



RTEMS BSP and Device Driver Development Guide

Release 4.11.2-rc5

©Copyright 2016, RTEMS Project (built 4th July 2017)

CONTENTS

I	BSP and Device Driver Development Guide	1
1	Introduction	3
2	Target Dependent Files	5
2.1	CPU Dependent	6
2.2	Board Dependent	7
2.3	Peripheral Dependent	8
2.4	Questions to Ask	9
2.5	CPU Dependent Executive Files	10
2.6	CPU Dependent Support Files	11
2.7	Board Support Package Structure	12
3	Makefiles	13
3.1	Makefiles Used During The BSP Building Process	14
3.2	Creating a New BSP Make Customization File	16
4	Linker Script	17
4.1	What is a “linkcmds” file?	18
4.2	Program Sections	19
4.3	Image of an Executable	20
4.4	Example Linker Command Script	21
4.5	Initialized Data	25
5	Miscellaneous Support Files	27
5.1	GCC Compiler Specifications File	28
5.2	README Files	29
5.3	Times	30
5.4	Tools Subdirectory	31
5.5	bsp.h Include File	32
5.6	tm27.h Include File	33
5.7	Calling Overhead File	34
5.8	sbrk() Implementation	35
5.9	bsp_fatal_extension() - Cleanup the Hardware	36
5.10	Configuration Macros	37
5.11	set_vector() - Install an Interrupt Vector	38
5.12	Interrupt Delay Profiling	39
5.13	Programmable Interrupt Controller API	40
6	Ada95 Interrupt Support	41

6.1	Introduction	42
6.2	Mapping Interrupts to POSIX Signals	43
6.3	Example Ada95 Interrupt Program	44
6.4	Version Requirements	45
7	Initialization Code	47
7.1	Introduction	48
7.2	Required Global Variables	49
7.3	Board Initialization	50
7.3.1	Start Code - Assembly Language Initialization	50
7.3.2	boot_card() - Boot the Card	50
7.3.3	bsp_work_area_initialize() - BSP Specific Work Area Initialization	51
7.3.4	bsp_start() - BSP Specific Initialization	52
7.3.5	bsp_predriver_hook() - BSP Specific Predriver Hook	52
7.3.6	Device Driver Initialization	52
7.3.7	RTEMS Postdriver Callback	52
7.4	The Interrupt Vector Table	54
7.4.1	Interrupt Vector Table on the gen68340 BSP	54
7.5	Chip Select Initialization	55
7.6	Integrated Processor Registers Initialization	56
7.7	Data Section Recopy	57
7.8	The RTEMS Configuration Table	58
8	Console Driver	59
8.1	Introduction	60
8.2	Termios	61
8.3	Driver Functioning Modes	62
8.4	Serial Driver Functioning Overview	63
8.4.1	Basics	63
8.4.2	Termios and Polled IO	64
8.4.3	Termios and Interrupt Driven IO	65
8.4.4	Initialization	67
8.4.5	Opening a serial device	68
8.4.6	Closing a Serial Device	69
8.4.7	Reading Characters from a Serial Device	69
8.4.8	Writing Characters to a Serial Device	69
8.4.9	Changing Serial Line Parameters	69
9	Clock Driver	71
9.1	Introduction	72
9.2	Clock Driver Shell	73
9.2.1	Initialization	73
9.2.1.1	Clock Tick Only Variant	73
9.2.1.2	Simple Timecounter Variant	74
9.2.1.3	Timecounter Variant	75
9.2.2	Install Clock Tick Interrupt Service Routine	75
9.2.3	Support At Tick	76
9.2.4	System Shutdown Support	76
9.2.5	Multiple Clock Driver Ticks Per Clock Tick	77
9.2.6	Clock Driver Ticks Counter	77
10	Timer Driver	79

10.1	Benchmark Timer	80
10.1.1	benchmark_timer_initialize	80
10.1.2	Read_timer	80
10.1.3	benchmark_timer_disable_subtracting_average_overhead	80
10.2	gen68340 UART FIFO Full Mode	81
11	Real-Time Clock Driver	83
11.1	Introduction	84
11.2	Initialization	86
11.3	setRealTimeToRTEMS	87
11.4	setRealTimeFromRTEMS	88
11.5	getRealTime	89
11.6	setRealTime	90
11.7	checkRealTime	91
12	ATA Driver	93
12.1	Terms	94
12.2	Introduction	95
12.3	Initialization	96
12.4	ATA Driver Architecture	97
12.4.1	ATA Driver Main Internal Data Structures	97
12.4.2	Brief ATA Driver Core Overview	98
13	IDE Controller Driver	99
13.1	Introduction	100
13.2	Initialization	101
13.3	Read IDE Controller Register	102
13.4	Write IDE Controller Register	103
13.5	Read Data Block Through IDE Controller Data Register	104
13.6	Write Data Block Through IDE Controller Data Register	105
14	Non-Volatile Memory Driver	107
14.1	Major and Minor Numbers	108
14.2	Non-Volatile Memory Driver Configuration	109
14.3	Initialize the Non-Volatile Memory Driver	111
14.4	Disable Read and Write Handlers	112
14.5	Open a Particular Memory Partition	113
14.6	Close a Particular Memory Partition	114
14.7	Read from a Particular Memory Partition	115
14.8	Write to a Particular Memory Partition	116
14.9	Erase the Non-Volatile Memory Area	117
15	Networking Driver	119
15.1	Introduction	120
15.2	Learn about the network device	121
15.3	Understand the network scheduling conventions	122
15.4	Network Driver Makefile	123
15.5	Write the Driver Attach Function	124
15.6	Write the Driver Start Function.	126
15.7	Write the Driver Initialization Function.	127
15.8	Write the Driver Transmit Task	128
15.9	Write the Driver Receive Task	129

15.10	Write the Driver Interrupt Handler	130
15.11	Write the Driver IOCTL Function	131
15.12	Write the Driver Statistic-Printing Function	132
16	Shared Memory Support Driver	133
16.1	Shared Memory Configuration Table	134
16.2	Primitives	136
16.2.1	Convert Address	136
16.2.2	Get Configuration	136
16.2.3	Locking Primitives	136
16.2.3.1	Initializing a Shared Lock	137
16.2.3.2	Acquiring a Shared Lock	137
16.2.3.3	Releasing a Shared Lock	137
16.3	Installing the MPCPI ISR	139
17	Frame Buffer Driver	141
17.1	Introduction	142
17.2	Driver Function Overview	143
17.2.1	Initialization	143
17.2.2	Opening the Frame Buffer Device	143
17.2.3	Closing the Frame Buffer Device	144
17.2.4	Reading from the Frame Buffer Device	144
17.2.5	Writing to the Frame Buffer Device	145
17.2.6	Frame Buffer IO Control	145
18	Analog Driver	147
18.1	Major and Minor Numbers	148
18.2	Analog Driver Configuration	149
18.3	Initialize an Analog Board	150
18.4	Open a Particular Analog	151
18.5	Close a Particular Analog	152
18.6	Read from a Particular Analog	153
18.7	Write to a Particular Analog	154
18.8	Reset DACs	155
18.9	Reinitialize DACS	156
18.10	Get Last Written Values	157
19	Discrete Driver	159
19.1	Major and Minor Numbers	160
19.2	Discrete I/O Driver Configuration	161
19.3	Initialize a Discrete I/O Board	162
19.4	Open a Particular Discrete Bitfield	163
19.5	Close a Particular Discrete Bitfield	164
19.6	Read from a Particular Discrete Bitfield	165
19.7	Write to a Particular Discrete Bitfield	166
19.8	Disable Discrete Outputs	167
19.9	Enable Discrete Outputs	168
19.10	Reinitialize Outputs	169
19.11	Get Last Written Values	170
20	Command and Variable Index	171

Part I

BSP AND DEVICE DRIVER DEVELOPMENT GUIDE

COPYRIGHT (c) 1988 - 2015.

On-Line Applications Research Corporation (OAR).

The authors have used their best efforts in preparing this material. These efforts include the development, research, and testing of the theories and programs to determine their effectiveness. No warranty of any kind, expressed or implied, with regard to the software or the material contained in this document is provided. No liability arising out of the application or use of any product described in this document is assumed. The authors reserve the right to revise this material and to make changes from time to time in the content hereof without obligation to notify anyone of such revision or changes.

The RTEMS Project is hosted at <http://www.rtems.org>. Any inquiries concerning RTEMS, its related support components, or its documentation should be directed to the Community Project hosted at <http://www.rtems.org>.

RTEMS Online Resources

Home	https://www.rtems.org/
Developers	https://devel.rtems.org/
Documentation	https://docs.rtems.org/
Bug Reporting	https://devel.rtems.org/query
Mailing Lists	https://lists.rtems.org/
Git Repositories	https://git.rtems.org/

INTRODUCTION

Before reading this documentation, it is strongly advised to read the RTEMS Development Environment Guide to get acquainted with the RTEMS directory structure. This document describes how to do a RTEMS Board Support Package, i.e. how to port RTEMS on a new target board. Discussions are provided for the following topics:

- RTEMS Board Support Package Organization
- Makefiles and the Linker Command Script
- Board Initialization Sequence
- Device Drivers:
 - Console Driver
 - Clock Driver
 - Timer Driver
 - Real-Time Clock Driver
 - Non-Volatile Memory Driver
 - Networking Driver
 - Shared Memory Support Driver
 - Analog Driver
 - Discrete Driver

The original version of this manual was written by Geoffroy Montel <g_montel@yahoo.com>. When he started development of the gen68340 BSP, this manual did not exist. He wrote the initial version of this manual as the result of his experiences. At that time, this document was viewed internally as the most important “missing manual” in the RTEMS documentation set.

The gen68340 BSP is a good example of the life of an RTEMS BSP. It is based upon a part not recommended for new designs and none of the core RTEMS Project team members have one of these boards. Thus we are unlikely to perform major updates on this BSP. So as long as it compiles and links all tests, it will be available.

The RTEMS Project team members are always trying to identify common code across BSPs and refactoring the code into shared routines. As part of this effort, the we will enhance the common BSP Framework. Not surprisingly, not every BSP takes advantage of every feature in the framework. The gen68340 does not take advantage of as many features as the ERC32 BSP does. So in many ways, the ERC32 is a better example BSP at this point. But even the ERC32

BSP does not include examples of every driver template and framework available to the BSP author. So in this guide we will try to point out good examples from other BSPs.

Our goal is for you to be able to reuse as much code as possible and write as little board specific code as possible.

TARGET DEPENDENT FILES

RTEMS has a multi-layered approach to portability. This is done to maximize the amount of software that can be reused. Much of the RTEMS source code can be reused on all RTEMS platforms. Other parts of the executive are specific to hardware in some sense. RTEMS classifies target dependent code based upon its dependencies into one of the following categories.

- CPU dependent
- Board dependent
- Peripheral dependent

2.1 CPU Dependent

This class of code includes the foundation routines for the executive proper such as the context switch and the interrupt subroutine implementations. Sources for the supported processor families can be found in `cpukit/score/cpu`. A good starting point for a new family of processors is the `no_cpu` directory, which holds both prototypes and descriptions of each needed CPU dependent function.

CPU dependent code is further subcategorized if the implementation is dependent on a particular CPU model. For example, the MC68000 and MC68020 processors are both members of the m68k CPU family but there are significant differences between these CPU models which RTEMS must take into account.

The source code found in the `cpukit/score/cpu` is required to only depend upon the CPU model variations that GCC distinguishes for the purposes of multilib'ing. Multilib is the term the GNU community uses to refer to building a single library source multiple times with different compiler options so the binary code generated is compatible. As an example, from GCC's perspective, many PowerPC CPU models are just a PPC603e. Remember that GCC only cares about the CPU code itself and need not be aware of any peripherals. In the embedded community, we are exposed to thousands of CPU models which are all based upon only a relative small number of CPU cores.

Similarly for the SPARC/ERC32 BSP, the `RTEMS_CPU` is specified as `erc32` which is the name of the CPU model and BSP for this SPARC V7 system on chip. But the multilib variant used is actually `v7` which indicates the ERC32 CPU core is a SPARC V7.

2.2 Board Dependent

This class of code provides the most specific glue between RTEMS and a particular board. This code is represented by the Board Support Packages and associated Device Drivers. Sources for the BSPs included in the RTEMS distribution are located in the directory `c/src/lib/libbsp`. The BSP source directory is further subdivided based on the CPU family and BSP.

Some BSPs may support multiple board models within a single board family. This is necessary when the board supports multiple variants on a single base board. For example, the Motorola MVME162 board family has a fairly large number of variations based upon the particular CPU model and the peripherals actually placed on the board.

2.3 Peripheral Dependent

This class of code provides a reusable library of peripheral device drivers which can be tailored easily to a particular board. The libchip library is a collection of reusable software objects that correspond to standard controllers. Just as the hardware engineer chooses a standard controller when designing a board, the goal of this library is to let the software engineer do the same thing.

The source code for the reusable peripheral driver library may be found in the directory `c/src/lib/libchip`. The source code is further divided based upon the class of hardware. Example classes include serial communications controllers, real-time clocks, non-volatile memory, and network controllers.

2.4 Questions to Ask

When evaluating what is required to support RTEMS applications on a particular target board, the following questions should be asked:

- Does a BSP for this board exist?
- Does a BSP for a similar board exist?
- Is the board's CPU supported?

If there is already a BSP for the board, then things may already be ready to start developing application software. All that remains is to verify that the existing BSP provides device drivers for all the peripherals on the board that the application will be using. For example, the application in question may require that the board's Ethernet controller be used and the existing BSP may not support this.

If the BSP does not exist and the board's CPU model is supported, then examine the reusable chip library and existing BSPs for a close match. Other BSPs and libchip provide starting points for the development of a new BSP. It is often possible to copy existing components in the reusable chip library or device drivers from BSPs from different CPU families as the starting point for a new device driver. This will help reduce the development effort required.

If the board's CPU family is supported but the particular CPU model on that board is not, then the RTEMS port to that CPU family will have to be augmented. After this is done, development of the new BSP can proceed.

Otherwise both CPU dependent code and the BSP will have to be written.

This type of development often requires specialized skills and there are people in the community who provide those services. If you need help in making these modifications to RTEMS try a search in a search engine with something like "rtems support". The RTEMS Project encourages users to use support services however we do not endorse any providers.

2.5 CPU Dependent Executive Files

The CPU dependent files in the RTEMS executive source code are found in the following directory:

```
1 cpukit/score/cpu/<CPU>
```

where <CPU> is replaced with the CPU family name.

Within each CPU dependent directory inside the executive proper is a file named <CPU>.h which contains information about each of the supported CPU models within that family.

2.6 CPU Dependent Support Files

The CPU dependent support files contain routines which aid in the development of applications using that CPU family. For example, the support routines may contain standard trap handlers for alignment or floating point exceptions or device drivers for peripheral controllers found on the CPU itself. This class of code may be found in the following directory:

```
1 c/src/lib/libcpu/<CPU>
```

CPU model dependent support code is found in the following directory:

```
1 c/src/lib/libcpu/<CPU>/<CPU_MODEL>
```

<CPU_MODEL> may be a specific CPU model name or a name indicating a CPU core or a set of related CPU models. The file `configure.ac` in each `c/src/lib/libcpu/<CPU>` directory contains the logic which enables the appropriate subdirectories for the specific CPU model your BSP has.

2.7 Board Support Package Structure

The BSPs are all under the `c/src/lib/libbsp` directory. Below this directory, there is a subdirectory for each CPU family. Each BSP is found under the subdirectory for the appropriate processor family (arm, powerpc, sparc, etc.). In addition, there is source code available which may be shared across all BSPs regardless of the CPU family or just across BSPs within a single CPU family. This results in a BSP using the following directories:

```
1 c/src/lib/libbsp/shared
2 c/src/lib/libbsp/<CPU>/shared
3 c/src/lib/libbsp/<CPU>/<BSP>
```

Under each BSP specific directory, there is a collection of subdirectories. For commonly provided functionality, the BSPs follow a convention on subdirectory naming. The following list describes the commonly found subdirectories under each BSP.

- `console`: is technically the serial driver for the BSP rather than just a console driver, it deals with the board UARTs (i.e. serial devices).
- `clock`: support for the clock tick - a regular time basis to the kernel.
- `timer`: support of timer devices.
- `rtc` or `tod`: support for the hardware real-time clock.
- `nvmem`: support for non-volatile memory such as EEPROM or Flash.
- `network`: the Ethernet driver.
- `shmsupp`: support of shared memory driver MPCIE layer in a multiprocessor system,
- `include`: include files for this BSP.
- `gnatsupp`: BSP specific support for the GNU Ada run-time. Each BSP that wishes to have the possibility to map faults or exceptions into Ada language exceptions or hardware interrupts into Ada interrupt tasks must provide this support.

There may be other directories in the BSP tree and the name should be indicative of the functionality of the code within that directory.

The build order of the BSP is determined by the Makefile structure. This structure is discussed in more detail in the *Chapter 3 - Makefiles* (page 13) chapter.

This manual refers to the gen68340 BSP for numerous concrete examples. You should have a copy of the gen68340 BSP available while reading this piece of documentation. This BSP is located in the following directory:

```
1 c/src/lib/libbsp/m68k/gen68340
```

Later in this document, the `$BSP340_ROOT` label will be used to refer to this directory.

MAKEFILES

This chapter discusses the Makefiles associated with a BSP. It does not describe the process of configuring, building, and installing RTEMS. This chapter will not provide detailed information about this process. Nonetheless, it is important to remember that the general process consists of four phases as shown here:

- bootstrap
- configure
- build
- install

During the bootstrap phase, you are using the `configure.ac` and `Makefile.am` files as input to GNU `autoconf` and `automake` to generate a variety of files. This is done by running the bootstrap script found at the top of the RTEMS source tree.

During the configure phase, a number of files are generated. These generated files are tailored for the specific host/target combination by the configure script. This set of files includes the Makefiles used to actually compile and install RTEMS.

During the build phase, the source files are compiled into object files and libraries are built.

During the install phase, the libraries, header files, and other support files are copied to the BSP specific installation point. After installation is successfully completed, the files generated by the configure and build phases may be removed.

3.1 Makefiles Used During The BSP Building Process

RTEMS uses the *GNU automake* and *GNU autoconf* automatic configuration package. Consequently, there are a number of automatically generated files in each directory in the RTEMS source tree. The bootstrap script found in the top level directory of the RTEMS source tree is executed to produce the automatically generated files. That script must be run from a directory with a `configure.ac` file in it. The bootstrap command is usually invoked in one of the following manners:

- `bootstrap` to regenerate all files that are generated by `autoconf` and `automake`.
- `bootstrap -c` to remove all files generated by `autoconf` and `automake`.
- `bootstrap -p` to regenerate `preinstall.am` files.

There is a file named `Makefile.am` in each directory of a BSP. This file is used by *automake* to produce the file named `Makefile.in` which is also found in each directory of a BSP. When modifying a `Makefile.am`, you can probably find examples of anything you need to do in one of the BSPs.

The configure process specializes the `Makefile.in` files at the time that RTEMS is configured for a specific development host and target. Makefiles are automatically generated from the `Makefile.in` files. It is necessary for the BSP developer to provide the `Makefile.am` files and generate the `Makefile.in` files. Most of the time, it is possible to copy the `Makefile.am` from another similar directory and edit it.

The `Makefile` files generated are processed when configuring and building RTEMS for a given BSP.

The BSP developer is responsible for generating `Makefile.am` files which properly build all the files associated with their BSP. Most BSPs will only have a single `Makefile.am` which details the set of source files to build to compose the BSP support library along with the set of include files that are to be installed.

This single `Makefile.am` at the top of the BSP tree specifies the set of header files to install. This fragment from the SPARC/ERC32 BSP results in four header files being installed.

```
1 include_HEADERS = include/bsp.h
2 include_HEADERS += include/tm27.h
3 include_HEADERS += include/erc32.h
4 include_HEADERS += include/coverhd.h
```

When adding new include files, you will be adding to the set of `include_HEADERS`. When you finish editing the `Makefile.am` file, do not forget to run `bootstrap -p` to regenerate the `preinstall.am`.

The `Makefile.am` also specifies which source files to build. By convention, logical components within the BSP each assign their source files to a unique variable. These variables which define the source files are collected into a single variable which instructs the GNU autotools that we are building `libbsp.a`. This fragment from the SPARC/ERC32 BSP shows how the startup related, miscellaneous support code, and the console device driver source is managed in the `Makefile.am`.

```
1 startup_SOURCES = ../../sparc/shared/bspclean.c ../../shared/bsplibc.c \
2 ../../shared/bspdriverhook.c \
3 ../../shared/bspptest.c ../../sparc/shared/bspstart.c \
```

```

4 ../../shared/bootcard.c ../../shared/sbrk.c startup/setvec.c \
5 startup/spurious.c startup/erc32mec.c startup/boardinit.S
6 clock_SOURCES = clock/ckinit.c
7 ...
8 noinst_LIBRARIES = libbsp.a
9 libbsp_a_SOURCES = $(startup_SOURCES) $(console_SOURCES) ...

```

When adding new files to an existing directory, do not forget to add the new files to the list of files to be built in the corresponding XXX_SOURCES variable in the Makefile.am and run “bootstrap”.

Some BSPs use code that is built in libcpu. If your BSP does this, then you will need to make sure the objects are pulled into your BSP library. The following from the SPARC/ERC32 BSP pulls in the cache, register window management and system call support code from the directory corresponding to its RTEMS_CPU model.

```

1 libbsp_a_LIBADD = ../../../../libcpu/@RTEMS_CPU@/cache.rel \
2 ../../../../libcpu/@RTEMS_CPU@/reg_win.rel \
3 ../../../../libcpu/@RTEMS_CPU@/syscall.rel

```

The Makefile.am files are ONLY processed by bootstrap and the resulting Makefile.in files are only processed during the configure process of a RTEMS build. Therefore, when developing a BSP and adding a new file to a Makefile.am, the already generated Makefile will not automatically include the new references unless you configured RTEMS with the --enable-maintainer-mode option. Otherwise, the new file will not be taken into account!

3.2 Creating a New BSP Make Customization File

When building a BSP or an application using that BSP, it is necessary to tailor the compilation arguments to account for compiler flags, use custom linker scripts, include the RTEMS libraries, etc.. The BSP must be built using this information. Later, once the BSP is installed with the toolset, this same information must be used when building the application. So a BSP must include a build configuration file. The configuration file is `make/custom/BSP.cfg`.

The configuration file is taken into account when building one's application using the RTEMS template Makefiles (`make/templates`). These application template Makefiles have been included with the RTEMS source distribution since the early 1990's. However there is a desire in the RTEMS user community to move all provided examples to GNU autoconf. They are included in the 4.9 release series and used for all examples provided with RTEMS. There is no definite timetable for obsoleting them. You are free to use these but be warned they have fallen out of favor with many in the RTEMS community and may disappear in the future.

The following is a slightly shortened version of the make customization file for the `gen68340` BSP. The original source for this file can be found in the `make/custom` directory.

```
1 # The RTEMS CPU Family and Model
2 RTEMS_CPU=m68k
3 RTEMS_CPU_MODEL=m68340
4 include $(RTEMS_ROOT)/make/custom/default.cfg
5 # This is the actual bsp directory used during the build process.
6 RTEMS_BSP_FAMILY=gen68340
7 # This contains the compiler options necessary to select the CPU model
8 # and (hopefully) optimize for it.
9 CPU_CFLAGS = -mcpu=cpu32
10 # optimize flag: typically -O2
11 CFLAGS_OPTIMIZE_V = -O2 -g -fomit-frame-pointer
```

The make customization files have generally grown simpler and simpler with each RTEMS release. Beginning in the 4.9 release series, the rules for linking an RTEMS application are shared by all BSPs. Only BSPs which need to perform a transformation from linked ELF file to a downloadable format have any additional actions for program link time. In 4.8 and older, every BSP specified the “make executable” or `make-exe` rule and duplicated the same actions.

It is generally easier to copy a `make/custom` file from a BSP similar to the one being developed.

LINKER SCRIPT

4.1 What is a “linkcmds” file?

The `linkcmds` file is a script which is passed to the linker at linking time. This file describes the memory configuration of the board as needed to link the program. Specifically it specifies where the code and data for the application will reside in memory.

The format of the linker script is defined by the GNU Loader `ld` which is included as a component of the GNU Binary Utilities. If you are using GNU/Linux, then you probably have the documentation installed already and are using these same tools configured for *native* use. Please visit the Binutils project <http://sourceware.org/binutils/> if you need more information.

4.2 Program Sections

An embedded systems programmer must be much more aware of the placement of their executable image in memory than the average applications programmer. A program destined to be embedded as well as the target system have some specific properties that must be taken into account. Embedded machines often mean average performances and small memory usage. It is the memory usage that concerns us when examining the linker command file.

Two types of memories have to be distinguished:

- RAM - volatile offering read and write access
- ROM - non-volatile but read only

Even though RAM and ROM can be found in every personal computer, one generally doesn't care about them. In a personal computer, a program is nearly always stored on disk and executed in RAM. Things are a bit different for embedded targets: the target will execute the program each time it is rebooted or switched on. The application program is stored in non-volatile memory such as ROM, PROM, EEPROM, or Flash. On the other hand, data processing occurs in RAM.

This leads us to the structure of an embedded program. In rough terms, an embedded program is made of sections. It is the responsibility of the application programmer to place these sections in the appropriate place in target memory. To make this clearer, if using the COFF object file format on the Motorola m68k family of microprocessors, the following sections will be present:

- code (.text) section: is the program's code and it should not be modified. This section may be placed in ROM.
- non-initialized data (.bss) section: holds uninitialized variables of the program. It can stay in RAM.
- initialized data (.data) section: holds the initialized program data which may be modified during the program's life. This means they have to be in RAM. On the other hand, these variables must be set to predefined values, and those predefined values have to be stored in ROM.

Note: Many programs and support libraries unknowingly assume that the .bss section and, possibly, the application heap are initialized to zero at program start. This is not required by the ISO/ANSI C Standard but is such a common requirement that most BSPs do this.

That brings us up to the notion of the image of an executable: it consists of the set of the sections that together constitute the application.

4.3 Image of an Executable

As a program executable has many sections (note that the user can define their own, and that compilers define theirs without any notice), one has to specify the placement of each section as well as the type of memory (RAM or ROM) the sections will be placed into. For instance, a program compiled for a Personal Computer will see all the sections to go to RAM, while a program destined to be embedded will see some of his sections going into the ROM.

The connection between a section and where that section is loaded into memory is made at link time. One has to let the linker know where the different sections are to be placed once they are in memory.

The following example shows a simple layout of program sections. With some object formats, there are many more sections but the basic layout is conceptually similar.

.text	RAM or ROM
.data	RAM
.bss	RAM

4.4 Example Linker Command Script

The GNU linker has a command language to specify the image format. This command language can be quite complicated but most of what is required can be learned by careful examination of a well-documented example. The following is a heavily commented version of the linker script used with the the gen68340 BSP This file can be found at \$BSP340_ROOT/startup/linkcmds.

```

1 /*
2  * Specify that the output is to be coff-m68k regardless of what the
3  * native object format is.
4  */
5 OUTPUT_FORMAT(coff-m68k)
6 /*
7  * Set the amount of RAM on the target board.
8  *
9  * NOTE: The default may be overridden by passing an argument to ld.
10 */
11 RamSize = DEFINED(RamSize) ? RamSize : 4M;
12 /*
13  * Set the amount of RAM to be used for the application heap. Objects
14  * allocated using malloc() come from this area. Having a tight heap
15  * size is somewhat difficult and multiple attempts to squeeze it may
16  * be needed reducing memory usage is important. If all objects are
17  * allocated from the heap at system initialization time, this eases
18  * the sizing of the application heap.
19  *
20  * NOTE 1: The default may be overridden by passing an argument to ld.
21  *
22  * NOTE 2: The TCP/IP stack requires additional memory in the Heap.
23  *
24  * NOTE 3: The GNAT/RTEMS run-time requires additional memory in
25  * the Heap.
26  */
27 HeapSize = DEFINED(HeapSize) ? HeapSize : 0x10000;
28 /*
29  * Set the size of the starting stack used during BSP initialization
30  * until first task switch. After that point, task stacks allocated
31  * by RTEMS are used.
32  *
33  * NOTE: The default may be overridden by passing an argument to ld.
34  */
35 StackSize = DEFINED(StackSize) ? StackSize : 0x1000;
36 /*
37  * Starting addresses and length of RAM and ROM.
38  *
39  * The addresses must be valid addresses on the board. The
40  * Chip Selects should be initialized such that the code addresses
41  * are valid.
42  */
43 MEMORY {
44 ram : ORIGIN = 0x10000000, LENGTH = 4M
45 rom : ORIGIN = 0x01000000, LENGTH = 4M
46 }
47 /*
48  * This is for the network driver. See the Networking documentation
49  * for more details.
50  */

```

```

51 ETHERNET_ADDRESS =
52 DEFINED(ETHERNET_ADDRESS) ? ETHERNET_ADDRESS : 0xDEAD12;
53 /*
54 * The following defines the order in which the sections should go.
55 * It also defines a number of variables which can be used by the
56 * application program.
57 *
58 * NOTE: Each variable appears with 1 or 2 leading underscores to
59 *       ensure that the variable is accessible from C code with a
60 *       single underscore. Some object formats automatically add
61 *       a leading underscore to all C global symbols.
62 */
63 SECTIONS {
64 /*
65 * Make the RomBase variable available to the application.
66 */
67 _RamSize = RamSize;
68 __RamSize = RamSize;
69 /*
70 * Boot PROM - Set the RomBase variable to the start of the ROM.
71 */
72 rom : {
73   _RomBase = .;
74   __RomBase = .;
75 } >rom
76 /*
77 * Dynamic RAM - set the RamBase variable to the start of the RAM.
78 */
79 ram : {
80   _RamBase = .;
81   __RamBase = .;
82 } >ram
83 /*
84 * Text (code) goes into ROM
85 */
86 .text : {
87   /*
88   * Create a symbol for each object (.o).
89   */
90   CREATE_OBJECT_SYMBOLS
91   /*
92   * Put all the object files code sections here.
93   */
94   *(.text)
95   . = ALIGN (16);      /* go to a 16-byte boundary */
96   /*
97   * C++ constructors and destructors
98   *
99   * NOTE: See the CROSSGCC mailing-list FAQ for
100  *       more details about the "[.....]".
101  */
102  __CTOR_LIST__ = .;
103  [.....]
104  __DTOR_END__ = .;
105  /*
106  * Declares where the .text section ends.
107  */

```

```

108  etext = .;
109  _etext = .;
110 } >rom
111 /*
112  * Exception Handler Frame section
113  */
114 .eh_fram : {
115  . = ALIGN (16);
116  *(.eh_fram)
117 } >ram
118 /*
119  * GCC Exception section
120  */
121 .gcc_exc : {
122  . = ALIGN (16);
123  *(.gcc_exc)
124 } >ram
125 /*
126  * Special variable to let application get to the dual-ported
127  * memory.
128  */
129 dpram : {
130  m340 = .;
131  _m340 = .;
132  . += (8 * 1024);
133 } >ram
134 /*
135  * Initialized Data section goes in RAM
136  */
137 .data : {
138  copy_start = .;
139  *(.data)
140  . = ALIGN (16);
141  _edata = .;
142  copy_end = .;
143 } >ram
144 /*
145  * Uninitialized Data section goes in ROM
146  */
147 .bss : {
148  /*
149  * M68K specific: Reserve some room for the Vector Table
150  * (256 vectors of 4 bytes).
151  */
152  M68Kvec = .;
153  _M68Kvec = .;
154  . += (256 * 4);
155  /*
156  * Start of memory to zero out at initialization time.
157  */
158  clear_start = .;
159  /*
160  * Put all the object files uninitialized data sections
161  * here.
162  */
163  *(.bss)
164  *(COMMON)

```

```
165 . = ALIGN (16);
166 _end = .;
167 /*
168  * Start of the Application Heap
169  */
170 _HeapStart = .;
171 __HeapStart = .;
172 . += HeapSize;
173 /*
174  * The Starting Stack goes after the Application Heap.
175  * M68K stack grows down so start at high address.
176  */
177 . += StackSize;
178 . = ALIGN (16);
179 stack_init = .;
180 clear_end = .;
181 /*
182  * The RTEMS Executive Workspace goes here. RTEMS
183  * allocates tasks, stacks, semaphores, etc. from this
184  * memory.
185  */
186 _WorkspaceBase = .;
187 __WorkspaceBase = .;
188 } >ram
```

4.5 Initialized Data

Now there's a problem with the initialized data: the `.data` section has to be in RAM as this data may be modified during the program execution. But how will the values be initialized at boot time?

One approach is to place the entire program image in RAM and reload the image in its entirety each time the program is run. This is fine for use in a debug environment where a high-speed connection is available between the development host computer and the target. But even in this environment, it is cumbersome.

The solution is to place a copy of the initialized data in a separate area of memory and copy it into the proper location each time the program is started. It is common practice to place a copy of the initialized `.data` section at the end of the code (`.text`) section in ROM when building a PROM image. The GNU tool `objcopy` can be used for this purpose.

The following figure illustrates the steps a linked program goes through to become a downloadable image.

<code>.data (RAM)</code>		<code>.data (RAM)</code>	
<code>.bss (RAM)</code>		<code>.bss (RAM)</code>	
<code>.text (ROM)</code>		<code>.text (ROM)</code>	<code>.text</code>
copy of <code>.data (ROM)</code>		copy of <code>.data</code>	
Step 1		Step 2	Step 3

In Step 1, the program is linked together using the BSP linker script.

In Step 2, a copy is made of the `.data` section and placed after the `.text` section so it can be placed in PROM. This step is done after the linking time. There is an example of doing this in the file `$RTEMS_ROOT/make/custom/gen68340.cfg`:

```

1 # make a PROM image using objcopy
2 m68k-rtms-objcopy --adjust-section-vma \
3 .data=`m68k-rtms-objdump --section-headers $(basename $@).exe | awk ' [...] '\` \
4 $(basename $@).exe

```

Note: The address of the “copy of `.data` section” is created by extracting the last address in the `.text` section with an `awk` script. The details of how this is done are not relevant.

Step 3 shows the final executable image as it logically appears in the target's non-volatile program memory. The board initialization code will copy the “copy of `.data` section” (which are stored in ROM) to their reserved location in RAM.

MISCELLANEOUS SUPPORT FILES

5.1 GCC Compiler Specifications File

The file `bsp_specs` defines the start files and libraries that are always used with this BSP. The format of this file is admittedly cryptic and this document will make no attempt to explain it completely. Below is the `bsp_specs` file from the PowerPC psim BSP:

```
1 %rename endfile old_endfile
2 %rename startfile old_startfile
3 %rename link old_link
4 *startfile:
5 %{!qrtems: %(old_startfile)} \
6 %{!nostdlib: %{qrtems: crt0.o%$ rtms_crti.o%$ crtbegin.o%$ start.o%$}}
7 *link:
8 %{!qrtems: %(old_link)} %{qrtems: -Qy -dp -Bstatic -e _start -u __vectors}
9 *endfile:
10 %{!qrtems: %(old_endfile)} %{qrtems: crtend.o%$ crtn.o%$}
```

The first section of this file renames the built-in definition of some specification variables so they can be augmented without embedded their original definition. The subsequent sections specify what behavior is expected when the `-qrtems` option is specified.

The `*startfile` section specifies that the BSP specific file `start.o` will be used instead of `crt0.o`. In addition, various EABI support files (`crti.o` etc.) will be linked in with the executable.

The `*link` section adds some arguments to the linker when it is invoked by GCC to link an application for this BSP.

The format of this file is specific to the GNU Compiler Suite. The argument used to override and extend the compiler built-in specifications is available in all recent GCC versions. The `-specs` option is present in all egcs distributions and gcc distributions starting with version 2.8.0.

5.2 README Files

Most BSPs provide one or more README files. Generally, there is a README file at the top of the BSP source. This file describes the board and its hardware configuration, provides vendor information, local configuration information, information on downloading code to the board, debugging, etc.. The intent of this file is to help someone begin to use the BSP faster.

A README file in a BSP subdirectory typically explains something about the contents of that subdirectory in greater detail. For example, it may list the documentation available for a particular peripheral controller and how to obtain that documentation. It may also explain some particularly cryptic part of the software in that directory or provide rationale on the implementation.

5.3 Times

This file contains the results of the RTEMS Timing Test Suite. It is in a standard format so that results from one BSP can be easily compared with those of another target board.

If a BSP supports multiple variants, then there may be multiple times files. Usually these are named `times.VARIANTn`.

5.4 Tools Subdirectory

Some BSPs provide additional tools that aid in using the target board. These tools run on the development host and are built as part of building the BSP. Most common is a script to automate running the RTEMS Test Suites on the BSP. Examples of this include:

- powerpc/psim includes scripts to ease use of the simulator
- m68k/mvme162 includes a utility to download across the VMEbus into target memory if the host is a VMEbus board in the same chassis.

5.5 bsp.h Include File

The file `include/bsp.h` contains prototypes and definitions specific to this board. Every BSP is required to provide a `bsp.h`. The best approach to writing a `bsp.h` is copying an existing one as a starting point.

Many `bsp.h` files provide prototypes of variables defined in the linker script (`linkcmds`).

5.6 tm27.h Include File

The tm27 test from the RTEMS Timing Test Suite is designed to measure the length of time required to vector to and return from an interrupt handler. This test requires some help from the BSP to know how to cause and manipulate the interrupt source used for this measurement. The following is a list of these:

- `MUST_WAIT_FOR_INTERRUPT` - modifies behavior of tm27.
- `Install_tm27_vector` - installs the interrupt service routine for the Interrupt Benchmark Test (tm27).
- `Cause_tm27_intr` - generates the interrupt source used in the Interrupt Benchmark Test (tm27).
- `Clear_tm27_intr` - clears the interrupt source used in the Interrupt Benchmark Test (tm27).
- `Lower_tm27_intr` - lowers the interrupt mask so the interrupt source used in the Interrupt Benchmark Test (tm27) can generate a nested interrupt.

All members of the Timing Test Suite are designed to run *WITHOUT* the Clock Device Driver installed. This increases the predictability of the tests' execution as well as avoids occasionally including the overhead of a clock tick interrupt in the time reported. Because of this it is sometimes possible to use the clock tick interrupt source as the source of this test interrupt. On other architectures, it is possible to directly force an interrupt to occur.

5.7 Calling Overhead File

The file `include/coverhd.h` contains the overhead associated with invoking each directive. This overhead consists of the execution time required to package the parameters as well as to execute the “jump to subroutine” and “return from subroutine” sequence. The intent of this file is to help separate the calling overhead from the actual execution time of a directive. This file is only used by the tests in the RTEMS Timing Test Suite.

The numbers in this file are obtained by running the “Timer Overhead” `tmoverhd` test. The numbers in this file may be 0 and no overhead is subtracted from the directive execution times reported by the Timing Suite.

There is a shared implementation of `coverhd.h` which sets all of the overhead constants to 0. On faster processors, this is usually the best alternative for the BSP as the calling overhead is extremely small. This file is located at:

```
1 c/src/lib/libbsp/shared/include/coverhd.h
```

5.8 sbrk() Implementation

Although nearly all BSPs give all possible memory to the C Program Heap at initialization, it is possible for a BSP to configure the initial size of the heap small and let it grow on demand. If the BSP wants to dynamically extend the heap used by the C Library memory allocation routines (i.e. malloc family), then the “sbrk” routine must be functional. The following is the prototype for this routine:

```
1 void * sbrk(size_t increment)
```

The increment amount is based upon the `sbrk_amount` parameter passed to the `bsp_libc_init` during system initialization.

If your BSP does not want to support dynamic heap extension, then you do not have to do anything special. However, if you want to support `sbrk`, you must provide an implementation of this method and define `CONFIGURE_MALLOC_BSP_SUPPORTS_SBRK` in `bsp.h`. This informs `rtems/confdefs.h` to configure the Malloc Family Extensions which support `sbrk`.

5.9 bsp_fatal_extension() - Cleanup the Hardware

The `bsp_fatal_extension()` is an optional BSP specific initial extension invoked once a fatal system state is reached. Most of the BSPs use the same shared version of `bsp_fatal_extension()` that does nothing or performs a system reset. This implementation is located in the following file:

```
1 c/src/lib/libbsp/shared/bspclean.c
```

The `bsp_fatal_extension()` routine can be used to return to a ROM monitor, insure that interrupt sources are disabled, etc.. This routine is the last place to ensure a clean shutdown of the hardware. The fatal source, internal error indicator, and the fatal code arguments are available to evaluate the fatal condition. All of the non-fatal shutdown sequences ultimately pass their exit status to `rtems_shutdown_executive` and this is what is passed to this routine in case the fatal source is `RTEMS_FATAL_SOURCE_EXIT`.

On some BSPs, it prints a message indicating that the application completed execution and waits for the user to press a key before resetting the board. The PowerPC/gen83xx and PowerPC/gen5200 BSPs do this when they are built to support the FreeScale evaluation boards. This is convenient when using the boards in a development environment and may be disabled for production use.

5.10 Configuration Macros

Each BSP can define macros in `bsp.h` which alter some of the the default configuration parameters in `rtems/confdefs.h`. This section describes those macros:

- `CONFIGURE_MALLOC_BSP_SUPPORTS_SBRK` must be defined if the BSP has proper support for `sbrk`. This is discussed in more detail in the previous section.
- `BSP_IDLE_TASK_BODY` may be defined to the entry point of a BSP specific IDLE thread implementation. This may be overridden if the application provides its own IDLE task implementation.
- `BSP_IDLE_TASK_STACK_SIZE` may be defined to the desired default stack size for the IDLE task as recommended when using this BSP.
- `BSP_INTERRUPT_STACK_SIZE` may be defined to the desired default interrupt stack size as recommended when using this BSP. This is sometimes required when the BSP developer has knowledge of stack intensive interrupt handlers.
- `BSP_ZERO_WORKSPACE_AUTOMATICALLY` is defined when the BSP requires that RTEMS zero out the RTEMS C Program Heap at initialization. If the memory is already zeroed out by a test sequence or boot ROM, then the boot time can be reduced by not zeroing memory twice.
- `BSP_DEFAULT_UNIFIED_WORK_AREAS` is defined when the BSP recommends that the unified work areas configuration should always be used. This is desirable when the BSP is known to always have very little RAM and thus saving memory by any means is desirable.

5.11 set_vector() - Install an Interrupt Vector

On targets with Simple Vectored Interrupts, the BSP must provide an implementation of the `set_vector` routine. This routine is responsible for installing an interrupt vector. It invokes the support routines necessary to install an interrupt handler as either a “raw” or an RTEMS interrupt handler. Raw handlers bypass the RTEMS interrupt structure and are responsible for saving and restoring all their own registers. Raw handlers are useful for handling traps, debug vectors, etc.

The `set_vector` routine is a central place to perform interrupt controller manipulation and encapsulate that information. It is usually implemented as follows:

```
1 rtems_isr_entry set_vector(          /* returns old vector */
2   rtems_isr_entry handler,          /* isr routine      */
3   rtems_vector_number vector,       /* vector number    */
4   int type                          /* RTEMS or RAW intr */
5 )
6 {
7   if the type is RAW
8     install the raw vector
9   else
10    use rtems_interrupt_catch to install the vector
11    perform any interrupt controller necessary to unmask the interrupt source
12    return the previous handler
13 }
```

Note: The i386, PowerPC and ARM ports use a Programmable Interrupt Controller model which does not require the BSP to implement `set_vector`. BSPs for these architectures must provide a different set of support routines.

5.12 Interrupt Delay Profiling

The RTEMS profiling needs support by the BSP for the interrupt delay times. In case profiling is enabled via the RTEMS build configuration option `--enable-profiling` (in this case the pre-processor symbol `RTEMS_PROFILING` is defined) a BSP may provide data for the interrupt delay times. The BSP can feed interrupt delay times with the `_Profiling_Update_max_interrupt_delay()` function (`#include <rtems/score/profiling.h>`). For an example please have a look at `c/src/lib/libbsp/sparc/leon3/clock/ckinit.c`.

5.13 Programmable Interrupt Controller API

A BSP can use the PIC API to install Interrupt Service Routines through a set of generic methods. In order to do so, the header files `libbsp/shared/include/irq-generic.h` and `libbsp/shared/include/irq-info.h` must be included by the bsp specific `irq.h` file present in the `include/` directory. The `irq.h` acts as a BSP interrupt support configuration file which is used to define some important MACROS. It contains the declarations for any required global functions like `bsp_interrupt_dispatch()`. Thus later on, every call to the PIC interface requires including `<bsp/irq.h>`

The generic interrupt handler table is initialized by invoking the `bsp_interrupt_initialize()` method from `bsp_start()` in the `bspstart.c` file which sets up this table to store the ISR addresses, whose size is based on the definition of macros, `BSP_INTERRUPT_VECTOR_MIN` and `BSP_INTERRUPT_VECTOR_MAX` in `include/bsp.h`

For the generic handler table to properly function, some bsp specific code is required, that should be present in `irq/irq.c`. The bsp-specific functions required to be written by the BSP developer are :

- `bsp_interrupt_facility_initialize()` contains bsp specific interrupt initialization code (Clear Pending interrupts by modifying registers, etc.). This method is called from `bsp_interrupt_initialize()` internally while setting up the table.
- `bsp_interrupt_handler_default()` acts as a fallback handler when no ISR address has been provided corresponding to a vector in the table.
- `bsp_interrupt_dispatch()` service the ISR by handling any bsp specific code & calling the generic method `bsp_interrupt_handler_dispatch()` which in turn services the interrupt by running the ISR after looking it up in the table. It acts as an entry to the interrupt switchboard, since the bsp branches to this function at the time of occurrence of an interrupt.
- `bsp_interrupt_vector_enable()` enables interrupts and is called in `irq-generic.c` while setting up the table.
- `bsp_interrupt_vector_disable()` disables interrupts and is called in `irq-generic.c` while setting up the table & during other important parts.

An interrupt handler is installed or removed with the help of the following functions :

```

1 rtems_status_code rtems_interrupt_handler_install( /* returns status code */
2   rtems_vector_number  vector,                /* interrupt vector */
3   const char           *info,                 /* custom identification text */
4   rtems_option         options,               /* Type of Interrupt */
5   rtems_interrupt_handler handler,          /* interrupt handler */
6   void                *arg                   /* parameter to be passed
7                                           to handler at the time of
8                                           invocation */
9 )
10 rtems_status_code rtems_interrupt_handler_remove( /* returns status code */
11   rtems_vector_number  vector,                /* interrupt vector */
12   rtems_interrupt_handler handler,          /* interrupt handler */
13   void                *arg                   /* parameter to be passed to handler */
14 )

```

ADA95 INTERRUPT SUPPORT

6.1 Introduction

This chapter describes what is required to enable Ada interrupt and error exception handling when using GNAT over RTEMS.

The GNAT Ada95 interrupt support RTEMS was developed by Jiri Gaisler <jgais@ws.estec.esa.nl> who also wrote this chapter.

6.2 Mapping Interrupts to POSIX Signals

In Ada95, interrupts can be attached with the `interrupt_attach` pragma. For most systems, the gnat run-time will use POSIX signal to implement the interrupt handling, mapping one signal per interrupt. For interrupts to be propagated to the attached Ada handler, the corresponding signal must be raised when the interrupt occurs.

The same mechanism is used to generate Ada error exceptions. Three error exceptions are defined: program, constraint and storage error. These are generated by raising the predefined signals: SIGILL, SIGFPE and SIGSEGV. These signals should be raised when a spurious or erroneous trap occurs.

To enable gnat interrupt and error exception support for a particular BSP, the following has to be done:

- Write an interrupt/trap handler that will raise the corresponding signal depending on the interrupt/trap number.
- Install the interrupt handler for all interrupts/traps that will be handled by gnat (including spurious).
- At startup, gnat calls `__gnat_install_handler()`. The BSP must provide this function which installs the interrupt/trap handlers.

Which CPU-interrupt will generate which signal is implementation defined. There are 32 POSIX signals (1 - 32), and all except the three error signals (SIGILL, SIGFPE and SIGSEGV) can be used. I would suggest to use the upper 16 (17 - 32) which do not have an assigned POSIX name.

Note that the pragma `interrupt_attach` will only bind a signal to a particular Ada handler - it will not unmask the interrupt or do any other things to enable it. This have to be done separately, typically by writing various device register.

6.3 Example Ada95 Interrupt Program

An example program (`irq_test`) is included in the Ada examples package to show how interrupts can be handled in Ada95. Note that generation of the test interrupt (`irqforce.c`) is BSP specific and must be edited.

Note: The `irq_test` example was written for the SPARC/ERC32 BSP.

6.4 Version Requirements

With RTEMS 4.0, a patch was required to `psignal.c` in RTEMS sources (to correct a bug associated to the default action of signals 15-32). The SPARC/ERC32 RTEMS BSP includes the “gnatsupp” subdirectory that can be used as an example for other BSPs.

With GNAT 3.11p, a patch is required for `a-init.c` to invoke the BSP specific routine that installs the exception handlers.

INITIALIZATION CODE

7.1 Introduction

The initialization code is the first piece of code executed when there's a reset/reboot. Its purpose is to initialize the board for the application. This chapter contains a narrative description of the initialization process followed by a description of each of the files and routines commonly found in the BSP related to initialization. The remainder of this chapter covers special issues which require attention such as interrupt vector table and chip select initialization.

Most of the examples in this chapter will be based on the SPARC/ERC32 and m68k/gen68340 BSP initialization code. Like most BSPs, the initialization for these BSP is divided into two subdirectories under the BSP source directory. The BSP source code for these BSPs is in the following directories:

```
1 c/src/lib/libbsp/m68k/gen68340
2 c/src/lib/libbsp/sparc/erc32
```

Both BSPs contain startup code written in assembly language and C. The gen68340 BSP has its early initialization start code in the `start340` subdirectory and its C startup code in the `startup` directory. In the `start340` directory are two source files. The file `startfor340only.s` is the simpler of these files as it only has initialization code for a MC68340 board. The file `start340.s` contains initialization for a 68349 based board as well.

Similarly, the ERC32 BSP has startup code written in assembly language and C. However, this BSP shares this code with other SPARC BSPs. Thus the `Makefile.am` explicitly references the following files for this functionality.

```
1 ../../sparc/shared/start.S
```

Note: In most BSPs, the directory named `start340` in the gen68340 BSP would be simply named `start` or `start` followed by a BSP designation.

7.2 Required Global Variables

Although not strictly part of initialization, there are a few global variables assumed to exist by reusable device drivers. These global variables should only be defined by the BSP when using one of these device drivers.

The BSP author probably should be aware of the Configuration Table structure generated by `<rtcms/confdefs.h>` during debug but should not explicitly reference it in the source code. There are helper routines provided by RTEMS to access individual fields.

In older RTEMS versions, the BSP included a number of required global variables. We have made every attempt to eliminate these in the interest of simplicity.

7.3 Board Initialization

This section describes the steps an application goes through from the time the first BSP code is executed until the first application task executes.

The initialization flows from assembly language start code to the shared `bootcard.c` framework then through the C Library, RTEMS, device driver initialization phases, and the context switch to the first application task. After this, the application executes until it calls `exit`, `rtems_shutdown_executive`, or some other normal termination initiating routine and a fatal system state is reached. The optional `bsp_fatal_extension` initial extension can perform BSP specific system termination.

The routines invoked during this will be discussed and their location in the RTEMS source tree pointed out as we discuss each.

7.3.1 Start Code - Assembly Language Initialization

The assembly language code in the directory `start` is the first part of the application to execute. It is responsible for initializing the processor and board enough to execute the rest of the BSP. This includes:

- initializing the stack
- zeroing out the uninitialized data section `.bss`
- disabling external interrupts
- copy the initialized data from ROM to RAM

The general rule of thumb is that the start code in assembly should do the minimum necessary to allow C code to execute to complete the initialization sequence.

The initial assembly language start code completes its execution by invoking the shared routine `boot_card()`.

The label (symbolic name) associated with the starting address of the program is typically called `start`. The start object file is the first object file linked into the program image so it is ensured that the start code is at offset 0 in the `.text` section. It is the responsibility of the linker script in conjunction with the compiler specifications file to put the start code in the correct location in the application image.

7.3.2 `boot_card()` - Boot the Card

The `boot_card()` is the first C code invoked. This file is the core component in the RTEMS BSP Initialization Framework and provides the proper sequencing of initialization steps for the BSP, RTEMS and device drivers. All BSPs use the same shared version of `boot_card()` which is located in the following file:

```
1 c/src/lib/libbsp/shared/bootcard.c
```

The `boot_card()` routine performs the following functions:

- It disables processor interrupts.
- It sets the command line argument variables for later use by the application.

- It invokes the BSP specific routine `bsp_work_area_initialize()` which is supposed to initialize the RTEMS Workspace and the C Program Heap. Usually the default implementation in `c/src/lib/libbsp/shared/bspgetworkarea.c` should be sufficient. Custom implementations can use `bsp_work_area_initialize_default()` or `bsp_work_area_initialize_with_table()` available as inline functions from `"#include <bsp/bootcard.h>"`.
- It invokes the BSP specific routine `bsp_start()` which is written in C and thus able to perform more advanced initialization. Often MMU, bus and interrupt controller initialization occurs here. Since the RTEMS Workspace and the C Program Heap was already initialized by `bsp_work_area_initialize()`, this routine may use `malloc()`, etc.
- It invokes the RTEMS directive `rtems_initialize_data_structures()` to initialize the RTEMS executive to a state where objects can be created but tasking is not enabled.
- It invokes the BSP specific routine `bsp_libc_init()` to initialize the C Library. Usually the default implementation in `c/src/lib/libbsp/shared/bsplibc.c` should be sufficient.
- It invokes the RTEMS directive `rtems_initialize_before_drivers()` to initialize the MPC1 Server thread in a multiprocessor configuration and execute API specific extensions.
- It invokes the BSP specific routine `bsp_predriver_hook`. For most BSPs, the implementation of this routine does nothing.
- It invokes the RTEMS directive `rtems_initialize_device_drivers()` to initialize the statically configured set of device drivers in the order they were specified in the Configuration Table.
- It invokes the BSP specific routine `bsp_postdriver_hook`. For most BSPs, the implementation of this routine does nothing. However, some BSPs use this hook and perform some initialization which must be done at this point in the initialization sequence. This is the last opportunity for the BSP to insert BSP specific code into the initialization sequence.
- It invokes the RTEMS directive `rtems_initialize_start_multitasking()` which initiates multitasking and performs a context switch to the first user application task and may enable interrupts as a side-effect of that context switch. The context switch saves the executing context. The application runs now. The directive `rtems_shutdown_executive()` will return to the saved context. The `exit()` function will use this directive. After a return to the saved context a fatal system state is reached. The fatal source is `RTEMS_FATAL_SOURCE_EXIT` with a fatal code set to the value passed to `rtems_shutdown_executive()`. The enabling of interrupts during the first context switch is often the source for fatal errors during BSP development because the BSP did not clear and/or disable all interrupt sources and a spurious interrupt will occur. When in the context of the first task but before its body has been entered, any C++ Global Constructors will be invoked.

That's it. We just went through the entire sequence.

7.3.3 `bsp_work_area_initialize()` - BSP Specific Work Area Initialization

This is the first BSP specific C routine to execute during system initialization. It must initialize the support for allocating memory from the C Program Heap and RTEMS Workspace commonly referred to as the work areas. Many BSPs place the work areas at the end of RAM although this is certainly not a requirement. Usually the default implementation in `file:c/src/lib/libbsp/shared/bspgetworkarea.c` should be sufficient. Custom implementations

can use `bsp_work_area_initialize_default()` or `bsp_work_area_initialize_with_table()` available as inline functions from `#include <bsp/bootcard.h>`.

7.3.4 `bsp_start()` - BSP Specific Initialization

This is the second BSP specific C routine to execute during system initialization. It is called right after `bsp_work_area_initialize()`. The `bsp_start()` routine often performs required fundamental hardware initialization such as setting bus controller registers that do not have a direct impact on whether or not C code can execute. The interrupt controllers are usually initialized here. The source code for this routine is usually found in the file `c/src/lib/libbsp/$CPU/$BSP/startup/bspstart.c`. It is not allowed to create any operating system objects, e.g. RTEMS semaphores.

After completing execution, this routine returns to the `boot_card()` routine. In case of errors, the initialization should be terminated via `bsp_fatal()`.

7.3.5 `bsp_predriver_hook()` - BSP Specific Predriver Hook

The `bsp_predriver_hook()` method is the BSP specific routine that is invoked immediately before the device drivers are initialized. RTEMS initialization is complete but interrupts and tasking are disabled.

The BSP may use the shared version of this routine which is empty. Most BSPs do not provide a specific implementation of this callback.

7.3.6 Device Driver Initialization

At this point in the initialization sequence, the initialization routines for all of the device drivers specified in the Device Driver Table are invoked. The initialization routines are invoked in the order they appear in the Device Driver Table.

The Driver Address Table is part of the RTEMS Configuration Table. It defines device drivers entry points (initialization, open, close, read, write, and control). For more information about this table, please refer to the *Configuring a System* chapter in the *RTEMS Application C User's Guide*.

The RTEMS initialization procedure calls the initialization function for every driver defined in the RTEMS Configuration Table (this allows one to include only the drivers needed by the application).

All these primitives have a major and a minor number as arguments:

- the major number refers to the driver type,
- the minor number is used to control two peripherals with the same driver (for instance, we define only one major number for the serial driver, but two minor numbers for channel A and B if there are two channels in the UART).

7.3.7 RTEMS Postdriver Callback

The `bsp_postdriver_hook()` BSP specific routine is invoked immediately after the device drivers and MPCIE are initialized. Interrupts and tasking are disabled.

Most BSPs use the shared implementation of this routine which is responsible for opening the device `/dev/console` for standard input, output and error if the application has configured the Console Device Driver. This file is located at:

```
1 c/src/lib/libbsp/shared/bsppost.c
```

7.4 The Interrupt Vector Table

The Interrupt Vector Table is called different things on different processor families but the basic functionality is the same. Each entry in the Table corresponds to the handler routine for a particular interrupt source. When an interrupt from that source occurs, the specified handler routine is invoked. Some context information is saved by the processor automatically when this happens. RTEMS saves enough context information so that an interrupt service routine can be implemented in a high level language.

On some processors, the Interrupt Vector Table is at a fixed address. If this address is in RAM, then usually the BSP only has to initialize it to contain pointers to default handlers. If the table is in ROM, then the application developer will have to take special steps to fill in the table.

If the base address of the Interrupt Vector Table can be dynamically changed to an arbitrary address, then the RTEMS port to that processor family will usually allocate its own table and install it. For example, on some members of the Motorola MC68xxx family, the Vector Base Register (`vbr`) contains this base address.

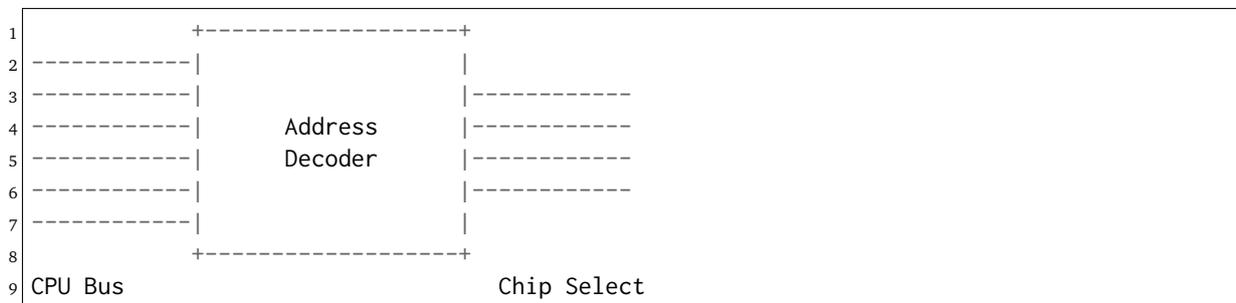
7.4.1 Interrupt Vector Table on the gen68340 BSP

The `gen68340` BSP provides a default Interrupt Vector Table in the file `$BSP_ROOT/start340/start340.s`. After the entry label is the definition of space reserved for the table of interrupts vectors. This space is assigned the symbolic name of `__uhoh` in the `gen68340` BSP.

At `__uhoh` label is the default interrupt handler routine. This routine is only called when an unexpected interrupts is raised. One can add their own routine there (in that case there's a call to a routine - `$BSP_ROOT/startup/dumpanic.c` - that prints which address caused the interrupt and the contents of the registers, stack, etc.), but this should not return.

7.5 Chip Select Initialization

When the microprocessor accesses a memory area, address decoding is handled by an address decoder, so that the microprocessor knows which memory chip(s) to access. The following figure illustrates this:



The Chip Select registers must be programmed such that they match the linkcmds settings. In the gen68340 BSP, ROM and RAM addresses can be found in both the linkcmds and initialization code, but this is not a great way to do this. It is better to define addresses in the linker script.

7.6 Integrated Processor Registers Initialization

The CPUs used in many embedded systems are highly complex devices with multiple peripherals on the CPU itself. For these devices, there are always some specific integrated processor registers that must be initialized. Refer to the processors' manuals for details on these registers and be VERY careful programming them.

7.7 Data Section Recopy

The next initialization part can be found in `$BSP340_ROOT/start340/init68340.c`. First the Interrupt Vector Table is copied into RAM, then the data section recopy is initiated (`_CopyDataClearBSSAndStart` in `$BSP340_ROOT/start340/startfor340only.s`).

This code performs the following actions:

- copies the `.data` section from ROM to its location reserved in RAM (see *Chapter 4 Section 5 - Initialized Data* (page 25) for more details about this copy),
- clear `.bss` section (all the non-initialized data will take value 0).

7.8 The RTEMS Configuration Table

The RTEMS configuration table contains the maximum number of objects RTEMS can handle during the application (e.g. maximum number of tasks, semaphores, etc.). It's used to allocate the size for the RTEMS inner data structures.

The RTEMS configuration table is application dependent, which means that one has to provide one per application. It is usually defined by defining macros and including the header file `<rtems/confdefs.h>`. In simple applications such as the tests provided with RTEMS, it is commonly found in the main module of the application. For more complex applications, it may be in a file by itself.

The header file `<rtems/confdefs.h>` defines a constant table named `Configuration`. With RTEMS 4.8 and older, it was accepted practice for the BSP to copy this table into a modifiable copy named `BSP_Configuration`. This copy of the table was modified to define the base address of the RTEMS Executive Workspace as well as to reflect any BSP and device driver requirements not automatically handled by the application. In 4.9 and newer, we have eliminated the BSP copies of the configuration tables and are making efforts to make the configuration information generated by `<rtems/confdefs.h>` constant and read only.

For more information on the RTEMS Configuration Table, refer to the *RTEMS Application C User's Guide*.

CONSOLE DRIVER

8.1 Introduction

This chapter describes the operation of a console driver using the RTEMS POSIX Termios support. Traditionally RTEMS has referred to all serial device drivers as console device drivers. A console driver can be used to do raw data processing in addition to the “normal” standard input and output device functions required of a console.

The serial driver may be called as the consequence of a C Library call such as `printf` or `scanf` or directly via the “read” or `write` system calls. There are two main functioning modes:

- `console`: formatted input/output, with special characters (end of line, tabulations, etc.) recognition and processing,
- `raw`: permits raw data processing.

One may think that two serial drivers are needed to handle these two types of data, but Termios permits having only one driver.

8.2 Termios

Termios is a standard for terminal management, included in the POSIX 1003.1b standard. As part of the POSIX and Open Group Single UNIX Specification, is commonly provided on UNIX implementations. The Open Group has the termios portion of the POSIX standard online at <http://opengroup.org/onlinepubs/007908775/xbd/termios.html>. The requirements for the <termios.h> file are also provided and are at <http://opengroup.org/onlinepubs/007908775/xsh/termios.h.html>.

Having RTEMS support for Termios is beneficial because:

- from the user's side because it provides standard primitive operations to access the terminal and change configuration settings. These operations are the same under UNIX and RTEMS.
- from the BSP developer's side because it frees the developer from dealing with buffer states and mutual exclusions on them. Early RTEMS console device drivers also did their own special character processing.
- it is part of an internationally recognized standard.
- it makes porting code from other environments easier.

Termios support includes:

- raw and console handling,
- blocking or non-blocking characters receive, with or without Timeout.

At this time, RTEMS documentation does not include a thorough discussion of the Termios functionality. For more information on Termios, type `man termios` on a Unix box or point a web browser at <http://www.freebsd.org/cgi/man.cgi>.

8.3 Driver Functioning Modes

There are generally three main functioning modes for an UART (Universal Asynchronous Receiver-Transmitter, i.e. the serial chip):

- polled mode
- interrupt driven mode
- task driven mode

In polled mode, the processor blocks on sending/receiving characters. This mode is not the most efficient way to utilize the UART. But polled mode is usually necessary when one wants to print an error message in the event of a fatal error such as a fatal error in the BSP. This is also the simplest mode to program. Polled mode is generally preferred if the serial port is to be used primarily as a debug console. In a simple polled driver, the software will continuously check the status of the UART when it is reading or writing to the UART. Termios improves on this by delaying the caller for 1 clock tick between successive checks of the UART on a read operation.

In interrupt driven mode, the processor does not block on sending/receiving characters. Data is buffered between the interrupt service routine and application code. Two buffers are used to insulate the application from the relative slowness of the serial device. One of the buffers is used for incoming characters, while the other is used for outgoing characters.

An interrupt is raised when a character is received by the UART. The interrupt subroutine places the incoming character at the end of the input buffer. When an application asks for input, the characters at the front of the buffer are returned.

When the application prints to the serial device, the outgoing characters are placed at the end of the output buffer. The driver will place one or more characters in the UART (the exact number depends on the UART) An interrupt will be raised when all the characters have been transmitted. The interrupt service routine has to send the characters remaining in the output buffer the same way. When the transmitting side of the UART is idle, it is typically necessary to prime the transmitter before the first interrupt will occur.

The task driven mode is similar to interrupt driven mode, but the actual data processing is done in dedicated tasks instead of interrupt routines.

8.4 Serial Driver Functioning Overview

The following Figure shows how a Termios driven serial driver works: Figure not included in ASCII version

The following list describes the basic flow.

- the application programmer uses standard C library call (printf, scanf, read, write, etc.),
- C library (ctx.g. RedHat (formerly Cygnus) Newlib) calls the RTEMS system call interface. This code can be found in the:file:cpukit/libcsupport/src directory.
- Glue code calls the serial driver entry routines.

8.4.1 Basics

The low-level driver API changed between RTEMS 4.10 and RTEMS 4.11. The legacy callback API is still supported, but its use is discouraged. The following functions are deprecated:

- `rtems_termios_open()` - use `rtems_termios_device_open()` in combination with `rtems_termios_device_install()` instead.
- `rtems_termios_close()` - use `rtems_termios_device_close()` instead.

This manual describes the new API. A new console driver should consist of three parts.

- The basic console driver functions using the Termios support. Add this the BSPs Makefile.am:

```
1 [...]
2 libbsp_a_SOURCES += ../../shared/console-termios.c
3 [...]
```

- A general serial module specific low-level driver providing the handler table for the Termios `rtems_termios_device_install()` function. This low-level driver could be used for more than one BSP.
- A BSP specific initialization routine `console_initialize()`, that calls `rtems_termios_device_install()` providing a low-level driver context for each installed device.

You need to provide a device handler structure for the Termios device interface. The functions are described later in this chapter. The first open and set attributes handler return a boolean status to indicate success (true) or failure (false). The polled read function returns an unsigned character in case one is available or minus one otherwise.

If you want to use polled IO it should look like the following. Termios must be told the addresses of the handler that are to be used for simple character IO, i.e. pointers to the `my_driver_poll_read()` and `my_driver_poll_write()` functions described later in *Termios and Polled IO* (page 64).

```
1 const rtems_termios_handler my_driver_handler_polled = {
2   .first_open = my_driver_first_open,
3   .last_close = my_driver_last_close,
4   .poll_read = my_driver_poll_read,
5   .write = my_driver_poll_write,
6   .set_attributes = my_driver_set_attributes,
```

```

7  .stop_remote_tx = NULL,
8  .start_remote_tx = NULL,
9  .mode = TERMIO_POLL
10 }

```

For an interrupt driven implementation you need the following. The driver functioning is quite different in this mode. There is no device driver read handler to be passed to Termios. Indeed a `console_read()` call returns the contents of Termios input buffer. This buffer is filled in the driver interrupt subroutine, see also *Termios and Interrupt Driven IO* (page 65). The driver is responsible for providing a pointer to the “`my_driver_interrupt_write()`” function.

```

1  const rtems_termios_handler my_driver_handler_interrupt = {
2  .first_open = my_driver_first_open,
3  .last_close = my_driver_last_close,
4  .poll_read = NULL,
5  .write = my_driver_interrupt_write,
6  .set_attributes = my_driver_set_attributes,
7  .stopRemoteTx = NULL,
8  .stop_remote_tx = NULL,
9  .start_remote_tx = NULL,
10 .mode = TERMIO_IRQ_DRIVEN
11 };

```

You can also provide handler for remote transmission control. This is not covered in this manual, so they are set to NULL in the above examples.

The low-level driver should provide a data structure for its device context. The initialization routine must provide a context for each installed device via `rtems_termios_device_install()`. For simplicity of the console initialization example the device name is also present. Here is an example header file.

```

1  #ifndef MY_DRIVER_H
2  #define MY_DRIVER_H
3
4  #include <rtems/termiostypes.h>
5  #include <some-chip-header.h>
6
7  /* Low-level driver specific data structure */
8  typedef struct {
9  rtems_termios_device_context base;
10 const char *device_name;
11 volatile module_register_block *regs;
12 /* More stuff */
13 } my_driver_context;
14
15 extern const rtems_termios_handler my_driver_handler_polled;
16 extern const rtems_termios_handler my_driver_handler_interrupt;
17
18 #endif /* MY_DRIVER_H */

```

8.4.2 Termios and Polled IO

The following handler are provided by the low-level driver and invoked by Termios for simple character IO.

The `my_driver_poll_write()` routine is responsible for writing `n` characters from `buf` to the serial device specified by `tty`.

```

1 static void my_driver_poll_write(
2     rtems_termios_device_context *base,
3     const char                    *buf,
4     size_t                        n
5 )
6 {
7     my_driver_context *ctx = (my_driver_context *) base;
8     size_t i;
9     /* Write */
10    for (i = 0; i < n; ++i) {
11        my_driver_write_char(ctx, buf[i]);
12    }
13 }

```

The `my_driver_poll_read` routine is responsible for reading a single character from the serial device specified by `tty`. If no character is available, then the routine should return minus one.

```

1 static int my_driver_poll_read(rtems_termios_device_context *base)
2 {
3     my_driver_context *ctx = (my_driver_context *) base;
4     /* Check if a character is available */
5     if (my_driver_can_read_char(ctx)) {
6         /* Return the character */
7         return my_driver_read_char(ctx);
8     } else {
9         /* Return an error status */
10        return -1;
11    }
12 }

```

8.4.3 Termios and Interrupt Driven IO

The UART generally generates interrupts when it is ready to accept or to emit a number of characters. In this mode, the interrupt subroutine is the core of the driver.

The `my_driver_interrupt_handler()` is responsible for processing asynchronous interrupts from the UART. There may be multiple interrupt handlers for a single UART. Some UARTs can generate a unique interrupt vector for each interrupt source such as a character has been received or the transmitter is ready for another character.

In the simplest case, the `my_driver_interrupt_handler()` will have to check the status of the UART and determine what caused the interrupt. The following describes the operation of an `my_driver_interrupt_handler` which has to do this:

```

1 static void my_driver_interrupt_handler(
2     rtems_vector_number vector,
3     void                *arg
4 )
5 {
6     rtems_termios_tty *tty = arg;
7     my_driver_context *ctx = rtems_termios_get_device_context(tty);
8     char buf[N];
9     size_t n;

```

```

10
11 /*
12  * Check if we have received something. The function reads the
13  * received characters from the device and stores them in the
14  * buffer. It returns the number of read characters.
15  */
16 n = my_driver_read_received_chars(ctx, buf, N);
17 if (n > 0) {
18     /* Hand the data over to the Termios infrastructure */
19     rtems_termios_enqueue_raw_characters(tty, buf, n);
20 }
21
22 /*
23  * Check if we have something transmitted. The functions returns
24  * the number of transmitted characters since the last write to the
25  * device.
26  */
27 n = my_driver_transmitted_chars(ctx);
28 if (n > 0) {
29     /*
30      * Notify Termios that we have transmitted some characters. It
31      * will call now the interrupt write function if more characters
32      * are ready for transmission.
33      */
34     rtems_termios_dequeue_characters(tty, n);
35 }
36 }

```

The `my_driver_interrupt_write()` function is responsible for telling the device that the `n` characters at `buf` are to be transmitted. If the value `n` is zero to indicate that no more characters are to send. The driver can disable the transmit interrupts now. This routine is invoked either from task context with disabled interrupts to start a new transmission process with exactly one character in case of an idle output state or from the interrupt handler to refill the transmitter. If the routine is invoked to start the transmit process the output state will become busy and Termios starts to fill the output buffer. If the transmit interrupt arises before Termios was able to fill the transmit buffer you will end up with one interrupt per character.

```

1 static void my_driver_interrupt_write(
2     rtems_termios_device_context *base,
3     const char *buf,
4     size_t n
5 )
6 {
7     my_driver_context *ctx = (my_driver_context *) base;
8
9     /*
10    * Tell the device to transmit some characters from buf (less than
11    * or equal to n). When the device is finished it should raise an
12    * interrupt. The interrupt handler will notify Termios that these
13    * characters have been transmitted and this may trigger this write
14    * function again. You may have to store the number of outstanding
15    * characters in the device data structure.
16    */
17    /*
18    * Termios will set n to zero to indicate that the transmitter is
19    * now inactive. The output buffer is empty in this case. The

```

```

20 * driver may disable the transmit interrupts now.
21 */
22 }

```

8.4.4 Initialization

The BSP specific driver initialization is called once during the RTEMS initialization process.

The `console_initialize()` function may look like this:

```

1 #include <my-driver.h>
2 #include <rtems/console.h>
3 #include <bsp.h>
4 #include <bsp/fatal.h>
5
6 static my_driver_context driver_context_table[M] = { /* Some values */ };
7
8 rtems_device_driver console_initialize(
9     rtems_device_major_number major,
10    rtems_device_minor_number minor,
11    void *arg
12 )
13 {
14     rtems_status_code sc;
15     #ifdef SOME_BSP_USE_INTERRUPTS
16         const rtems_termios_handler *handler = &my_driver_handler_interrupt;
17     #else
18         const rtems_termios_handler *handler = &my_driver_handler_polled;
19     #endif
20
21     /*
22      * Initialize the Termios infrastructure. If Termios has already
23      * been initialized by another device driver, then this call will
24      * have no effect.
25      */
26     rtems_termios_initialize();
27
28     /* Initialize each device */
29     for (
30         minor = 0;
31         minor < RTEMS_ARRAY_SIZE(driver_context_table);
32         ++minor
33     ) {
34         my_driver_context *ctx = &driver_context_table[minor];
35
36         /*
37          * Install this device in the file system and Termios. In order
38          * to use the console (i.e. being able to do printf, scanf etc.
39          * on stdin, stdout and stderr), one device must be registered as
40          * "/dev/console" (CONSOLE_DEVICE_NAME).
41          */
42         sc = rtems_termios_device_install(
43             ctx->device_name,
44             major,
45             minor,
46             handler,

```

```

47     NULL,
48     ctx
49 );
50 if (sc != RTEMS_SUCCESSFUL) {
51     bsp_fatal(SOME_BSP_FATAL_CONSOLE_DEVICE_INSTALL);
52 }
53 }
54
55 return RTEMS_SUCCESSFUL;
56 }

```

8.4.5 Opening a serial device

The `console_open()` function provided by `console-termios.c` is called whenever a serial device is opened. The device registered as `"/dev/console"` (`CONSOLE_DEVICE_NAME`) is opened automatically during RTEMS initialization. For instance, if UART channel 2 is registered as `"/dev/tty1"`, the `console_open()` entry point will be called as the result of an `fopen("/dev/tty1",mode)` in the application.

During the first open of the device Termios will call the `my_driver_first_open()` handler.

```

1 static bool my_driver_first_open(
2     rtems_termios_tty      *tty,
3     rtems_termios_device_context *base,
4     struct termios        *term,
5     rtems_libio_open_close_args_t *args
6 )
7 {
8     my_driver_context *ctx = (my_driver_context *) base;
9     rtems_status_code sc;
10    bool ok;
11
12    /*
13     * You may add some initialization code here.
14     */
15
16    /*
17     * Sets the initial baud rate. This should be set to the value of
18     * the boot loader. This function accepts only exact Termios baud
19     * values.
20     */
21    sc = rtems_termios_set_initial_baud(tty, MY_DRIVER_BAUD_RATE);
22    if (sc != RTEMS_SUCCESSFUL) {
23        /* Not a valid Termios baud */
24    }
25
26    /*
27     * Alternatively you can set the best baud.
28     */
29    rtems_termios_set_best_baud(term, MY_DRIVER_BAUD_RATE);
30
31    /*
32     * To propagate the initial Termios attributes to the device use
33     * this.
34     */

```

```

35 ok = my_driver_set_attributes(base, term);
36 if (!ok) {
37     /* This is bad */
38 }
39
40 /*
41  * Return true to indicate a successful set attributes, and false
42  * otherwise.
43  */
44 return true;
45 }

```

8.4.6 Closing a Serial Device

The `console_close()` provided by `console-termios.c` is invoked when the serial device is to be closed. This entry point corresponds to the device driver close entry point.

Termios will call the `my_driver_last_close()` handler if the last close happens on the device.

```

1 static void my_driver_last_close(
2     rtems_termios_tty      *tty,
3     rtems_termios_device_context *base,
4     rtems_libio_open_close_args_t *args
5 )
6 {
7     my_driver_context *ctx = (my_driver_context *) base;
8
9     /*
10    * The driver may do some cleanup here.
11    */
12 }

```

8.4.7 Reading Characters from a Serial Device

The `console_read()` provided by `console-termios.c` is invoked when the serial device is to be read from. This entry point corresponds to the device driver read entry point.

8.4.8 Writing Characters to a Serial Device

The `console_write()` provided by `console-termios.c` is invoked when the serial device is to be written to. This entry point corresponds to the device driver write entry point.

8.4.9 Changing Serial Line Parameters

The `console_control()` provided by `console-termios.c` is invoked when the line parameters for a particular serial device are to be changed. This entry point corresponds to the device driver IO control entry point.

The application writer is able to control the serial line configuration with Termios calls (such as the `ioctl()` command, see the Termios documentation for more details). If the driver is to support dynamic configuration, then it must have the `console_control()` piece of code.

Basically `ioctl()` commands call `console_control()` with the serial line configuration in a Termios defined data structure.

The driver is responsible for reinitializing the device with the correct settings. For this purpose Termios calls the `my_driver_set_attributes()` handler.

```
1 static bool my_driver_set_attributes(  
2     rtems_termios_device_context *base,  
3     const struct termios        *term  
4 )  
5 {  
6     my_driver_context *ctx = (my_driver_context *) base;  
7  
8     /*  
9      * Inspect the termios data structure and configure the device  
10     * appropriately. The driver should only be concerned with the  
11     * parts of the structure that specify hardware setting for the  
12     * communications channel such as baud, character size, etc.  
13     */  
14     /*  
15     * Return true to indicate a successful set attributes, and false  
16     * otherwise.  
17     */  
18     return true;  
19 }
```

CLOCK DRIVER

9.1 Introduction

The purpose of the clock driver is to provide two services for the operating system.

- A steady time basis to the kernel, so that the RTEMS primitives that need a clock tick work properly. See the *Clock Manager* chapter of the *RTEMS Application C User's Guide* for more details.
- An optional time counter to generate timestamps of the uptime and wall clock time.

The clock driver is usually located in the `clock` directory of the BSP. Clock drivers should use the *Clock Driver Shell* available via the `clockdrv_shell.h` include file.

9.2 Clock Driver Shell

The *Clock Driver Shell* include file defines the clock driver functions declared in `#include <rtems/clockdrv.h>` which are used by RTEMS configuration file `#include <rtems/confdefs.h>`. In case the application configuration defines `#define CONFIGURE_APPLICATION_NEEDS_CLOCK_DRIVER`, then the clock driver is registered and should provide its services to the operating system. A hardware specific clock driver must provide some functions, defines and macros for the *Clock Driver Shell* which are explained here step by step. A clock driver file looks in general like this.

```

1 /*
2  * A section with functions, defines and macros to provide hardware specific
3  * functions for the Clock Driver Shell.
4  */
5 #include "../../shared/clockdrv_shell.h"

```

9.2.1 Initialization

Depending on the hardware capabilities one out of three clock driver variants must be selected.

- The most basic clock driver provides only a periodic interrupt service routine which calls `rtems_clock_tick()`. The interval is determined by the application configuration via `#define CONFIGURE_MICROSECONDS_PER_TICK` and can be obtained via `rtems_configuration_get_microseconds_per_tick()`. The timestamp resolution is limited to the clock tick interval.
- In case the hardware lacks support for a free running counter, then the module used for the clock tick may provide support for timestamps with a resolution below the clock tick interval. For this so called simple timecounters can be used.
- The desired variant uses a free running counter to provide accurate timestamps. This variant is mandatory on SMP configurations.

9.2.1.1 Clock Tick Only Variant

```

1 static void some_support_initialize_hardware( void )
2 {
3     /* Initialize hardware */
4 }
5
6 #define Clock_driver_support_initialize_hardware() \
7     some_support_initialize_hardware()
8
9 /* Indicate that this clock driver lacks a proper timecounter in hardware */
10
11 #define CLOCK_DRIVER_USE_DUMMY_TIMECOUNTER
12
13 #include "../../shared/clockdrv_shell.h"

```

9.2.1.2 Simple Timecounter Variant

```

1 #include <rtems/timecounter.h>
2
3 static rtems_timecounter_simple some_tc;
4
5 static uint32_t some_tc_get( rtems_timecounter_simple *tc )
6 {
7     return some.counter;
8 }
9
10 static bool some_tc_is_pending( rtems_timecounter_simple *tc )
11 {
12     return some.is_pending;
13 }
14
15 static uint32_t some_tc_get_timecount( struct timecounter *tc )
16 {
17     return rtems_timecounter_simple_downcounter_get(
18         tc,
19         some_tc_get,
20         some_tc_is_pending
21     );
22 }
23
24 static void some_tc_tick( void )
25 {
26     rtems_timecounter_simple_downcounter_tick( &some_tc, some_tc_get );
27 }
28
29 static void some_support_initialize_hardware( void )
30 {
31     uint32_t frequency = 123456;
32     uint64_t us_per_tick = rtems_configuration_get_microseconds_per_tick();
33     uint32_t timecounter_ticks_per_clock_tick =
34         ( frequency * us_per_tick ) / 1000000;
35
36     /* Initialize hardware */
37     rtems_timecounter_simple_install(
38         &some_tc,
39         frequency,
40         timecounter_ticks_per_clock_tick,
41         some_tc_get_timecount
42     );
43 }
44
45 #define Clock_driver_support_initialize_hardware() \
46     some_support_initialize_hardware()
47 #define Clock_driver_timecounter_tick() \
48     some_tc_tick()
49
50 #include "../shared/clockdrv_shell.h"

```

9.2.1.3 Timecounter Variant

This variant is preferred since it is the most efficient and yields the most accurate timestamps. It is also mandatory on SMP configurations to obtain valid timestamps. The hardware must provide a periodic interrupt to service the clock tick and a free running counter for the timecounter. The free running counter must have a power of two period. The `tc_counter_mask` must be initialized to the free running counter period minus one, e.g. for a 32-bit counter this is `0xffffffff`. The `tc_get_timecount` function must return the current counter value (the counter values must increase, so if the counter counts down, a conversion is necessary). Use `RTEMS_TIMECOUNTER_QUALITY_CLOCK_DRIVER` for the `tc_quality`. Set `tc_frequency` to the frequency of the free running counter in Hz. All other fields of the struct `timecounter` must be zero initialized. Install the initialized timecounter via `rtems_timecounter_install()`.

```

1 #include <rtems/timecounter.h>
2
3 static struct timecounter some_tc;
4
5 static uint32_t some_tc_get_timecount( struct timecounter *tc )
6 {
7     some.free_running_counter;
8 }
9
10 static void some_support_initialize_hardware( void )
11 {
12     uint64_t us_per_tick = rtems_configuration_get_microseconds_per_tick();
13     uint32_t frequency = 123456;
14
15     /*
16      * The multiplication must be done in 64-bit arithmetic to avoid an integer
17      * overflow on targets with a high enough counter frequency.
18      */
19     uint32_t interval = (uint32_t) ( ( frequency * us_per_tick ) / 1000000 );
20
21     /*
22      * Initialize hardware and set up a periodic interrupt for the configuration
23      * based interval.
24      */
25     some_tc.tc_get_timecount = some_tc_get_timecount;
26     some_tc.tc_counter_mask = 0xffffffff;
27     some_tc.tc_frequency = frequency;
28     some_tc.tc_quality = RTEMS_TIMECOUNTER_QUALITY_CLOCK_DRIVER;
29     rtems_timecounter_install( &some_tc );
30 }
31
32 #define Clock_driver_support_initialize_hardware() \
33     some_support_initialize_hardware()
34
35 #include "../shared/clockdrv_shell.h"

```

9.2.2 Install Clock Tick Interrupt Service Routine

The clock driver must provide a function to install the clock tick interrupt service routine via `Clock_driver_support_install_isr()`.

```

1 #include <bsp/irq.h>
2 #include <bsp/fatal.h>
3
4 static void some_support_install_isr( rtems_interrupt_handler isr )
5 {
6     rtems_status_code sc;
7     sc = rtems_interrupt_handler_install(
8         SOME_IRQ,
9         "Clock",
10        RTEMS_INTERRUPT_UNIQUE,
11        isr,
12        NULL
13    );
14    if ( sc != RTEMS_SUCCESSFUL ) {
15        bsp_fatal( SOME_FATAL_IRQ_INSTALL );
16    }
17 }
18
19 #define Clock_driver_support_install_isr( isr, old ) \
20     some_support_install_isr( isr )
21
22 #include "../shared/clockdrv_shell.h"

```

9.2.3 Support At Tick

The hardware specific support at tick is specified by `Clock_driver_support_at_tick()`.

```

1 static void some_support_at_tick( void )
2 {
3     /* Clear interrupt */
4 }
5
6 #define Clock_driver_support_at_tick() \
7     some_support_at_tick()
8
9 #include "../shared/clockdrv_shell.h"

```

9.2.4 System Shutdown Support

The *Clock Driver Shell* provides the routine `Clock_exit()` that is scheduled to be run during system shutdown via the `atexit()` routine. The hardware specific shutdown support is specified by `Clock_driver_support_shutdown_hardware()` which is used by `Clock_exit()`. It should disable the clock tick source if it was enabled. This can be used to prevent clock ticks after the system is shutdown.

```

1 static void some_support_shutdown_hardware( void )
2 {
3     /* Shutdown hardware */
4 }
5
6 #define Clock_driver_support_shutdown_hardware() \
7     some_support_shutdown_hardware()

```

```

8
9 #include "../../../shared/clockdrv_shell.h"

```

9.2.5 Multiple Clock Driver Ticks Per Clock Tick

In case the hardware needs more than one clock driver tick per clock tick (e.g. due to a limited range of the hardware timer), then this can be specified with the optional `#define CLOCK_DRIVER_ISRS_PER_TICK` and `#define CLOCK_DRIVER_ISRS_PER_TICK_VALUE` defines. This is currently used only for x86 and it hopefully remains that way.

```

1 /* Enable multiple clock driver ticks per clock tick */
2 #define CLOCK_DRIVER_ISRS_PER_TICK 1
3
4 /* Specify the clock driver ticks per clock tick value */
5 #define CLOCK_DRIVER_ISRS_PER_TICK_VALUE 123
6
7 #include "../../../shared/clockdrv_shell.h"

```

9.2.6 Clock Driver Ticks Counter

The *Clock Driver Shell* provide a global variable that is simply a count of the number of clock driver interrupt service routines that have occurred. This information is valuable when debugging a system. This variable is declared as follows:

```

1 volatile uint32_t Clock_driver_ticks;

```


TIMER DRIVER

The timer driver is primarily used by the RTEMS Timing Tests. This driver provides as accurate a benchmark timer as possible. It typically reports its time in microseconds, CPU cycles, or bus cycles. This information can be very useful for determining precisely what pieces of code require optimization and to measure the impact of specific minor changes.

The gen68340 BSP also uses the Timer Driver to support a high performance mode of the on-CPU UART.

10.1 Benchmark Timer

The RTEMS Timing Test Suite requires a benchmark timer. The RTEMS Timing Test Suite is very helpful for determining the performance of target hardware and comparing its performance to that of other RTEMS targets.

This section describes the routines which are assumed to exist by the RTEMS Timing Test Suite. The names used are *EXACTLY* what is used in the RTEMS Timing Test Suite so follow the naming convention.

10.1.1 benchmark_timer_initialize

Initialize the timer source.

```

1 void benchmark_timer_initialize(void)
2 {
3     initialize the benchmark timer
4 }
```

10.1.2 Read_timer

The benchmark_timer_read routine returns the number of benchmark time units (typically microseconds) that have elapsed since the last call to benchmark_timer_initialize.

```

1 benchmark_timer_t benchmark_timer_read(void)
2 {
3     stop time = read the hardware timer
4     if the subtract overhead feature is enabled
5         subtract overhead from stop time
6     return the stop time
7 }
```

Many implementations of this routine subtract the overhead required to initialize and read the benchmark timer. This makes the times reported more accurate.

Some implementations report 0 if the hardware timer value change is sufficiently small. This is intended to indicate that the execution time is below the resolution of the timer.

10.1.3 benchmark_timer_disable_subtracting_average_overhead

This routine is invoked by the “Check Timer” (tmck) test in the RTEMS Timing Test Suite. It makes the benchmark_timer_read routine NOT subtract the overhead required to initialize and read the benchmark timer. This is used by the tmoverhd test to determine the overhead required to initialize and read the timer.

```

1 void benchmark_timer_disable_subtracting_average_overhead(bool find_flag)
2 {
3     disable the subtract overhead feature
4 }
```

The benchmark_timer_find_average_overhead variable is used to indicate the state of the “subtract overhead feature”.

10.2 gen68340 UART FIFO Full Mode

The gen68340 BSP is an example of the use of the timer to support the UART input FIFO full mode (FIFO means First In First Out and roughly means buffer). This mode consists in the UART raising an interrupt when n characters have been received (n is the UART's FIFO length). It results in a lower interrupt processing time, but the problem is that a scanf primitive will block on a receipt of less than n characters. The solution is to set a timer that will check whether there are some characters waiting in the UART's input FIFO. The delay time has to be set carefully otherwise high rates will be broken:

- if no character was received last time the interrupt subroutine was entered, set a long delay,
- otherwise set the delay to the delay needed for n characters receipt.

REAL-TIME CLOCK DRIVER

11.1 Introduction

The Real-Time Clock (*RTC*) driver is responsible for providing an interface to an *RTC* device. The capabilities provided by this driver are:

- Set the RTC TOD to RTEMS TOD
- Set the RTEMS TOD to the RTC TOD
- Get the RTC TOD
- Set the RTC TOD to the Specified TOD
- Get the Difference Between the RTEMS and RTC TOD

Note: In this chapter, the abbreviation *TOD* is used for *Time of Day*.

The reference implementation for a real-time clock driver can be found in `c/src/lib/libbsp/shared/tod.c`. This driver is based on the `libchip` concept and can be easily configured to work with any of the RTC chips supported by the RTC chip drivers in the directory `c/src/lib/lib/libchip/rtc`. There is a `README` file in this directory for each supported RTC chip. Each of these `README` explains how to configure the shared `libchip` implementation of the RTC driver for that particular RTC chip.

The DY-4 DMV177 BSP used the shared `libchip` implementation of the RTC driver. There were no DMV177 specific configuration routines. A BSP could use configuration routines to dynamically determine what type of real-time clock is on a particular board. This would be useful for a BSP supporting multiple board models. The relevant parts of the DMV177's `RTC_Table` configuration table is below:

```

1 #include <bsp.h>
2 #include <libchip/rtc.h>
3 #include <libchip/icm7170.h>
4
5 bool dmv177_icm7170_probe(int minor);
6
7 rtc_tbl RTC_Table[] = {
8     { "/dev/rtc0",           /* sDeviceName */
9       RTC_ICM7170,         /* deviceType */
10      &icm7170_fns,        /* pDeviceFns */
11      dmv177_icm7170_probe, /* deviceProbe */
12      (void *) ICM7170_AT_1_MHZ, /* pDeviceParams */
13      DMV170_RTC_ADDRESS,   /* ulCtrlPort1 */
14      0,                    /* ulDataPort */
15      icm7170_get_register_8, /* getRegister */
16      icm7170_set_register_8, /* setRegister */
17    }
18 };
19 unsigned long RTC_Count = (sizeof(RTC_Table)/sizeof(rtc_tbl));
20 rtems_device_minor_number RTC_Minor;
21
22 bool dmv177_icm7170_probe(int minor)
23 {
24     volatile unsigned16 *card_resource_reg;
25     card_resource_reg = (volatile unsigned16 *) DMV170_CARD_RESOURCE_REG;
26     if ( (*card_resource_reg & DMV170_RTC_INST_MASK) == DMV170_RTC_INSTALLED )

```

```
27     return TRUE;  
28     return FALSE;  
29 }
```

11.2 Initialization

The `rtc_initialize` routine is responsible for initializing the RTC chip so it can be used. The shared `libchip` implementation of this driver supports multiple RTCs and bases its initialization order on the order the chips are defined in the `RTC_Table`. Each chip defined in the table may or may not be present on this particular board. It is the responsibility of the `deviceProbe` to indicate the presence of a particular RTC chip. The first RTC found to be present is considered the preferred RTC.

In the shared `libchip` based implementation of the driver, the following actions are performed:

```

1 rtems_device_driver rtc_initialize(
2   rtems_device_major_number  major,
3   rtems_device_minor_number  minor_arg,
4   void                       *arg
5 )
6 {
7   for each RTC configured in RTC_Table
8     if the deviceProbe for this RTC indicates it is present
9       set RTC_Minor to this device
10      set RTC_Present to TRUE
11      break out of this loop
12
13   if RTC_Present is not TRUE
14     return RTEMS_INVALID_NUMBER to indicate that no RTC is present
15
16   register this minor number as the "/dev/rtc"
17
18   perform the deviceInitialize routine for the preferred RTC chip
19
20   for RTCs past this one in the RTC_Table
21     if the deviceProbe for this RTC indicates it is present
22       perform the deviceInitialize routine for this RTC chip
23       register the configured name for this RTC
24 }

```

The `deviceProbe` routine returns `TRUE` if the device configured by this entry in the `RTC_Table` is present. This configuration scheme allows one to support multiple versions of the same board with a single BSP. For example, if the first generation of a board had Vendor A's RTC chip and the second generation had Vendor B's RTC chip, `RTC_Table` could contain information for both. The `deviceProbe` configured for Vendor A's RTC chip would need to return `TRUE` if the board was a first generation one. The `deviceProbe` routines are very board dependent and must be provided by the BSP.

11.3 setRealTimeToRTEMS

The setRealTimeToRTEMS routine sets the current RTEMS TOD to that of the preferred RTC.

```
1 void setRealTimeToRTEMS(void)
2 {
3     if no RTCs are present
4         return
5
6     invoke the deviceGetTime routine for the preferred RTC
7     set the RTEMS TOD using rtems_clock_set
8 }
```

11.4 setRealTimeFromRTEMS

The setRealTimeFromRTEMS routine sets the preferred RTC TOD to the current RTEMS TOD.

```
1 void setRealTimeFromRTEMS(void)
2 {
3     if no RTCs are present
4         return
5
6     obtain the RTEMS TOD using rtems_clock_get
7     invoke the deviceSetTime routine for the preferred RTC
8 }
```

11.5 getRealTime

The `getRealTime` returns the preferred RTC TOD to the caller.

```
1 void getRealTime( rtems_time_of_day *tod )
2 {
3     if no RTCs are present
4     return
5
6     invoke the deviceGetTime routine for the preferred RTC
7 }
```

11.6 setRealTime

The setRealTime routine sets the preferred RTC TOD to the TOD specified by the caller.

```
1 void setRealTime( rtems_time_of_day *tod )
2 {
3   if no RTCs are present
4     return
5
6   invoke the deviceSetTime routine for the preferred RTC
7 }
```

11.7 checkRealTime

The checkRealTime routine returns the number of seconds difference between the RTC TOD and the current RTEMS TOD.

```
1 int checkRealTime( void )
2 {
3     if no RTCs are present
4         return -1
5
6     obtain the RTEMS TOD using rtems_clock_get
7     get the TOD from the preferred RTC using the deviceGetTime routine
8     convert the RTEMS TOD to seconds
9     convert the RTC TOD to seconds
10
11     return the RTEMS TOD in seconds - RTC TOD in seconds
12 }
```


ATA DRIVER

12.1 Terms

ATA device - physical device attached to an IDE controller

12.2 Introduction

ATA driver provides generic interface to an ATA device. ATA driver is hardware independent implementation of ATA standard defined in working draft “AT Attachment Interface with Extensions (ATA-2)” X3T10/0948D revision 4c, March 18, 1996. ATA Driver based on IDE Controller Driver and may be used for computer systems with single IDE controller and with multiple as well. Although current implementation has several restrictions detailed below ATA driver architecture allows easily extend the driver. Current restrictions are:

- Only mandatory (see draft p.29) and two optional (READ/WRITE MULTIPLE) commands are implemented
- Only PIO mode is supported but both poll and interrupt driven

The reference implementation for ATA driver can be found in `cpukit/libblock/src/ata.c`.

12.3 Initialization

The `ata_initialize` routine is responsible for ATA driver initialization. The main goal of the initialization is to detect and register in the system all ATA devices attached to IDE controllers successfully initialized by the IDE Controller driver.

In the implementation of the driver, the following actions are performed:

```

1 rtems_device_driver ata_initialize(
2   rtems_device_major_number major,
3   rtems_device_minor_number minor,
4   void *arg
5 )
6 {
7   initialize internal ATA driver data structure
8
9   for each IDE controller successfully initialized by the IDE Controller driver
10  if the controller is interrupt driven
11    set up interrupt handler
12
13  obtain information about ATA devices attached to the controller
14  with help of EXECUTE DEVICE DIAGNOSTIC command
15
16  for each ATA device detected on the controller
17    obtain device parameters with help of DEVICE IDENTIFY command
18
19  register new ATA device as new block device in the system
20 }
```

Special processing of ATA commands is required because of absence of multitasking environment during the driver initialization.

Detected ATA devices are registered in the system as physical block devices (see `libblock` library description). Device names are formed based on IDE controller minor number device is attached to and device number on the controller (0 - Master, 1 - Slave). In current implementation 64 minor numbers are reserved for each ATA device which allows to support up to 63 logical partitions per device.

controller minor	device number	device name	ata device minor
0	0	hda	0
0	1	hdb	64
1	0	hdc	128
1	1	hdd	172
...

12.4 ATA Driver Architecture

12.4.1 ATA Driver Main Internal Data Structures

ATA driver works with ATA requests. ATA request is described by the following structure:

```

1 /* ATA request */
2 typedef struct ata_req_s {
3   Chain_Node      link;   /* link in requests chain */
4   char            type;   /* request type */
5   ata_registers_t regs;   /* ATA command */
6   uint32_t        cnt;    /* Number of sectors to be exchanged */
7   uint32_t        cbuf;   /* number of current buffer from breq in use */
8   uint32_t        pos;    /* current position in 'cbuf' */
9   blkdev_request  *breq;  /* blkdev_request which corresponds to the ata request */
10  rtems_id         sema;   /* semaphore which is used if synchronous
11                          * processing of the ata request is required */
12  rtems_status_code status; /* status of ata request processing */
13  int              error;  /* error code */
14 } ata_req_t;

```

ATA driver supports separate ATA requests queues for each IDE controller (one queue per controller). The following structure contains information about controller's queue and devices attached to the controller:

```

1 /*
2  * This structure describes controller state, devices configuration on the
3  * controller and chain of ATA requests to the controller.
4  */
5 typedef struct ata_ide_ctrl_s {
6   bool      present; /* controller state */
7   ata_dev_t device[2]; /* ata devices description */
8   Chain_Control reqs; /* requests chain */
9 } ata_ide_ctrl_t;

```

Driver uses array of the structures indexed by the controllers minor number.

The following structure allows to map an ATA device to the pair (IDE controller minor number device is attached to, device number on the controller):

```

1 /*
2  * Mapping of RTEMS ATA devices to the following pairs:
3  * (IDE controller number served the device, device number on the controller)
4  */
5 typedef struct ata_ide_dev_s {
6   int ctrl_minor; /* minor number of IDE controller serves RTEMS ATA device */
7   int device; /* device number on IDE controller (0 or 1) */
8 } ata_ide_dev_t;

```

Driver uses array of the structures indexed by the ATA devices minor number.

ATA driver defines the following internal events:

```

1 /* ATA driver events */
2 typedef enum ata_msg_type_s {
3   ATA_MSG_GEN_EVT = 1, /* general event */

```

```
4  ATA_MSG_SUCCESS_EVT,      /* success event */
5  ATA_MSG_ERROR_EVT,       /* error event */
6  ATA_MSG_PROCESS_NEXT_EVT /* process next ata request event */
7 } ata_msg_type_t;
```

12.4.2 Brief ATA Driver Core Overview

All ATA driver functionality is available via ATA driver ioctl. Current implementation supports only two ioctls: BLKIO_REQUEST and ATAIO_SET_MULTIPLE_MODE. Each ATA driver ioctl() call generates an ATA request which is appended to the appropriate controller queue depending on ATA device the request belongs to. If appended request is single request in the controller's queue then ATA driver event is generated.

ATA driver task which manages queue of ATA driver events is core of ATA driver. In current driver version queue of ATA driver events implemented as RTEMS message queue. Each message contains event type, IDE controller minor number on which event happened and error if an error occurred. Events may be generated either by ATA driver ioctl call or by ATA driver task itself. Each time ATA driver task receives an event it gets controller minor number from event, takes first ATA request from controller queue and processes it depending on request and event types. An ATA request processing may also includes sending of several events. If ATA request processing is finished the ATA request is removed from the controller queue. Note, that in current implementation maximum one event per controller may be queued at any moment of the time.

(This part seems not very clear, hope I rewrite it soon)

IDE CONTROLLER DRIVER

13.1 Introduction

The IDE Controller driver is responsible for providing an interface to an IDE Controller. The capabilities provided by this driver are:

- Read IDE Controller register
- Write IDE Controller register
- Read data block through IDE Controller Data Register
- Write data block through IDE Controller Data Register

The reference implementation for an IDE Controller driver can be found in `$RTEMS_SRC_ROOT/c/src/libchip/ide`. This driver is based on the `libchip` concept and allows to work with any of the IDE Controller chips simply by appropriate configuration of BSP. Drivers for a particular IDE Controller chips locate in the following directories: drivers for well-known IDE Controller chips locate into `$RTEMS_SRC_ROOT/c/src/libchip/ide`, drivers for IDE Controller chips integrated with CPU locate into `$RTEMS_SRC_ROOT/c/src/lib/libcpu/myCPU` and drivers for custom IDE Controller chips (for example, implemented on FPGA) locate into `$RTEMS_SRC_ROOT/c/src/lib/libbsp/myBSP`. There is a `README` file in these directories for each supported IDE Controller chip. Each of these `README` explains how to configure a BSP for that particular IDE Controller chip.

13.2 Initialization

IDE Controller chips used by a BSP are statically configured into `IDE_Controller_Table`. The `ide_controller_initialize` routine is responsible for initialization of all configured IDE controller chips. Initialization order of the chips based on the order the chips are defined in the `IDE_Controller_Table`.

The following actions are performed by the IDE Controller driver initialization routine:

```
1 rtems_device_driver ide_controller_initialize(  
2   rtems_device_major_number  major,  
3   rtems_device_minor_number  minor_arg,  
4   void                       *arg  
5 )  
6 {  
7   for each IDE Controller chip configured in IDE_Controller_Table  
8     if (BSP dependent probe(if exists) AND device probe for this IDE chip  
9       indicates it is present)  
10      perform initialization of the particular chip  
11      register device with configured name for this chip  
12 }
```

13.3 Read IDE Controller Register

The `ide_controller_read_register` routine reads the content of the IDE Controller chip register. IDE Controller chip is selected via the minor number. This routine is not allowed to be called from an application.

```
1 void ide_controller_read_register(  
2     rtems_device_minor_number  minor,  
3     unsigned32                 reg,  
4     unsigned32                 *value  
5 )  
6 {  
7     get IDE Controller chip configuration information from  
8     IDE_Controller_Table by minor number  
9  
10    invoke read register routine for the chip  
11 }
```

13.4 Write IDE Controller Register

The `ide_controller_write_register` routine writes IDE Controller chip register with specified value. IDE Controller chip is selected via the minor number. This routine is not allowed to be called from an application.

```
1 void ide_controller_write_register(  
2     rtems_device_minor_number minor,  
3     unsigned32                reg,  
4     unsigned32                value  
5 )  
6 {  
7     get IDE Controller chip configuration information from  
8     IDE_Controller_Table by minor number  
9  
10    invoke write register routine for the chip  
11 }
```

13.5 Read Data Block Through IDE Controller Data Register

The `ide_controller_read_data_block` provides multiple consequent read of the IDE Controller Data Register. IDE Controller chip is selected via the minor number. The same functionality may be achieved via separate multiple calls of `ide_controller_read_register` routine but `ide_controller_read_data_block` allows to escape functions call overhead. This routine is not allowed to be called from an application.

```
1 void ide_controller_read_data_block(  
2     rtems_device_minor_number  minor,  
3     unsigned16                 block_size,  
4     blkdev_sg_buffer           *bufs,  
5     uint32_t                   *cbuf,  
6     uint32_t                   *pos  
7 )  
8 {  
9     get IDE Controller chip configuration information from  
10    IDE_Controller_Table by minor number  
11  
12    invoke read data block routine for the chip  
13 }
```

13.6 Write Data Block Through IDE Controller Data Register

The `ide_controller_write_data_block` provides multiple consequent write into the IDE Controller Data Register. IDE Controller chip is selected via the minor number. The same functionality may be achieved via separate multiple calls of `ide_controller_write_register` routine but `ide_controller_write_data_block` allows to escape functions call overhead. This routine is not allowed to be called from an application.

```
1 void ide_controller_write_data_block(  
2     rtems_device_minor_number  minor,  
3     unsigned16                 block_size,  
4     blkdev_sg_buffer           *bufs,  
5     uint32_t                   *cbuf,  
6     uint32_t                   *pos  
7 )  
8 {  
9     get IDE Controller chip configuration information from  
10    IDE_Controller_Table by minor number  
11  
12    invoke write data block routine for the chip  
13 }
```


NON-VOLATILE MEMORY DRIVER

The Non-Volatile driver is responsible for providing an interface to various types of non-volatile memory. These types of memory include, but are not limited to, Flash, EEPROM, and battery backed RAM. The capabilities provided by this class of device driver are:

- Initialize the Non-Volatile Memory Driver
- Optional Disable Read and Write Handlers
- Open a Particular Memory Partition
- Close a Particular Memory Partition
- Read from a Particular Memory Partition
- Write to a Particular Memory Partition
- Erase the Non-Volatile Memory Area

There is currently only one non-volatile device driver included in the RTEMS source tree. The information provided in this chapter is based on drivers developed for applications using RTEMS. It is hoped that this driver model information can form the basis for a standard non-volatile memory driver model that can be supported in future RTEMS distribution.

14.1 Major and Minor Numbers

The major number of a device driver is its index in the RTEMS Device Address Table.

A minor number is associated with each device instance managed by a particular device driver. An RTEMS minor number is an unsigned32 entity. Convention calls dividing the bits in the minor number down into categories that specify an area of non-volatile memory and a partition with that area. This results in categories like the following:

- area - indicates a block of non-volatile memory
- partition - indicates a particular address range with an area

From the above, it should be clear that a single device driver can support multiple types of non-volatile memory in a single system. The minor number is used to distinguish the types of memory and blocks of memory used for different purposes.

14.2 Non-Volatile Memory Driver Configuration

There is not a standard non-volatile driver configuration table but some fields are common across different drivers. The non-volatile memory driver configuration table is typically an array of structures with each structure containing the information for a particular area of non-volatile memory. The following is a list of the type of information normally required to configure each area of non-volatile memory.

memory_type

is the type of memory device in this area. Choices are battery backed RAM, EEPROM, Flash, or an optional user-supplied type. If the user-supplied type is configured, then the user is responsible for providing a set of routines to program the memory.

memory

is the base address of this memory area.

attributes

is a pointer to a memory type specific attribute block. Some of the fields commonly contained in this memory type specific attribute structure area:

use_protection_algorithm

is set to TRUE to indicate that the protection (i.e. locking) algorithm should be used for this area of non-volatile memory. A particular type of non-volatile memory may not have a protection algorithm.

access

is an enumerated type to indicate the organization of the memory devices in this memory area. The following is a list of the access types supported by the current driver implementation:

- simple unsigned8
- simple unsigned16
- simple unsigned32
- simple unsigned64
- single unsigned8 at offset 0 in an unsigned16
- single unsigned8 at offset 1 in an unsigned16
- single unsigned8 at offset 0 in an unsigned32
- single unsigned8 at offset 1 in an unsigned32
- single unsigned8 at offset 2 in an unsigned32
- single unsigned8 at offset 3 in an unsigned32

depth

is the depth of the programming FIFO on this particular chip. Some chips, particularly EEPROMs, have the same programming algorithm but vary in the depth of the amount of data that can be programmed in a single block.

number_of_partitions

is the number of logical partitions within this area.

Partitions

is the address of the table that contains an entry to describe each partition in this area. Fields within each element of this table are defined as follows:

offset

is the offset of this partition from the base address of this area.

length

is the length of this partition.

By dividing an area of memory into multiple partitions, it is possible to easily divide the non-volatile memory for different purposes.

14.3 Initialize the Non-Volatile Memory Driver

At system initialization, the non-volatile memory driver's initialization entry point will be invoked. As part of initialization, the driver will perform whatever initialization is required on each non-volatile memory area.

The discrete I/O driver may register device names for memory partitions of particular interest to the system. Normally this will be restricted to the device `"/dev/nv_memory"` to indicate the entire device driver.

14.4 Disable Read and Write Handlers

Depending on the target's non-volatile memory configuration, it may be possible to write to a status register and make the memory area completely inaccessible. This is target dependent and beyond the standard capabilities of any memory type. The user has the optional capability to provide handlers to disable and enable access to a particular memory area.

14.5 Open a Particular Memory Partition

This is the driver open call. Usually this call does nothing other than validate the minor number. With some drivers, it may be necessary to allocate memory when a particular device is opened. If that is the case, then this is often the place to do this operation.

14.6 Close a Particular Memory Partition

This is the driver close call. Usually this call does nothing.

With some drivers, it may be necessary to allocate memory when a particular device is opened. If that is the case, then this is the place where that memory should be deallocated.

14.7 Read from a Particular Memory Partition

This corresponds to the driver read call. After validating the minor number and arguments, this call enables reads from the specified memory area by invoking the user supplied “enable reads handler” and then reads the indicated memory area. When invoked the argument_block is actually a pointer to the following structure type:

```
1 typedef struct {
2     uint32_t  offset;
3     void      *buffer;
4     uint32_t  length;
5     uint32_t  status;
6 } Non_volatile_memory_Driver_arguments;
```

The driver reads length bytes starting at offset into the partition and places them at buffer. The result is returned in status.

After the read operation is complete, the user supplied “disable reads handler” is invoked to protect the memory area again.

14.8 Write to a Particular Memory Partition

This corresponds to the driver write call. After validating the minor number and arguments, this call enables writes to the specified memory area by invoking the “enable writes handler”, then unprotecting the memory area, and finally actually writing to the indicated memory area. When invoked the argument_block is actually a pointer to the following structure type:

```
1 typedef struct {  
2     uint32_t  offset;  
3     void      *buffer;  
4     uint32_t  length;  
5     uint32_t  status;  
6 } Non_volatile_memory_Driver_arguments;
```

The driver writes length bytes from buffer and writes them to the non-volatile memory starting at offset into the partition. The result is returned in status.

After the write operation is complete, the “disable writes handler” is invoked to protect the memory area again.

14.9 Erase the Non-Volatile Memory Area

This is one of the IOCTL functions supported by the I/O control device driver entry point. When this IOCTL function is invoked, the specified area of non-volatile memory is erased.

NETWORKING DRIVER

15.1 Introduction

This chapter is intended to provide an introduction to the procedure for writing RTEMS network device drivers. The example code is taken from the 'Generic 68360' network device driver. The source code for this driver is located in the `c/src/lib/libbsp/m68k/gen68360/network` directory in the RTEMS source code distribution. Having a copy of this driver at hand when reading the following notes will help significantly.

Legacy Networking Stack

This docuemntation is for the legacy FreeBSD networking stack in the RTEMS source tree.

15.2 Learn about the network device

Before starting to write the network driver become completely familiar with the programmer's view of the device. The following points list some of the details of the device that must be understood before a driver can be written.

- Does the device use DMA to transfer packets to and from memory or does the processor have to copy packets to and from memory on the device?
- If the device uses DMA, is it capable of forming a single outgoing packet from multiple fragments scattered in separate memory buffers?
- If the device uses DMA, is it capable of chaining multiple outgoing packets, or does each outgoing packet require intervention by the driver?
- Does the device automatically pad short frames to the minimum 64 bytes or does the driver have to supply the padding?
- Does the device automatically retry a transmission on detection of a collision?
- If the device uses DMA, is it capable of buffering multiple packets to memory, or does the receiver have to be restarted after the arrival of each packet?
- How are packets that are too short, too long, or received with CRC errors handled? Does the device automatically continue reception or does the driver have to intervene?
- How is the device Ethernet address set? How is the device programmed to accept or reject broadcast and multicast packets?
- What interrupts does the device generate? Does it generate an interrupt for each incoming packet, or only for packets received without error? Does it generate an interrupt for each packet transmitted, or only when the transmit queue is empty? What happens when a transmit error is detected?

In addition, some controllers have specific questions regarding board specific configuration. For example, the SONIC Ethernet controller has a very configurable data bus interface. It can even be configured for sixteen and thirty-two bit data buses. This type of information should be obtained from the board vendor.

15.3 Understand the network scheduling conventions

When writing code for the driver transmit and receive tasks, take care to follow the network scheduling conventions. All tasks which are associated with networking share various data structures and resources. To ensure the consistency of these structures the tasks execute only when they hold the network semaphore (`rtems_bsdnet_semaphore`). The transmit and receive tasks must abide by this protocol. Be very careful to avoid 'deadly embraces' with the other network tasks. A number of routines are provided to make it easier for the network driver code to conform to the network task scheduling conventions.

- `void rtems_bsdnet_semaphore_release(void)` This function releases the network semaphore. The network driver tasks must call this function immediately before making any blocking RTEMS request.
- `void rtems_bsdnet_semaphore_obtain(void)` This function obtains the network semaphore. If a network driver task has released the network semaphore to allow other network-related tasks to run while the task blocks, then this function must be called to reobtain the semaphore immediately after the return from the blocking RTEMS request.
- `rtems_bsdnet_event_receive(rtems_event_set, rtems_option, rtems_interval, rtems_event_set *)` The network driver task should call this function when it wishes to wait for an event. This function releases the network semaphore, calls `rtems_event_receive` to wait for the specified event or events and reobtains the semaphore. The value returned is the value returned by the `rtems_event_receive`.

15.4 Network Driver Makefile

Network drivers are considered part of the BSD network package and as such are to be compiled with the appropriate flags. This can be accomplished by adding `-D__INSIDE_RTEMS_BSD_TCPIP_STACK__` to the command line. If the driver is inside the RTEMS source tree or is built using the RTEMS application Makefiles, then adding the following line accomplishes this:

```
1 DEFINES += -D__INSIDE_RTEMS_BSD_TCPIP_STACK__
```

This is equivalent to the following list of definitions. Early versions of the RTEMS BSD network stack required that all of these be defined.

```
1 -D_COMPILING_BSD_KERNEL_ -DKERNEL -DINET -DNFS -DDIAGNOSTIC -DBOOTP_COMPAT
```

Defining these macros tells the network header files that the driver is to be compiled with extended visibility into the network stack. This is in sharp contrast to applications that simply use the network stack. Applications do not require this level of visibility and should stick to the portable application level API.

As a direct result of being logically internal to the network stack, network drivers use the BSD memory allocation routines. This means, for example, that `malloc` takes three arguments. See the SONIC device driver (`c/src/lib/libchip/network/sonic.c`) for an example of this. Because of this, network drivers should not include `<stdlib.h>`. Doing so will result in conflicting definitions of `malloc()`.

Application level code including network servers such as the FTP daemon are *not* part of the BSD kernel network code and should not be compiled with the BSD network flags. They should include `<stdlib.h>` and not define the network stack visibility macros.

15.5 Write the Driver Attach Function

The driver attach function is responsible for configuring the driver and making the connection between the network stack and the driver.

Driver attach functions take a pointer to an `rtems_bsdnet_ifconfig` structure as their only argument, and set the driver parameters based on the values in this structure. If an entry in the configuration structure is zero the attach function chooses an appropriate default value for that parameter.

The driver should then set up several fields in the `ifnet` structure in the device-dependent data structure supplied and maintained by the driver:

`ifp->if_softc`

Pointer to the device-dependent data. The first entry in the device-dependent data structure must be an `arpcom` structure.

`ifp->if_name`

The name of the device. The network stack uses this string and the device number for device name lookups. The device name should be obtained from the name entry in the configuration structure.

`ifp->if_unit`

The device number. The network stack uses this number and the device name for device name lookups. For example, if `ifp->if_name` is `scc` and `ifp->if_unit` is `1`, the full device name would be `scc1`. The unit number should be obtained from the name entry in the configuration structure.

`ifp->if_mtu`

The maximum transmission unit for the device. For Ethernet devices this value should almost always be `1500`.

`ifp->if_flags`

The device flags. Ethernet devices should set the flags to `IFF_BROADCAST|IFF_SIMPLEX`, indicating that the device can broadcast packets to multiple destinations and does not receive and transmit at the same time.

`ifp->if_snd.ifq_maxlen`

The maximum length of the queue of packets waiting to be sent to the driver. This is normally set to `ifqmaxlen`.

`ifp->if_init`

The address of the driver initialization function.

`ifp->if_start`

The address of the driver start function.

`ifp->if_ioctl`

The address of the driver `ioctl` function.

`ifp->if_output`

The address of the output function. Ethernet devices should set this to `ether_output`.

RTEMS provides a function to parse the driver name in the configuration structure into a device name and unit number.

```
1 int rtems_bsdnet_parse_driver_name (
2   const struct rtems_bsdnet_ifconfig *config,
```

```
3 char **namep  
4 );
```

The function takes two arguments; a pointer to the configuration structure and a pointer to a pointer to a character. The function parses the configuration name entry, allocates memory for the driver name, places the driver name in this memory, sets the second argument to point to the name and returns the unit number. On error, a message is printed and -1 is returned.

Once the attach function has set up the above entries it must link the driver data structure onto the list of devices by calling `if_attach`. Ethernet devices should then call `ether_ifattach`. Both functions take a pointer to the device's `ifnet` structure as their only argument.

The attach function should return a non-zero value to indicate that the driver has been successfully configured and attached.

15.6 Write the Driver Start Function.

This function is called each time the network stack wants to start the transmitter. This occurs whenever the network stack adds a packet to a device's send queue and the `IFF_OACTIVE` bit in the device's `if_flags` is not set.

For many devices this function need only set the `IFF_OACTIVE` bit in the `if_flags` and send an event to the transmit task indicating that a packet is in the driver transmit queue.

15.7 Write the Driver Initialization Function.

This function should initialize the device, attach to interrupt handler, and start the driver transmit and receive tasks. The function:

```
1 rtems_id rtems_bsdnet_newproc(  
2   char *name,  
3   int  stacksize,  
4   void (*entry)(void *),  
5   void *arg  
6 );
```

should be used to start the driver tasks.

Note that the network stack may call the driver initialization function more than once. Make sure multiple versions of the receive and transmit tasks are not accidentally started.

15.8 Write the Driver Transmit Task

This task is responsible for removing packets from the driver send queue and sending them to the device. The task should block waiting for an event from the driver start function indicating that packets are waiting to be transmitted. When the transmit task has drained the driver send queue the task should clear the `IFF_OACTIVE` bit in `if_flags` and block until another outgoing packet is queued.

15.9 Write the Driver Receive Task

This task should block until a packet arrives from the device. If the device is an Ethernet interface the function `ether_input` should be called to forward the packet to the network stack. The arguments to `ether_input` are a pointer to the interface data structure, a pointer to the ethernet header and a pointer to an mbuf containing the packet itself.

15.10 Write the Driver Interrupt Handler

A typical interrupt handler will do nothing more than the hardware manipulation required to acknowledge the interrupt and send an RTEMS event to wake up the driver receive or transmit task waiting for the event. Network interface interrupt handlers must not make any calls to other network routines.

15.11 Write the Driver IOCTL Function

This function handles ioctl requests directed at the device. The ioctl commands which must be handled are:

SIOCGIFADDR, SIOCSIFADDR

If the device is an Ethernet interface these commands should be passed on to `ether_ioctl`.

SIOCSIFFLAGS

This command should be used to start or stop the device, depending on the state of the interface `IFF_UP` and `IFF_RUNNING` bits in `if_flags`:

IFF_RUNNING

Stop the device.

IFF_UP

Start the device.

IFF_UP | IFF_RUNNING

Stop then start the device.

0

Do nothing.

15.12 Write the Driver Statistic-Printing Function

This function should print the values of any statistic/diagnostic counters the network driver may use. The driver ioctl function should call the statistic-printing function when the ioctl command is SIO_RTEMS_SHOW_STATS.

SHARED MEMORY SUPPORT DRIVER

The Shared Memory Support Driver is responsible for providing glue routines and configuration information required by the Shared Memory Multiprocessor Communications Interface (MPCI). The Shared Memory Support Driver tailors the portable Shared Memory Driver to a particular target platform.

This driver is only required in shared memory multiprocessing systems that use the RTEMS multiprocessing support. For more information on RTEMS multiprocessing capabilities and the MPCI, refer to the *Multiprocessing Manager* chapter of the *RTEMS Application C User's Guide*.

16.1 Shared Memory Configuration Table

The Shared Memory Configuration Table is defined in the following structure:

```

1 typedef volatile uint32_t vol_u32;
2
3 typedef struct {
4   vol_u32 *address;      /* write here for interrupt */
5   vol_u32 value;        /* this value causes interrupt */
6   vol_u32 length;       /* for this length (0,1,2,4) */
7 } Shm_Interrupt_information;
8
9 struct shm_config_info {
10  vol_u32      *base;          /* base address of SHM */
11  vol_u32      length;        /* length (in bytes) of SHM */
12  vol_u32      format;        /* SHM is big or little endian */
13  vol_u32      (*convert)();  /* neutral conversion routine */
14  vol_u32      poll_intr;     /* POLLED or INTR driven mode */
15  void         (*cause_intr)( uint32_t );
16  Shm_Interrupt_information Intr; /* cause intr information */
17 };
18
19 typedef struct shm_config_info shm_config_table;

```

where the fields are defined as follows:

base

is the base address of the shared memory buffer used to pass messages between the nodes in the system.

length

is the length (in bytes) of the shared memory buffer used to pass messages between the nodes in the system.

format

is either SHM_BIG or SHM_LITTLE to indicate that the neutral format of the shared memory area is big or little endian. The format of the memory should be chosen to match most of the inter-node traffic.

convert

is the address of a routine which converts from native format to neutral format. Ideally, the neutral format is the same as the native format so this routine is quite simple.

poll_intr, cause_intr

is either INTR_MODE or POLLED_MODE to indicate how the node will be informed of incoming messages.

Intr

is the information required to cause an interrupt on a node. This structure contains the following fields:

address

is the address to write at to cause an interrupt on that node. For a polled node, this should be NULL.

value

is the value to write to cause an interrupt.

length

is the length of the entity to write on the node to cause an interrupt. This can be 0 to indicate polled operation, 1 to write a byte, 2 to write a sixteen-bit entity, and 4 to write a thirty-two bit entity.

16.2 Primitives

16.2.1 Convert Address

The `Shm_Convert_address` is responsible for converting an address of an entity in the shared memory area into the address that should be used from this node. Most targets will simply return the address passed to this routine. However, some target boards will have a special window onto the shared memory. For example, some VMEbus boards have special address windows to access addresses that are normally reserved in the CPU's address space.

```

1 void *Shm_Convert_address( void *address )
2 {
3     return the local address version of this bus address
4 }
```

16.2.2 Get Configuration

The `Shm_Get_configuration` routine is responsible for filling in the Shared Memory Configuration Table passed to it.

```

1 void Shm_Get_configuration(
2     uint32_t      localnode,
3     shm_config_table **shmcfg
4 )
5 {
6     fill in the Shared Memory Configuration Table
7 }
```

16.2.3 Locking Primitives

This is a collection of routines that are invoked by the portable part of the Shared Memory Driver to manage locks in the shared memory buffer area. Accesses to the shared memory must be atomic. Two nodes in a multiprocessor system must not be manipulating the shared data structures simultaneously. The locking primitives are used to insure this.

To avoid deadlock, local processor interrupts should be disabled the entire time the locked queue is locked.

The locking primitives operate on the lock field of the `Shm_Locked_queue_Control` data structure. This structure is defined as follows:

```

1 typedef struct {
2     vol_u32 lock; /* lock field for this queue */
3     vol_u32 front; /* first envelope on queue */
4     vol_u32 rear; /* last envelope on queue */
5     vol_u32 owner; /* receiving (i.e. owning) node */
6 } Shm_Locked_queue_Control;
```

where each field is defined as follows:

lock

is the lock field. Every node in the system must agree on how this field will be used. Many

processor families provide an atomic “test and set” instruction that is used to manage this field.

front

is the index of the first message on this locked queue.

rear

is the index of the last message on this locked queue.

owner

is the node number of the node that currently has this structure locked.

16.2.3.1 Initializing a Shared Lock

The `Shm_Initialize_lock` routine is responsible for initializing the lock field. This routine usually is implemented as follows:

```

1 void Shm_Initialize_lock(
2   Shm_Locked_queue_Control *lq_cb
3 )
4 {
5   lq_cb->lock = LQ_UNLOCKED;
6 }
```

16.2.3.2 Acquiring a Shared Lock

The `Shm_Lock` routine is responsible for acquiring the lock field. Interrupts should be disabled while that lock is acquired. If the lock is currently unavailable, then the locking routine should delay a few microseconds to allow the other node to release the lock. Doing this reduces bus contention for the lock. This routine usually is implemented as follows:

```

1 void Shm_Lock(
2   Shm_Locked_queue_Control *lq_cb
3 )
4 {
5   disable processor interrupts
6   set Shm_isrstat to previous interrupt disable level
7
8   while ( TRUE ) {
9     atomically attempt to acquire the lock
10    if the lock was acquired
11      return
12    delay some small period of time
13  }
14 }
```

16.2.3.3 Releasing a Shared Lock

The `Shm_Unlock` routine is responsible for releasing the lock field and reenabling processor interrupts. This routine usually is implemented as follows:

```
1 void Shm_Unlock(  
2   Shm_Locked_queue_Control *lq_cb  
3 )  
4 {  
5   set the lock to the unlocked value  
6   reenable processor interrupts to their level prior  
7   to the lock being acquired. This value was saved  
8   in the global variable Shm_isrstat  
9 }
```

16.3 Installing the MPCCI ISR

The `Shm_setvec` is invoked by the portable portion of the shared memory to install the interrupt service routine that is invoked when an incoming message is announced. Some target boards support an interprocessor interrupt or mailbox scheme and this is where the ISR for that interrupt would be installed.

On an interrupt driven node, this routine would be implemented as follows:

```
1 void Shm_setvec( void )
2 {
3     install the interprocessor communications ISR
4 }
```

On a polled node, this routine would be empty.

FRAME BUFFER DRIVER

In this chapter, we present the basic functionality implemented by a frame buffer driver:

- `frame_buffer_initialize()`
- `frame_buffer_open()`
- `frame_buffer_close()`
- `frame_buffer_read()`
- `frame_buffer_write()`
- `frame_buffer_control()`

17.1 Introduction

The purpose of the frame buffer driver is to provide an abstraction for graphics hardware. By using the frame buffer interface, an application can display graphics without knowing anything about the low-level details of interfacing to a particular graphics adapter. The parameters governing the mapping of memory to displayed pixels (planar or linear, bit depth, etc) is still implementation-specific, but device-independent methods are provided to determine and potentially modify these parameters.

The frame buffer driver is commonly located in the console directory of the BSP and registered by the name `/dev/fb0`. Additional frame buffers (if available) are named `/dev/fb1*`, `*/dev/fb2`, etc.

To work with the frame buffer, the following operation sequence is used: `open()`, `ioctl()` to get the frame buffer info, `read()` and/or `write()`, and `close()`.

17.2 Driver Function Overview

17.2.1 Initialization

The driver initialization is called once during the RTEMS initialization process and returns `RTEMS_SUCCESSFUL` when the device driver is successfully initialized. During the initialization, a name is assigned to the frame buffer device. If the graphics hardware supports console text output, as is the case with the pc386 VGA hardware, initialization into graphics mode may be deferred until the device is `open()` ed.

The `frame_buffer_initialize()` function may look like this:

```

1 rtems_device_driver frame_buffer_initialize(
2   rtems_device_major_number major,
3   rtems_device_minor_number minor,
4   void *arg)
5 {
6   rtems_status_code status;
7
8   printk( "frame buffer driver initializing..\n" );
9
10  /*
11   * Register the device
12   */
13  status = rtems_io_register_name("/dev/fb0", major, 0);
14  if (status != RTEMS_SUCCESSFUL)
15  {
16    printk("Error registering frame buffer device!\n");
17    rtems_fatal_error_occurred( status );
18  }
19
20  /*
21   * graphics hardware initialization goes here for non-console
22   * devices
23   */
24
25  return RTEMS_SUCCESSFUL;
26 }

```

17.2.2 Opening the Frame Buffer Device

The `frame_buffer_open()` function is called whenever a frame buffer device is opened. If the frame buffer is registered as `/dev/fb0`, the `frame_buffer_open` entry point will be called as the result of an `open("/dev/fb0", mode)` in the application.

Thread safety of the frame buffer driver is implementation-dependent. The VGA driver shown below uses a mutex to prevent multiple `open()` operations of the frame buffer device.

The `frame_buffer_open()` function returns `RTEMS_SUCCESSFUL` when the device driver is successfully opened, and `RTEMS_UNSATISFIED` if the device is already open:

```

1 rtems_device_driver frame_buffer_close(
2   rtems_device_major_number major,
3   rtems_device_minor_number minor,
4   void *arg)

```

```

5 )
6 {
7   if (pthread_mutex_unlock(&mutex) == 0) {
8     /* restore previous state.  for VGA this means return to text mode.
9      * leave out if graphics hardware has been initialized in
10     * frame_buffer_initialize()
11     */
12     ega_hwterm();
13     printk( "FBVGA close called.\n" );
14     return RTEMS_SUCCESSFUL;
15   }
16   return RTEMS_UNSATISFIED;
17 }

```

In the previous example, the function `ega_hwinit()` takes care of hardware-specific initialization.

17.2.3 Closing the Frame Buffer Device

The `frame_buffer_close()` is invoked when the frame buffer device is closed. It frees up any resources allocated in `frame_buffer_open()`, and should restore previous hardware state. The entry point corresponds to the device driver close entry point.

Returns `RTEMS_SUCCESSFUL` when the device driver is successfully closed:

```

1 rtems_device_driver frame_buffer_close(
2   rtems_device_major_number major,
3   rtems_device_minor_number minor,
4   void *arg)
5 {
6   pthread_mutex_unlock(&mutex);
7
8   /* TODO check mutex return value, RTEMS_UNSATISFIED if it failed.  we
9    * don't want to unconditionally call ega_hwterm()... */
10  /* restore previous state.  for VGA this means return to text mode.
11   * leave out if graphics hardware has been initialized in
12   * frame_buffer_initialize() */
13  ega_hwterm();
14  printk( "frame buffer close called.\n" );
15  return RTEMS_SUCCESSFUL;
16 }

```

17.2.4 Reading from the Frame Buffer Device

The `frame_buffer_read()` is invoked from a `read()` operation on the frame buffer device. Read functions should allow normal and partial reading at the end of frame buffer memory. This method returns `RTEMS_SUCCESSFUL` when the device is successfully read from:

```

1 rtems_device_driver frame_buffer_read(
2   rtems_device_major_number major,
3   rtems_device_minor_number minor,
4   void *arg)
5 )
6 {

```

```

7  rtems_libio_rw_args_t *rw_args = (rtems_libio_rw_args_t *)arg;
8  rw_args->bytes_moved = ((rw_args->offset + rw_args->count) > fb_fix.smem_len ) ?
9                          (fb_fix.smem_len - rw_args->offset) : rw_args->count;
10 memcopy(rw_args->buffer,
11         (const void *) (fb_fix.smem_start + rw_args->offset),
12         rw_args->bytes_moved);
13 return RTEMS_SUCCESSFUL;
14 }

```

17.2.5 Writing to the Frame Buffer Device

The `frame_buffer_write()` is invoked from a `write()` operation on the frame buffer device. The frame buffer write function is similar to the read function, and should handle similar cases involving partial writes.

This method returns `RTEMS_SUCCESSFUL` when the device is successfully written to:

```

1 rtems_device_driver frame_buffer_write(
2   rtems_device_major_number major,
3   rtems_device_minor_number minor,
4   void *arg
5 )
6 {
7   rtems_libio_rw_args_t *rw_args = (rtems_libio_rw_args_t *)arg;
8   rw_args->bytes_moved = ((rw_args->offset + rw_args->count) > fb_fix.smem_len ) ?
9                          (fb_fix.smem_len - rw_args->offset) : rw_args->count;
10  memcopy((void *) (fb_fix.smem_start + rw_args->offset),
11         rw_args->buffer,
12         rw_args->bytes_moved);
13  return RTEMS_SUCCESSFUL;
14 }

```

17.2.6 Frame Buffer IO Control

The frame buffer driver allows several `ioctl`s, partially compatible with the Linux kernel, to obtain information about the hardware.

All `ioctl()` operations on the frame buffer device invoke `frame_buffer_control()`.

`Ioctls supported:`

- `ioctl`s to get the frame buffer screen info (fixed and variable).
- `ioctl` to set and get palette.

```

1 rtems_device_driver frame_buffer_control(
2   rtems_device_major_number major,
3   rtems_device_minor_number minor,
4   void *arg
5 )
6 {
7   rtems_libio_ioctl_args_t *args = arg;
8
9   printk( "FBVGA ioctl called, cmd=%x\n", args->command );
10 }

```

```
11  switch( args->command ) {
12      case FBIOGET_FSCREENINFO:
13          args->iocctl_return = get_fix_screen_info( ( struct fb_fix_screeninfo * ) args->
↳buffer );
14          break;
15      case FBIOGET_VSCREENINFO:
16          args->iocctl_return = get_var_screen_info( ( struct fb_var_screeninfo * ) args->
↳buffer );
17          break;
18      case FBIOPUT_VSCREENINFO:
19          /* not implemented yet*/
20          args->iocctl_return = -1;
21          return RTEMS_UNSATISFIED;
22      case FBIOGETCMAP:
23          args->iocctl_return = get_palette( ( struct fb_cmap * ) args->buffer );
24          break;
25      case FBIOPUTCMAP:
26          args->iocctl_return = set_palette( ( struct fb_cmap * ) args->buffer );
27          break;
28      default:
29          args->iocctl_return = 0;
30          break;
31  }
32
33  return RTEMS_SUCCESSFUL;
34 }
```

See `rtems/fb.h` for more information on the list of ioctls and data structures they work with.

ANALOG DRIVER

The Analog driver is responsible for providing an interface to Digital to Analog Converters (DACs) and Analog to Digital Converters (ADCs). The capabilities provided by this class of device driver are:

- Initialize an Analog Board
- Open a Particular Analog
- Close a Particular Analog
- Read from a Particular Analog
- Write to a Particular Analog
- Reset DACs
- Reinitialize DACS

Most analog devices are found on I/O cards that support multiple DACs or ADCs on a single card.

There are currently no analog device drivers included in the RTEMS source tree. The information provided in this chapter is based on drivers developed for applications using RTEMS. It is hoped that this driver model information can form the basis for a standard analog driver model that can be supported in future RTEMS distribution.

18.1 Major and Minor Numbers

The major number of a device driver is its index in the RTEMS Device Address Table.

A minor number is associated with each device instance managed by a particular device driver. An RTEMS minor number is an unsigned32 entity. Convention calls for dividing the bits in the minor number down into categories like the following:

- board - indicates the board a particular device is located on
- port - indicates the particular device on a board.

From the above, it should be clear that a single device driver can support multiple copies of the same board in a single system. The minor number is used to distinguish the devices.

18.2 Analog Driver Configuration

There is not a standard analog driver configuration table but some fields are common across different drivers. The analog driver configuration table is typically an array of structures with each structure containing the information for a particular board. The following is a list of the type of information normally required to configure an analog board:

board_offset

is the base address of a board.

DAC_initial_values

is an array of the voltages that should be written to each DAC during initialization. This allows the driver to start the board in a known state.

18.3 Initialize an Analog Board

At system initialization, the analog driver's initialization entry point will be invoked. As part of initialization, the driver will perform whatever board initialization is required and then set all outputs to their configured initial state.

The analog driver may register a device name for each DAC and ADC in the system.

18.4 Open a Particular Analog

This is the driver open call. Usually this call does nothing other than validate the minor number. With some drivers, it may be necessary to allocate memory when a particular device is opened. If that is the case, then this is often the place to do this operation.

18.5 Close a Particular Analog

This is the driver close call. Usually this call does nothing.

With some drivers, it may be necessary to allocate memory when a particular device is opened. If that is the case, then this is the place where that memory should be deallocated.

18.6 Read from a Particular Analog

This corresponds to the driver read call. After validating the minor number and arguments, this call reads the indicated device. Most analog devices store the last value written to a DAC. Since DACs are output only devices, saving the last written value gives the appearance that DACs can be read from also. If the device is an ADC, then it is sampled.

Note: Many boards have multiple analog inputs but only one ADC. On these boards, it will be necessary to provide some type of mutual exclusion during reads. On these boards, there is a MUX which must be switched before sampling the ADC. After the MUX is switched, the driver must delay some short period of time (usually microseconds) before the signal is stable and can be sampled. To make matters worse, some ADCs cannot respond to wide voltage swings in a single sample. On these ADCs, one must do two samples when the voltage swing is too large. On a practical basis, this means that the driver usually ends up double sampling the ADC on these systems.

The value returned is a single precision floating point number representing the voltage read. This value is stored in the `argument_block` passed in to the call. By returning the voltage, the caller is freed from having to know the number of bits in the analog and board dependent conversion algorithm.

18.7 Write to a Particular Analog

This corresponds to the driver write call. After validating the minor number and arguments, this call writes the indicated device. If the specified device is an ADC, then an error is usually returned.

The value written is a single precision floating point number representing the voltage to be written to the specified DAC. This value is stored in the `argument_block` passed in to the call. By passing the voltage to the device driver, the caller is freed from having to know the number of bits in the analog and board dependent conversion algorithm.

18.8 Reset DACs

This is one of the IOCTL functions supported by the I/O control device driver entry point. When this IOCTL function is invoked, all of the DACs are written to 0.0 volts.

18.9 Reinitialize DACS

This is one of the IOCTL functions supported by the I/O control device driver entry point. When this IOCTL function is invoked, all of the DACs are written with the initial value configured for this device.

18.10 Get Last Written Values

This is one of the IOCTL functions supported by the I/O control device driver entry point. When this IOCTL function is invoked, the following information is returned to the caller:

- last value written to the specified DAC
- timestamp of when the last write was performed

DISCRETE DRIVER

The Discrete driver is responsible for providing an interface to Discrete Input/Outputs. The capabilities provided by this class of device driver are:

- Initialize a Discrete I/O Board
- Open a Particular Discrete Bitfield
- Close a Particular Discrete Bitfield
- Read from a Particular Discrete Bitfield
- Write to a Particular Discrete Bitfield
- Reset DACs
- Reinitialize DACS

Most discrete I/O devices are found on I/O cards that support many bits of discrete I/O on a single card. This driver model is centered on the notion of reading bitfields from the card.

There are currently no discrete I/O device drivers included in the RTEMS source tree. The information provided in this chapter is based on drivers developed for applications using RTEMS. It is hoped that this driver model information can form the discrete I/O driver model that can be supported in future RTEMS distribution.

19.1 Major and Minor Numbers

The major number of a device driver is its index in the RTEMS Device Address Table.

A minor number is associated with each device instance managed by a particular device driver. An RTEMS minor number is an unsigned32 entity. Convention calls for dividing the bits in the minor number down into categories that specify a particular bitfield. This results in categories like the following:

- `board` - indicates the board a particular bitfield is located on
- `word` - indicates the particular word of discrete bits the bitfield is located within
- `start` - indicates the starting bit of the bitfield
- `width` - indicates the width of the bitfield

From the above, it should be clear that a single device driver can support multiple copies of the same board in a single system. The minor number is used to distinguish the devices.

By providing a way to easily access a particular bitfield from the device driver, the application is insulated with knowing how to mask fields in and out of a discrete I/O.

19.2 Discrete I/O Driver Configuration

There is not a standard discrete I/O driver configuration table but some fields are common across different drivers. The discrete I/O driver configuration table is typically an array of structures with each structure containing the information for a particular board. The following is a list of the type of information normally required to configure an discrete I/O board:

board_offset

is the base address of a board.

relay_initial_values

is an array of the values that should be written to each output word on the board during initialization. This allows the driver to start with the board's output in a known state.

19.3 Initialize a Discrete I/O Board

At system initialization, the discrete I/O driver's initialization entry point will be invoked. As part of initialization, the driver will perform whatever board initialization is required and then set all outputs to their configured initial state.

The discrete I/O driver may register a device name for bitfields of particular interest to the system. Normally this will be restricted to the names of each word and, if the driver supports it, an "all words".

19.4 Open a Particular Discrete Bitfield

This is the driver open call. Usually this call does nothing other than validate the minor number. With some drivers, it may be necessary to allocate memory when a particular device is opened. If that is the case, then this is often the place to do this operation.

19.5 Close a Particular Discrete Bitfield

This is the driver close call. Usually this call does nothing.

With some drivers, it may be necessary to allocate memory when a particular device is opened. If that is the case, then this is the place where that memory should be deallocated.

19.6 Read from a Particular Discrete Bitfield

This corresponds to the driver read call. After validating the minor number and arguments, this call reads the indicated bitfield. A discrete I/O devices may have to store the last value written to a discrete output. If the bitfield is output only, saving the last written value gives the appearance that it can be read from also. If the bitfield is input, then it is sampled.

Note: Many discrete inputs have a tendency to bounce. The application may have to take account for bounces.

The value returned is an unsigned32 number representing the bitfield read. This value is stored in the `argument_block` passed in to the call.

Note: Some discrete I/O drivers have a special minor number used to access all discrete I/O bits on the board. If this special minor is used, then the area pointed to by `argument_block` must be the correct size.

19.7 Write to a Particular Discrete Bitfield

This corresponds to the driver write call. After validating the minor number and arguments, this call writes the indicated device. If the specified device is an ADC, then an error is usually returned.

The value written is an unsigned32 number representing the value to be written to the specified bitfield. This value is stored in the `argument_block` passed in to the call.

Note: Some discrete I/O drivers have a special minor number used to access all discrete I/O bits on the board. If this special minor is used, then the area pointed to by `argument_block` must be the correct size.

19.8 Disable Discrete Outputs

This is one of the IOCTL functions supported by the I/O control device driver entry point. When this IOCTL function is invoked, the discrete outputs are disabled.

Note: It may not be possible to disable/enable discrete output on all discrete I/O boards.

19.9 Enable Discrete Outputs

This is one of the IOCTL functions supported by the I/O control device driver entry point. When this IOCTL function is invoked, the discrete outputs are enabled.

Note: It may not be possible to disable/enable discrete output on all discrete I/O boards.

19.10 Reinitialize Outputs

This is one of the IOCTL functions supported by the I/O control device driver entry point. When this IOCTL function is invoked, the discrete outputs are rewritten with the configured initial output values.

19.11 Get Last Written Values

This is one of the IOCTL functions supported by the I/O control device driver entry point. When this IOCTL function is invoked, the following information is returned to the caller:

- last value written to the specified output word
- timestamp of when the last write was performed

COMMAND AND VARIABLE INDEX

There are currently no Command and Variable Index entries.

- genindex
- search

INDEX

BSP_DEFAULT_UNIFIED_WORK_AREAS, 37
BSP_IDLE_TASK_BODY, 37
BSP_IDLE_TASK_STACK_SIZE, 37
bsp_interrupt_dispatch(), 40
bsp_interrupt_facility_initialize(), 40
bsp_interrupt_handler_default(), 40
BSP_INTERRUPT_STACK_SIZE, 37
bsp_interrupt_vector_disable(), 40
bsp_interrupt_vector_enable(), 40
BSP_ZERO_WORKSPACE_AUTOMATICALLY,
37
CONFIGURE_MALLOC_BSP_SUPPORTS_
SBRK, 35, 37