11.05.01/vpu directory:

Table 14-2. VPU Library Files

File	Description
vpu_io.c	Interfaces with the kernel driver for opening the VPU device and allocating memory
vpu_io.h	Header file for IOCTLs
vpu_lib.c	Core codec implementation in user space
vpu_lib.h	Header file of the codec
vpu_reg.h	Register definition of VPU
vpu_util.c	File implementing common utilities used by the codec
vpu_util.h	Header file

Table 14-3 lists the firmware files available in the following directories:

<ltib_dir>/rpm/BUILD/firmware-imx-11.05.01/lib/firmware/vpu/ directory

Table 14-3. VPU firmware Files

File	Description
vpu_fw_xxx.bin	VPU firmware

NOTE

To get the to files in Table 14-2, run the command: `./ltib -m prep -p imx-lib` in the console

14.4 Menu Configuration Options

To get to the VPU driver, use the command `./ltib -c` when located in the <ltib_dir>. On the screen displayed, select **Configure the kernel** and exit. When the next screen appears select the following options to enable the VPU driver:

- CONFIG_MXC_VPU—Provided for the VPU driver. In menuconfig, this option is available under
Device Drivers > MXC support drivers > MXC VPU (Video Processing Unit) support

14.5 Programming Interface

There is only a user-space programming interface for the VPU module. A user in the application layer cannot access the kernel driver interface directly. The VPU library access the kernel driver interface for users.

The codec library APIs are listed below:

```
RetCode vpu_EncOpen(EncHandle* pHandle, EncOpenParam* pop);
RetCode vpu_EncClose(EncHandle encHandle);
RetCode vpu_EncGetInitialInfo(EncHandle encHandle, EncInitialInfo* initialInfo);
RetCode vpu_EncRegisterFrameBuffer(EncHandle encHandle, FrameBuffer* pBuffer, int num,
```

```

        int stride);
RetCode vpu_EncGetBitstreamBuffer(EncHandle handle, PhysicalAddress* prdPtr,
        PhysicalAddress* pwrPtr, Uint32* size);
RetCode vpu_EncUpdateBitstreamBuffer(EncHandle handle, Uint32 size);
RetCode vpu_EncStartOneFrame(EncHandle encHandle, EncParam* pParam);
RetCode vpu_EncGetOutputInfo(EncHandle encHandle, EncOutputInfo* info);
RetCode vpu_EncGiveCommand (EncHandle pHandle, CodecCommand cmd, void* pParam);
RetCode vpu_DecOpen(DecHandle* pHandle, DecOpenParam* pop);
RetCode vpu_DecClose(DecHandle decHandle);
RetCode vpu_DecGetBitstreamBuffer(DecHandle pHandle, PhysicalAddress* pRdptr,
        PhysicalAddress* pWrptr, Uint32* size);
RetCode vpu_DecUpdateBitstreamBuffer(DecHandle decHandle, Uint32 size);
RetCode vpu_DecSetEscSeqInit(DecHandle pHandle, int escape);
RetCode vpu_DecGetInitialInfo(DecHandle decHandle, DecInitialInfo* info);
RetCode vpu_DecRegisterFrameBuffer(DecHandle decHandle, FrameBuffer* pBuffer, int num,
        int stride, DecBufInfo* pBufInfo);
RetCode vpu_DecStartOneFrame(DecHandle handle, DecParam* param);
RetCode vpu_DecGetOutputInfo(DecHandle decHandle, DecOutputInfo* info);
RetCode vpu_DecBitBufferFlush(DecHandle handle);
RetCode vpu_DecClrDispFlag(DecHandle handle, int index);
RetCode vpu_DecGiveCommand(DecHandle pHandle, CodecCommand cmd, void* pParam);
int vpu_WaitForInt(int timeout_in_ms);
RetCode vpu_SWReset(DecHandle handle, int index);

```

System I/O operations are listed below:

```

int IOSystemInit(void);
int IOSystemShutdown(void);
int IOGetPhyMem(vpu_mem_desc* buff);
int IOFreePhyMem(vpu_mem_desc* buff);
int IOGetVirtMem (vpu_mem_desc* buff);
int IOFreeVirtMem(vpu_mem_desc* buff);

```

14.6 Defining an Application

The most important definition for an application is the codec memory descriptor. It is used for `request`, `free`, `mmap` and `munmap` memory as follows:

```

typedef struct vpu_mem_desc
{
    int size;                /*request memory size*/
    unsigned long phy_addr;  /*physical memory get from system*/
    unsigned long cpu_addr;  /*address for system usage while freeing, user doesn't need
                            to handle or use it*/
    unsigned long virt_uaddr; /*virtual user space address*/
} vpu_mem_desc;

```


Chapter 15

Low-level Power Management (PM) Driver

This section describes the low-level Power Management (PM) driver which controls the low-power modes.

15.1 Hardware Operation

The i.MX5 supports four low power modes: RUN, WAIT, STOP, and LPSR (low power screen).

[Table 15-1](#) lists the detailed clock information for the different low power modes.

Table 15-1. Low Power Modes

Mode	Core	Modules	PLL	CKIH/FPM	CKIL
RUN	Active	Active, Idle or Disable	On	On	On
WAIT	Disable	Active, Idle or Disable	On	On	On
STOP	Disable	Disable	Off	Off	On
LPSR	Disable	Disable	Off	On	On

For the detailed information about lower power modes, see the MX53 IC spec.

15.2 Software Operation

The i.MX5 PM driver maps the low-power modes to the kernel power management states as listed below:

- Standby—maps to WAIT mode which offers minimal power saving, while providing a very low-latency transition back to a working system
- Mem (suspend to RAM)—maps to STOP mode which offers significant power saving as all blocks in the system are put into a low-power state, except for memory, which is placed in self-refresh mode to retain its contents
- System idle—maps to WAIT mode

The i.MX5 PM driver performs the following steps to enter and exit low power mode:

1. Enable the `gpc_dvfs_clk`
2. Allow the Cortex-A8 platform to issue a deep sleep mode request
3. If STOP mode:
 - a) Program CCM CLPCR register to set low power control register.
 - b) Request switching off ARM/NENO power when `pdn_req` is asserted.
 - c) Request switching off embedded memory peripheral power when `pdn_req` is asserted.
 - d) Program TZIC wakeup register to set wakeup interrupts
4. Call `cpu_do_idle` to execute WFI pending instructions for wait mode

Low-level Power Management (PM) Driver

5. If STOP mode, execute `cpu_do_suspend_workaround` in RAM. Change the drive strength of DDR SDCLK as “low” to minum the power leakage in SDCLK. Execute WFI pending instructions for stop mode
6. Generate a wakeup interrupt and exit low power mode. If STOP mode, restore DDR drive strength.
7. Disable `gpc_dvfs_clk`

15.3 Source Code Structure

Table 15-2 shows the PM driver source files. These files are available in

`<ltib_dir>/rpm/BUILD/linux/arch/arm/mach-mx5/`

Table 15-2. PM Driver Files

File	Description
<code>pm.c</code>	Supports suspend operation
<code>system.c</code>	Supports low-power modes
<code>wfi.S</code>	Assemble file for <code>cpu_cortexa8_do_idle</code>
<code>suspend.S</code>	Assemble file for <code>cpu_do_suspend_workaround</code>

15.4 Menu Configuration Options

The following Linux kernel configuration options are provided for this module. To get to these options, use the `./ltib -c` command when located in the `<ltib dir>`. On the screen displayed, select **Configure the Kernel** and exit. When the next screen appears, select the following options to enable this module:

- `CONFIG_PM`—Build support for power management. In menuconfig, this option is available under
Power management options > Power Management support
By default, this option is Y.
- `CONFIG_SUSPEND`—Build support for suspend. In menuconfig, this option is available under
Power management options > Suspend to RAM and standby

15.5 Programming Interface

The `mxc_cpu_ip_set` API in the `system.c` function is provided for low-power modes. This implements all the steps required to put the system into WAIT and STOP modes.

Chapter 16

Dynamic Voltage Frequency Scaling (DVFS) Driver

The Dynamic Voltage Frequency Scaling (DVFS) device driver allows simple dynamic voltage frequency scaling. The frequency of the core (CPU) clock domain and the voltage of the core power domain can be changed on the fly with all modules continuing their normal operations. The voltage of the core power domain can be changed through the PMIC. The frequency of the core clock domain can be changed by switching temporarily to an alternate PLL clock, and then returning to the updated PLL, already locked at a specific frequency, or by merely changing the post dividers division factors.

16.1 Hardware Operation

The DVFS core module is a power management module. The purpose of the DVFS module is to detect the appropriate operation frequency for the IC. DVFS core is operated under control of the GPC (General Power Controller) block. The hardware DVFS core interrupt is served by GPC IRQ. The DVFS core domain performance update procedure includes both voltage and frequency changes in appropriate order by the GPC controller (hardware). For more information on the HW DVFS Core block refer to the DVFS chapter in the *Multimedia Applications Processor* documentation.

16.2 Software Operation

The DVFS device driver allows the frequency of the core clock domain and the voltage of the core power domain to be changed on the fly. The frequency of the core clock domain and the voltage of the core power domain are changed by switching between defined freq-voltage operating points. The frequencies are manipulated using the clock framework API, while the voltage is set using the regulators API.

To Enable the DVFS core use this command:

```
echo 1 > /sys/devices/platform/mxc_dvfs_core.0/enable
```

To Disable The DVFS core use this command:

```
echo 0 > /sys/devices/platform/mxc_dvfs_core.0/enable
```

16.3 Source Code Structure

Table 16-1 lists the source files and headers available in the following directory:

```
<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc/
```

Table 16-1. DVFS Driver Files

File	Description
dvfs_core.c	Linux DVFS functions

In addition, the partial of DVFS core parameters are located into arch/arm/mach-mx5/bus_freq.c.

For DVFS CPU working point settings, see arch/arm/mach-mx5/mx53_wp.c.

16.4 Menu Configuration Options

There are no menu configuration options for this driver. The DVFS core is included by default.

16.4.1 Board Configuration Options

There are no board configuration options for the Linux DVFS core device driver.

Chapter 17

CPU Frequency Scaling (CPUFREQ) Driver

The CPU frequency scaling device driver allows the clock speed of the CPU to be changed on the fly. Once the CPU frequency is changed, the voltage VDDGP is changed to the voltage value defined in `mx53_wp.c`. This method can reduce power consumption (thus saving battery power), because the CPU uses less power as the clock speed is reduced.

17.1 Software Operation

The CPUFREQ device driver is designed to change the CPU frequency and voltage on the fly. If the frequency is not defined in `mx53_wp.c`, the CPUFREQ driver changes the CPU frequency to the nearest frequency in the array. The frequencies are manipulated using the clock framework API, while the voltage is set using the regulators API. The CPU frequencies in the array are based on the boot CPU frequency which can be changed by using the clock command in U-Boot. Refer to the API document for more information on the functions implemented in the driver (in the doxygen folder of the documentation package).

To view what values the CPU frequency can be changed to in KHz (The values in the first column are the frequency values) use this command:

```
cat /sys/devices/system/cpu/cpu0/cpufreq/stats/time_in_state
```

To change the CPU frequency to a value that is given by using the command above (for example, to 800 MHz) use this command:

```
echo 800000 > /sys/devices/system/cpu/cpu0/cpufreq/scaling_setspeed
```

The frequency 800000 is in KHz, which is 800 MHz.

The maximum frequency can be checked using this command:

```
cat /sys/devices/system/cpu/cpu0/cpufreq/scaling_max_freq
```

Use the following command to view the current CPU frequency in KHz:

```
cat /sys/devices/system/cpu/cpu0/cpufreq/cpuinfo_cur_freq
```

Use the following command to view available governors:

```
cat /sys/devices/system/cpu/cpu0/cpufreq/scaling_available_governors
```

Use the following command to set governors:

```
echo conservative > /sys/devices/system/cpu/cpu0/cpufreq/scaling_governor
```

17.2 Source Code Structure

[Table 17-1](#) shows the source files and headers available in the following directory:

CPU Frequency Scaling (CPUFREQ) Driver

<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc/

Table 17-1. CPUFREQ Driver Files

File	Description
cpufreq.c	CPUFREQ functions

For CPU frequency working point settings, see arch/arm/mach-mx5/mx53_wp.c.

17.3 Menu Configuration Options

The following Linux kernel configuration is provided for this module:

- CONFIG_CPU__FREQ—In menuconfig, this option is located under CPU Power Management > CPU Frequency scaling

The following options can be selected:

- CPU Frequency scaling
- CPU frequency translation statistics
- Default CPU frequency governor (userspace)
- Performance governor
- Powersave governor
- Userspace governor for userspace frequency scaling
- Conservative CPU frequency governor
- CPU frequency driver for i.MX CPUs

17.3.1 Board Configuration Options

There are no board configuration options for the CPUFREQ device driver.

Chapter 18

Software Based Peripheral Domain Frequency Scaling

The frequency of the clocks in the peripheral domain can be changed using the software based Bus Frequency Scaling driver. Enabling this driver can significantly lower the power numbers in the LP domain. Depending on the platform, the voltage of the peripheral domain can also be dropped using the on board PMIC.

18.1 Software based Bus Frequency Scaling

The SW will automatically lower the frequency of the various clocks in the peripheral domain based on which drivers are active (it is assumed that the drivers will use the clock API to enable/disable their clocks). Two setpoints are defined for the peripheral bus clock:

AHB_HIGH_SET_POINT - The module requires the AHB clock to be at the highest frequency (133MHz).

AHB_MED_SET_POINT - The module requires the AHB clock be above 66.5MHz.

The Bus Frequency Scaling driver will take into account the above two associations for the various clocks in the system before changing the peripheral clock.

To enable the SW based Bus Frequency Scaling (*not needed to enter LPAPM mode*) use this command:

```
echo 1 > /sys/devices/platform/busfreq.0/enable
```

To disable the SW based Bus Frequency Scaling use this command:

```
echo 0 > /sys/devices/platform/busfreq.0/enable
```

Based on which clocks are active, the system can be in any of the three modes specified below:

18.1.1 Low Power Audio Playback Mode (LPAPM)

When all the clocks that need either of the above two mentioned setpoints are disabled, the system can enter an ultra low power mode where the AHB clock and other main clocks in the LP domain are dropped down to 24MHz (For MX53, AHB clock, AXI-B clocks are dropped to $400/8=50$ MHZ). On certain platforms and depending on the type of memory used, the DDR frequency is also dropped down to 24MHz. This mode is most commonly entered when the system is idle and the display is turned off. The implementation automatically detects when this mode can be entered and calls into the Bus Frequency driver to change the clocks (and voltages if it can be done) appropriately. On certain platforms, the entire SoC is clocked off the 24MHz oscillator and all PLLs are turned off to save more power.

If any driver that needs the higher AHB clock enables its clock, LPAPM mode will be exited. **Entry and exit from the LPAPM mode does not require the Bus Frequency Scaling driver to be enabled.**

18.1.2 Medium Frequency Setpoint

In this mode the AHB and some of the LP domain clocks are divided down such that the AHB clock is above 66.5MHz. In this mode all drivers that require AHB_HIGH_SET_POINT are disabled. Depending on the platform, the voltage can also be dropped.

18.1.3 High Frequency Setpoint

In this mode none of the frequencies on the peripheral domain are scaled since drivers that need the AHB_HIGH_SETPOINT are active.

18.2 Source Code Structure

Table 18-1 lists the source files and headers

Table 18-1. Bus Frequency Scaling Driver Files

File	directory	Description
bus_freq.c	arch/arm/mach-mx5	SW bus frequency driver functions

18.3 Menu Configuration Options

There is no option for the SW based Bus Frequency Scaling driver, it included by default.

18.3.1 Board Configuration Options

There are no board configuration options for the Linux Bus Frequency Scaling device driver.

Chapter 19

MAX17085 charger Driver

The MAX17085B is an all-in-one notebook power solution integrating a multichemistry battery charger.

19.1 Overview

The MAX17085 charger driver register two power supply into system -- ‘ac’ and ‘battery.’

The ‘ac’ provides property ONLINE under:

```
/sys/class/power_supply/ac/
```

The ‘battery’ provides properties STATUS, PRESENT, HEALTH, TECHNOLOGY, VOLTAGE_NOW, CAPACITY, TEMP and MANUFACTURER under:

```
/sys/class/power_supply/battery/
```

19.1.1 Hardware Operation

There are some gpios which related with this battery charger driver:

1. ac_in: read this gpio’s value to check online status.
2. pwr_good: read this gpio’s value to check the battery health
3. charge_now & charge_done: these two gpios control two led on SMD board, when battery’s capacity less than 20%, charge_now should be set to 1 and charge_done should be set to 0, when 20% <= battery capacity <80%, both charge_now and charge_done should be set to 1, when battery capacity >= 80%, charge_now should be set to 0, and charge_done should be set to 1.

Now on SMD board, battery voltage is gotten from da9052 ADC, the data is not very accurate by this method. The better way is to get battery related information from I2C bus, off course, the battery should support this feature.

19.1.2 Software Operation

One delayed workqueue is running after driver probe, which will update ‘ac’ and ‘battery’ properties information every 1 second.

Now for properties PRESENT, TECHNOLOGY, TEMP and MANUFACTURER, the driver only provide a fake value.

Every time ‘ac’ online status (online or offline) change, or ‘battery’ status (charging, not-charging, discharging or full) change, or ‘battery’ capacity change, an uevent will be sent out to user space.

19.2 Source Code Structure Configuration

Table 19-1 describes the source files associated with the MAX17085 charger driver, which are available in the directory `<ltib_dir>/rpm/BUILD/linux/drivers/power/`.

Table 19-1. MAX17085 charger Driver Source File

File	Description
max17085_battery.c	Source file for max17085 charger driver

19.3 Driver Configuration

This module can be selected using the ltib menu options.

To get to the Maxim MAX17085 charger driver use the command `./ltib -c` when located in the `<ltib_dir>`. On the screen displayed, select **Configure the kernel** and exit. When the next screen appears select the following options to enable the Maxim MAX17085 charger driver.

- Device Drivers > Power supply class support
Chooses Maxim MAX17085 charger.

Chapter 20

ISL29023 Ambient Light Sensor Driver

The ISL29023 Ambient Light Sensor driver is a device driver with a flexible programming interface exposed to the software to help the users to configure the mode of the sensor so that the intensity of the ambient light can be got. It can be used to change the backlight of the LCD according to the ambient light, which may reduce the power consumption sometimes.

20.1 ISL29023 Features

- Simple Output Code Directly Proportional to lux
- Variable Conversion Resolution up to 16-bits
- Adjustable Sensitivity up to 65 Counts per lux
- Selectable Range (via I2C): Range1 to 1000Lux, Rane2 to 4000Lux, Range3 to 16000Lux and Range4 to 64000Lux.
- Integrated 50/60Hz Noise Rejection
- Temperature Compensated
- Programmable Threshold Interrupt
- Works Under Various Light Sources, including Sunlight

20.2 Driver Requirements

The ISL29023 device driver is based on a I²C driver and makes use of input device system, therefore, the user must enable this support in the Linux kernel. The driver should provide device attribution interfaces to read or write device mode and lux value. Moreover, the driver should provide poll function so that the user may sleep when ambient light intensity doesn't exceed interrupt thredhold set by the user, which reduces the power consumption comparing to busy checking implementation.

20.3 Driver Architecture

Figure 20-1 shows the software architecture. The ISL29023 device driver provides I2C register accessing mode. At driver initial phase, a I²C client is registered to the I²C system and is used during the process of ISL29023 operations. The ISL29023 device registers itself to the input system that provides user access facilities.

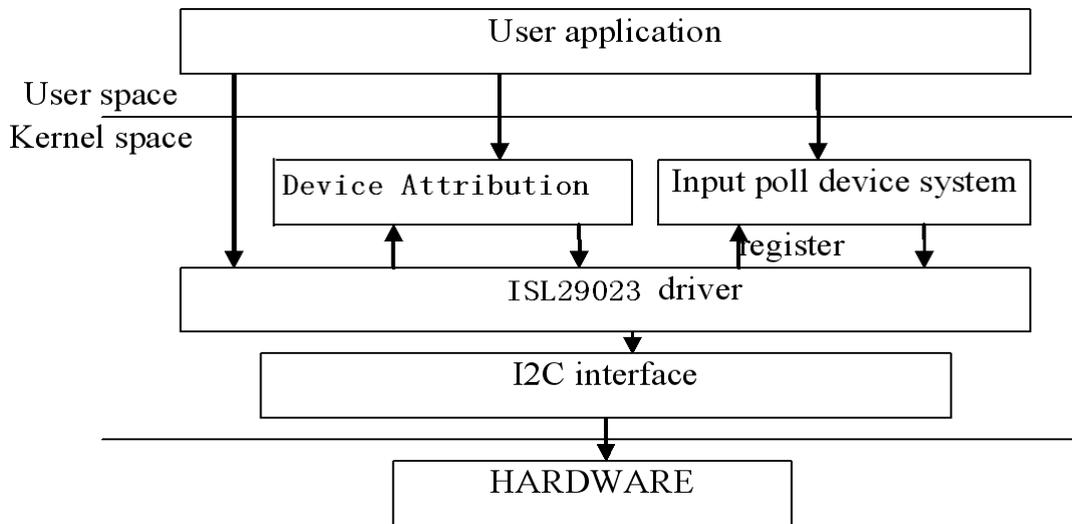


Figure 20-1. Driver Architecture

20.4 Driver Source Code Structure

The driver source code structure contains only one file located in the directory:

<ltib_dir>/rpm/BUILD/linux/drivers/input/misc/

Table 20-1. Driver Source Code Structure File

File	Description
isl29023.c	Implementation of the isl29023 device driver.

20.5 Driver Configuration

To get to the ISL29023 driver use the command `./ltib -c` when located in the <ltib dir>. On the screen displayed, select **Configure the kernel** and exit. When the next screen appears select the following options to enable the ISL29023 driver:

- Device Drivers → Input device support → Miscellaneous devices → Intersil ISL29023 ambient light sensor

Chapter 21

Advanced Linux Sound Architecture (ALSA) System on a Chip (ASoC) Sound Driver

This section describes the ASoC driver architecture and implementation. ASoC aims to improve code reuse by dividing the ALSA kernel driver into machine layer, platform (CPU) layer, and audio codec components. Any modifications to one component do not impact another components. The machine layer registers the platform layer and the audio codec, and sets up the connection between them, using the DAI link interface. More detailed information about ASoC can be found in the Linux kernel documentation in the linux source tree at `linux/Documentation/sound/alsa/soc` and at <http://www.alsa-project.org/main/index.php/ASoC>.

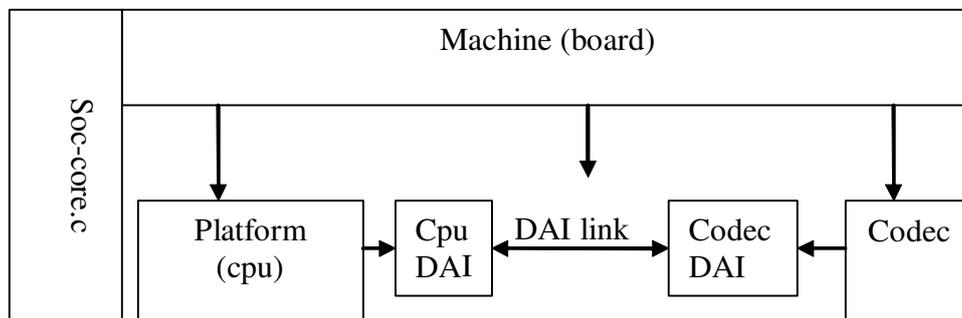


Figure 21-1. ALSA SoC Software Architecture

The ALSA SoC driver has the following components as shown in [Figure 21-1](#):

- Machine driver—handles any machine specific controls and audio events, such as turning on an external amp at the beginning of playback.
- Platform driver—contains the audio DMA engine and audio interface drivers (for example, I²S, AC97, PCM) for that platform.
- Codec driver—platform independent and contains audio controls, audio interface capabilities, the codec DAPM definition, and codec I/O functions.

21.1 SoC Sound Card

Currently, the stereo codec (`sgtl5000`), 5.1 codec (`wm8580`), 4-channel ADC codec (`ak5702`), 7.1 codec (`cs42888`), built-in ADC/DAC codec, and Bluetooth codec drivers are implemented using SoC architecture. The five sound card drivers are built in independently. The stereo sound card supports stereo playback and mono capture. The 5.1 sound card supports up to six channels of audio playback. The 4-channel sound card supports up to four channels of audio record. The Bluetooth sound card supports Bluetooth PCM playback and record with Bluetooth devices. The built-in ADC/DAC codec supports stereo playback and record.

NOTE**21.1.1 Stereo Codec Features**

The stereo codec supports the following features:

- Sample rates for playback and capture are 32 KHz, 44.1 KHz, 48 KHz, and 96 KHz
- Channels:
 - Playback: supports two channels. (stereo)
 - Capture: supports two channels. (Only one channel has valid voice data due to hardware connection)
- Audio formats:
 - Playback:
 - SNDRV_PCM_FMTBIT_S16_LE
 - SNDRV_PCM_FMTBIT_S20_3LE
 - SNDRV_PCM_FMTBIT_S24_LE
 - Capture:
 - SNDRV_PCM_FMTBIT_S16_LE
 - SNDRV_PCM_FMTBIT_S20_3LE
 - SNDRV_PCM_FMTBIT_S24_LE

21.1.2 Sound Card Information

The registered sound card information can be listed as follows using the commands `aplay -l` and `arecord -l`.

```
root@freescale /$ aplay -l
**** List of PLAYBACK Hardware Devices ****
card 0: imx3stack [imx-3stack], device 0: SGTL5000 SGTL5000-PCM-0 []
  Subdevices: 1/1
  Subdevice #0: subdevice #0
root@freescale /$ arecord -l
**** List of CAPTURE Hardware Devices ****
card 0: imx3stack [imx-3stack], device 0: SGTL5000 SGTL5000-PCM-0 []
  Subdevices: 1/1
  Subdevice #0: subdevice #0
```

21.2 ASoC Driver Source Architecture

As shown in [Figure 21-1](#), `imx-pcm.c` is shared by the stereo ALSA SoC driver, the 5.1 ALSA SoC driver and the Bluetooth codec driver. This file is responsible for preallocating DMA buffers and managing DMA channels.

The stereo codec is connected to the CPU through the SSI interface. `imx-ssi.c` registers the CPU DAI driver for the stereo ALSA SoC and configures the on-chip SSI interface. `sgtl5000.c` registers the stereo codec and hifi DAI drivers. The direct hardware operations on the stereo codec are in `sgtl5000.c`.

`imx-3stack-sgt15000.c` is the machine layer code which creates the driver device and registers the stereo sound card.

Figure 21-2 shows the ALSA SoC source file relationship.

Figure 21-2. ALSA Soc Source File Relationship

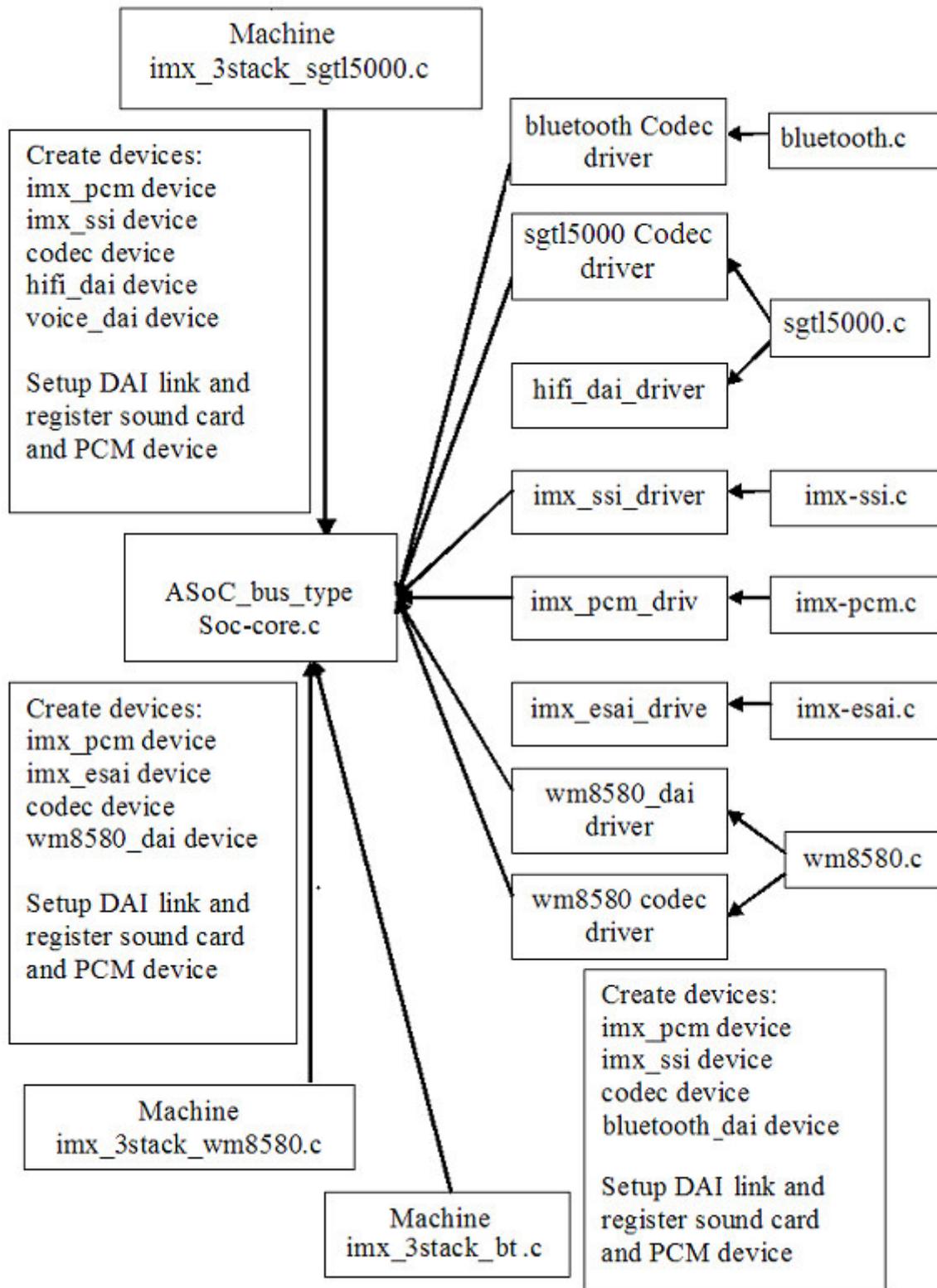


Table 21-1 shows the stereo codec SoC driver source files. These files are under the `<ltib_dir>/rpm/BUILD/linux/sound/soc` directory.

Table 21-1. Stereo Codec SoC Driver Files

File	Description
<code>imx/imx-3stack-sgtl5000.c</code>	Machine layer for stereo codec ALSA SoC
<code>imx/imx-pcm.c</code>	Platform layer for stereo codec ALSA SoC
<code>imx/imx-pcm.h</code>	Header file for PCM driver and AUDMUX register definitions
<code>imx/imx-ssi.c</code>	Platform DAI link for stereo codec ALSA SoC
<code>imx/imx-ssi.h</code>	Header file for platform DAI link and SSI register definitions
<code>imx/imx-ac97.c</code>	AC97 driver for i.MX chips
<code>codecs/sgtl5000.c</code>	Codec layer for stereo codec ALSA SoC
<code>codecs/sgtl5000.h</code>	Header file for stereo codec driver

21.3 Menu Configuration Options

The following Linux kernel configuration options are provided for this module. To get to these options, use the `./ltib -c` command when located in the `<ltib_dir>`. Select **Configure the Kernel** on the screen displayed and exit. When the next screen appears, select the following options to enable this module:

- SoC Audio support for i.MX SGTL5000. In menuconfig, this option is available under Device drivers > Sound card support > Advanced Linux Sound Architecture > ALSA for SoC audio support > SoC Audio for the Freescale i.MX CPU
- `CONFIG_SND_MXC_SOC_IRAM`: This config is used to allow audio DMA playback buffers in IRAM. In menuconfig, this option is available under Device drivers > Sound card support > Advanced Linux Sound Architecture > ALSA for SoC audio support > Locate Audio DMA playback buffers in IRAM
- `CONFIG_MXC_SSI_DUAL_FIFO`: This config is used to enable 2 SSI FIFO for audio transfer. In menuconfig, this option is available under Device drivers > Sound card support > Advanced Linux Sound Architecture > ALSA for SoC audio support > MXC SSI enable dual fifo

21.4 Hardware Operation

The following sections describe the hardware operation of the ASoC driver.

21.4.1 Stereo Audio Codec

The stereo audio codec is controlled by the I²C interface. The audio data is transferred from the user data buffer to/from the SSI FIFO through the DMA channel. The DMA channel is selected according to the

audio sample bits. AUDMUX is used to set up the path between the SSI port and the output port which connects with the codec. The codec works in master mode and provides the BCLK and LRCLK. The BCLK and LRCLK can be configured according to the audio sample rate.

The SGTL5000 ASoC codec driver exports the audio record/playback/mixer APIs according to the ASoC architecture. The ALSA related audio function and the FM loopback function cannot be performed simultaneously.

The codec driver is generic and hardware independent code that configures the codec to provide audio capture and playback. It does not contain code that is specific to the target platform or machine. The codec driver handles:

- Codec DAI and PCM configuration
- Codec control I/O—using I²C
- Mixers and audio controls
- Codec audio operations
- DAC Digital mute control

The SGTL5000 codec is registered as an I²C client when the module initializes. The APIs are exported to the upper layer by the structure `snd_soc_dai_ops`. The `io_probe` routine initializes the codec hardware to the desired state.

Headphone insertion/removal can be detected through a MCU interrupt signal. The driver reports the event to user space through sysfs.

21.5 Software Operation

The following sections describe the hardware operation of the ASoC driver.

21.5.1 Sound Card Registration

The codecs have the same registration sequence:

1. The codec driver registers the codec driver, DAI driver, and their operation functions
2. The platform driver registers the PCM driver, CPU DAI driver and their operation functions, preallocates buffers for PCM components and sets playback and capture operations as applicable
3. The machine layer creates the DAI link between codec and CPU registers the sound card and PCM devices

21.5.2 Device Open

The ALSA driver:

- Allocates a free substream for the operation to be performed
- Opens the low level hardware device
- Assigns the hardware capabilities to ALSA runtime information. (the runtime structure contains all the hardware, DMA, and software capabilities of an opened substream)
- Configures DMA read or write channel for operation

- Configures CPU DAI and codec DAI interface.
- Configures codec hardware
- Triggers the transfer

After triggering for the first time, the subsequent DMA read/write operations are configured by the DMA callback.

21.6 Platform Data

struct `mxc_audio_platform_data` defined in `include/linux/fsl_devices.h` is used to pass the platform data of audio codec. Its value needs to be updated according to Hardware design.

- `ssi_num`: indicate which SSI channel is used.
- `src_port`: indicate which AUDMUX port is connected with SSI
- `ext_port`: indicate which AUDMUX port is connected with external audio codec.
- `hp_irq`: the irq number of headphone detect
- `hp_status`: the callback function to detect headphone status: inserted or removal
- `init`: the callback function to initialize audio codec. For example, configure the clock of audio codec
- See header file for the details of more variables.

Chapter 22

The Sony/Philips Digital Interface (S/PDIF) Driver

The Sony/Philips Digital Interface (S/PDIF) audio module is a stereo transceiver that allows the processor to receive and transmit digital audio. The S/PDIF transceiver allows the handling of both S/PDIF channel status (CS) and User (U) data and includes a frequency measurement block that allows the precise measurement of an incoming sampling frequency.

22.1 S/PDIF Overview

Figure 22-1 shows the block diagram of the S/PDIF interface.

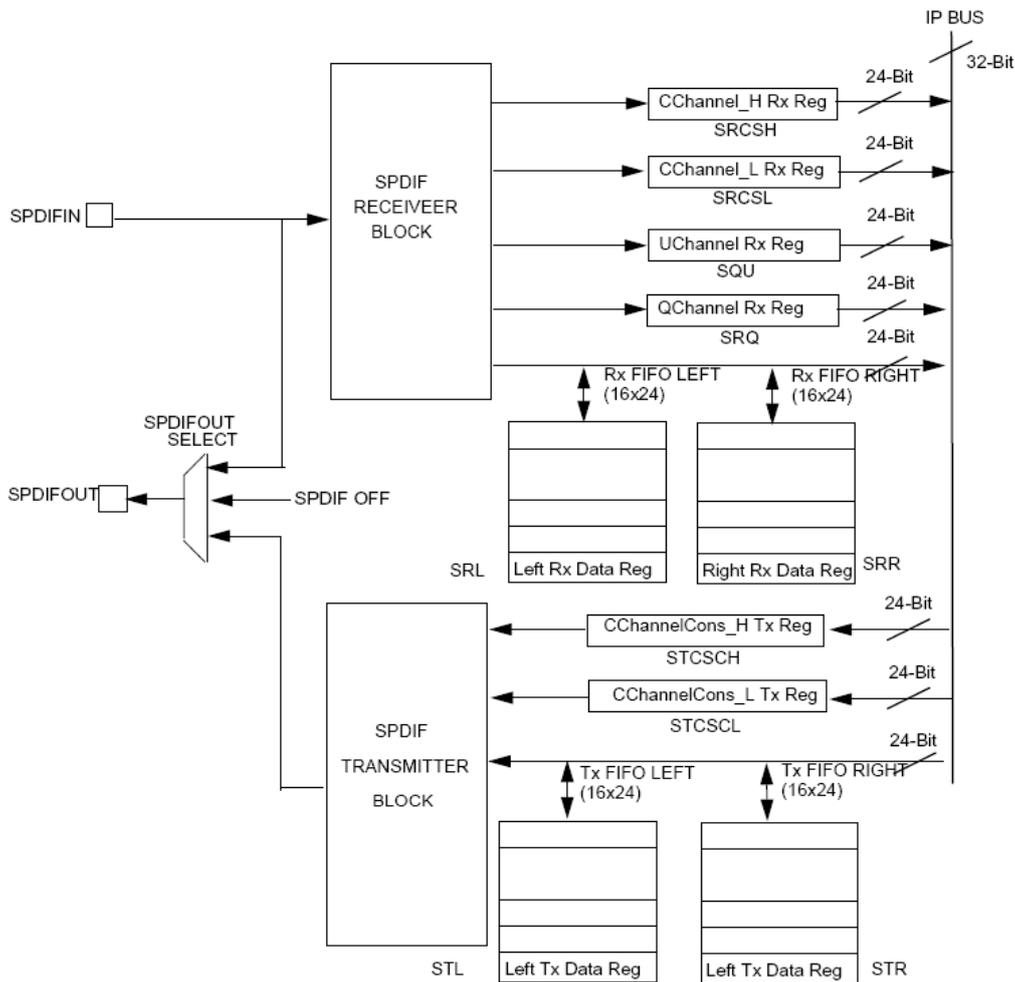


Figure 22-1. S/PDIF Transceiver Data Interface Block Diagram

22.1.1 Hardware Overview

The S/PDIF is composed of two parts:

The Sony/Philips Digital Interface (S/PDIF) Driver

- The S/PDIF receiver extracts the audio data from each S/PDIF frame and places the data in the S/PDIF Rx left and right FIFOs. The Channel Status and User Bits are also extracted from each frame and placed in the corresponding registers. The S/PDIF receiver provides a bypass option for direct transfer of the S/PDIF input signal to the S/PDIF transmitter.
- For the S/PDIF transmitter, the audio data is provided by the processor through the SPDIFTxLeft and SPDIFTxRight registers. The Channel Status bits are provided through the corresponding registers. The S/PDIF transmitter generates a S/PDIF output bitstream in the biphasic mark format (IEC958), which consists of audio data, channel status and user bits.

In the S/PDIF transmitter, the IEC958 biphasic bit stream is generated on both edges of the S/PDIF Transmit clock. The S/PDIF Transmit clock is generated by the S/PDIF internal clock dividers and the sources are from outside of the S/PDIF block. The S/PDIF receiver can recover the S/PDIF Rx clock from the S/PDIF stream. [Figure 22-1](#) shows the clock structure of the S/PDIF transceiver. MX53 supports S/PDIF Rx and Tx. But some MX53 boards can only support S/PDIF Tx or Rx.

22.1.2 Software Overview

The S/PDIF driver is designed under ALSA System on Chip (ASoC) layer. The ASoC driver for S/PDIF provides one playback device for Tx and one capture device for Rx. The playback output audio format can be linear PCM data or compressed data with 16-bit default, up to 24-bit expandable support and the allowed sampling bit rates are 44.1, 48 or 32 KHz. The capture input audio format can be linear PCM data or compressed 24-bit data and the allowed sampling bit rates are from 16 to 96 KHz. The driver provides the same interface for PCM and compressed data transmission.

22.1.3 The ASoC layer

The point of the ASoC layer is to divide audio drivers for embedded platforms into separate layers that can be reused. ASoC divides an audio driver into a codec driver, a machine layer, a DAI (digital audio interface) layer, and a platform layer. The Linux kernel documentation has some concise description of these layers in `linux/Documentation/sound/alsa/soc`. In the case of the S/PDIF driver, we are able to reuse the platform layer (`imx-pcm.c`) that is used by the ssi stereo codec driver.

22.2 S/PDIF Tx Driver

The S/PDIF Tx driver supports the following features:

- 32, 44.1 and 48 KHz sample rates. Signed 16 and 24-bit little Endian sample format. Due to S/PDIF SDMA feature, the 24-bit output sample file must have 32-bits in one channel per frame, and only the 24 LSBs are valid

In the ALSA subsystem, the supported format is defined as `S16_LE` and `S24_LE`.

- Two channels
- Driver installation and information query

If the driver is built as a kernel module, run `modprobe` to install it:

```
#modprobe snd-spdif
```

- The device ID can be determined by using the ‘`aplay -l`’ or ‘`arecord -l`’ utility to list out the playback and record audio devices

For example:

```
root@freescale ~$ aplay -l
**** List of PLAYBACK Hardware Devices ****
card 0: imx3stack [imx-3stack], device 0: SGTL5000 SGTL5000-0 []
  Subdevices: 1/1
  Subdevice #0: subdevice #0
card 1: imx3stackspdif [imx-3stack-spdif], device 0: IMX SPDIF mxc spdif-0 []
  Subdevices: 1/1
  Subdevice #0: subdevice #0
```

- Also, the S/PDIF ALSA driver information is exported to user by `/sys` and `/proc` file system.

For example:

```
#cat /proc/asound/cards
0 [imx3stack      ]: SGTL5000 - imx-3stack
                    imx-3stack (SGTL5000)
1 [imx3stackspdif ]: mxc spdif - imx-3stack-spdif
                    imx-3stack-spdif (mxc spdif)
```

The number at the beginning of the `MXC_SPDIF` line is the card ID. The string in the square brackets is the card name

- Get Playback PCM device info

```
#cat /proc/asound/TXRX/pcm[card id]p/info
```

- Software operation

The ALSA utility provides a common method for user spaces to operate and use ALSA drivers

```
#aplay -D "hw:2,0" -t wav audio.wav
```

NOTE

The `-D` parameter of `aplay` indicates the PCM device with card ID and PCM device ID: `hw:[card id],[pcm device id]`

The “`iecset`” utility provides a common method to set or dump the IEC958 status bits.

```
#iecset -c 1
```

22.2.1 Driver Design

Before S/PDIF playback, the configuration, interrupt, clock and channel registers are initialized. During S/PDIF playback, the channel status bits are fixed. The DMA and interrupts are enabled. S/PDIF has 16 TX sample FIFOs on Left and Right channel respectively. When both FIFOs are empty, an empty interrupt is generated if the empty interrupt is enabled. If no data are refilled in the 20.8 μ s (1/48000), an underrun interrupt is generated. Overrun is avoided if only 16 sample FIFOs are filled for each channel every time. If auto re-synchronization is enabled, the hardware checks if the left and right FIFO are in sync, and if not, it sets the filling pointer of the right FIFO to be equal to the filling pointer of the left FIFO and an interrupt is generated.

22.2.2 Provided User Interface

The S/PDIF transmitter driver provides one ALSA mixer sound control interface to the user besides the common PCM operations interface. It provides the interface for the user to write S/PDIF channel status codes into the driver so they can be sent in the S/PDIF stream. The input parameter of this interface is the IEC958 digital audio structure shown below, and only status member is used:

```
struct snd_aes_iec958 {
    unsigned char status[24];          /* AES/IEC958 channel status bits */
    unsigned char subcode[147];      /* AES/IEC958 subcode bits */
    unsigned char pad;                /* nothing */
    unsigned char dig_subframe[4];    /* AES/IEC958 subframe bits */
};
```

22.3 Interrupts and Exceptions

S/PDIF Tx/Rx hardware block has many interrupts to indicate the success, exception and event. The driver handles the following interrupts:

- DPLL Lock and Loss Lock—Saves the DPLL lock status; this is used when getting the Rx sample rate
- U/Q Channel Full and overrun/underrun—Puts the U/Q channel register data into queue buffer, and update the queue buffer write pointer
- U/Q Channel Sync—Saves the ID of the buffer whose U/Q data is ready for read out
- U/Q Channel Error—Resets the U/Q queue buffer

22.4 Source Code Structure

Table 22-1 lists the source files for the driver. These files are under the `<ltib_dir>/rpm/BUILD/linux/` directory.

Table 22-1. S/PDIF Driver Files

File	Description
sound/soc/codecs/mxc_spdif.c	S/PDIF ALSA SOC codec driver
sound/soc/codecs/mxc_spdif.h	S/PDIF ALSA SOC codec driver header
sound/soc/imx/imx-spdif.c	S/PDIF ALSA SOC machine layer
sound/soc/imx/imx-spdif.h	S/PDIF ALSA SOC machine layer header
sound/soc/imx/imx-spdif-dai.c	S/PDIF ALSA SOC DAI layer
sound/soc/imx/imx-pcm-dai.h	S/PDIF ALSA SOC DAI layer header
sound/soc/imx/imx-pcm.c	ALSA SOC platform layer
sound/soc/imx/imx-pcm.h	ALSA SOC platform layer header

22.5 Menu Configuration Options

The following Linux kernel configurations are provided for this module:

- **CONFIG_SND**—Configuration option for the Advanced Linux Sound Architecture (ALSA) subsystem. This option is dependent on **CONFIG_SOUND** option. In the menuconfig this option is available under
Device Drivers > Sound card support > Advanced Linux Sound Architecture
By default, this option is Y.
- **CONFIG_SND_MXC_SPDIF**—Configuration option for the S/PDIF driver. This option is dependent on **CONFIG_SND** option. In the menuconfig this option is available under
Device Drivers > Sound card support > Advanced Linux Sound Architecture > ALSA for SoC audio support > SoC Audio support for IMX - S/PDIF. By default, this option is Y.
- **SND_MXC_SOC_SPDIF_DAI** and **SND_SOC_MXC_SPDIF** - automatically configured by **CONFIG_SND_MXC_SPDIF**. By default, these options are Y.

22.6 Platform Data

struct `mxc_spdif_platform_data` defined in `include/linux/fsl_devices.h` is used to pass SPDIF platform data according to the detailed Hardware design:

- `spdif_tx`: indicate whether TX is supported. 1 - support TX. 0- Don't support TX
- `spdif_rx`: indicate whether RX is supported. 1 - support RX. 0- Don't support RX
- `spdif_clk_44100`: indicate the clock source (in S/PDIF register STC) of 44.1KHz sample rate. -1 - Don't support this sample rate.
- `spdif_clk_48000`: indicate the clock source (in S/PDIF register STC) of 48KHz sample rate. -1 - Don't support this sample rate.
- `spdif_core_clk`: indicate SPDIF core clocks.
- See header file for the details about more variables.

Chapter 23

Asynchronous Sample Rate Converter (ASRC) Driver

The Asynchronous Sample Rate Converter (ASRC) converts the sampling rate of a signal associated to an input clock into a signal associated to a different output clock. The ASRC supports concurrent sample rate conversion of up to 10 channels. The sample rate conversion of each channel is associated to a pair of incoming and outgoing sampling rates. The ASRC supports up to three sampling rate pairs simultaneously.

23.1 Hardware Operation

ASRC includes the following features:

- Supports ratio (F_{sin}/F_{sout}) range between 1/24 to 8.
- Designed for rate conversion between 44.1 KHz, 32 KHz, 48 KHz, and 96 KHz.
- Other input sampling rates in the range of 8 KHz to 100 KHz are also supported, but with less performance (see IC spec for more details).
- Other output sampling rates in the range of 30 KHz to 100 KHz are also supported, but with less performance.
- Automatic accommodation to slow variations in the incoming and outgoing sampling rates.
- Tolerant to sample clock jitter.
- Designed mainly for real-time streaming audio usage. Can be used for non-realtime streaming audio usage when the input sampling clocks are not available.
- In any usage case, the output sampling clocks must be activated.
- In case of real-time streaming audio, both input and output clocks need to be available and activated.
- In case of non-realtime streaming audio, the input sampling rate clocks can be avoided by setting ideal-ratio values into ASRC interface registers.

The ASRC supports polling, interrupt and DMA modes, but only DMA mode is used in the platform for better performance. The ASRC supports following DMA channels:

- Peripheral to peripheral, for example: ASRC to SPDIF
- Memory to peripheral, for example: memory to ASRC
- Peripheral to memory, for example: ASRC to memory

For more information, see the chapter on ASRC in the *Multimedia Applications Processor* documentation.

23.2 Software Operation

As an assistant component in the audio system, the ASRC driver implementation depends on the use cases in the platform. Currently ASRC is used in following two scenarios.

- Memory > ASRC > Memory, ASRC is controlled by user application or ALSA plug-in.
- Memory > ASRC > peripheral, ASRC is controlled directly by other ALSA driver.

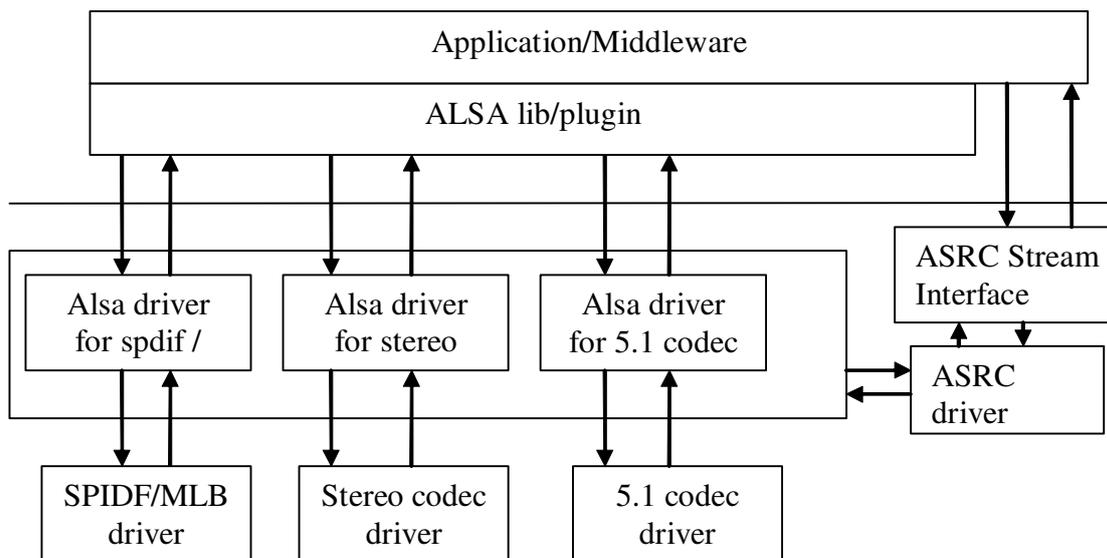


Figure 23-1. Audio Driver Interactions

As illustrated in [Figure 23-1](#), the ASRC stream interface provides the interface for the user space. The ASRC registers itself under `/dev/mxc_asrc` and creates proc file `/proc/driver/asrc` when the module is inserted. proc is used to track the channel number for each pair. If all the pairs are not used, users can adjust the channel number through the proc file. The total channels number should equal five, or else the adjusted value cannot be saved properly. The minimum unit here is one (two channels), for example three represents six channels (three pairs).

23.2.1 Sequence for Memory to ASRC to Memory

- Open `/dev/mxc_asrc` device
- Request ASRC pair - `ASRC_REQ_PAIR`
- Configure ASRC pair - `ASRC_CONFIG_PAIR`
- Query DMA buffer info - `ASRC_QUERYBUF`
- Write the raw audio data (to be converted) into the DMA input buffer. Then, put the DMA input buffer in the input buffer queue (`ASRC_Q_INBUF`) and put the DMA output buffer in the output buffer queue (`ASRC_Q_OUTBUF`), so that the ASRC driver can get the buffers. To avoid an underrun, it would be better to queue in three buffers to both input and output.
- Start ASRC - `ASRC_START_CONV`
- Dequeue ASRC output and input buffer, copy the converted audio data for further process from output buffer and write new audio data to input buffer.
- Repeat enqueue and dequeue steps until conversion is complete
- Stop ASRC conversion - `ASRC_STOP_CONV`
- Release ASRC pair - `ASRC_RELEASE_PAIR`
- Close `/dev/mxc_asrc` device

23.2.2 Sequence for Memory to ASRC to Peripheral

- The sound card has been registered and start to enable the DMA channel in ALSA driver
- Request ASRC pair - `asrc_req_pair`
- Configure ASRC pair - `asrc_config_pair`
- Enable the DMA channel from Memory to ASRC and from ASRC to Memory
- Start DMA channel and start ASRC conversion - `asrc_start_conv`
- When audio data playback complete, stop DMA channel and ASRC - `asrc_stop_conv`
- Release ASRC pair - `asrc_release_pair`

23.3 Source Code Structure

Table 23-1 lists the source files available in the devices directory:

```
<ltib_dir>/rpm/BUILD/linux/drivers/mxc/asrc
```

```
<ltib_dir>/rpm/BUILD/linux/include/linux/
```

Table 23-1. ASRC Source File List

File	Description
<code>mxc_asrc.h</code>	ASRC register definitions and export function declarations
<code>mxc_asrc.c</code>	ASRC driver implementation codes including stream interface

23.3.1 Linux Menu Configuration Options

Device drivers > MXC support drivers > MXC Asynchronous Sample Rate Converter support > ASRC support

23.4 Platform Data

struct `mxc_asrc_platform_data` defined in `include/linux/fsl_devices.h` is used to pass the platform information of ASRC according to different SOC:

- `channel_bits`: indicates the channel bit information.
- `clk_map_ver`: the mapping relationship in different SOC is different. This version number can be used to indicate clock map information.
- `asrc_core_clk`: asrc core clock information which is used as ASRC register access.
- `asrc_audio_clk`: asrc process clock.

23.5 Programming Interface (Exported API and IOCTLs)

The ASRC Exported API allows the ALSA driver to use ASRC services. The ASRC IOCTLs in Table 23-2 are used for user space applications.

Table 23-2. ASRC Exported Functions

Function/ioctl	Description
<code>int asrc_req_pair(int chn_num, enum asrc_pair_index *index)</code>	Request the ASRC pair
<code>void asrc_release_pair(enum asrc_pair_index index)</code>	Release ASRC pair
<code>int asrc_config_pair(struct asrc_config *config)</code>	Configure the ASRC hardware
<code>void asrc_start_conv(enum asrc_pair_index index)</code>	Start ASRC conversion for specific pair
<code>void asrc_stop_conv(enum asrc_pair_index index)</code>	Stop ASRC conversion
<code>ASRC_REQ_PAIR</code>	Request ASRC pair
<code>ASRC_CONFIG_PAIR</code>	Configure ASRC pair and allocate DMA buffer
<code>ASRC_RELEASE_PAIR</code>	Release ASRC pair and release DMA buffer
<code>ASRC_QUERYBUF</code>	Query buffer information
<code>ASRC_Q_INBUF</code>	Queue ASRC input buffer (audio data to be converted)
<code>ASRC_DQ_INBUF</code>	Dequeue ASRC input buffer (audio processed)
<code>ASRC_Q_OUTBUF</code>	Queue ASRC output buffer (empty buffer to hold the converted buffer)
<code>ASRC_DQ_OUTBUF</code>	Dequeue ASRC output buffer (buffer hold converted audio data)
<code>ASRC_START_CONV</code>	Start ASRC conversion
<code>ASRC_STOP_CONV</code>	Stop ASRC conversion

- 0 -- INCLK_NONE
- 1 -- INCLK_ESAI_RX
- 2 -- INCLK_SSI1_RX
- 3 -- INCLK_SSI2_RX
- 4 -- INCLK_SPDIF_RX
- 5 -- INCLK_MLB_CLK
- 6 -- INCLK_ESAI_TX
- 7 -- INCLK_SSI1_TX
- 8 -- INCLK_SSI2_TX
- 9 -- INCLK_SPDIF_TX
- 10 -- INCLK_ASRC1_CLK
- default option for input clock source is 0, using the INCLK_NONE option.
- 0 -- OUTCLK_NONE
- 1 -- OUTCLK_ESAI_TX

- 2 -- OUTCLK_SSI1_TX
- 3 -- OUTCLK_SSI2_TX
- 4 -- OUTCLK_SPDIF_TX
- 5 -- OUTCLK_MLB_CLK
- 6 -- OUTCLK_ESAI_RX
- 7 -- OUTCLK_SSI1_RX
- 8 -- OUTCLK_SSI2_RX
- 9 -- OUTCLK_SPDIF_RX
- 10 -- OUTCLK_ASRCK1_CLK
- default option for output clock source is 10, using the OUTCLK_ASRCK1_CLK option.

Chapter 24

SPI NOR Flash Memory Technology Device (MTD) Driver

The SPI NOR Flash Memory Technology Device (MTD) driver provides the support to the data Flash through the SPI interface. By default, the SPI NOR Flash MTD driver creates static MTD partitions to support data Flash. If RedBoot partitions exist, they have higher priority than static partitions, and the MTD partitions can be created from the RedBoot partitions.

24.1 Hardware Operation

On some boards, the SPI NOR - AT45DB321D is equipped, while on some boards M25P32 is equipped. Check the SPI NOR type on the boards and then configure it properly.

The AT45DB321D is a 2.7 V, serial-interface sequential access Flash memory. The AT45DB321D serial interface is SPI compatible for frequencies up to 66 MHz. The memory is organized as 8,192 pages of 512 bytes or 528 bytes. The AT45DB321D also contains two SRAM buffers of 512/528 bytes each which allow receiving of data while a page in the main memory is being reprogrammed, as well as writing a continuous data stream.

The M25P32 is a 32 Mbit (4M x 8) Serial Flash memory, with advanced write protection mechanisms, accessed by a high speed SPI-compatible bus up to 75MHz. The memory is organized as 64 sectors, each containing 256 pages. Each page is 256 bytes wide. Thus, the whole memory can be viewed as consisting of 16384 pages, or 4,194,304 bytes. The memory can be programmed 1 to 256 bytes at a time, using the Page Program instruction. The whole memory can be erased using the Bulk Erase instruction, or a sector at a time, using the Sector Erase instruction.

Unlike conventional Flash memories that are accessed randomly, these two SPI NOR accesses data sequentially. They operate from a single 2.7–3.6 V power supply for program and read operations. They are enabled through a chip select pin and accessed through a three-wire interface: Serial Input, Serial Output, and Serial Clock.

24.2 Software Operation

In a Flash-based embedded Linux system, a number of Linux technologies work together to implement a file system. Figure 24-1 illustrates the relationships between some of the standard components.

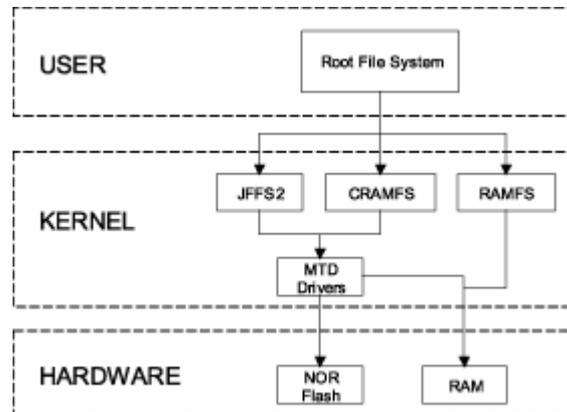


Figure 24-1. Components of a Flash-Based File System

The MTD subsystem for Linux is a generic interface to memory devices, such as Flash and RAM, providing simple read, write and erase access to physical memory devices. Devices called `mtdblock` devices can be mounted by JFFS, JFFS2 and CRAMFS file systems. The SPI NOR MTD driver is based on the MTD data Flash driver in the kernel by adding SPI access. In the initialization phase, the SPI NOR MTD driver detects a data Flash by reading the JEDEC ID. Then the driver adds the MTD device. The SPI NOR MTD driver also provides the interfaces to read, write, erase NOR Flash.

24.3 Driver Features

This NOR MTD implementation supports the following features:

- Provides necessary information for the upper layer MTD driver

24.4 Source Code Structure

The SPI NOR MTD driver is implemented in the following directory:

`<ltlib_dir>/rpm/BUILD/linux/drivers/mtd/devices/`

Table 24-1 shows the driver files:

Table 24-1. SPI NOR MTD Driver Files

File	Description
<code>mxc_m25p80.c</code>	Source file

24.5 Menu Configuration Options

To get to the SPI NOR MTD driver, use the command `./ltib -c` when located in the `<ltib dir>`. On the screen displayed, select **Configure the kernel** and exit. When the next screen appears select the following options to enable the SPI NOR MTD driver accordingly:

- `CONFIG_MTD_MXC_DATAFLASH`: This config enables the access to AT DataFlash chips, using FSL SPI. In menuconfig, this option is available under
Device Drivers > Memory Technology Device (MTD) support > Self-contained MTD device drivers > Support for AT DataFlash via FSL SPI interface
- `CONFIG_MTD_MXC_M25P80`: This enables access to most modern SPI flash chips, used program and data storage. Series supported include Atmel AT26DF Spansion S25SL, SST 25VF, ST M25P, and Winbond W25X. In menuconfig, this option is available under
Device Drivers > Memory Technology Device (MTD) support > Self-contained MTD device drivers > Support SPI Flash chips (for example, M25P) via FSL SPI interface

Chapter 25

SATA Driver

25.1 Hardware Operation

The detailed hardware operation of SATA is detailed in the Synopsys DesignWare Cores SATA AHCI documentation, named `SATA_Data_Book.pdf`.

25.2 Software Operation

The details about the libata APIs, see the libATA Developer's Guide named `libata.pdf` published by Jeff Gazik.

The SATA AHCI driver is based on the LIBATA layer of the block device infrastructure of the Linux kernel. FSL integrated AHCI linux driver combined the standard AHCI drivers handle the details of the integrated freescale's SATA AHCI controller, while the LIBATA layer understands and executes the SATA protocols. The SATA device, such as a hard disk, is exposed to the application in user space by the `/dev/sda*` interface. Filesystems are built upon the block device. The AHCI specified integrated DMA engine, which assists the SATA controller hardware in the DMA transfer modes.

25.3 Source Code Structure Configuration

The source codes of freescale's AHCI sata driver is integrated into the plat-mxc relative files.

```
<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc/ahci_sata.c.
```

The standard AHCI and AHCI platform drivers are used to do the actual sata operations.

The source codes of the standard AHCI and AHCI platform drivers are located in `drivers/ata/` folder, named as `ahci.c` and `ahci-platform.c`.

25.4 Linux Menu Configuration Options

The following Linux kernel configurations are provided for SATA driver:

- `CONFIG_SATA_AHCI_PLATFORM`: Configure options for SATA driver. In the menuconfig this option is available under "Device Drivers --->Serial ATA (prod) and Parallel ATA (experimental) drivers -> Platform AHCI SATA support".
- `CONFIG_SATA_AHCI_FSL_NO_HOTPLUG_MODE`: Configure options to disable SATA HOTPLUG mode which is used to close SATA internal clock if SATA device is not found. In the menuconfig this option is available under "Device Drivers --->Serial ATA (prod) and Parallel ATA (experimental) drivers -> Freescale i.MX SATA AHCI NO HOTPLUG mode"

In busybox, enable "fdisk" under "Linux System Utilities".

25.5 Board Configuration Options

With the power off, install the SATA cable and hard drive.

25.6 Programming Interface

The application interface to the SATA driver is the standard POSIX device interface (for example: open, close, read, write, and ioctl) on `/dev/sda*`.

25.7 Usage Example

NOTE

There would be a known error message when the SATA disk is initialized, such as:

```
ata1.00: serial number mismatch '090311PB0300QKG3TB1A' != "
ata1.00: revalidation failed (errno=-19)
pls ignore that.
```

1. After building the kernel and the SATA AHCI driver and deploying, boot the target, and log in as root.
2. Make sure that the AHCI and AHCI platform drivers are built in kernel or loaded into kernel. Use the following commands to load the drivers into kernel.

```
# insmod libata.ko
# insmod libahci.ko
# insmod ahci-platform.ko
```

You should see messages similar to the following:

```
ahci: SSS flag set, parallel bus scan disabled
ahci ahci.0: AHCI 0001.0100 32 slots 1 ports 3 Gbps 0x1 impl platform mode
ahci ahci.0: flags: ncq sntf stag pm led clo only pmp pio slum part ccc
scsi0 : ahci
ata1: SATA max UDMA/133 irq_stat 0x00000040, connection status changed irq 28
ata1: SATA link up 1.5 Gbps (SStatus 113 SControl 300)
ata1.00: ATA-8: Hitachi HTS545032B9A300, PB30C60G, max UDMA/133
ata1.00: 625142448 sectors, multi 0: LBA48 NCQ (depth 31/32)
ata1.00: serial number mismatch '090311PB0300QKG3TB1A' != ''
ata1.00: revalidation failed (errno=-19)
ata1: limiting SATA link speed to 1.5 Gbps
ata1.00: limiting speed to UDMA/133:PIO3
ata1: SATA link up 1.5 Gbps (SStatus 113 SControl 310)
ata1.00: configured for UDMA/133
scsi 0:0:0:0: Direct-Access      ATA          Hitachi HTS54503 PB30 PQ: 0 ANSI: 5
sd 0:0:0:0: [sda] 625142448 512-byte logical blocks: (320 GB/298 GiB)
sd 0:0:0:0: [sda] Write Protect is off
sd 0:0:0:0: [sda] Write cache: enabled, read cache: enabled, doesn't support DPO or
FUA
sda: sda1 sda2 sda3
sd 0:0:0:0: [sda] Attached SCSI disk
```

You may use standard Linux utilities to partition and create a file system on the drive (for example: `fdisk` and `mke2fs`) to be mounted and used by applications.

The device nodes for the drive and its partitions appears under `/dev/sda*`. For example, to check basic kernel settings for the drive, execute `hdparm /dev/sda`.

25.8 Usage Example

Create Partitons

The following command can be used to find out the capacities of the hard disk. If the hard disk is pre-formatted, this command shows the size of the hard disk, partitions, and filesystem type:

```
$fdisk -l /dev/sda
```

If the hard disk is not formatted, create the partitions on the hard disk using the following command:

```
$fdisk /dev/sda
```

After the partition, the created files resemble `/dev/sda[1-4]`.

Block Read/Write Test:

The command, `dd`, is used for for reading/writing blocks. Note this command can corrupt the partitions and filesystem on Hard disk.

To clear the first 5 KB of the card, do the following:

```
$dd if=/dev/zero of=/dev/sda1 bs=1024 count=5
```

The response should be as follows:

```
5+0 records in
```

```
5+0 records out
```

To write a file content to the card enter the following text, substituting the name of the file to be written for `file_name`, do the following:

```
$dd if=file_name of=/dev/sda1
```

To read 1KB of data from the card enter the following text, substituting the name of the file to be written for `output_file`, do the following:

```
$dd if=/dev/sda1 of=output_file bs=1024 count=1
```

Files System Tests

Format the hard disk partitons using `mkfs.vfat` or `mkfs.ext2`, depending on the filesystem:

```
$mkfs.ext2 /dev/sda1
$mkfs.vfat /dev/sda1
```

Mount the file system as follows:

```
$mkdir /mnt/sda1
$mount -t ext2 /dev/sda1 /mnt/sda1
```

After mounting, file/directory, operations can be performed in `/mnt/sda1`.

Unmount the filesystem as follows:

```
$umount /mnt/sda1
```

25.9 SATA temperature monitor

If SATA device is detected or `CONFIG_SATA_AHCI_FSL_NO_HOTPLUG_MODE` is enabled so that SATA clock can be opened, the chip temperature can be monitored by the following command:

SATA Driver

```
cat /sys/devices/platform/ahci.0/temperature
```

Chapter 26

MMC/SD/SDIO Host Driver

The MultiMediaCard (MMC)/ Secure Digital (SD)/ Secure Digital Input Output (SDIO) Host driver implements a standard Linux driver interface to the enhanced MMC/SD host controller (eSDHC). The host driver is part of the Linux kernel MMC framework.

The MMC driver has the following features:

- 1-bit or 4-bit operation for SD and SDIO cards
- Supports card insertion and removal detections
- Supports the standard MMC commands
- PIO and DMA data transfers
- Power management
- Supports 1/4/8-bit operations for MMC cards
- Support eMMC4.4 SDR and DDR mode

26.1 Hardware Operation

The MMC communication is based on an advanced 11-pin serial bus designed to operate in a low voltage range. The eSDHC module support MMC along with SD memory and I/O functions. The eSDHC controls the MMC, SD memory, and I/O cards by sending commands to cards and performing data accesses to and from the cards. The SD memory card system defines two alternative communication protocols: SD and SPI. The eSDHC only support the SD bus protocol.

The eSDHC command transfer type and eSDHC command argument registers allow a command to be issued to the card. The eSDHC command, system control and protocol control registers allow the users to specify the format of the data and response and to control the read wait cycle.

The block length register defines the number of bytes in a block (block size). As the Stream mode of MMC is not supported, the block length must be set for every transfer.

There are four 32-bit registers used to store the response from the card in the eSDHC. The eSDHC reads these four registers to get the command response directly. The eSDHC uses a fully configurable 128×32-bit FIFO for read and write. The buffer is used as temporary storage for data being transferred between the host system and the card, and vice versa. The eSDHC data buffer access register bits hold 32-bit data upon a read or write transfer.

For receiving data, the steps are as follows:

1. The eSDHC controller generates a DMA request when there are more words received in the buffer than the amount set in the RD_WML register
2. Upon receiving this request, DMA engine starts transferring data from the eSDHC FIFO to system memory by reading the data buffer access register

To transmitting data, the steps are as follows:

1. The eSDHC controller generates a DMA request whenever the amount of the buffer space exceeds the value set in the WR_WML register
2. Upon receiving this request, the DMA engine starts moving data from the system memory to the eSDHC FIFO by writing to the Data Buffer Access Register for a number of pre-defined bytes

The read-only eSDHC Present State and Interrupt Status Registers provide eSDHC operations status, application FIFO status, error conditions, and interrupt status.

When certain events occur, the module has the ability to generate interrupts as well as set the corresponding Status Register bits. The eSDHC interrupt status enable and signal enable registers allow the user to control if these interrupts occur.

26.2 Software Operation

The Linux OS contains an MMC bus driver which implements the MMC bus protocols. The MMC block driver handles the file system read/write calls and uses the low level MMC host controller interface driver to send the commands to the eSDHC.

The MMC driver is responsible for implementing standard entry points for `init`, `exit`, `request`, and `set_ios`. The driver implements the following functions:

- The `init` function `sdhci_drv_init()`—Registers the `device_driver` structure.
- The `probe` function `sdhci_probe` and `sdhci_probe_slot()`—Performs initialization and registration of the MMC device specific structure with MMC bus protocol driver. The driver probes for memory and IRQ resources. Configures the IOMUX to enable eSDHC I/O pins and resets the hardware.
- `sdhci_set_ios()`—Sets bus width, voltage level, and clock rate according to core driver requirements.
- `sdhci_request()`—Handles both read and write operations. Sets up the number of blocks and block length. Configures an DMA channel, allocates safe DMA buffer and starts the DMA channel. Configures the eSDHC transfer type register eSDHC command argument register to issue a command to the card. This function starts the SDMA and starts the clock.
- MMC driver ISR `sdhci_cd_irq()`—Called when the MMC/SD card is detected or removed.
- MMC driver ISR `sdhci_irq()`—Interrupt from eSDHC called when command is done or errors like CRC or buffer underrun or overflow occurs.
- DMA completion routine `sdhci_dma_irq()`—Called after completion of a DMA transfer. Informs the MMC core driver of a request completion by calling `mmc_request_done()` API.

Figure shows how the MMC-related drivers are layered.

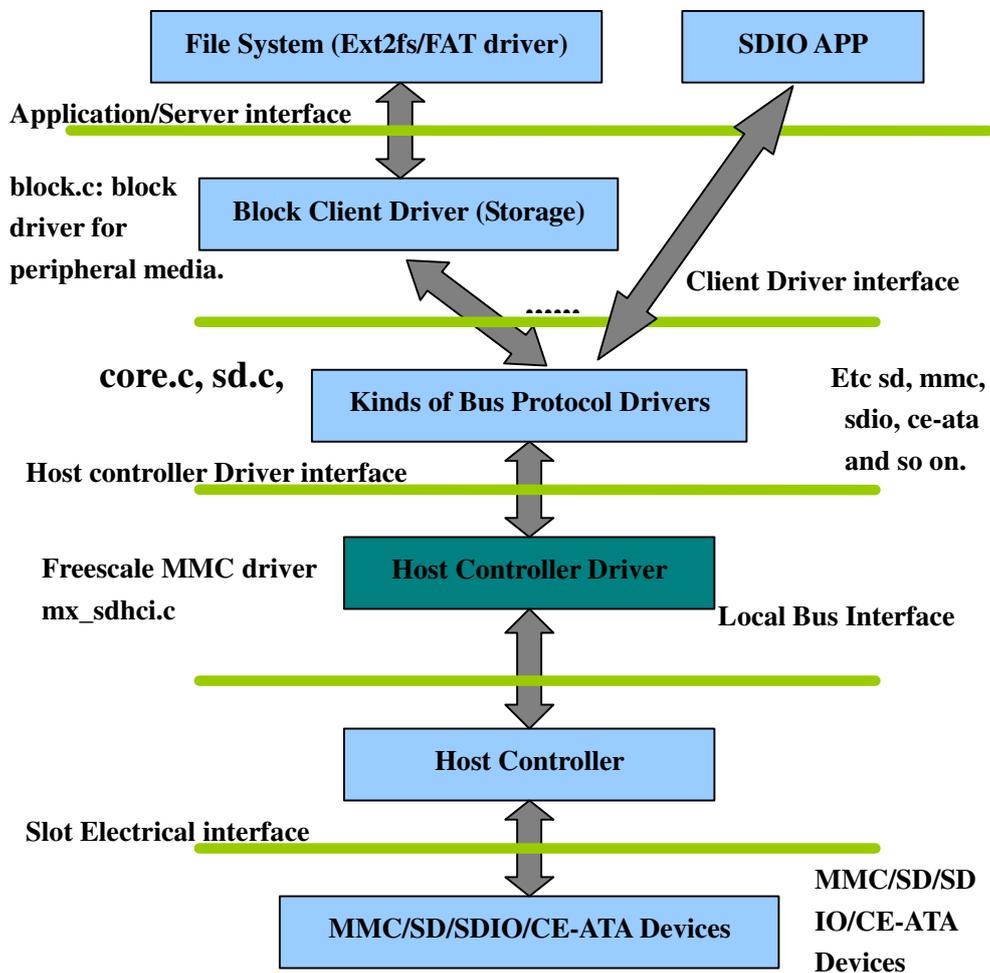


Figure 26-1. MMC Drivers Layering

26.3 Driver Features

The MMC driver supports the following features:

- Supports multiple eSDHC modules
- Provides all the entry points to interface with the Linux MMC core driver
- MMC and SD cards
- Recognizes data transfer errors such as command time outs and CRC errors
- Power management

26.4 Source Code Structure

Table 26-1 shows the eSDHC source files available in the source directory:

```
<ltib_dir>/rpm/BUILD/linux/drivers/mmc/host/.
```

Table 26-1. eSDHC Driver Files MMC/SD Driver Files

File	Description
mx_sdhci.h	Header file defining registers
mx_sdhci.c	eSDHC driver

26.5 Menu Configuration Options

The following Linux kernel configuration options are provided for this module. To get to these options, use the `./ltib -c` command when located in the `<ltib_dir>`. On the screen displayed, select Configure the Kernel and exit. When the next screen appears, select the following options to enable this module:

- **CONFIG_MMC**—Build support for the MMC bus protocol. In `menuconfig`, this option is available under
Device Drivers > MMC/SD/SDIO Card support
By default, this option is Y.
- **CONFIG_MMC_BLOCK**—Build support for MMC block device driver, which can be used to mount the file system. In `menuconfig`, this option is available under
Device Drivers > MMC/SD Card Support > MMC block device driver
By default, this option is Y.
- **CONFIG_MMC_IMX_ESDHCI**—Driver used for the i.MX eSDHC ports. In `menuconfig`, this option is found under
Device Drivers > MMC/SD Card Support > Freescale i.MX Secure Digital Host Controller Interface support
- **CONFIG_MMC_IMX_ESDHCI_PIO_MODE**—Sets i.MX Multimedia card Interface to PIO mode. In `menuconfig`, this option is found under
Device Drivers > MMC/SD Card support > Freescale i.MX Secure Digital Host Controller Interface PIO mode
This option is dependent on **CONFIG_MMC_IMX_ESDHCI**. By default, this option is not set and DMA mode is used.
- **CONFIG_MMC_UNSAFE_RESUME**—Used for embedded systems which use a MMC/SD/SDIO card for rootfs. In `menuconfig`, this option is found under
Device drivers > MMC/SD/SDIO Card Support > Allow unsafe resume.

26.6 Platform Data

struct `mxc_mmc_platform_data` defined in `arch/arm/plat-mxc/include/mach/mmc.h` is used to pass platform informaton:

- `.caps`: set the capability of the slot. 1bit, 4bit or 8bit mode. SDR mode or DDR mode

- `.min_clk`: the minimal clock value
- `.max_clk`: the maximum clock value
- `.card_inserted_state`: indicated the card status. If no CD pin was connected, the value can be set as 1.
- `.status`: the callback function to get card status: inserted or removed.
- `.wp_status`: the callback function to check write protection status
- `.clock_mmc`: the clock name of SDHC.
- See the header file for more variables. The user should pass the right platform to enable MMC/SD according to HW information.

26.7 How to add a SDHC slot support

To add a SDHC slot support, PIN, clock, platform data need to be taken into consideration. Take SDHC3 slot in MX53 START as the example, the following changes need to be done:

- Modify `arch/arm/mach-mx5/mx53_loco.c` to add PIN supports. In `mx53_loco_pads`, add for example `MX53_PAD_ATA_DATA8__SD3_DAT0`. In `mx53_loco_io_init`, do gpio configurations for CD and WP pins.
- In `arch/arm/mach-mx5/devices.c`, ensure `mxcsdhc3_device` and `mxcsdhc3_resources` are configured.
- Check `arch/arm/mach-mx5/clock.c` and ensure `esdhc3_clk` is configured well.
- Modify `arch/arm/mach-mx5/mx53_loco.c` to register `sdhc3` device. Add platform data “`mmc3_data`” and call “`mx_register_device(&mxcsdhc3_device, &mmc3_data);`”

26.8 Programming Interface

This driver implements the functions required by the MMC bus protocol to interface with the i.MX eSDHC module. See the *BSP API* document (in the doxygen folder of the documentation package), for additional information.

Chapter 27

Symmetric/Asymmetric Hashing and Random Accelerator (Sahara) Drivers

27.1 Overview

The Symmetric/Asymmetric Hashing and Random Accelerator (Sahara) implements block encryption algorithms, hashing algorithms, a stream cipher algorithm, public key algorithms, and pseudo-random number generation. It has a slave IP bus interface for the host to write configuration and command information, and to read status information. It also has a DMA controller, with an AHB bus interface, to reduce the burden on the host to move the required data to and from memory.

27.2 Software Operation

27.2.1 API Notes

Kernel users should not use blocking mode unless the code is operating on behalf of the kernel process which needs to sleep because blocking mode attempts to put the current process to sleep. Therefore blocking mode cannot be used from bottom half code or from interrupt code.

Kernel users must provide a `kmalloc`-ed buffer address for all data types (key structures, context structures, input/output buffers, and so on)

User-mode users should beware of (or even avoid) using the stack for I/O, as cache line boundaries can cause problems. This can even be true for such simple things as having a context object on the stack, or retrieving a random number into a `uint32_t` stack variable. This applies to key structures, context structures, and input/output buffers.

27.2.2 Architecture

The conceptual model is shown in [Figure 27-1](#). All of the processes in [Figure 27-1](#) are implemented as common code, except for the following platform-centric processes:

- UM Extension
- Init/Cleanup
- Translator
- Completion Notification

Symmetric/Asymmetric Hashing and Random Accelerator (Sahara) Drivers

The driver operates in poll or interrupt mode, based on how the code is built (compile time option). The modes are mutually exclusive.

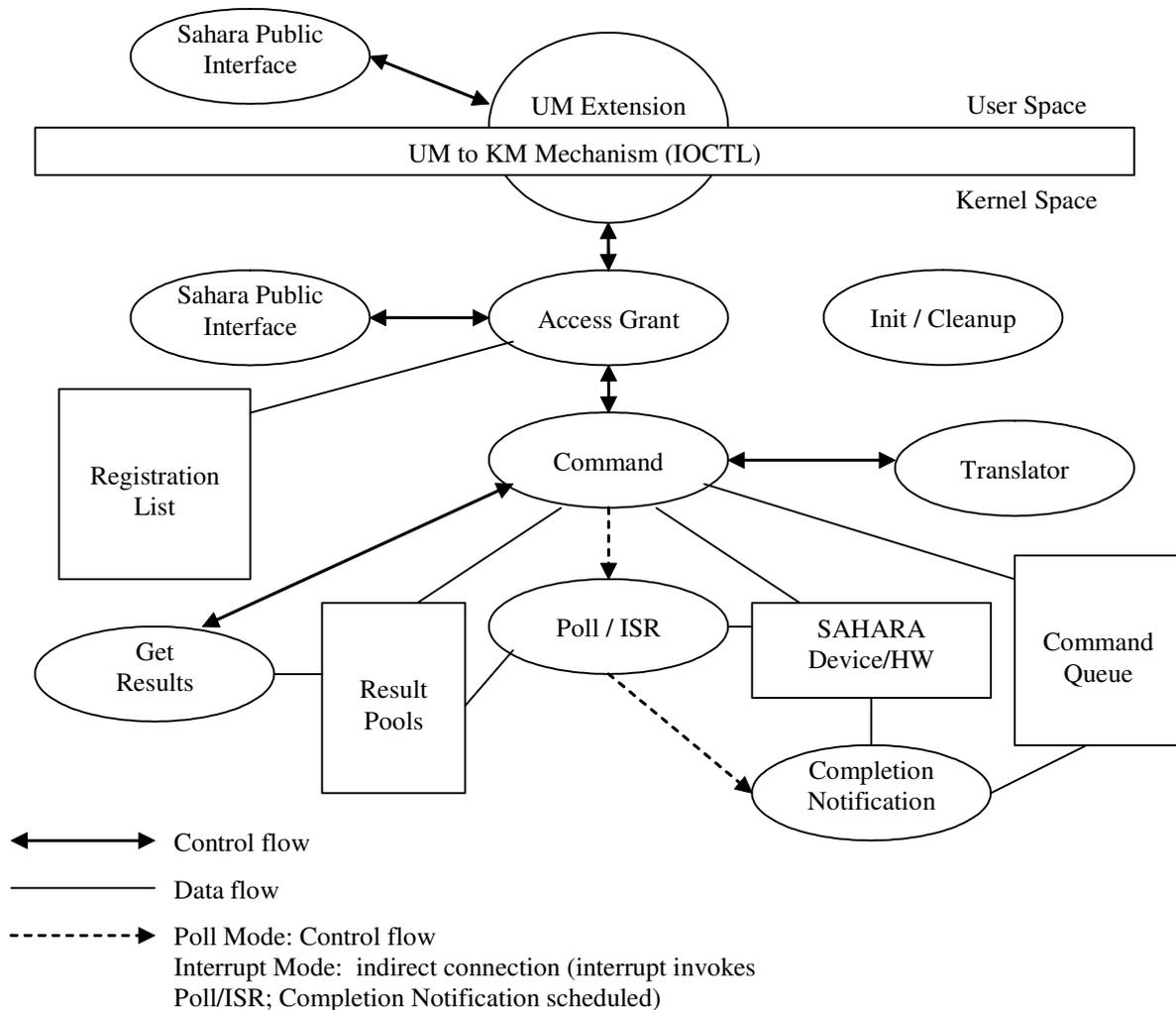


Figure 27-1. Sahara Architecture Overview

27.2.2.1 Registration List

The registration list maintains a list of the tasks that are registered with the driver.

27.2.2.2 Command Queue

The command queue maintains a list of commands (pointers to descriptor chains and their associated user) destined for the Sahara hardware. A pointer is maintained to the current (active) command as well as where the next command is to be entered into the queue.

27.2.2.3 Result Pools

The results pool maintains a list of completed commands. After the Sahara hardware completes, the status, along with its user association is placed in this pool.

27.2.2.4 Sahara Hardware

27.2.2.5 Initialize and Cleanup

This process is invoked by the OS to do the following tasks:

- Initialize the driver when the OS wishes to start the driver
- Cleanup the driver when the OS wishes to shut down the driver

The following steps are used to initialize the driver:

1. Map Sahara registers into kernel space
2. Check that the Sahara version number is
3. Attach handler to Sahara interrupt line (top half) if in interrupt mode
4. Initialize Sahara interrupt
5. Seed the random number generator. The RNG Auto Reseed in the control register cannot be set at startup (Hardware Erratum for RNG reseed). The available choices are:
 - Set this bit after the first random number is obtained
 - Never set this bit but rather detect when the `RNG Reseed Req` bit is set in the Status register and put the RNG in Seed Generation Mode. This is used for this architecture
 - Check for the reseed and set auto reseed when it becomes true
6. Install the tasklet (bottom half), if in interrupt mode (that is, install Complete Notification process)
7. Set up pointers to the command queue, the result pool, and the registration list
8. Populate the Capability Object (most of this can be done at compile time) as follows:
 - Command queue size
 - Result pool size
 - Registration list size
 - Driver version number
 - Algorithms and modes
9. Zero/initialize registration list, command queue, and result pool
10. Register as a device (to IOCTL)
11. If a failure is encountered anywhere within the Init subprocess, it is terminated, the Cleanup subprocess is initiated and an error is returned to the OS

The following steps are used to clean up a process:

1. Unregister as a device (to IOCTL)
2. Uninstall interrupt handler (top half) if in interrupt mode
3. Uninstall tasklet (bottom half) if in interrupt mode

4. Reset Sahara (leave Sahara interrupt disabled)
5. Null pointers to command queue, result pool, and registration list

27.2.2.6 Sahara Public Interface

This is the only access users are permitted to the Sahara functionality (Refer to the API document included in doxygen format). The interface is the same in both User and Kernel Space.

- Converts service requests into descriptor chains, for those requests that required descriptors
 - For final block of data, ensure that it is consumed correctly (Hardware Erratum for buffer length issue)
 - Descriptor pointers are created based on information in the SKO, HCO, and/or SCCO
 - Descriptor pointers reference input and output data buffers, fields in the SKO, HCO, and/or SCCO
- Returns error if input parameters are inconsistent or otherwise in error
- Passes pointers to a descriptor chain and a UCO to the next process
- Receives status information from the rest of the driver to return through the API return value
- Passes raw descriptor chains through (must be registered, that is, have a UCO). It is necessary to determine if the hardware erratum for buffer length issue applies to this descriptor chain and, if so, modify the chain appropriately
- Passes information into, and receives from, the Access Grant or UM Extension process, as appropriate

27.2.2.7 UM Extension

When the Sahara public interface is built for user space, the user mode extension is included in the build to provide a way for the user space sahara public interface to communicate into kernel mode.

- Transports information passed from Sahara Public Interface from User to Kernel space and back
- Passes information into, and receives from, the Access Grant process
- Passes information into, and receives from, the Sahara Public Interface in User Space
- When signaled by the Completion Notification process, invokes the User callback routine (the callback was acquired during registration)

27.2.2.8 Access Grant

All tasks must be registered with the driver before being able to request services.

- If this is a registration request, do the following:
 - Enter user information in Registration List, such as: ID, maximum number of outstanding commands possible (Result Pool size requested)
 - Populate its User Context Object
 - Return `success` or `failure` as appropriate
- If this is a deregistration request and the user is not registered, return `never registered`

- If this is a deregistration request and the user is registered
 - Remove user information in Registration List
 - Depopulate its User Context Object
 - Return `success` or `failure` as appropriate
- If this is not a registration or deregistration request (that is, any other User request), access the Registration List to see if the requestor is registered with the driver
 - If User is registered, pass the request to the Command process
 - If the User is not registered, return `unregistered` error to the requesting process

27.2.2.9 Command

The Command determines what service was requested and directs the driver to fulfill that service. The system determines whether it is a service that the driver can fulfill without the use of the Sahara HW or not

For requests that involve Sahara hardware, the system does the following:

1. Checks that there is room in the Command Queue. If there is not, returns a `queue full` status and terminates
2. Checks that there is room in the Result Pool. If there is not, returns a `pool full` status and terminates
3. Checks that this user has not reached its maximum number of outstanding requests. If it has, return `request limit reached`
4. Invokes the Translator process to convert received memory addresses
5. If Command Queue is empty, enters descriptor chain pointer into the Sahara Descriptor Address Register (DAR). This starts the processing of descriptors which continues until the Command Queue is empty
6. Enters the UCO and descriptor pointer in Command Queue, and whatever additional information may be needed, to await execution
7. Checks if the `RNG_Reseed_Req` bit is set in the Status register and, if so, puts an RNG Reseed descriptor into the command queue to reseed the RNG

User Blocking/Non-blocking requests are handled as listed [Table 27-1](#).

Table 27-1. Blocking/Non-Blocking Definitions

Feature	Driver Poll Mode	Driver Interrupt Mode
User Blocking	User waits for request completion. Driver never gives up processor.	User waits for request completion. Driver queues request, suspends calling task, and releases processor (on completion the Driver un-suspends task / returns)
User Non-blocking with callback	Driver never gives up processor, therefore User is blocked until request completion (the callback is invoked prior to request completion)	Driver queues request and returns. Upon request completion, the callback is invoked
User Non-blocking without callback	Driver never gives up processor, therefore User is blocked until request completion	Driver queues request and returns. (User is not given any indication of completion. It enters a User Poll mode and polls for the results)

8. If in poll mode, transfer control to Poll/ISR process (if in interrupt mode, the Poll/ISR process is invoked through the interrupt mechanism)

Requests that do not involve Sahara hardware, are processed and immediately returned to the user. For example, if a `get_results` request is received, the list is populated with the user results and the driver returns to the user.

27.2.2.10 Translator

The translator has the following features:

- Translates pointer addresses from virtual addresses to physical addresses
- Ensures that blocks of data that have become fragmented due to page discontinuity are handled with links in the descriptor chain
- Locks pages so addresses remain stable
- Clears processor cache

27.2.2.11 Polling and Interrupts

Polling has the following features:

1. Continuously checks if operation is done (poll the State field in the Status Register) to determine when the Sahara hardware has completed
2. Moves the content of the in-progress element from the Command Queue to the Result Pool
3. Copies Sahara Status and Error Status registers into the result pool
4. Writes `Clr_Error` in Command register and flag as FAILED if State field in Status register is 010 or 110 (otherwise set to PASSED)
5. Loads the next command into Sahara, if one exists (to keep Sahara loaded with two commands at a time if possible)
6. If in Interrupt mode, schedule tasklet (bottom half) process Completion Notification (that is, place it in the ready queue)
7. If polling, transfer control to process Completion Notification

27.2.2.12 Completion Notification

Using compiler switches, this runs as a tasklet or is invoked as a function as follows:

1. Invoke callback function, available in UCO, if in interrupt mode and callbacks are not suppressed by user
 - If the User is in Kernel Space, invoke callback
 - If the User is in User Space, signal UM Extension to invoke callback
2. Clean up memory, flags, and so on as needed
3. Unlock pages

27.2.2.13 Get Results

When a Get Results request is received (a request that does not involve Sahara hardware), the following are performed and the result is immediately returned to the user:

1. If no results are found for this user, return `no results found status`
2. If at least one result is found for the user, populate the user supplied result list in whatever order the results are found in the Result Pool (return the lesser of the max number of requests or number of results in pool)
3. If the status is PASSED (set by Poll/ISR process), check and return the following:
 - Failed if State field in Status register is 011. Also sends notification to Sahara Public Interface to reject all future calls to Sahara driver
 - Failed if SCC Fail bit in Status register is set
 - Specific descriptor error from Error Source field in the Error Status register, if the Error bit in the Status register is set
 - Failed if Error bit in Status register is set and the Error Source field in the Error Status register shows No Error
 - Passed otherwise
4. Clear result pool entry
5. Adjust number of outstanding requests

27.3 Driver Features

The SAHARA driver supports the following features:

- Hashing with MD5, SHA-1, SHA-224 and SHA-256 algorithms
- HMAC with the same algorithms as for hashing
- Symmetric cryptography support for AES, DES, and triple DES, in ECB, CBC, and CTR modes (though only AES is supported in CTR mode); ARC4 support is also provided
- CCM for AES
- Wrapped keys (hiding keys in the SCC), using the SCC key to encrypt or decrypt, HMAC functions, or CCM
- Generation of an arbitrary number of bytes of random data
- User mode and kernel mode; callbacks and non-callback non-blocking

27.4 Source Code Structure

[Table 27-2](#) lists the source files associated with the SAHARA driver that are available in the directory `<ltib_dir>/rpm/BUILD/linux/drivers/mxc/security/sahara2.`

Table 27-2. Sahara Source Files

File	Description
sah_driver_interface.c	Sahara low level driver
sah_hardware_interface.c	Provides an interface to the SAHARA hardware registers
sah_interrupt_handler.c	Sahara Interrupt Handler
sah_memory_mapper.c	Re-creates SAHARA Data structures in kernel memory such that they are suitable for DMA
sah_queue.c	Provides FIFO Queue implementation
sah_queue_manager.c	This file provides a Queue Manager implementation. The Queue Manager manages additions and removal from the queue and updates the status of queue entries. Also calls <code>sah_HW_*</code> functions to interact with the hardware.
sah_status_manager.c	Contains functions which processes the SAHARA status registers
sf_util.c	Security Functions component API - Utility functions
fsl_shw_auth.c	Contains the routines which do the combined encryption and authentication
fsl_shw_hash.c	Implements Cryptographic Hashing functions of the API
fsl_shw_hmac.c	Provides HMAC functions of the API
fsl_shw_rand.c	Generates random numbers
fsl_shw_sym.c	Provides Symmetric-Key encryption support for block cipher algorithms
fsl_shw_user.c	Implements user and platform capabilities functions
fsl_shw_wrap.c	Implements Key-Wrap (Black Key) functions
km_adaptor.c	Adaptor provides interface to driver for kernel user

Table 27-3 lists the header files associated with the SAHARA driver are found in the directory

`<ltib_dir>/rpm/BUILD/linux/drivers/mxc/security/sahara2/include.`

Table 27-3. Sahara Header Files

File	Description
fsl_shw.h	Sahara Definition of the Freescale Security Hardware API
fsl_platform.h	File to isolate code which might be platform-dependent
sahara.h	All of the defines used throughout user and kernel space
sah_driver_common.h	Provides types and defined values for use in the Driver Interface
sah_hardware_interface.h	Provides an interface to the SAHARA hardware registers
sah_interrupt_handler.h	Provides a hardware interrupt handling mechanism for device driver
sah_kernel.h	Provides definitions for items that user-space and kernel-space share
sah_memory_mapper.h	Re-creates SAHARA Data structures in kernel memory such that they are suitable for DMA
sah_queue_manager.h	This file provides a Queue Manager implementation. The Queue Manager manages additions and removal from the queue and updates the status of queue entries. It also calls <code>sah_HW_*</code> functions to interact with the hardware.
sah_status_manager.h	SAHARA Status Manager Types and Function Prototypes

Table 27-3. Sahara Header Files (continued)

File	Description
sf_util.h	Security Function Utility Functions
diagnostic.h	Macros for outputting kernel and user space diagnostics
adaptor.h	The Adaptor component provides an interface to the device driver

27.5 Menu Configuration Options

The following Linux kernel configurations are provided for this module:

- **CONFIG_MXC_SAHARA**—Configuration option for Sahara Hardware support. In the menuconfig this option is found under
MXC support drivers > MXC Security Drivers > SAHARA2 Security Hardware Support
- **CONFIG_MXC_SAHARA_USER_MODE**—The driver can be configured to provide an interface to user space (used by the library). This configuration switch is currently ignored, and the user space interface is currently always provided. In the menuconfig this option is found under
MXC support drivers > MXC Security Drivers > SAHARA2 Security Hardware Support
- **CONFIG_MXC_SAHARA_POLL_MODE**—The driver can be configured to poll the Sahara2 hardware device for end-of-operation status, or it can (by default) process an interrupt for end-of-operation. In the menuconfig this option is found under
MXC support drivers > MXC Security Drivers > SAHARA2 Security Hardware Support
- **CONFIG_MXC_SAHARA_POLL_MODE_TIMEOUT**—To avoid infinite polling, a time-out is provided. Should the time-out be reached, a fault is reported causing the Sahara to be reset. This time-out period is configurable. When poll mode is selected, the value for **CONFIG_MXC_SAHARA_POLL_MODE_TIMEOUT** can be modified. Poll mode works nearly the same as interrupt mode, that is, blocking mode returns the result of the descriptor chain (succeeded, erred, and so on); non-blocking mode queues results in a results pool and `fsl_shw_get_results()` retrieves them; callback mode (non-blocking mode only) the callback is made just before control is returned from the API call (in interrupt mode it is some time after).

27.6 Programming Interface

This driver implements all the methods that are required by the Linux serial API to interface with the Sahara driver. It implements and provides a set of control methods to the core Sahara driver present in Linux. Refer to the API document (included doxygen document) for more information on the methods implemented in the driver.

27.7 Interrupt Requirements

There is no interrupt requirement in this module.

Chapter 28

Security Drivers

The security drivers provide several APIs that facilitate access to various security features in the processor. The secure controller (SCC) consists of two modules, a secure RAM module and a secure monitor module. The SCC key encryption module (KEM) has a security feature for storing encrypted data in the on-chip RAM (Red data = unencrypted data, Black data = encrypted data), with a total size of 2 Kbytes. This module is needed in cases where data must be stored securely in external memory in encrypted form. This module can clear the secure RAM during intrusion.

The security design covers the following modules:

- Boot Security
- SCC (Secure RAM, Secure Monitor)
- Algorithm Integrity Checker
- Security Timer
- Key Encryption Module (KEM), Zeroization module

28.1 Hardware Overview

The platform has several different security blocks. The details of the individual blocks are described in the following sections.

28.1.1 Boot Security

During boot, the boot pins must be set to enable the processor to boot. The SCC module must be enabled by blowing specific fuses. By booting in this manner, the integrity of the data in the Flash (kernel image) can be assured. Any violation in the data integrity raises an alarm.

28.1.2 Secure RAM

Figure 28-1 shows the SCC-Secure RAM and its modules. Individual modules are described in the following sections.

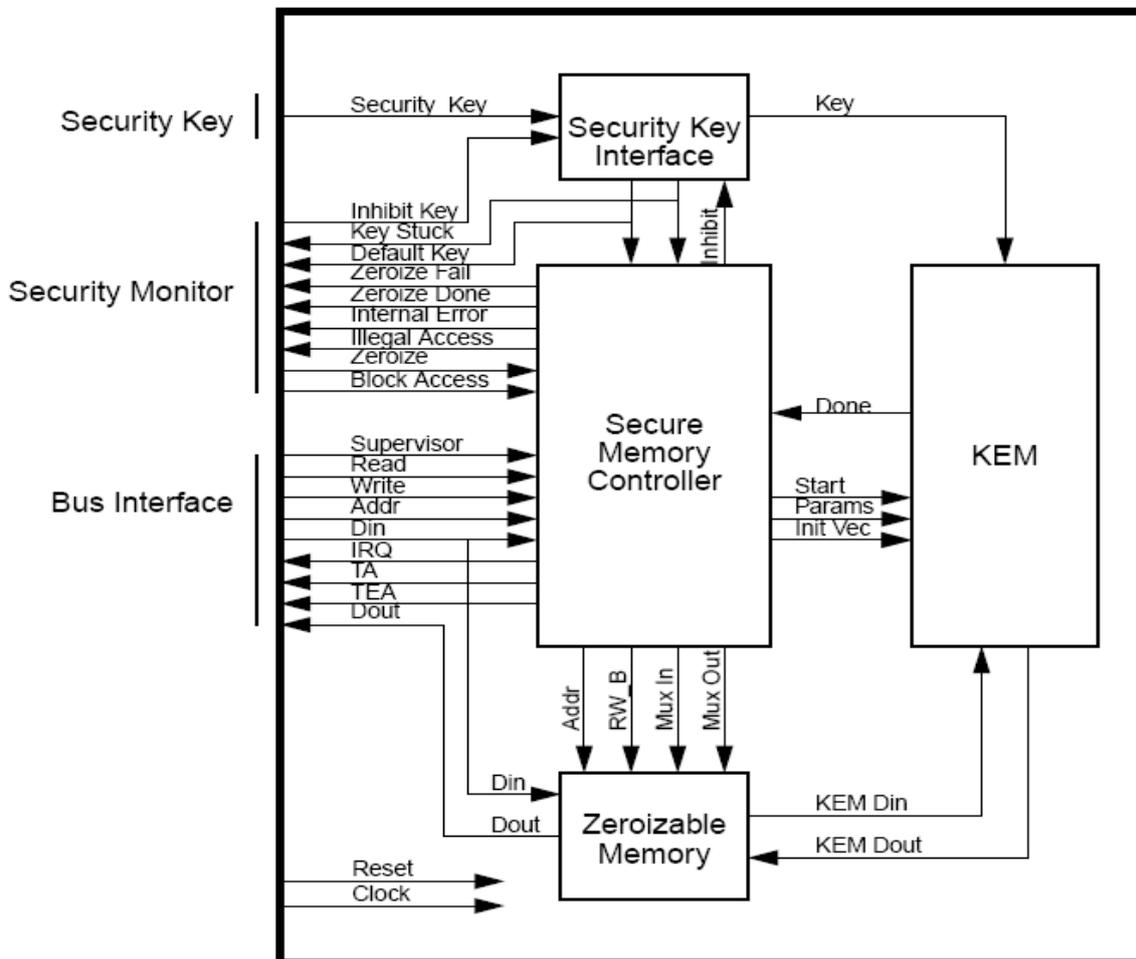


Figure 28-1. Secure RAM Block Diagram

28.1.3 KEM

The KEM uses the algorithm and a -bit key for encryption of data. The key is programmed during manufacture and is accessible only to the encryption module. It is not accessible on any bus external to the secure memory module. The data in the external RAM is stored in an encrypted format. The data is encrypted using algorithm so that it can be decoded only using the SCC module.

28.1.4 Zeroizable Memory

The memory module can be multiplexed in and out of the RAM to allow the memory controller to switch paths according to the Secure RAM state and the host read and write accesses. When zeroing sections of memory, only the memory controller has access. When encrypting or decrypting, only the KEM module

has access. When the Secure RAM is in the Idle state, the host can access the memory. The Zeroize Done signal is used to reset the encryption module and the memory controller. While the Zeroize Done signal is low, any attempted access by the host is ignored. When the Zeroize signal is asserted, or when the Zeroize Memory bit in the Interrupt Control register is set, not only is the Red and Black memory initialized, but most of the registers are also reset. The Red Start, Black Start, Length, Control, Error Status, Init Vector 0, and Init Vector 1 registers are cleared. The encryption engine is also reset. The Zeroization takes place whenever there is a security violation like external bus intrusion. The Red and Black memory area is usually cleared during system boot-up.

28.1.5 Security Key Interface Module

The Security Key Interface module uses a -bit encryption key. The physical structures for the encryption key resides elsewhere. The Secret Key Interface contains a key mux to select between the encryption key and the default key and test the logic to determine the validity of the encryption key. In the Secure state the encryption key is used. In the Non-Secure state, the default key prevents unauthorized access to SCC-encrypted data and is useful for test purposes.

28.1.6 Secure Memory Controller

The Secure Memory controller implements an internal data handler that moves data in and out of the KEM, a memory clear function, and all of the supervisor-accessible Control and Status registers.

28.1.7 Security Monitor

The Security Monitor (SMN) is a critical component of security assurance for the platform. It determines when and how Secure RAM resources are available to the system, and it also provides mechanisms for verifying software algorithm integrity. This block ensures that the system is running in such a manner as to provide protection for the sensitive data that is resident in the SCC. The Security Monitor consists of five main sub-blocks:

- Secure State Controller
- Security Policy
- Algorithm Integrity Checker (AIC)
- Security Timer
- Debug Detector

Figure 28-2 shows a block diagram of the SMN.

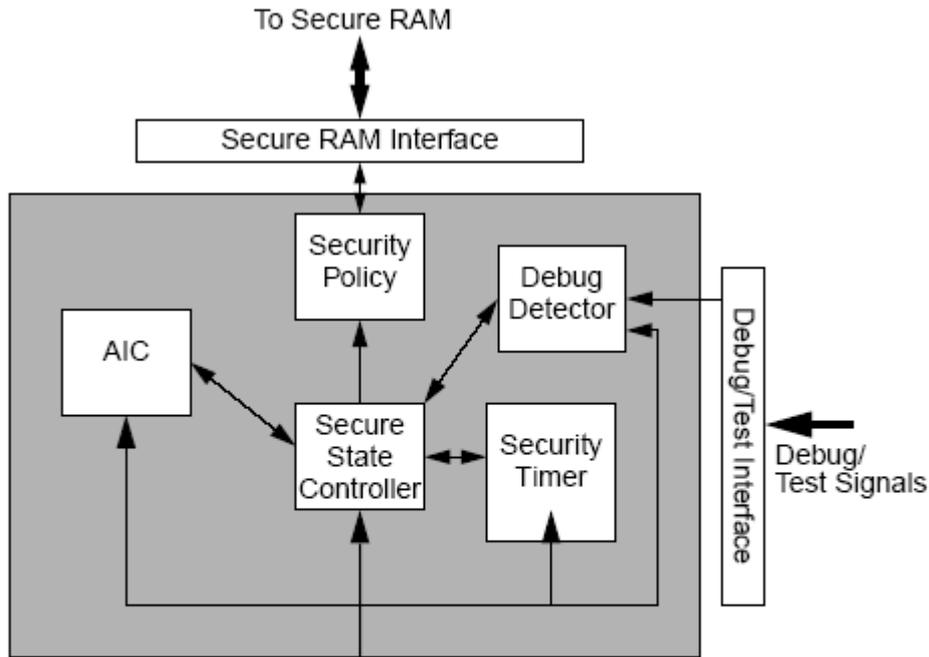


Figure 28-2. Security Monitor Block Diagram

28.1.8 Secure State Controller

The Secure State Controller, shown in Figure 28-3, is a state machine that controls the security states of the chip.

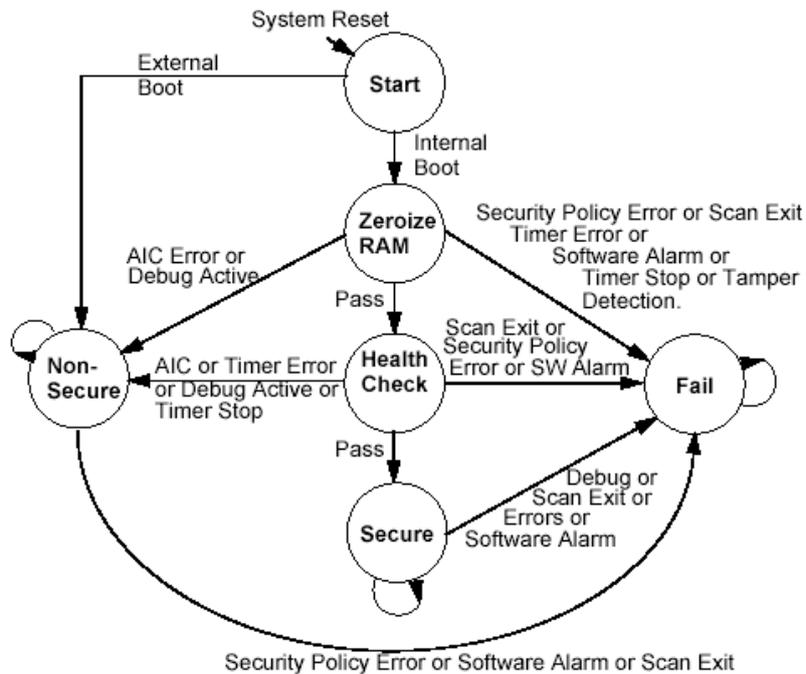


Figure 28-3. Secure State Controller State Diagram

28.1.9 Security Policy

The Security Policy block uses state information from the Secure State Controller along with inputs from the Secure RAM to determine what access to the Secure RAM is allowed based on the policy table. The policy table is available in the L3 specification document of the corresponding platform.

28.1.10 Algorithm Integrity Checker (AIC)

The Algorithm Integrity Checker (AIC) is used in conjunction with software to provide assurance that critical software (such as a software encryption algorithm) operates correctly. It is also an integral part of the power-up procedure as it must be used to achieve a secure state.

28.1.11 Secure Timer

The Secure Timer is a 32-bit programmable timer. It is used in conjunction with the Secure State Controller during power-up to ensure that the transition to the Secure state happens in the appropriate amount of time. After power-up, the timer can be used as a watchdog timer for any time-critical routines or algorithms. If the timer is allowed to expire, it generates an error.

28.1.12 Debug Detector

The debug detector monitors the various debug and test signals and informs the secure state controller of the status. The secure state controller receives an alert when debug modes, such as JTAG and scan are active. The debug detector status register can be read by the host processor to determine which debug signals are currently active. Refer to the SCC section in L3 specification document of the corresponding platform for more information on the SCC-Debug Detector.

28.2 Software Operation

Besides the hardware security modules, there is optional, specialized software that helps to deliver security.

28.2.1 SCC Common Software Operations

The SCC driver is only available to other kernel modules. That is, there is no node file in `/dev`. Thus, it is not possible for a user-mode program to access the driver, and it is not possible for a user program to access the device directly.

The driver does not allow storage of data in either the Red or Black memories. Any decrypted information is returned to the user. If the user wants to use the information at a later point, the encrypted form must again be passed to the driver, and it must be decrypted again.

The SCC encrypts and decrypts using with an internally stored key. When the SCC is in Secure mode, it uses its secret, unique-per-chip key. When it is in Non-Secure mode, it uses a default key. This ensures that secrets stay secret if the SCC is not in Secure mode.

Security Drivers

Not all functions are implemented, such as interfaces to the ASC/AIC components and the timer functions. These and other features must be accessed through `scc_read_register()` and `scc_write_register()`, using the `#define` values provided.

28.3 Driver Features

The SCC driver supports the following features:

- Checks whether the SCC fuse is blown or not (SCC Disabled/Enabled)
- Configures the Red and Black memory area addresses and number of blocks to be encrypted/decrypted
- Loads the data to be encrypted
- Loads the data to be decrypted
- Starts the Cipherring mechanism
- Reports back the status of the KEM module
- Zeros blocks in the Red/Black memory area
- Checks for the boot type: internal or external
- Raises a software alarm
- Reports back the status of the Zeroize module
- Configures the AIC start and end algorithm sequence number
- Checks the sequence of the algorithm
- Finds the next sequence number given the current sequence number
- Configures the Security Timer
- Reports back the status of the Security Timer module

28.4 Source Code Structure

This section contains the various files that implement the Security modules. [Table 28-1](#) lists the headers and source files associated with the security driver.

- The C source files are available in the directory, `<ltib_dir>/rpm/BUILD/linux/drivers/mxc/security` directory.
- Header files are available in the directory, `<ltib_dir>/rpm/BUILD/linux/include/linux`.

Table 28-1. SCCDriver Files

File	Description
Makefile	Used to compile, link and generate the final binary image

28.5 Menu Configuration Options

The following Linux kernel configurations are provided for this module. In order to get to the security configuration, use the command `./ltib -c` when located in the `<ltib dir>`. In the screen select **Configure kernel**, exit and a new screen appears.

Chapter 29

Fast Ethernet Controller (FEC) Driver

The Fast Ethernet Controller (FEC) driver performs the full set of IEEE 802.3/Ethernet CSMA/CD media access control and channel interface functions. The FEC requires an external interface adapter and transceiver function to complete the interface to the Ethernet media. It supports half or full-duplex operation on 10 Mbps or 100 Mbps related Ethernet networks.

The FEC driver supports the following features:

- Full/Half duplex operation
- Link status change detect
- Auto-negotiation (determines the network speed and full or half-duplex operation)
- Transmit features such as automatic retransmission on collision and CRC generation
- Obtaining statistics from the device such as transmit collisions

The network adapter can be accessed through the `ifconfig` command with interface name `ethx`. The driver auto-probes the external adaptor (PHY device).

29.1 Hardware Operation

The FEC is an Ethernet controller that interfaces the system to the LAN network. The FEC supports different standard MAC-PHY (physical) interfaces for connection to an external Ethernet transceiver. The FEC supports the 10/100 Mbps MII and the 10 Mbps-only 7-wire serial network interface (SNI), which uses a subset of the MII pins.

A brief overview of the device functionality is provided here. For details see the FEC chapter of the *i.MX53 Multimedia Applications Processor Reference Manual*.

In MII mode, there are 18 signals defined by the IEEE 802.3 standard and supported by the EMAC. SNI mode uses a subset of the 18 signals. These signals are listed in [Table 29-1](#).

Table 29-1. Pin Usage in MII and SNI Modes

Direction	EMAC Pin Name	MII Usage	SNI Usage	RMII Usage
In/Out	FEC_MDIO	Management Data Input/Output	General I/O	Management Data Input/Output
Out	FEC_MDC	Management Data Clock	General output	Management Data Clock
Out	FEC_TXD[0]	Data out, bit 0	Data out	Data out, bit 0
Out	FEC_TXD[1]	Data out, bit 1	General output	Data out, bit 1
Out	FEC_TXD[2]	Data out, bit 2	General output	Not Used
Out	FEC_TXD[3]	Data out, bit 3	General output	Not Used
Out	FEC_TX_EN	Transmit Enable	Transmit Enable	Transmit Enable
Out	FEC_TX_ER	Transmit Error	General output	Not Used
In	FEC_CRIS	Carrier Sense	Not Used	Not Used

Table 29-1. Pin Usage in MII and SNI Modes (continued)

Direction	EMAC Pin Name	MII Usage	SNI Usage	RMII Usage
In	FEC_COL	Collision	Collision	Not Used
In	FEC_TX_CLK	Transmit Clock	Transmit Clock	Synchronous clock reference (REF_CLK)
In	FEC_RX_ER	Receive Error	General input	Receive Error
In	FEC_RX_CLK	Receive Clock	Receive Clock	Not Used
In	FEC_RX_DV	Receive Data Valid	Receive Data Valid	Not Used
In	FEC_RXD[0]	Data in, bit 0	Data in	Data in, bit 0
In	FEC_RXD[1]	Data in, bit 1	General input	Data in, bit 1
In	FEC_RXD[2]	Data in, bit 2	General input	Not Used
In	FEC_RXD[3]	Data in, bit 3	General input	Not Used

The MII management interface consists of two pins, FEC_MDIO and FEC_MDC. The FEC hardware operation can be divided in the following parts. For detailed information consult the *i.MX53 Multimedia Applications Processor Reference Manual*.

- **Transmission**—The Ethernet transmitter is designed to work with almost no intervention from software. Once ECR[ETHER_EN] is asserted and data appears in the transmit FIFO, the Ethernet MAC is able to transmit onto the network. When the transmit FIFO fills to the watermark (defined by the TFWR), the MAC transmit logic asserts FEC_TX_EN and starts transmitting the preamble (PA) sequence, the start frame delimiter (SFD), and then the frame information from the FIFO. However, the controller defers the transmission if the network is busy (FEC_CRD asserts).
Before transmitting, the controller waits for carrier sense to become inactive, then determines if carrier sense stays inactive for 60 bit times. If the transmission begins after waiting an additional 36 bit times (96 bit times after carrier sense originally became inactive). Both buffer (TXB) and frame (TXF) interrupts may be generated as determined by the settings in the EIMR.
- **Reception**—The FEC receiver is designed to work with almost no intervention from the host and can perform address recognition, CRC checking, short frame checking, and maximum frame length checking. When the driver enables the FEC receiver by asserting ECR[ETHER_EN], it immediately starts processing receive frames. When FEC_RX_DV asserts, the receiver checks for a valid PA/SFD header. If the PA/SFD is valid, it is stripped and the frame is processed by the receiver. If a valid PA/SFD is not found, the frame is ignored. In MII mode, the receiver checks for at least one byte matching the SFD. Zero or more PA bytes may occur, but if a 00 bit sequence is detected prior to the SFD byte, the frame is ignored.

After the first six bytes of the frame have been received, the FEC performs address recognition on the frame. During reception, the Ethernet controller checks for various error conditions and once the entire frame is written into the FIFO, a 32-bit frame status word is written into the FIFO. This status word contains the M, BC, MC, LG, NO, CR, OV, and TR status bits, and the frame length. Receive Buffer (RXB) and Frame Interrupts (RXF) may be generated if enabled by the EIMR register. When the receive frame is complete, the FEC sets the L bit in the RxBD, writes the other frame status bits into the RxBD, and clears the E bit. The Ethernet controller next generates a

maskable interrupt (RXF bit in EIR, maskable by RXF bit in EIMR), indicating that a frame has been received and is in memory. The Ethernet controller then waits for a new frame.

- **Interrupt management**—When an event occurs that sets a bit in the EIR, an interrupt is generated if the corresponding bit in the interrupt mask register (EIMR) is also set. The bit in the EIR is cleared if a one is written to that bit position; writing zero has no effect. This register is cleared upon hardware reset. These interrupts can be divided into operational interrupts, transceiver/network error interrupts, and internal error interrupts. Interrupts which may occur in normal operation are GRA, TXF, TXB, RXF, RXB. Interrupts resulting from errors/problems detected in the network or transceiver are HBERR, BABR, BAPT, LC, and RL. Interrupts resulting from internal errors are HBERR and UN. Some of the error interrupts are independently counted in the MIB block counters. Software may choose to mask off these interrupts as these errors are visible to network management through the MIB counters.
- **PHY management**—phylib was used to manage all the FEC phy related operation such as phy discovery, link status, and state machine. MDIO bus will be created in FEC driver and registered into the system. You can refer to Documentation/networking/phy.txt under linux source directory for more information.

29.2 Software Operation

The FEC driver supports the following functions:

- **Module initialization**—Initializes the module with the device specific structure
- **Rx/Tx transmission**
- **Interrupt servicing routine**
- **PHY management**
- **FEC management** such init/start/stop

29.3 Source Code Structure

Table 29-2 shows the source files available in the

<ltib_dir>/rpm/BUILD/linux/drivers/net directory.

Table 29-2. FEC Driver Files

File	Description
fec.h	Header file defining registers
fec.c	Linux driver for Ethernet LAN controller

For more information about the generic Linux driver, see the

<ltib_dir>/rpm/BUILD/linux/drivers/net/fec.c source file.

29.4 Menu Configuration Options

The following Linux kernel configuration option is provided for this module. To get to this option, use the `./ltib -c` command when located in the <ltib_dir>. On the screen displayed, select **Configure the Kernel** and exit. When the next screen appears, select the following option to enable this module:

- CONFIG_FEC—Provided for this module. This option is available under Device Drivers > Network device support > Ethernet (10 or 100Mbit) > FEC Ethernet controller.

To mount NFS-rootfs through FEC, disable the other Network config in the menuconfig if need.

29.5 Programming Interface

Table 29-2 lists the source files for the FEC driver. The following section shows the modifications that were required to the original Ethernet driver source for porting it to the i.MX device.

29.5.1 Device-Specific Defines

Device-specific defines are added to the header file (`fec.h`) and they provide common board configuration options.

`fec.h` defines the struct for the register access and the struct for the buffer descriptor. For example,

```

/*
 *      Define the buffer descriptor structure.
 */
struct bufdesc {
    unsigned short   cbd_datlen;           /* Data length */
    unsigned short   cbd_sc;              /* Control and status info */
    unsigned long    cbd_bufaddr;        /* Buffer address */
};
/*
 *      Define the register access structure.
 */
#define FEC_IEVENT          0x004 /* Interrupt event reg */
#define FEC_IMASK          0x008 /* Interrupt mask reg */
#define FEC_R_DES_ACTIVE   0x010 /* Receive descriptor reg */
#define FEC_X_DES_ACTIVE   0x014 /* Transmit descriptor reg */
#define FEC_ECNTL         0x024 /* Ethernet control reg */
#define FEC_MII_DATA       0x040 /* MII manage frame reg */
#define FEC_MII_SPEED      0x044 /* MII speed control reg */
#define FEC_MIB_CTRLSTAT   0x064 /* MIB control/status reg */
#define FEC_R_CNTRL        0x084 /* Receive control reg */
#define FEC_X_CNTRL        0x0c4 /* Transmit Control reg */
#define FEC_ADDR_LOW       0x0e4 /* Low 32bits MAC address */
#define FEC_ADDR_HIGH      0x0e8 /* High 16bits MAC address */
#define FEC_OPD            0x0ec /* Opcode + Pause duration */
#define FEC_HASH_TABLE_HIGH 0x118 /* High 32bits hash table */
#define FEC_HASH_TABLE_LOW  0x11c /* Low 32bits hash table */
#define FEC_GRP_HASH_TABLE_HIGH 0x120 /* High 32bits hash table */
#define FEC_GRP_HASH_TABLE_LOW 0x124 /* Low 32bits hash table */
#define FEC_X_WMRK         0x144 /* FIFO transmit water mark */
#define FEC_R_BOUND        0x14c /* FIFO receive bound reg */
#define FEC_R_FSTART       0x150 /* FIFO receive start reg */
#define FEC_R_DES_START    0x180 /* Receive descriptor ring */
#define FEC_X_DES_START    0x184 /* Transmit descriptor ring */
#define FEC_R_BUFF_SIZE    0x188 /* Maximum receive buff size */
#define FEC_MIIGSK_CFGFR   0x300 /* MIIGSK config register */
#define FEC_MIIGSK_ENR     0x308 /* MIIGSK enable register */

```

29.5.2 Getting a MAC Address

The MAC address can be set through bootloader such as u-boot. FEC driver will use it to configure the MAC address for network devices.

Chapter 30

Inter-IC (I²C) Driver

I²C is a two-wire, bidirectional serial bus that provides a simple, efficient method of data exchange, minimizing the interconnection between devices. The I²C driver for Linux has two parts:

- I²C bus driver—low level interface that is used to talk to the I²C bus
- I²C chip driver—acts as an interface between other device drivers and the I²C bus driver

30.1 I²C Bus Driver Overview

The I²C bus driver is invoked only by the I²C chip driver and is not exposed to the user space. The standard Linux kernel contains a core I²C module that is used by the chip driver to access the I²C bus driver to transfer data over the I²C bus. The chip driver uses a standard kernel space API that is provided in the Linux kernel to access the core I²C module. The standard I²C kernel functions are documented in the files available under `Documentation/i2c` in the kernel source tree. This bus driver supports the following features:

- Compatible with the I²C bus standard
- Bit rates up to 400 Kbps
- Starts and stops signal generation/detection
- Acknowledge bit generation/detection
- Interrupt-driven, byte-by-byte data transfer
- Standard I²C master mode

30.2 I²C Device Driver Overview

The I²C device driver implements all the Linux I²C data structures that are required to communicate with the I²C bus driver. It exposes a custom kernel space API to the other device drivers to transfer data to the device that is connected to the I²C bus. Internally, these API functions use the standard I²C kernel space API to call the I²C core module. The I²C core module looks up the I²C bus driver and calls the appropriate function in the I²C bus driver to transfer data. This driver provides the following functions to other device drivers:

- Read function to read the device registers
- Write function to write to the device registers

The camera driver uses the APIs provided by this driver to interact with the camera.

30.3 Hardware Operation

The I²C module provides the functionality of a standard I²C master and slave. It is designed to be compatible with the standard Philips I²C bus protocol. The module supports up to 64 different clock frequencies that can be programmed by setting a value to the Frequency Divider Register (IFDR). It also generates an interrupt when one of the following occurs:

- One byte transfer is completed

- Address is received that matches its own specific address in slave-receive mode
- Arbitration is lost

30.4 Software Operation

The I²C driver for Linux has two parts: an I²C bus driver and an I²C chip driver.

30.4.1 I²C Bus Driver Software Operation

The I²C bus driver is described by a structure called `i2c_adapter`. The most important field in this structure is `struct i2c_algorithm *algo`. This field is a pointer to the `i2c_algorithm` structure that describes how data is transferred over the I²C bus. The algorithm structure contains a pointer to a function that is called whenever the I²C chip driver wants to communicate with an I²C device.

During startup, the I²C bus adapter is registered with the I²C core when the driver is loaded. Certain architectures have more than one I²C module. If so, the driver registers separate `i2c_adapter` structures for each I²C module with the I²C core. These adapters are unregistered (removed) when the driver is unloaded.

After transmitting each packet, the I²C bus driver waits for an interrupt indicating the end of a data transmission before transmitting the next byte. It times out and returns an error if the transfer complete signal is not received. Because the I²C bus driver uses wait queues for its operation, other device drivers should be careful not to call the I²C API methods from an interrupt mode.

30.4.2 I²C Device Driver Software Operation

The I²C driver controls an individual I²C device on the I²C bus. A structure, `i2c_driver`, describes the I²C chip driver. The fields of interest in this structure are `flags` and `attach_adapter`. The `flags` field is set to a value `I2C_DF_NOTIFY` so that the chip driver can be notified of any new I²C devices, after the driver is loaded. The `attach_adapter` callback function is called whenever a new I²C bus driver is loaded in the system. When the I²C bus driver is loaded, this driver stores the `i2c_adapter` structure associated with this bus driver so that it can use the appropriate methods to transfer data.

30.5 Driver Features

The I²C driver supports the following features:

- I²C communication protocol
- I²C master mode of operation

NOTE

The I²C driver do not support the I²C slave mode of operation.

30.6 Source Code Structure

Table 30-1 shows the I²C bus driver source files available in the directory:

`<ltib_dir>/rpm/BUILD/linux/drivers/i2c/busses.`

Table 30-1. I²C Bus Driver Files

File	Description
i2c-imx.c	I ² C bus driver source file

30.7 Menu Configuration Options

The following Linux kernel configuration option is provided for this module. To get to this option, use the `./ltib -c` command when located in the `<ltib_dir>`. On the screen displayed, select **Configure the Kernel** and exit. When the next screen appears, select the following options to enable this module:

Device Drivers > I2C support > I2C Hardware Bus support > IMX I2C interface.

30.8 Programming Interface

The I²C device driver can use the standard SMBus interface to read and write the registers of the device connected to the I²C bus. For more information, see `<ltib_dir>/rpm/BUILD/linux/include/linux/i2c.h`.

30.9 Interrupt Requirements

The I²C module generates many kinds of interrupts. The highest interrupt rate is associated with the transfer complete interrupt as shown in Table 30-2.

Table 30-2. I²C Interrupt Requirements

Parameter	Equation	Typical	Best Case
Rate	Transfer Bit Rate/8	25,000/sec	50,000/sec
Latency	8/Transfer Bit Rate	40 μ s	20 μ s

The typical value of the transfer bit-rate is 200 Kbps. The best case values are based on a baud rate of 400 Kbps (the maximum supported by the I²C interface).

Chapter 31

Configurable Serial Peripheral Interface (CSPI) Driver

The CSPI driver implements a standard Linux driver interface to the CSPI controllers. It supports the following features:

- Interrupt- and SDMA-driven transmit/receive of bytes
- Multiple master controller interface
- Multiple slaves select
- Multi-client requests

31.1 Hardware Operation

CSPI is used for fast data communication with fewer software interrupts than conventional serial communications. Each CSPI is equipped with a data FIFO and is a master/slave configurable serial peripheral interface module, allowing the processor to interface with external SPI master or slave devices.

The primary features of the CSPI includes:

- Master/slave-configurable
- Two chip selects allowing a maximum of four different slaves each for master mode operation
- Up to 32-bit programmable data transfer
- 8×32 -bit FIFO for both transmit and receive data
- Configurable polarity and phase of the Chip Select (SS) and SPI Clock (SCLK)

31.2 Software Operation

The following sections describe the CSPI software operation.

31.2.1 SPI Sub-System in Linux

The CSPI driver layer is located between the client layer (PMIC and SPI Flash are examples of clients) and the hardware access layer. [Figure 31-1](#) shows the block diagram for SPI subsystem in Linux.

The SPI requests go into I/O queues. Requests for a given SPI device are executed in FIFO order, and complete asynchronously through completion callbacks. There are also some simple synchronous

Configurable Serial Peripheral Interface (CSPI) Driver

wrappers for those calls, including ones for common transaction types like writing a command and then reading its response.

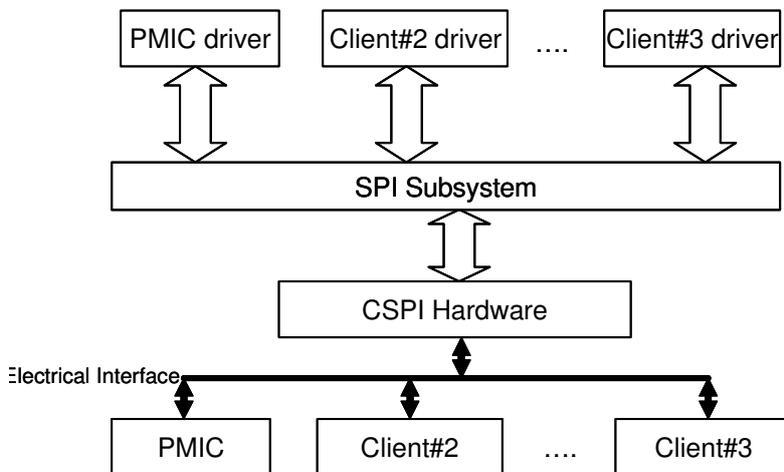


Figure 31-1. SPI Subsystem

All SPI clients must have a protocol driver associated with them and they must all be sharing the same controller driver. Only the controller driver can interact with the underlying SPI hardware module.

Figure 31-2 shows how the different SPI drivers are layered in the SPI subsystem.

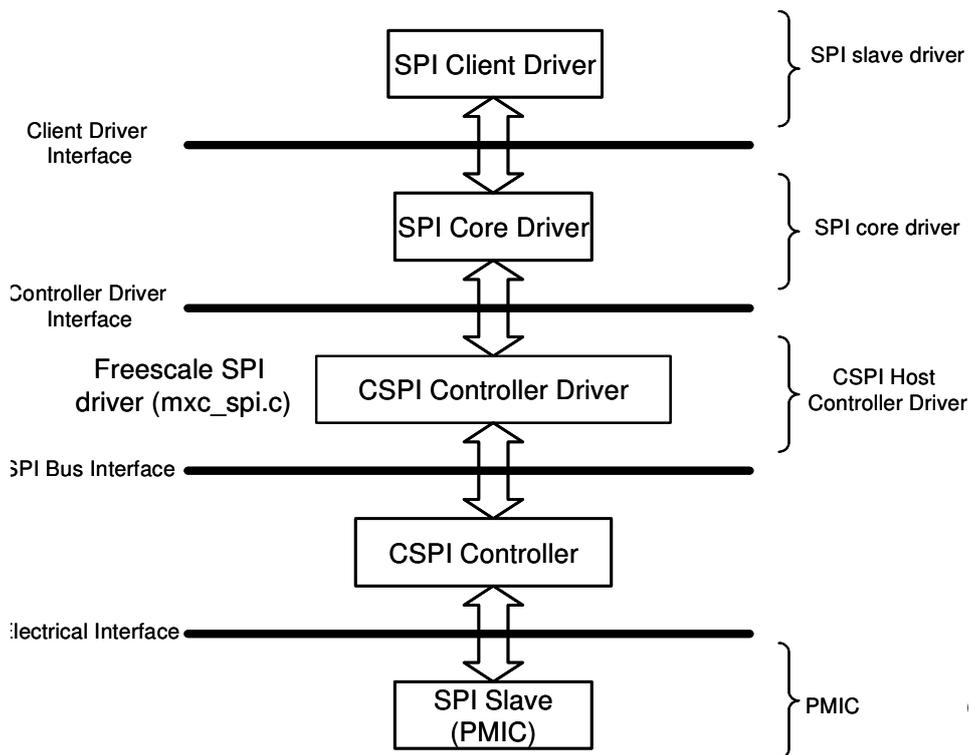


Figure 31-2. Layering of SPI Drivers in SPI Subsystem

31.2.2 Software Limitations

The CSPI driver limitations are as follows:

- Does not currently have SPI slave logic implementation
- Does not support a single client connected to multiple masters
- Does not currently implement the user space interface with the help of the device node entry but supports `sysfs` interface

31.2.3 Standard Operations

The CSPI driver is responsible for implementing standard entry points for init, exit, chip select and transfer. The driver implements the following functions:

- Init function `mxc_spi_init()`—Registers the `device_driver` structure.
- Probe function `mxc_spi_probe()`—Performs initialization and registration of the SPI device specific structure with SPI core driver. The driver probes for memory and IRQ resources. Configures the IOMUX to enable CSPI I/O pins, requests for IRQ and resets the hardware.
- Chip select function `mxc_spi_chipselect()`—Configures the hardware CSPI for the current SPI device. Sets the word size, transfer mode, data rate for this device.
- SPI transfer function `mxc_spi_transfer()`—Handles data transfers operations.
- SPI setup function `mxc_spi_setup()`—Initializes the current SPI device.
- SPI driver ISR `mxc_spi_isr()`—Called when the data transfer operation is completed and an interrupt is generated.

31.2.4 CSPI Synchronous Operation

Figure 31-3 shows how the CSPI provides synchronous read/write operations.

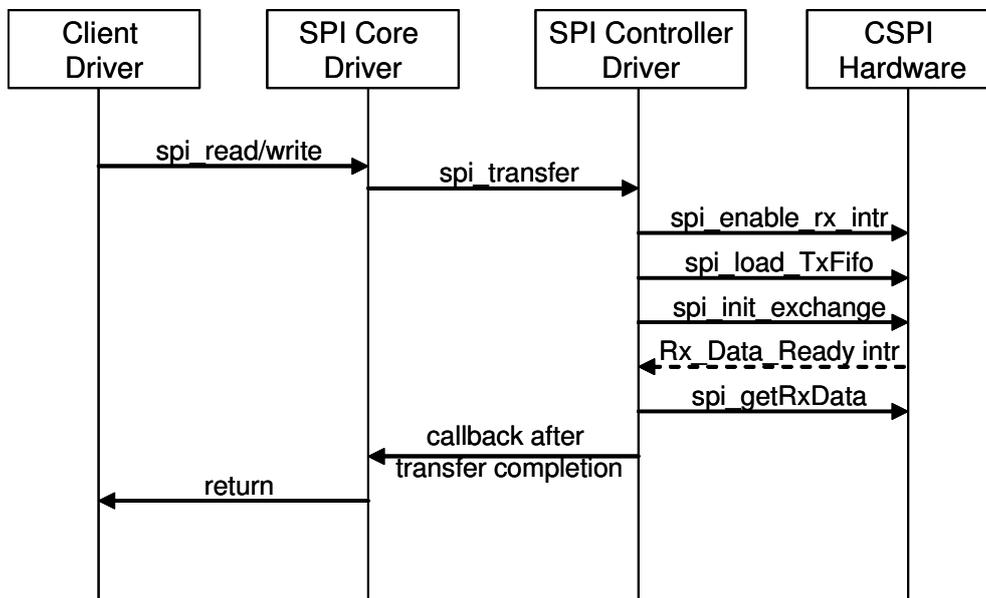


Figure 31-3. CSPI Synchronous Operation

31.3 Driver Features

The CSPI module supports the following features:

- Implements each of the functions required by a CSPI module to interface to Linux
- Multiple SPI master controllers
- Multi-client synchronous requests

31.4 Source Code Structure

Table 31-1 shows the source files available in the devices directory:

<ltib_dir>/rpm/BUILD/linux/drivers/spi/

Table 31-1. CSPI Driver Files

File	Description
mxc_spi.c	SPI Master Controller driver

31.5 Menu Configuration Options

The following Linux kernel configuration options are provided for this module. To get to these options, use the `./ltib -c` command when located in the <ltib_dir>. On the screen displayed, select **Configure the Kernel** and exit. When the next screen appears, select the following options to enable this module:

- CONFIG_SPI—Build support for the SPI core. In menuconfig, this option is available under

Device Drivers > SPI Support.

- `CONFIG_BITBANG`—Library code that is automatically selected by drivers that need it. `SPI_MXC` selects it. In menuconfig, this option is available under Device Drivers > SPI Support > Utilities for Bitbanging SPI masters.
- `CONFIG_SPI_MXC`—Implements the SPI master mode for MXC CSPI. In menuconfig, this option is available under Device Drivers > SPI Support > MXC CSPI controller as SPI Master.
- `CONFIG_SPI_MXC_SELECTn`—Selects the CSPI hardware modules into the build (where $n = 1$ or 2). In menuconfig, this option is available under Device Drivers > SPI Support > CSPI n .
- `CONFIG_SPI_MXC_TEST_LOOPBACK`—To select the enable testing of CSPIs in loop back mode. In menuconfig, this option is available under Device Drivers > SPI Support > LOOPBACK Testing of CSPIs.
By default this is disabled as it is intended to use only for testing purposes.

31.6 Programming Interface

This driver implements all the functions that are required by the SPI core to interface with the CSPI hardware. For more information, see the API document generated by Doxygen (in the doxygen folder of the documentation package).

31.7 Interrupt Requirements

The SPI interface generates interrupts. CSPI interrupt requirements are listed in [Table 31-2](#).

Table 31-2. CSPI Interrupt Requirements

Parameter	Equation	Typical	Worst Case
BaudRate/ Transfer Length	$(\text{BaudRate}/(\text{TransferLength})) * (1/\text{Rxtl})$	31250	1500000

The typical values are based on a baud rate of 1 Mbps with a receiver trigger level (Rxtl) of 1 and a 32-bit transfer length. The worst-case is based on a baud rate of 12 Mbps (max supported by the SPI interface) with a 8-bits transfer length.

Chapter 32

Secure Real Time Clock (SRTC) Driver

The Secure Real Time Clock (SRTC) module is used to keep the time and date. It provides a certifiable time to the user and can raise an alarm if tampering with counters is detected. The SRTC is composed of two sub-modules: Low power domain (LP) and High power domain (HP). The SRTC driver only supports the LP domain with low security mode.

32.1 Hardware Operation

The SRTC is a real time clock with enhanced security capabilities. It provides an accurate, constant time, regardless of the main system power state and without the need to use an external on-board time source, such as an external RTC. The SRTC can wake up the system when a pre-set alarm is reached.

32.2 Software Operation

The following sections describe the software operation of the SRTC driver.

32.2.1 IOCTL

The SRTC driver complies with the Linux RTC driver model. See the Linux documentation in `<ltib_dir>/rpm/BUILD/linux/Documentation/rtc.txt` for information on the RTC API.

Besides the initialization function, the SRTC driver provides IOCTL functions to set up the RTC timers and alarm functions. The following RTC IOCTLs are implemented by the SRTC driver:

- `RTC_RD_TIME`
- `RTC_SET_TIME`
- `RTC_AIE_ON`
- `RTC_AIE_OFF`
- `RTC_ALM_READ`
- `RTC_ALM_SET`

In addition, the following IOCTLs were added to allow user space application such as Digital Rights Management (DRM) to track changes in the time, which is user settable. The DRM application needs a way to track how much the time changed by so that it can manage its own secure clock = SRTC time counter + `secureclk_offset`. The `secureclk_offset` should be calculated by the DRM application based on changes to the SRTC time counter.

- `RTC_READ_TIME_47BIT`: allows a read of the 47-bit LP time counter on SRTC
- `RTC_WAIT_TIME_SET`: allows user thread to block until 47-bit LP time counter is set. At which point, the user thread is woken up and is provided the SRTC offset (which is the difference between the new and old LP counter)

The DRM process, which is not part of the BSP and is to be implemented by the device manufacturer, must be loaded during bootup before the user has a chance to change the time. This ensures that any time change

by the user is not missed by the DRM process. While the device is powered off, the SRTC time counter will continue to tick, drawing power from the coin cell. At bootup, the DRM process should first read the 47 bit SRTC time count to account for the time that has elapsed since poweroff. Any detection of clock rollback should invalidate the DRM clock. Given that no rollback is detected, the DRM should proceed to call the `RTC_WAIT_TIME_SET` ioctl to catch any future changes in time. Any user changes to time before the DRM process calls this ioctl are missed, which compromises the integrity of the DRM secure clock. Therefore, it is essential that the DRM process is able to call this ioctl before the user is able to change the time. The priority of the DRM process should also be set to a highest possible value to ensure that it is awakened upon the time change and gets a chance to process the event. These system integration tasks are left up to the device manufacturer to implement.

The driver information can be access by the proc file system. For example,

```
root@freescale /unit_tests$ cat /proc/driver/rtc
rtc_time      : 12:48:29
rtc_date      : 2009-08-07
alarm_time    : 14:41:16
alarm_date    : 1970-01-13
alarm_IRQ     : no
alarm_pending : no
24hr         : yes
```

32.2.2 Keep Alive in the Power Off State

To keep preserve the time when the device is in the power off state, the SRTC clock source should be set to CKIL and the voltage input, `NVCC_SRTC_POW`, should remain active. Usually these signals are connected to the PMIC and software can configure the PMIC registers to enable the SRTC clock source and power supply. Ordinarily, when the main battery is removed and the device is in power off state, a coin-cell battery is used as a backup power supply. To avoid SRTC time loss, the voltage of the coin-cell battery should be sufficient to power the SRTC. If the coin-cell battery is chargeable, it is recommend to automatically enable the coin-cell charger so that the SRTC is properly powered.

32.3 Driver Features

The SRTC driver includes the following features:

- Implements all the functions required by Linux to provide the real time clock and alarm interrupt
- Reserves time in power off state
- Alarm wakes up the system from low power modes

32.4 Source Code Structure

The RTC module is implemented in the following directory:

```
<ltib_dir>/rpm/BUILD/linux/drivers/rtc
```

[Table 32-1](#) shows the RTC module files.

Table 32-1. RTC Driver Files

File	Description
rtc-mxc_v2.c	SRTC driver implementation file

The source file for the SRTC specifies the SRTC function implementations.

32.5 Menu Configuration Options

To get to the SRTC driver, use the command `./ltib -c` when located in the `<ltib dir>`. On the screen displayed, select **Configure the kernel** and exit. When the next screen appears select the following options to enable the SRTC driver:

- Device Drivers > Real Time Clock > Freescale MXC Secure Real Time Clock

Chapter 33

Watchdog (WDOG) Driver

The Watchdog Timer module protects against system failures by providing an escape from unexpected hang or infinite loop situations or programming errors. Some platforms may have two WDOG modules with one of them having interrupt capability.

33.1 Hardware Operation

Once the WDOG timer is activated, it must be serviced by software on a periodic basis. If servicing does not take place in time, the WDOG times out. Upon a time-out, the WDOG either asserts the `wdog_b` signal or a `wdog_rst_b` system reset signal, depending on software configuration. The watchdog module cannot be deactivated once it is activated.

33.2 Software Operation

The Linux OS has a standard WDOG interface that allows support of a WDOG driver for a specific platform. WDOG can be suspended/resumed in STOP/DOZE and WAIT modes independently. Since some bits of the WDOG registers are only one-time programmable after booting, ensure these registers are written correctly.

33.3 Generic WDOG Driver

The generic WDOG driver is implemented in the `<ltib_dir>/rpm/BUILD/linux/drivers/watchdog/mxc_wdt.c` file. It provides functions for various IOCTLs and read/write calls from the user level program to control the WDOG.

33.3.1 Driver Features

This WDOG implementation includes the following features:

- Generates the reset signal if it is enabled but not serviced within a predefined timeout value (defined in milliseconds in one of the WDOG source files)
- Does not generate the reset signal if it is serviced within a predefined timeout value
- Provides IOCTL/read/write required by the standard WDOG subsystem

33.3.2 Menu Configuration Options

The following Linux kernel configuration option is provided for this module. To get to this option, use the `./ltib -c` command when located in the `<ltib_dir>`. On the screen displayed, select **Configure the Kernel** and exit. When the next screen appears, select the following option to enable this module:

- `CONFIG_MXC_WATCHDOG`—Enables Watchdog timer module. This option is available under Device Drivers > Watchdog Timer Support > MXC watchdog.

33.3.3 Source Code Structure

Table 33-1 shows the source files for WDOG drivers that are in the following directory:

<ltib_dir>/rpm/BUILD/linux/drivers/watchdog.

Table 33-1. WDOG Driver Files

File	Description
mxc_wdt.c	WDOG function implementations
mxc_wdt.h	Header file for WDOG implementation

Watchdog system reset function is located under

<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc/system.c

33.3.4 Programming Interface

The following IOCTLs are supported in the WDOG driver:

- WDIOC_GETSUPPORT
- WDIOC_GETSTATUS
- WDIOC_GETBOOTSTATUS
- WDIOC_KEEPLIVE
- WDIOC_SETTIMEOUT
- WDIOC_GETTIMEOUT

For detailed descriptions about these IOCTLs, see

<ltib_dir>/rpm/BUILD/linux/Documentation/watchdog.

Chapter 34

Touch Screen (P1003) Driver

34.1 Driver Overview

P1003 is a touch screen driver based on ILITEK touch screen controller, also named as HanStar P1003 touch screen. It's a multipointer (up to 2 point) capacitive touch screen. It is use 3.3V power supply and I2C serial interface.

34.2 Hardware Operation

For the information on hardware operations, refer to P1003/ILITEK datasheet and respective application processors specification.

34.3 Software Operation

This driver is a standard Linux input device driver. For information on software operation, refer to the document in the kernel source: `Documents/input/input.txt` and `Documents/input/input-programing.txt`.

34.4 Source Code Structure

Table 34-1 lists the driver source file available in the directory, `<ltib_dir>/rpm/BUILD/linux/drivers/input/touchscreen`.

Table 34-1. TouchScreen Driver File List

File	Description
<code>p1003_fw33-ts.c</code>	Touchscreen driver implementation file.

34.5 Linux Menu Configuration Options

The following Linux kernel configuration option is provided for this module:

- `CONFIG_TOUCHSCREEN_P1003`—Build support for Hanstar P1003 driver. In `menuconfig`, this option is available under `Device Drivers -> Input -> Touchscreen`

34.6 I2C slave address

This touch screen driver is a standard i2c slave device, you should configure the I2C slave address in your MSL code.

This driver's slave address is: `0x41`

34.7 Capacitive calibration for mass production

Since capacitive touch screen may affect the sensitivity by the envrioment, it was suggested do a capcitive calibration after assemble the shell.

Touch Screen (P1003) Driver

There three Note one capacitive calibration:

- This command is only suggested to be used for mass production purpose.
- When using this command, it is very important to avoid any touch object surrounding the whole system during the calibrating period.

This driver implement a calibration interface under sysfs:

```
/sys/devices/platform/imx-i2c.X/i2c-X/X-0041/calibrate
```

The X will change to the bus number of this i2c slave device attached.

you can do the calibration like this:

```
echo calibration > /sys/devices/platform/imx-i2c.X/i2c-X/X-0041/calibrate
```

After the calibration finished, kernel will print:

```
p1003_fwv33 2-0041: calibration started  
p1003_fwv33 2-0041: calibration finished
```

And this write will be returned.

Chapter 35

Touch Screen (eGalax) Driver

35.1 Driver Overview

eGalax is a touch screen driver based on EETI touch screen controller, also named as EETI eGalax touch screen. It's a multipointer capacitive touch screen. It is use 3.3V power supply and I2C serial interface.

35.2 Hardware Operation

For the information on hardware operations, refer to eGalax datasheet and respective application processors specification.

35.3 Software Operation

This driver is a standard Linux input device driver. For information on software operation, refer to the document in the kernel source: `Documents/input/input.txt` and `Documents/input/input-programing.txt`.

35.4 Source Code Structure

Table 35-1 lists the driver source file available in the directory, `<ltlib_dir>/rpm/BUILD/linux/drivers/input/touchscreen`.

Table 35-1. TouchScreen Driver File List

File	Description
<code>egalax_ts.c</code>	Touchscreen driver implementation file.

35.5 Linux Menu Configuration Options

The following Linux kernel configuration option is provided for this module:

- **TOUCHSCREEN_EGALAX**—Build support for EETI eGalax driver. In `menuconfig`, this option is available under `Device Drivers -> Input -> Touchscreen`

35.6 I2C slave address

This touch screen driver is a standard i2c slave device, you should configure the I2C slave address in your MSL code.

This driver's slave address is: `0x4`

35.7 Enable in Ubuntu

To support ubuntu with single touch event, the source code needs to be modified and enabled for single mode:

- Modify `egalax_ts.c` and add `"#define FORCE_SINGLE_POINTER_SUPPORT"`.

Touch Screen (eGalax) Driver

- Rebuild the kernel

Chapter 36

Capacitive Touch Button(MPR121) Driver

36.1 Driver Overview

The MPR121 is the second generation sensor controller after the initial release of the MPR03x series devices. The MPR121 will feature increased internal intelligence in addition to Freescale's second generation capacitance detection engine. Some of the major additions include an increased electrode count, a hardware configurable IIC address, an expanded filtering system with debounce, and completely independent electrodes with auto-configuration built in. The device also features a 13th simulated electrode that represents the simultaneous charging of all the electrodes connected together to allow for increased

36.2 Hardware Operation

For more information about hardware operation, refer to Freescale MPR121 data sheet, which can free download at internet.

36.3 Software Operation

This driver is a standard Linux input device driver. For information on software operation, refer to the document in the kernel source: `Documents/input/input.txt` and `Documents/input/input-programing.txt`.

36.4 Source Code Structure

Table 36-1 lists the driver source file available in the directory, `<ltib_dir>/rpm/BUILD/linux/drivers/input/keyboard/`.

Table 36-1. Button Driver File List

File	Description
<code>mpr121.c</code>	Touchscreen driver implementation file.

36.5 Linux Menu Configuration Options

The following Linux kernel configuration option is provided for this module:

- `CONFIG_KEYBOARD_MPR121`—Build support for Freescale MPR121 driver. In `menuconfig`, this option is available under `Device Drivers -> Input -> Keyboard`

36.6 I2C slave address

This keyboard driver is a standard i2c slave device, the driver's slave address is configurable by hardware pin4(ADDR), you should configure your 7-bit I2C slave address in your MSL.

36.7 Setting of platform data

MPR121 need three platform data to enable the driver:

The header file is under: `linux/include/i2c/mpr.h`

- `vdd_uv`: this is VDD voltage which supply to MPR121 chip, this is used by chip to adjust the capacitive sensitivity, it should be configure by you hardware design. This member is in $\mu\text{V}(1/10^6 \text{ volt})$. For example, 3.3V is 3300000.
- `matrix`: this is the matrix of keyboard, it up to 12.
- `keycount`: this is the count of keyboard matrix, usually is can be `ARRAY_SIZE(keyboard_matrix)`.

Chapter 37

MMA8451 Accelerometer Driver

The MMA8451 is a digital accelerometer device with a flexible programming interface exposed to the software. It can be used on many applications, such as orientation detection, real-time activity analysis, motion detection, shock and vibration monitor, and so forth.

37.1 MMA8451 Features

Refer to MMA841 datasheet.

37.2 Driver Requirements

MMA8451 driver is based on a I²C driver and makes use of hardware monitor system and input poll device system; therefore, the user must enable this support in the Linux kernel.

37.3 Driver Architecture

Figure 37-1 shows the software architecture. The MMA841 uses the I²C for register access. At driver initial phase, a I²C client is registered to the I²C system and is used during the process of MMA8451 operations. The MMA8451 registers itself to the hardware monitor system and the input poll device system that provide user access facilities.

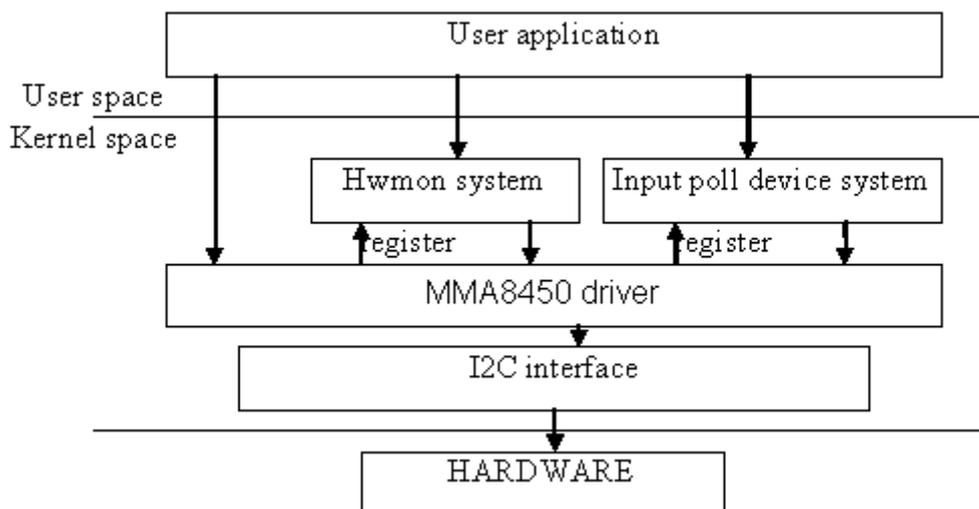


Figure 37-1. Driver Architecture

37.4 Driver Source Code Structure

The driver source code structure contains only one file located in the directory:

```
<ltib_dir>/rpm/BUILD/linux/drivers/hwmon/
```

Table 37-1. Driver Source Code Structure File

File	Description
mxc_mma8451.c	Implementation of the mma8451 accelerometer driver.

37.5 Driver Configuration

To get to the MMA8451 driver use the command `./ltib -c` when located in the `<ltib dir>`. On the screen displayed, select **Configure the kernel** and exit. When the next screen appears select the following options to enable the MMA8451 driver:

- Device Drivers > Hardware Monitoring support > MMA8451 device driver

Chapter 38

MAG3110 Magnetometer Driver

The MAG3110 is a small, low-power, digital 3-axis magnetometer. The device can be used in conjunction with a 3-axis accelerometer to produce orientation independent accurate compass heading information. It features a standard I²C serial interface output and smart embedded functions.

The MAG3110 is capable of measuring magnetic fields with an Output Data Rate (ODR) up to 80 Hz; these output data rates correspond to sample intervals from 12 ms to several seconds.

38.1 MAG3110 Features

Refer to MAG3110 datasheet.

38.2 Driver Requirements

MAG3110 driver is based on a I²C driver and makes use of hardware monitor system and input poll device system; therefore, the user must enable this support in the Linux kernel.

38.3 Driver Architecture

Figure 38-1 shows the software architecture. The MAG3110 uses the I²C for register access. At driver initial phase, a I²C client is registered to the I²C system and is used during the process of MAG3110 operations. The MAG3110 registers itself to the hardware monitor system and the input poll device system that provide user access facilities.

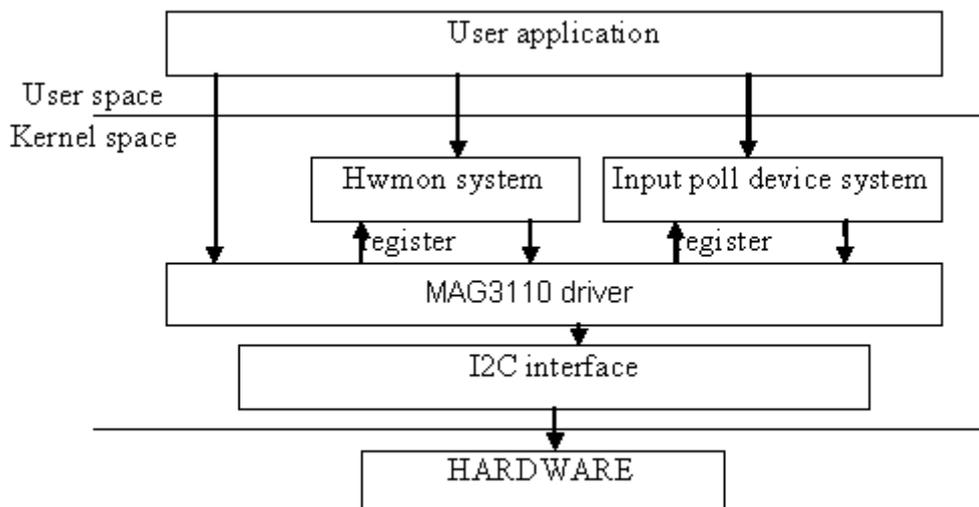


Figure 38-1. Driver Architecture

38.4 Driver Source Code Structure

The driver source code structure contains only one file located in the directory:

`<ltib_dir>/rpm/BUILD/linux/drivers/hwmon/`

Table 38-1. Driver Source Code Structure File

File	Description
mag3110.c	Implementation of the mag3110 accelerometer driver.

38.5 Driver Configuration

To get to the MAG3110 driver use the command `./ltib -c` when located in the `<ltib_dir>`. On the screen displayed, select **Configure the kernel** and exit. When the next screen appears select the following options to enable the MAG3110 driver:

- Device Drivers > Hardware Monitoring support > Freescale MAG3110 e-compass sensor

Chapter 39

AR6003 WiFi

39.1 Hardware Operation

The officially supported WiFi chip with FSL BSP is AR6003 from Atheros.

The Atheros AR6003 is a single chip, small form factor IEEE 802.11 a/b/g/n MAC/baseband/ radio optimized for low-power mobile applications.

39.2 Software Operation

FSL BSP uses the open source ath6kl driver from kernel 2.6.35 for AR6003.

39.3 Driver features

AR6003 is a single stream, SDIO based 802.11 chipset from Atheros optimized for mobile and embedded devices. ath6kl is a cfg80211 driver for AR6003 and supports both the station and AP mode of operation.

Station mode supports 802.11 a/b/g/n with HT20 on 2.4/5GHz and HT40 only on 5GHz. Some of the other features include WPA/WPA2, WPS, WMM, WMM-PS, and BT coexistence. AP mode can be operated only in b/g mode with support for a subset of features mentioned above.

The driver supports cfg80211 but comes with its own set of wext ioctls which have historically supported some of our customers with features like BT 3.0 and AP mode of operation.

For further details, refer to: <http://wireless.kernel.org/en/users/Drivers/ath6kl>

The driver requires firmware that runs on the chip's network processor. The majority of it is stored in ROM. The binaries that are downloaded and executed from RAM are as follows:

- 1) Patch against the code in ROM for bug fixes and feature enhancements.
- 2) Code to copy the data from the OTP region of the memory into RAM.
- 3) Calibration file carrying board specific data.

The above files need to be present in the directory '/lib/firmware/ath6k/AR6003/hw2.0/' for the driver to initialize the chip upon enumeration. The files can be downloaded from the link specified at the following location: <http://wireless.kernel.org/en/users/Drivers/ath6kl#Download>

This driver is only provided in the interim while we work on the mac80211 replacement, ath6k. Once the mac80211 driver achieves feature parity with the ath6kl driver, the ath6kl will be deprecated and removed from staging.

39.4 Source Code Structure

The AR6003 driver source files are available in the directory,

<ltlib_dir>/rpm/BUILD/linux/drivers/staging/ath6kl/

39.5 Linux Menu Configuration Options

The following Linux kernel configuration option is provided for this module:

- `CONFIG_ATH6K_LEGACY`—Build support for AR6003 support (non mac80211).

Note: There are also a few other options under `CONFIG_ATH6K_LEGACY`. By default you may not need to use them. Refer to the option help for details.

Chapter 40

AR3001 Bluetooth

40.1 Hardware Operation

USI module (Name: AR6003 + 3001 Dual band Combo module) which combine WiFi and bluetooth functions is used on i.MX53 Tablet platform. The bluetooth chip AR3001 is connected to i.MX53 through UART.

40.2 Software Operation

The AR3001 bluetooth driver is back-ported from 2.6.38 kernel to 2.6.35 kernel. Also, we implement a rfkill interface to this driver on i.mx platform based on rfkill interface.

40.3 Source Code Structure

The AR3001 driver source files are these two files:

```
<ltib_dir>/rpm/BUILD/linux/drivers/bluetooth/hci_ath.c
<ltib_dir>/rpm/BUILD/linux/drivers/bluetooth/hci_ldisc.c
```

For rfkill interface of this driver, the source code is under:

```
<ltib_dir>/rpm/BUILD/linux/arch/arm/mach-mx5/mx53_smd_rfkill.c
```

rfkill need a platform data that defined in MSL:

```
struct mxc_bt_rfkill_platform_data {
    int (*power_change) (int status);
};
```

The power_change function will be called when rfkill interface need change BT's power state, this is commonly change a gpio state, or change regulator setting regrading your Hardware design.

The UART configuration for UART3 is under

```
<ltib_dir>/rpm/BUILD/linux/arch/arm/mach-mx5/serial.h
```

40.4 UART related config

AR3001 is a uart interface BT chip, so UART 's config is really important to it. It have two part of config:

1. Baud rate, the baud rate can be in range 115200 - 3,000,000 bps, and not all bandrate in this range is supported by your BT's hardware, you need check the detail uart bandrate information of you BT module. We can archive 3M bps in i.MX53 Tablet reference board.

If you found your UART can't archive high baudrate(eg. 3M), you need first check two thing,

1. Your uart's clock, this clock souce must above $3M * 16 = 48M$, or i.MX UART can't archive this bandrate.
2. Wether the bandrate is supported by your BT Hardawre Module.

2. DMA transfer:

For BT's case, you need to enable DMA to reduce CPU usage, you need change it by the UART's config in above section.

40.5 Linux Menu Configuration Options

The following Linux kernel configuration option is provided for this module:

- CONFIG_BT_ATH3K—Build support for AR6003 support (non mac80211).
- MXC_BLUETOOTH_RFKILL — This is rfkill driver, can be used to control BT's power by rfkill interface.

40.6 To run AR3001 under ubuntu

The script to run AR3001 in Ubuntu is located into

```
<ltlib_dir>/rpm/BUILD/imx-test-11.05.01/test/ar3k_bt/ar3k-bt-start.sh.
```

You need first run this script to init BT's chip, this script include some step like hciattach, enable/disable rfkill interface. To make sure the BT's is reset, and inited by a right bandrate and right driver.

Comments on the script:

```
sudo pkill -9 hciattach-ar3k.bin
```

Make sure only one hciattach instance is running, kill others.

```
sudo su -c "echo 1 > /sys/class/rfkill/rfkill0/state"
```

Make the BT chip reset.

```
sudo chmod 777 /dev/ttymx2
```

Chmod to let hciattach can access the UART.

```
sudo ./hciattach-ar3k.bin -n ttymx2 ath3k 3000000 flow sleep &
```

Start hciattach to init the BT's sco interface and download config.

Chapter 41

Pulse-Width Modulator (PWM) Driver

The pulse-width modulator (PWM) has a 16-bit counter and is optimized to generate sound from stored sample audio images and generate tones. The PWM has 16-bit resolution and uses a 4x16 data FIFO to generate sound. The software module is composed of a Linux driver that allows privileged users to control the backlight by the appropriate duty cycle of the PWM Output (PWMO) signal.

41.1 Hardware Operation

Figure 41-1 shows the PWM block diagram.

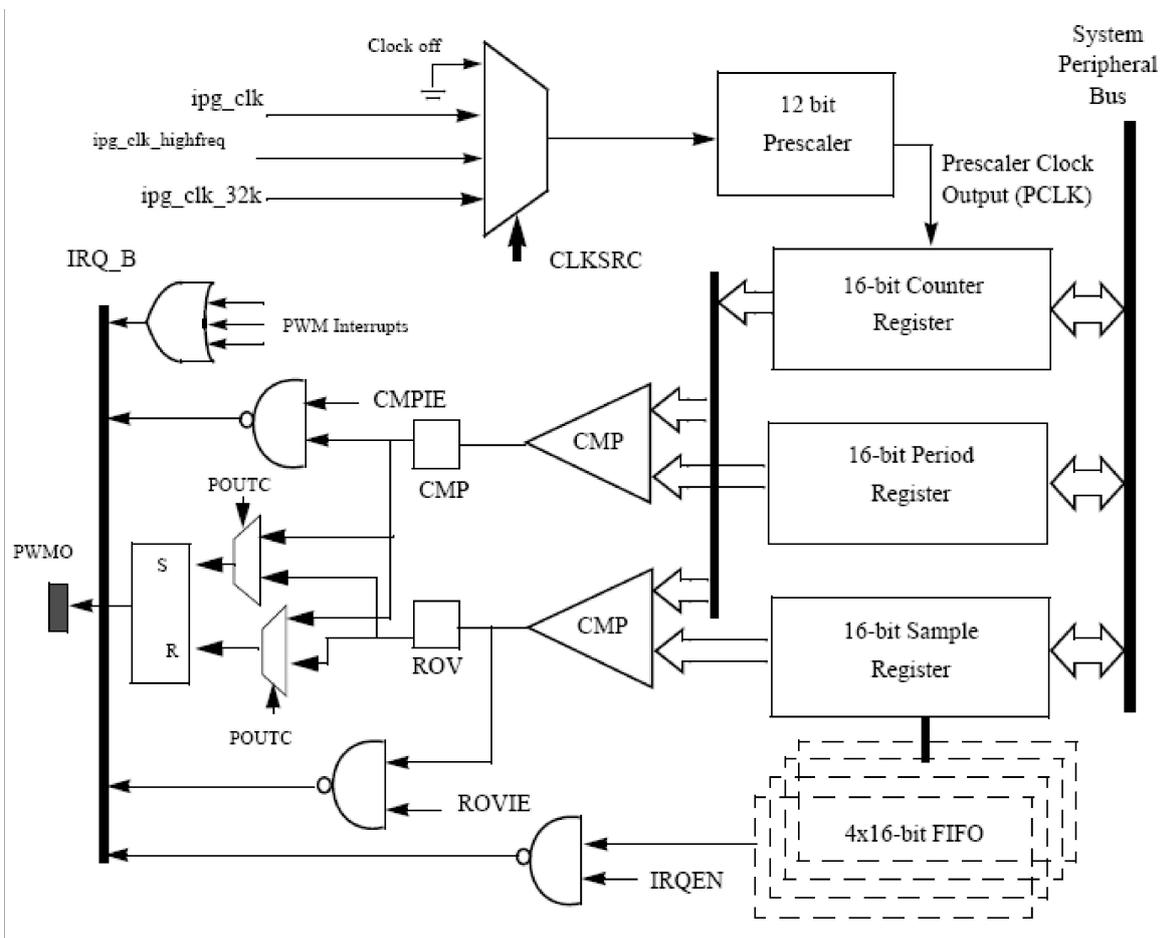


Figure 41-1. PWM Block Diagram

The PWM follows IP Bus protocol for interfacing with the processor core. It does not interface with any other modules inside the device except for the clock and reset inputs from the Clock Control Module (CCM) and interrupt signals to the processor interrupt handler. The PWM includes a single external output signal, PMWO. The PWM includes the following internal signals:

- Three clock inputs

Pulse-Width Modulator (PWM) Driver

- Four interrupt lines
- One hardware reset line
- Four low power and debug mode signals
- Four scan signals
- Standard IP slave bus signals

41.2 Clocks

The clock that feeds the prescaler can be selected from:

- High frequency clock—provided by the CCM. The PWM can be run from this clock in low power mode.
- Low reference clock—32 KHz low reference clock provided by the CCM. The PWM can be run from this clock in the low power mode.
- Global functional clock—for normal operations. In low power modes this clock can be switched off.

The clock input source is determined by the CLKSRC field of the PWM control register. The CLKSRC value should only be changed when the PWM is disabled.

41.3 Software Operation

The PWM device driver reduces the amount of power sent to a load by varying the width of a series of pulses to the power source. One common and effective use of the PWM is controlling the backlight of a QVGA panel with a variable duty cycle.

Table 41-1 provides a summary of the interface functions in source code.

Table 41-1. PWM Driver Summary

Function	Description
<code>struct pwm_device *pwm_request(int pwm_id, const char *label)</code>	Request a PWM device
<code>void pwm_free(struct pwm_device *pwm)</code>	Free a PWM device
<code>int pwm_config(struct pwm_device *pwm, int duty_ns, int period_ns)</code>	Change a PWM device configuration
<code>int pwm_enable(struct pwm_device *pwm)</code>	Start a PWM output toggling
<code>int pwm_disable(struct pwm_device *pwm)</code>	Stop a PWM output toggling

The function `pwm_config()` includes most of the configuration tasks for the PWM module, including the clock source option, and period and duty cycle of the PWM output signal. It is recommended to select the peripheral clock of the PWM module, rather than the local functional clock, as the local functional clock can change.

41.4 Driver Features

The PWM driver includes the following software and hardware support:

- Duty cycle modulation
- Varying output intervals
- Two power management modes—full on and full of

41.5 Source Code Structure

Table 41-2 lists the source files and headers available in the following directories:

<ltib_dir>/rpm/BUILD/linux/arch/arm/plat-mxc/pwm.c

<ltib_dir>/rpm/BUILD/linux/include/linux/pwm.h

Table 41-2. PWM Driver Files

File	Description
pwm.h	Functions declaration
pwm.c	Functions definition

41.6 Menu Configuration Options

To get to the PWM driver, use the command `./ltib -c` when located in the <ltib dir>. On the screen displayed, select **Configure the kernel** and exit. When the next screen appears select the following option to enable the PWM driver:

- System Type > Enable PWM driver
- Select the following option to enable the Backlight driver:
Device Drivers > Graphics support > Backlight & LCD device support > Generic PWM based Backlight Driver

Chapter 42

OProfile

OProfile is a system-wide profiler for Linux systems, capable of profiling all running code at low overhead. OProfile is released under the GNU GPL. It consists of a kernel driver, a daemon for collecting sample data, and several post-profiling tools for turning data into information.

42.1 Overview

OProfile leverages the hardware performance counters of the CPU to enable profiling of a wide variety of interesting statistics, which can also be used for basic time-spent profiling. All code is profiled: hardware and software interrupt handlers, kernel modules, the kernel, shared libraries, and applications.

42.2 Features

The features of the OProfile are as follows:

- Unobtrusive—No special recompilations or wrapper libraries are necessary. Even debug symbols (-g option to `gcc`) are not necessary unless users want to produce annotated source. No kernel patch is needed; just insert the module.
- System-wide profiling—All code running on the system is profiled, enabling analysis of system performance.
- Performance counter support—Enables collection of various low-level data and association for particular sections of code.
- Call-graph support—With an 2.6 kernel, OProfile can provide `gprof`-style call-graph profiling data.
- Low overhead—OProfile has a typical overhead of 1–8% depending on the sampling frequency and workload.
- Post-profile analysis—Profile data can be produced on the function-level or instruction-level detail. Source trees, annotated with profile information, can be created. A hit list of applications and functions that utilize the most CPU time across the whole system can be produced.
- System support—Works with almost any 2.2, 2.4 and 2.6 kernels, and works on based platforms.

42.3 Hardware Operation

OProfile is a statistical continuous profiler. In other words, profiles are generated by regularly sampling the current registers on each CPU (from an interrupt handler, the saved PC value at the time of interrupt is stored), and converting that runtime PC value into something meaningful to the programmer.

OProfile achieves this by taking the stream of sampled PC values, along with the detail of which task was running at the time of the interrupt, and converting the values into a file offset against a particular binary file. Each PC value is thus converted into a tuple (group or set) of binary-image offset. The userspace tools can use this data to reconstruct where the code came from, including the particular assembly instructions, symbol, and source line (through the binary debug information if present).

Regularly sampling the PC value like this approximates what actually was executed and how often and more often than not, this statistical approximation is good enough to reflect reality. In common operation,

the time between each sample interrupt is regulated by a fixed number of clock cycles. This implies that the results reflect where the CPU is spending the most time. This is a very useful information source for performance analysis.

The ARM CPU provides hardware performance counters capable of measuring these events at the hardware level. Typically, these counters increment once per each event and generate an interrupt on reaching some pre-defined number of events. OProfile can use these interrupts to generate samples and the profile results are a statistical approximation of which code caused how many instances of the given event.

42.4 Software Operation

42.4.1 Architecture Specific Components

If OProfile supports the hardware performance counters available on a particular architecture. Code for managing the details of setting up and managing these counters can be located in the kernel source tree in the relevant `<ltib_dir>/rpm/BUILD/linux/arch/arm/oprofile` directory. The architecture-specific implementation operates through filling in the `oprofile_operations` structure at initialization. This provides a set of operations, such as `setup()`, `start()`, `stop()`, and so on, that manage the hardware-specific details the performance counter registers.

The other important facility available to the architecture code is `oprofile_add_sample()`. This is where a particular sample taken at interrupt time is fed into the generic OProfile driver code.

42.4.2 oprofilefs Pseudo Filesystem

OProfile implements a pseudo-filesystem known as `oprofilefs`, which is mounted from userspace at `/dev/oprofile`. This consists of small files for reporting and receiving configuration from userspace, as well as the actual character device that the OProfile userspace receives samples from. At `setup()` time, the architecture-specific code may add further configuration files related to the details of the performance counters. The filesystem also contains a `stats` directory with a number of useful counters for various OProfile events.

42.4.3 Generic Kernel Driver

The generic kernel driver resides in `<ltib_dir>/rpm/BUILD/linux/drivers/oprofile/`, and forms the core of how OProfile operates in the kernel. The generic kernel driver takes samples delivered from the architecture-specific code (through `oprofile_add_sample()`), and buffers this data (in a transformed configuration) until releasing the data to the userspace daemon through the `/dev/oprofile/buffer` character device.

42.4.4 OProfile Daemon

The OProfile userspace daemon takes the raw data provided by the kernel and writes it to the disk. It takes the single data stream from the kernel and logs sample data against a number of sample files (available in `/var/lib/oprofile/samples/current/`). For the benefit of the separate functionality, the names and paths

of these sample files are changed to reflect where the samples were from. This can include thread IDs, the binary file path, the event type used, and more.

After this final step from interrupt to disk file, the data is now persistent (that is, changes in the running of the system do not invalidate stored data). This enables the post-profiling tools to run on this data at any time (assuming the original binary files are still available and unchanged).

42.4.5 Post Profiling Tools

The collected data must be presented to the user in a useful form. This is the job of the post-profiling tools. In general, they collate a subset of the available sample files, load and process each one correlated against the relevant binary file, and produce user readable information.

42.5 Requirements

The requirements of OProfile are as follows:

- Add Oprofile support with Cortex-A8 Event Monitor

42.6 Source Code Structure

Oprofile platform-specific source files are available in the directory:

`<ltib_dir>/rpm/BUILD/linux/arch/arm/oprofile/`

Table 42-1. OProfile Source Files

File	Description
op_arm_model.h	Header File with the register and bit definitions
common.c	Source file with the implementation required for all platforms
op_model_v7.c	Source file for ARM V7 (Cortex A8) Event Monitor Driver
op_model_v7.h	Header file for ARM V7 (Cortex A8) Event Monitor Driver

The generic kernel driver for Oprofile is located under `<ltib_dir>/rpm/BUILD/linux/drivers/oprofile/`

42.7 Menu Configuration Options

The following Linux kernel configurations are provided for this module. To get to the Oprofile configuration, use the command `./ltib -c` from the `<ltib dir>`. On the screen, first go to Package list and select oprofile. Then return to the first screen and, select **Configure Kernel**, then exit, and a new screen appears.

- `CONFIG_OPROFILE`—configuration option for the oprofile driver. In the menuconfig this option is available under
General Setup > Profiling support (EXPERIMENTAL) > OProfile system profiling (EXPERIMENTAL)

42.8 Programming Interface

This driver implements all the methods required to configure and control PMU and L2 cache EVTMON counters. Refer to the doxygen documentation for more information (in the doxygen folder of the documentation package).

42.9 Interrupt Requirements

The number of interrupts generated with respect to the OProfile driver are numerous. The latency requirements are not needed. The rate at which interrupts are generated depends on the event.

42.10 Example Software Configuration

The following steps show an example of how to configure the OProfile:

1. Use the command `./ltib -c` from the `<ltib dir>`. On the screen, first go to Package list and select oprofile. The current version in ltib is 0.9.5.
2. Then return to the first screen and select `Configure Kernel`, follow the instruction from [Section 42.7, “Menu Configuration Options,”](#) to enable Oprofile in the kernel space.
3. Save the configuration and start to build.
4. Copy Oprofile binaries to target rootfs. Copy `vmlinux` to `/boot` directory and run Oprofile

```

root@ubuntu:/boot# opcontrol --separate=kernel --vmlinux=/boot/vmlinux
root@ubuntu:/boot# opcontrol --reset
Signalling daemon... done
root@ubuntu:/boot# opcontrol --setup --event=CPU_CYCLES:100000
root@ubuntu:/boot# opcontrol --start
Profiler running.
root@ubuntu:/boot# opcontrol --dump
root@ubuntu:/boot# opreport
Overflow stats not available
CPU: ARM V7 PMNC, speed 0 MHz (estimated)
Counted CPU_CYCLES events (Number of CPU cycles) with a unit mask of 0x00 (No unit mask) count 100000
CPU_CYCLES:100000|
  samples|      %|
-----|-----|
      4 22.2222 grep
      CPU_CYCLES:100000|

```

```
      samples|      %|
-----|
          4 100.000 libc-2.9.so
2 11.1111 cat
CPU_CYCLES:100000|
      samples|      %|
-----|
          1 50.0000 ld-2.9.so
          1 50.0000 libc-2.9.so
...
root@ubuntu:/boot# opcontrol --stop
Stopping profiling.
```

