DSC56800EX Quick Start User Guide

DSC56800EXQSUG
Rev. 2
04/2015

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Introduction

This user's manual is targeted for Freescale 56F82xxx and 56F84xxx application developers. Its purpose is to describe the development environment, the software modules and the tools for the 56F82xxx and 56F84xxx and the Application Programming Interface (API). Simply, this manual describes how to use the Freescale DSC56800EX_Quick_Start tool to develop software for the Freescale 56F82xxx and 56F84xxx Digital Signal Controllers (DSC).

1.1 Overview

The DSC56800EX_Quick_Start development environment provides fully debugged peripheral drivers, examples and interfaces, that allow programmers to create their own C application code, independent of the core architecture. This environment has been developed to complement the existing development environment for Freescale 56F8xxx embedded processors. It provides a software infrastructure that allows development of efficient, ready to use high level software applications, that are fully portable and reusable between different core architectures. The maximum portability is achieved for devices with comparable on-chip peripheral modules.

This manual contains information specific only to DSC56800EX_Quick_Start tool as it applies to the Freescale 56F8xxx software development. Therefore it is required that users of the DSC56800EX_Quick_Start tool should be familiar with the 56800E family in general, as described in the ***DSP56800E and DSP56800EX 16-Bit DSP Core Reference Manual*** (DSP56800ERM/D), ***MC56F84XXX Reference Manual*** (MC56F84XXXRM) and the **56F82XXX Reference Manual** (MC56F82XXXRM), before continuing. The 56F82xxx and 56F84xxx devices are supported by a complete set of hardware development boards - Tower modules (TWRs).

Comprehensive information about available tools and documentation can be found on Freescale web pages:

freescale.com

Freescale DSC56800EX_Quick_Start tool is designed for and can be fully integrated with Freescale CodeWarrior development tools. Before starting to explore the full feature set of the DSC56800EX_Quick_Start, one should install and become familiar with the CodeWarrior development environment.

All together, the DSC56800EX_Quick_Start, the CodeWarrior, and the TWRs create a complete and scalable tool solution for easy, fast and efficient development.

1.1.1 Features

The DSC56800EX_Quick_Start environment is composed of the following major components: core-system infrastructure, on-chip drivers with defined API, sample example applications, Graphical Configuration Tool and FreeMASTER software support. This section brings very illustrative information about these components, while the comprehensive description can be found in specially targeted chapters.

1.1.1.1 Core-system Infrastructure

The core-system infrastructure creates the fundamental infrastructure for the 56F82xxx and 56F84xxx device operation and enables further integration with other components, e.g. on-chip drivers. The basic development support provided includes: setting of the required operation mode, commonly used macro definitions, portable architecture-dependent register declaration, mechanism for static configuration of on-chip peripherals as well as interrupt vectors, and the project templates.

1.1.1.2 On-chip Drivers

The on-chip drivers isolate the hardware-specific functionality into a set of driver commands with defined API. The API standardizes the interface between the software and the hardware, see Figure 1-1. This isolation enables a high degree of portability or architectural and hardware independence for application code. This is mainly valid for devices with similar peripheral modules. The driver code reuses lead for greater efficiency and performance.

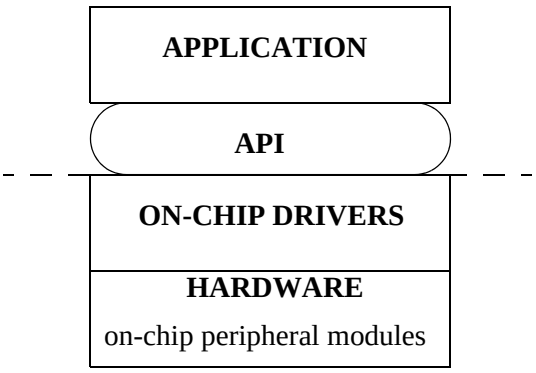


Figure 1-1. Software Structure

1.1.1.3 Sample Applications

The DSC56800EX_Quick_Start tool contains many sample applications that demonstrate how to use on-chip drivers and how to implement some user-specific tasks. These sample examples are kept simple and illustrative and their intention is to minimize the learning curve.

1.1.1.4 Graphical Configuration Tool

The Graphical Configuration Tool (GCT) is a graphical user interface (GUI), designed to provide static chip and on-chip peripheral module setting/initialization, including association of the interrupt vectors with user interrupt service routines.

The Graphical Configuration Tool is not required in order to use the DSC56800EX_Quick_Start environment, i.e. it is optional. Nevertheless, this tool simplifies the configuration of on-chip peripheral

modules and the device itself. It also guides the user by supplying a lot of useful information and hints. It is therefore recommended to use the Graphical Configuration Tool.

1.1.1.5 FreeMASTER Software

The FreeMASTER application is a software tool initially created for developers of Motor Control applications, but it may be extended to any other application development. This tool allows remote control of an application using a user-friendly graphical environment running on a PC. It also provides the ability to view some real-time application variables in both textual and graphical form.

Main features:

- Graphical environment
- Visual Basic Script or Java Script can be used for control of target board
- Easy to understand navigation
- Connection to target board possible over a network, including Internet
- Demo mode with password protection support
- Visualization of real-time data in Scope window
- Acquisition of fast data changes using integrated Recorder
- Value interpretation using custom defined text messages
- Built-in support for standard variable types (integer, floating point, bit fields)
- Several built-in transformations for real type variables
- Automatic variable extraction from CodeWarrior linker output files (MAP, ELF)
- Remote control of application execution

The FreeMASTER tool is not required in order to use the DSC56800EX_Quick_Start environment, i.e. it is optional. Nevertheless, FreeMASTER is a versatile tool to be used for multipurpose algorithms and applications. It provides a lot of excellent features, including:

- Real-Time debugging
- Diagnostic tool
- Demonstration tool
- Education tool

The full description can be found in the ***FreeMASTER User Manual*** attached to the FreeMASTER tool.

1.2 Quick Start

This chapter provides the information required to get the DSC56800EX_Quick_Start tool installed and running.

1.2.1 CodeWarrior for Microcontrollers

CodeWarrior Development Studio V10.3 (or later) is a complete Integrated Development Environment (IDE) that provides a highly visual and automated framework to accelerate development of the most complex embedded applications.

CodeWarrior for Microcontrollers integrates the development tools for the ColdFire®, ColdFire+, DSC, Kinetis, Qorivva, PX, RS08, S08, and S12Z architectures into a single product based on the Eclipse open development platform. Eclipse offers an excellent framework for building software development environments and is a standard framework used by many embedded software vendors.

As previously mentioned, DSC56800EX_Quick_Start tool is designed for and can be integrated with CodeWarrior for Microcontrollers development tool. With CodeWarrior for Microcontrollers tool, users can build applications and integrate other software included as part of the DSC56800EX_Quick_Start release. Once the software is built, CodeWarrior tools allows users to download executable images into the target platform and run or debug the downloaded code.

To install CodeWarrior for Microcontrollers V10.3, it is recommended to use the installation guide attached to the actual version of CodeWarrior for Microcontrollers, if available.

1.2.2 Install DSC56800EX_Quick_Start

In order for the DSC56800EX_Quick_Start to integrate itself with the development tools, the CodeWarrior tools should be installed prior to the installation of DSC56800EX_Quick_Start installation (see previous section). If the DSC56800EX_Quick_Start tool is installed while CodeWarrior is not present, users can only browse the installed software package, but will not be able to build, download and run the released code. However, the installation can be simply completed once CodeWarrior is installed, see Section 1.2.1.

The installation itself consists of copying the required files to the destination hard drive, checking the presence of CodeWarrior and creating the shortcut under the Start->Programs menu. It is recommended to use the default installation directory path *c:\Freescale\...* .

NOTE

Each DSC56800EX_Quick_Start release is installed in its own new directory named *DSC56800EX_Quick_Start rX.Y* (where *X.Y* denotes the release number). Thus, it enables to maintain the older releases and projects. It gives free choice to select the active release.

To start the installation process, perform the following steps:

1. Execute DSC56800EX_Quick_Start_rXY.exe
2. Follow the DSC56800EX_Quick_Start software installation instructions on your screen.
3. In case the installation directory is different than default path, it is essential to change DSC56800EX_Quick_Start path variable in CodeWarrior Development Studio

1.2.2.1 Install Graphical Configuration Tool

Graphical Configuration Tool is installed together with the DSC56800EX_Quick_Start environment as part of the *Typical* installation. Graphical configuration tool can also be installed as a selectable component within the *Custom* installation.

Graphical Configuration Tool is able to work as stand-alone, but integration with the CodeWarrior IDE markedly increases the efficiency of this tool. The integration is based on the IDE user-configurable menus and its interface for external plug-ins.

NOTE

External Tool Configurations are set only for the actual Workspace. Newly created Workspace requires new configuration setting for GCT integration.

To integrate the Graphical Configuration Tool with CodeWarrior Workspace, perform the following steps:

a) Launch CodeWarrior IDE from the Start->Programs->Freescale CodeWarrior menu.

b) Open the *External Tools Configurations* dialog window using Run->External Tools->External Tools Configurations.

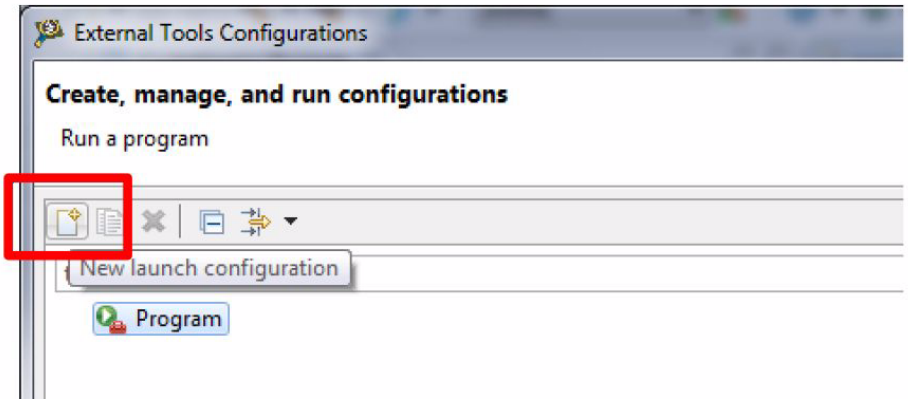


Figure 1-2. External Tool Configurations

c) Set the GCT launcher settings in Main tab Location (path to the project folder should be less than 120 characters and must not contain a "space" character), Working directory and Arguments as a system variable ${project_loc}.

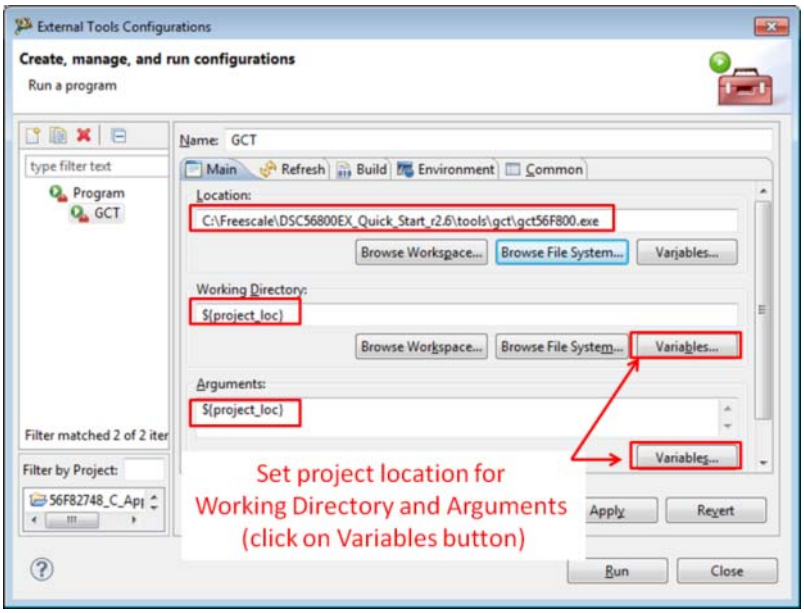


Figure 1-3. GCT Integration

d) Untick the *Build before lanunch* box and click *Apply.*

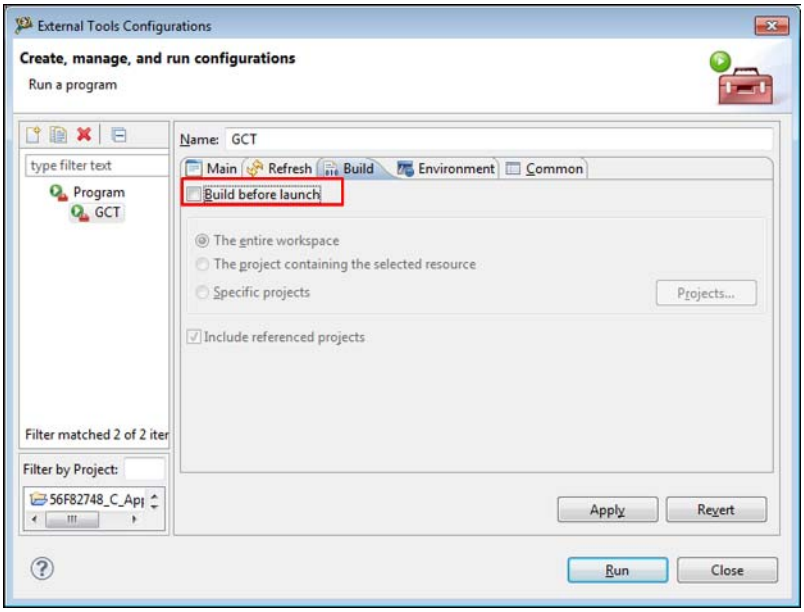


Figure 1-4. Build Before Launch

e) Click on *Run* button.

f) Optionally the key bidding for GCT might be set.

g) Open *Window -> Preferences* dialog box.

h) Search for "*keys*" and "*run last*" in Preferences window.

i) Select "*Run Last Launched External Tool*" in command menu.

j) Set required binding.

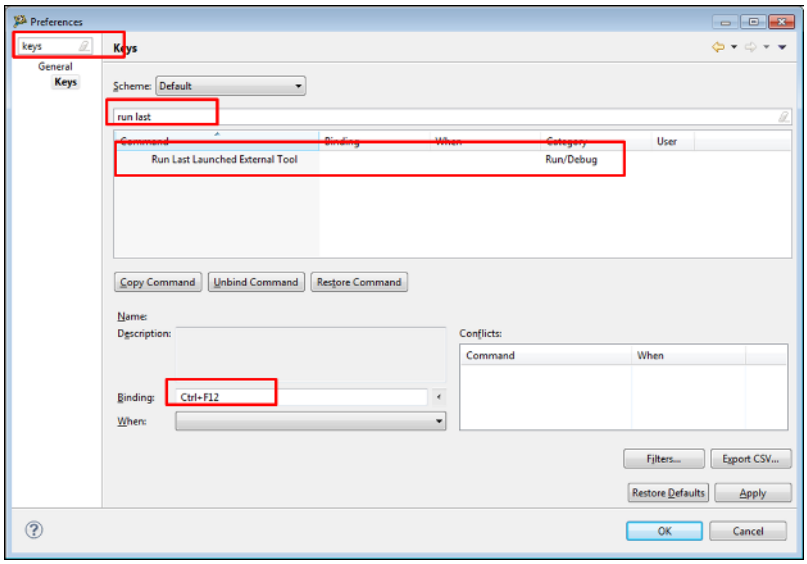


Figure 1-5. GCT Key Binding

k) Click on "*Apply*" and "*OK*" buttons.

Now you should be able to execute the Graphical Configuration Tool from the CodeWarrior IDE menu *Run->External Tools->GCT* by clicking on the icon or by pressing the chosen key shortcut. Note that the DSC56800EX_Quick_Start project should be open in the Workspace to quickly execute the Graphical Configuration Tool.

1.2.2.2 Install FreeMASTER (PC Master Software)

1.2.2.2.1 System Requirements

The FreeMASTER application can run on any computer with Microsoft Windows 98 or later operating system. Before installing, the Internet Explorer 4.5.5 or higher.

Operating system: Microsoft Windows XP, Windows 2000, Windows NT4 with SP6, Windows 98, through Window 7 (on the host side)

Required software: Internet Explorer 4.5.5 or higher installed. For selected features (e.g. regular expression-based parsing), Internet Explorer 5.5 or higher is required.

Hard drive space: 108 MB

Other hardware requirements: Mouse, serial RS-232 port for local control, network access for remote control

1.2.2.2.2 Target Development Board Requirements

To enable the FreeMASTER connection to the target board application, follow the instructions provided with the embedded-side development tool. The recommended and fastest way to start using FreeMASTER is by trying the sample application.

FreeMASTER software relies on the following items to be provided by the target development board:

Interface: Serial communication port or the JTAG port (available on all Freescale EVM boards).

Data RAM Memory: Approximately 160 words of data memory plus the size of the recorder buffer is needed for the full configuration. Optionally, some features can be disabled to reduce required data memory size.

Program Flash Memory: Required size is approximately 2K words for the full configuration. Optionally, some features can be removed to reduce required program memory size

1.2.2.2.3 Enabling FreeMASTER on Target Application

To enable the FreeMASTER operation on the target board application, see description and an example in Chapter 6, “FreeMASTER Driver.”

1.2.2.2.4 How to Install

The FreeMASTER application is an optional part of the DSC56800EX_Quick_Start environment and must be installed separately, e.g. running the **FMASTERSW_v16.exe** (or later).

1.2.3 Build and Run Sample Application

Once the DSC56800EX_Quick_Start tool is installed, the user can build and run any released demo application for the TWR DSC modules by opening and building the project and using the CodeWarrior development environment. *pwm_demo* is used as an example in this case.

Two methods can be used to open an example project Import (Step 2&3) or drag&drop (Step 4):

Step 1: Launch CodeWarrior IDE from the Start->Programs->Freescale CodeWarrior menu and open existing or create new *Workspace*.

Step 2: Choose *File->Import* command and select *General->Existing Projects into Workspace* and click on *Next.*

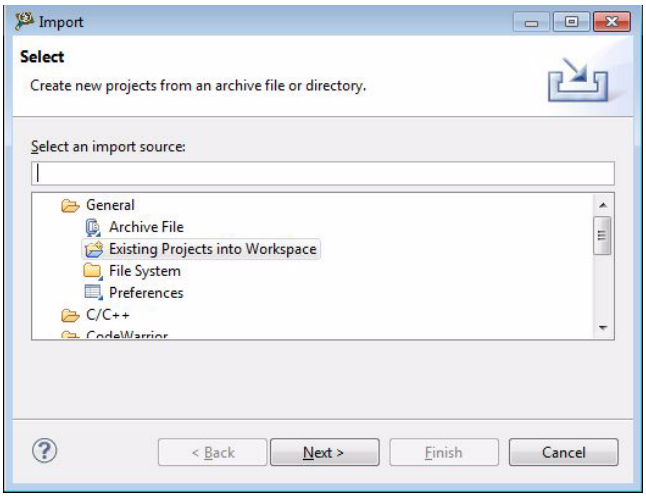


Figure 1-6. Import Dialog Box

Step 3: Select root directory of the example project, e.g ..*\DSC56800EX_Quick_Start r2.6\sample_applications\MC56F8200TWR\pwm_demo*. The example project might be copied into the CodeWarrior Workspace by ticking *Copy project into workspace* tick box and click on *Finish.*

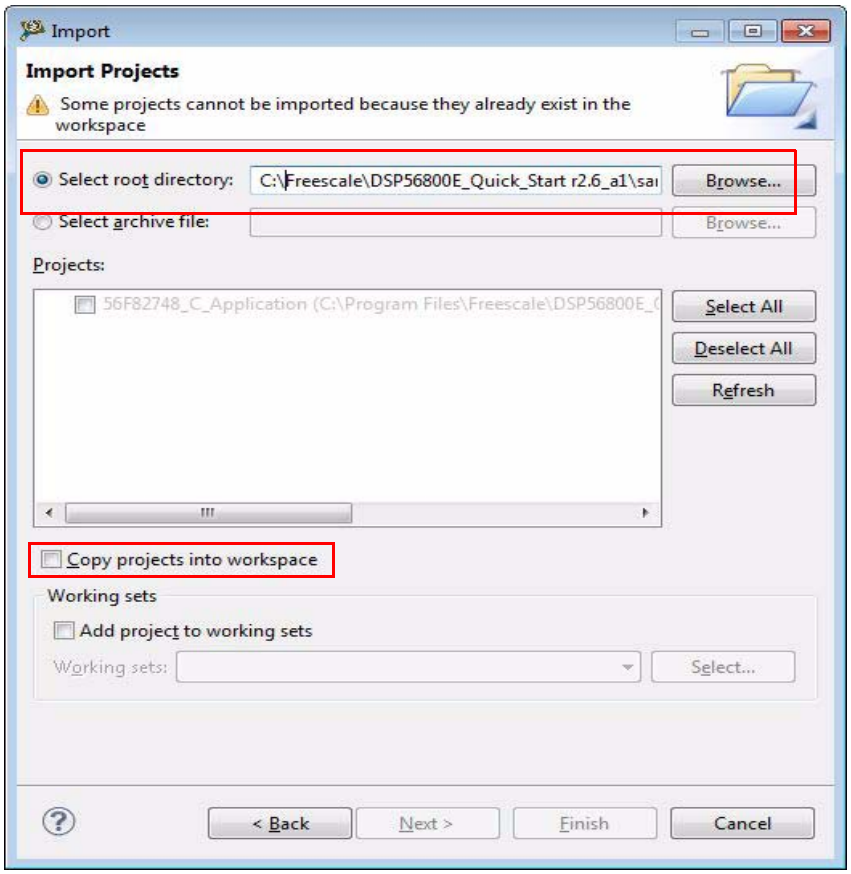


Figure 1-7. Root Directory Selection

NOTE

Select the corresponding directory according to your TWR DSC board

Step 4: Select root directory of the example project, e.g. *..\DSC56800EX_Quick_Start r2.6\sample_applications\MC56F8200TWR\pwm_demo*. Drag and drop *.project* file to the CodeWarrior Workspace Project Tab.

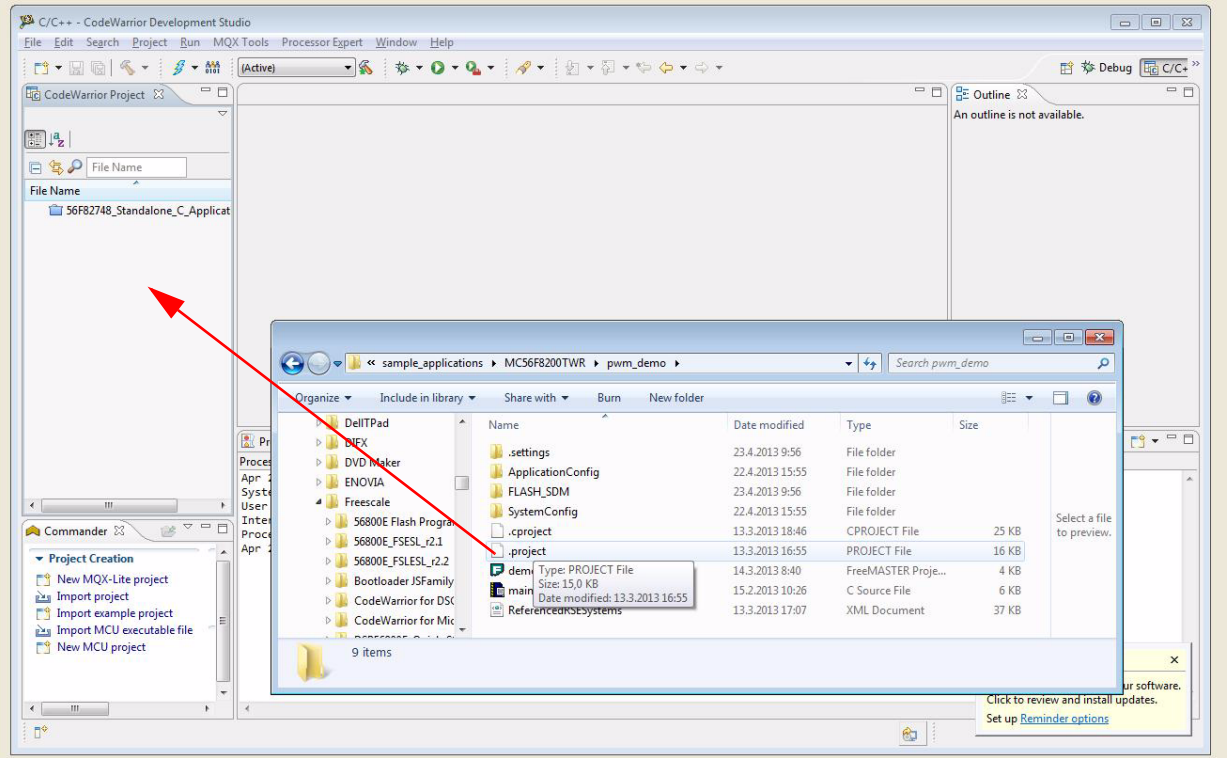


Figure 1-8. Drag & Drop CodeWarrior Project File

Step 5: Clean the project right clicking on the project a choosing *Clean* command.

Step 6: Build the application code by pressing Ctrl+B or choosing Project->Build All command. Check if there is zero errors after the application building.

Step 7: Run the application by pressing the green arrow (Run) or choose the *Run->Run* command from the menu. Select proper debug interface for SDM configuration.

At this point, the application is running - the LEDs associated to the PWM outputs are flashing and the green LED is blinking periodically.

The subsequent chapters describe how to create a new application, how to use interrupts, how to use on-chip drivers, and other information required to successfully create a new application.

Chapter 2
Core System Infrastructure

The Core System Infrastructure is one of the three main blocks that compose the 56800EX_Quick_Start tool (see Section 1.1.1 where the partitioning is described). Its purpose is to provide the fundamental infrastructure for the 56800EX device operation (e.g. sets the operation mode, the interrupt handling, the initialization of the global variables, CodeWarrior Compiler options). It also provides some additional support (commonly used macros, data types) and enables further integration with On-chip Drivers.

2.1 Boot Sequence

The Core System Infrastructure provides the fundamental code which is executed before the user's main function. This code provides basic settings needed to initialize the chip, settings required by the CodeWarrior Compiler, initialization of global variables. Finally it passes control to the user's application code (the *main* function).

NOTE

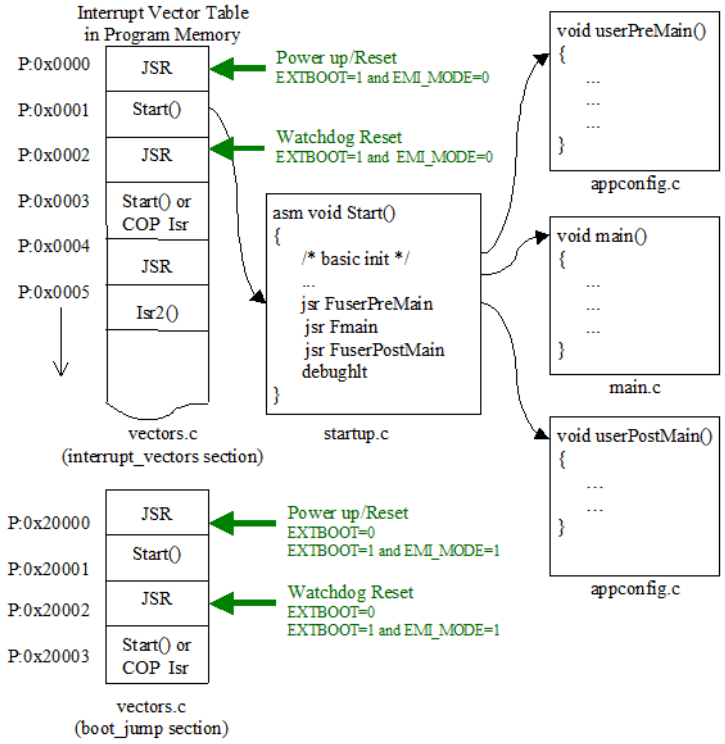
This chapter describes the boot process of the 56F82xxx and 56F84xxx family of microcontrollers.

For the 56F82xxx and 56F84xxx devices, the post-reset execution flow may be briefly described as follows (also see Figure 2-1):

1. After processor reset, the execution starts at the Hardware Reset vector in program memory, where the 56800EX_Quick_Start tool places its jump to the *Start()* assembly routine. The reset vector is located at address 0x0000 and the jump is supplied directly from the first entry of vector table located in the *interrupt_vectors* section in *vectors.c* file.
2. If the chip reset is generated by the watchdog module (COP), the same rules as in the previous point apply. Again the COP Reset vector is supplied from the full vector table at address 0x0000 (*interrupt_vectors* section). The default value of COP Reset vector is *Start()*, so the standard power-up code is processed. The user is able to redefine the COP Reset service routine same way the other interrupt vectors are installed (see Section 2.6.2 on page -35 for more details).
3. *Start()* assembly routine (in *startup.c* file)
4. *userPreMain()* function (in *appconfig.c* file)
5. user's *main()* function (in default project it is located in *main.c*)
6. *userPostMain()* function (in *appconfig.c* file)

The following subsections provide a detailed description of all initialization performed before user's *main()* function is called.

Figure 2-1. Boot Sequence



2.1.1 Power-up/Reset

The 56800EX core specifies two reset vectors: Hardware Reset and COP Watchdog Reset. These reset vectors are located at the locations of interrupt vector table at address 0x0000. These vectors identify the address of the program code where the program control is passed to on reset. In applications developed with the 56800EX_Quick_Start tool, the default entry point is the *Start()* assembly routine in the *startup.c* file.

In the 56800EX_Quick_Start tool, the vector table (*vectors.c*) is always linked at address 0x0000 for any processor configuration. The startup code then configures the interrupt controller to use the address 0x0000 as the vector table base address.

2.1.2 *Start()* - entry point

The entry point of all projects developed with the 56800EX_Quick_Start tool is the *Start()* assembly routine located in the *startup.c* file in {project}\SystemConfig directory. This routine performs the following initialization:

- the interrupt controller uses the address 0x0000 as the vector base address
- sets the OMR register according to the settings in global application configuration file (*appconfig.h*)

- initializes the On-chip Clock Synthesis (OCCS) module, sets the PLL (by values from *appconfig.h*) and waits while the generated clock is stable
- initializes the stack pointer (SP) to the address after any data segments
- clears the *.bss* segment which holds the uninitialized global and static C variables
- copies the initial values from Flash memory to initialized global C variables (*.data* segment). The P-Flash memory is used to hold the initialization data.
- clears and initializes variables in the *fardata.bss* and *fardata.data* segments
- clears and initializes variables in the *.bss.pmem* and *.bss.data* segment (program RAM-based variables)
- initializes the program RAM-based code of the *pramcode* section.

When all the initialization is done, the functions *userPreMain(), main(), userPostMain()* are called.

2.1.3 userPreMain()

The *userPreMain()* function is called before the main application code in the *main()* function. The user can add any additional initialization code here. The function is located in the *appconfig.c* file.

2.1.4 *main()* the User's Application Code

The *main()* function is called after all the code described above is executed (i.e. the processor is initialized and the user's pre-main code is executed). It is the place where the user writes the application code. By default the function is located in the *main.c* file, but the file can be renamed by the user.

2.1.5 userPostMain()

The *userPostMain()* function is called after the main application code is finished. The user can add any additional code he/she wishes. By default the processor is halted by *debughlt* instruction here. The function is located in the *appconfig.c* file.

2.2 Data Types

The 56800EX_Quick_Start tool defines some basic data types to support code portability between different hardware architectures and tools. These basic data types, which are defined in the C header file *types.h*, support International Telecommunication Union (ITU) generic word types, integer, fractional, and complex data types. This is used throughout the interface definitions for the On-Chip Drivers. Note that in some development environments these data type definitions are located in the *prototype.h* file.

1. Generic word types

- Word8 - to represent 8-bit signed character variable/value
- UWord8 - to represent 16-bit unsigned character variable/value
- Word16 - to represent 16-bit signed variable/value
- UWord16 - to represent 16-bit unsigned variable/value
- Word32 - to represent 32-bit signed variable/value

- UWord32 - to represent 32-bit unsigned variable/value

2. Integer types

- Int8 - to represent 8-bit signed character variable/value
- UInt8 - to represent 8-bit unsigned character variable/value
- Int16 - to represent 16-bit signed variable/value
- UInt16 - to represent 16-bit unsigned variable/value
- Int32 - to represent 32-bit signed variable/value
- UInt32 - to represent 32-bit unsigned variable/value

3. Fractional types

- Frac16 - to represent 16-bit signed variable/value
- Frac32 - to represent 32-bit signed variable/value
- CFrac16 - to represent 16-bit complex numbers
- CFrac32 - to represent 32-bit complex numbers

4. Miscellaneous types

- bool - to represent boolean variable (true/false)

5. Constants

- true - represents true value
- false - represents false value
- NULL - represents null pointer
- PASS - represents pass as function result
- FAIL - represents fail as function result
- MAX_32 - maximum 32-bit signed (Word32) value
- MIN_32 - minimum 32-bit signed (Word32) value
- MAX_16 - maximum 16-bit signed (Word16) value
- MIN_16 - minimum 16-bit signed (Word16) value

2.3 *ArchIO* Peripheral Register Structures

The global symbol *ArchIO* provides a C interface (structure type) to all peripheral and core registers mapped in data memory. All registers are accessed via this structure so there is no need to know and specify the concrete addresses of the registers to write or read. This mechanism increases code readability and portability and simplifies access to registers. The *ArchIO* is declared in the C header file *arch.h.*

The *ArchIO* is of type *arch_sIO, which is* the structure type composed from another structures, one for each peripheral module.

There are two possible approaches how to define and use the ArchIO structure:

- define ArchIO as the direct (numeric) address of memory-mapped peripheral registers casted to the proper structure type.
- define ArchIO as the *extern* variable while defining its address by a directive in linker command file.

The second approach is used in the 56800EX_Quick_Start tool implementation by default.

Example 2-1. Using the ArchIO structure

```
UWord16 RegValue;

RegValue = ArchIO.TimerD.Channel0.HoldReg;
ArchIO.TimerD.Channel0.CompareReg1 = 0x8000;
```

The Example 2-1 reads the timer/counter D0 Hold Register (HOLD) and writes to the timer/counter D0 Compare Register 1 (CMP1).

Example 2-2. Using the ArchIO structure

```
UWord16 RegValue;

RegValue = periphMemRead(&ArchIO.TimerD.Channel0.HoldReg);
periphMemWrite(0x8000, &ArchIO.TimerD.Channel0.CompareReg1);
```

Example 2-2 shows the same operation using the *periphMemRead* and *periphMemWrite* macros described later in Section 2.5:

2.4 Core System's Routines and Macros

This section describes routines, macros and intrinsic function redefinition provided by the Core System Infrastructure.

2.4.1 Architecture dependent routines

This section describes architecture dependent routines and macros which provide interface to the 56800EX core architecture. It encapsulates the unique features of the 56800EX architecture into the abstract APIs. All routines are defined in the *arch.h* header file.

2.4.1.1 archEnableInt - enable interrupts

Call(s):

```
void archEnableInt(void);
```

Arguments: None.

Description: The *archEnableInt* macro enables all interrupts by clearing bits I1 (Bit 9) and I0 (Bit 8) in the Status Register (SR).

Example 2-3. archEnableInt macro usage

```
archEnableInt();
```

2.4.1.2 archEnableIntLvl123 - enable interrupt levels 1, 2 and 3

Call(s):

void archEnableIntLvl123(void);

Arguments: None.

Description: The *archEnableInt*Lvl123 macro enables interrupts at levels 1, 2 and 3 while masking the interrupts at level 0. It is accomplished by clearing bit I1 (Bit 9) and setting bit I0 (Bit 8) in the Status Register (SR).

Example 2-4. archEnableIntLvl123 macro usage

```
archEnableIntLvl123();
```

2.4.1.3 archEnableIntLvl23 - enable interrupts levels 2 and 3

Call(s):

void archEnableIntLvl23(void);

Arguments: None.

Description: The *archEnableIntLvl23* macro enables interrupts at levels 2 and 3 while masking interrupts at levels 0 and 1. It is accomplished by setting bit I1 (Bit 9) and clearing I0 (Bit 8) in the Status Register (SR).

Example 2-5. archEnableIntLvl23 macro usage

```
archEnableIntLvl23();
```

2.4.1.4 archDisableInt - disable interrupts

Call(s):

```
void archDisableInt(void);
```

Arguments: None.

Description: The *archDisableInt* macro disables all maskable interrupts by setting bits I1 and I0 (Bits 9 - 8) in the Status Register (SR).

Example 2-6. archDisableInt macro usage

```
archDisableInt();
```

2.4.1.5 archResetLimitBit - reset limit bit

Call(s):

```
void archResetLimitBit(void);
```

Arguments: None.

Description: The *archResetLimitBit* macro resets limit bit (L) - Bit 6 in the Status Register (SR).

Example 2-7. archResetLimitBit macro usage

```
archResetLimitBit();
```

2.4.1.6 archSetNoSat - set no saturation mode

Call(s):

```
void archSetNoSat(void);
```

Arguments: None.

Description: The *archSetNoSat* macro disables the saturation mode. This macro clears the saturation (SA) bit - Bit 4 in the Operating Mode Register (OMR).

Example 2-8. archSetNoSat macro usage

```
archResetLimitBit();
```

2.4.1.7 archSetSat32 - set saturation mode

Call(s):

```
void archSetSat32(void);
```

Arguments: None.

Description: The *archSetSat32* macro sets the saturation mode. This macro sets the saturation (SA) bit - Bit 4 in the Operating Mode Register (OMR).

Example 2-9. archSetSat32 macro usage

```
archSetSat32();
```

2.4.1.8 archSet2CompRound - set two's complement rounding mode

Call(s):

```
void archSet2CompRound(void);
```

Arguments: None.

Description: The *archSet2CompRound* macro sets the two's complement rounding mode. This macro sets the rounding (R) bit - Bit 5 in the Operating Mode Register (OMR).

Example 2-10. archSet2CompRound macro usage

```
archSet2CompRound();
```

2.4.1.9 archSetConvRound - set convergent rounding mode

Call(s):

```
void archSetConvRound(void);
```

Arguments: None.

Description: The *archSetConvRound* macro sets the convergent rounding mode. This macro clears the rounding (R) bit - Bit 5 in the Operating Mode Register (OMR).

Example 2-11. archSetConvRound macro usage

```
archSetConvRound();
```

2.4.1.10 archStop - stop processing state

Call(s):

```
void archStop(void);
```

Arguments: None.

Description: The *archStop* macro places the processor into the stop processing state by executing a *stop* instruction.

Example 2-12. archStop macro usage

```
archStop();
```

2.4.1.11 archTrap - initiate a software interrupt

Call(s):

```
void archTrap(void);
```

Arguments: None.

Description: The *archTrap* macro initiates a software interrupt by executing a *swi* instruction.

Example 2-13. archTrap macro usage

```
archTrap();
```

2.4.1.12 archWait - wait processing state

Call(s):

```
void archWait(void);
```

Arguments: None.

Description: The *archWait* macro places the processor into the wait processing state by executing a *wait* instruction.

Example 2-14. archWait macro usage

```
archWait();
```

2.4.1.13 archGetLimitBit - get limit bit

Call(s):

```
Word16 archGetLimitBit(void);
```

Arguments: None.

Description: The *archGetLimitBit* inline function returns the status of the limit bit (L) - Bit 6 in the Status Register (SR).

Returns: The returned value is masked value of the L-bit in SR. It is either 0 - limit bit is cleared or non-zero (0x40) - limit bit is set.

Example 2-15. archGetLimitBit function usage

```
if(archGetLimitBit())
{
        ...
}
```

2.4.1.14 archGetSetSaturationMode - get and set saturation mode

Call(s):

```
Word16 archGetSetSaturationMode(bool bSatMode);
```

Arguments:

Table 2-1. archGetSetSaturationMode arguments

bSatMode	in	State of the saturation mode to be set. false - set no saturation mode true - set saturation mode

Description: The *archGetSetSaturationMode* inline function sets the saturation mode to a user specified value. The function manipulates with the saturation (SA) bit - Bit 4 in the Operating Mode Register (OMR).

Returns: Saturation mode prior to the new state (the return value is masked SA-bit from the previous OMR value).

Example 2-16. archGetSetSaturationMode function usage

```
Word16 bSatMode;
bSatMode = archGetSetSaturationMode(true);
```

2.4.1.15 archDelay - delay

Call(s):

```
void archDelay(UWord16 Ticks);
```

Arguments:

Table 2-2. archDelay arguments

Ticks	in	Number of CPU cycles to delay (0 to 0xFFFF)

Description: The *archDelay* inline function delays the program execution by the specified number of CPU cycles.

Returns: None.

Special Issues: The delay corresponds just roughly to the number of CPU cycles.

Example 2-17. archDelay function usage

```
archDelay(1000);
```

2.5 Macros for peripheral memory access

This section describes macros for peripheral memory access. The macros are used to read, write, set, clear, change the memory mapped on-chip peripherals. Using these macros offers a greater portability than simply referencing on-chip peripherals with direct memory accesses. All macros are defined in the periph.h header file.

Required Header File(s):

```
#include “types.h“
#include “periph.h“
```

2.5.1 periphMemRead - memory read

Call(s):

```
UWord16 periphMemRead(UWord16 *pAddr);
```

Arguments:

Table 2-3. *periphMemRead* arguments

pAddr	in	The memory address from which to read a 16-bit word.

Description: The *periphMemRead* macro reads a 16-bit word from the memory location addressed by parameter pAddr.

Example 2-18. periphMemRead macro usage

```
UWord16 RegValue;

RegValue = periphMemRead(&ArchIO.TimerD.ch0.hold);
```

This code reads the content of the timer/counter D0 Hold Register (HOLD).

2.5.2 periphMemWrite - memory write

Call(s):

```
UWord16 periphMemWrite(UWord16 Data, UWord16 *pAddr);
```

Arguments:

Table 2-4. *periphMemWrite* arguments

Data	in	The 16-bit data to write to the memory.
pAddr	in	The memory address to which to write a 16-bit word.

Description: The *periphMemWrite* macro writes a 16-bit word (parameter Data) to the memory addressed by parameter pAddr.

Example 2-19. periphMemWrite macro usage

```
periphMemWrite(0x1234, (UWord16 *) 0x0D60);
periphMemWrite(0xABCD, &ArchIO.TimerD.ch0.cmp1);
```

This code writes 0x1234 to the memory location at address 0x0D60 and value 0xABCD into the timer/counter D0 Compare Register 1.

2.5.3 periphBitSet - set selected bits

Call(s):

```
void periphBitSet(UWord16 Mask, UWord16 *pAddr);
```

Arguments:

Table 2-5. *periphBitSet* arguments

Mask	in	Bit mask.
pAddr	in	The memory address.

Description: The *periphBitSet* macro sets the selected bits in a memory location addressed by parameter pAddr.

Example 2-20. periphBitSet macro usage

```
periphBitSet(0xC000, &ArchIO.TimerD.ch0.scr);
```

This code sets bits 15 and 14 in the timer/counter D0 Status and Control Register (SCR).

2.5.4 periphMemInvBitSet - invert memory content and set selected bits

Call(s):

```
void periphMemInvBitSet(UWord16 Mask, UWord16 *pAddr);
```

Arguments:

Table 2-6. *periphMemInvBitSet* arguments

Mask	in	Bit mask.

Table 2-6. *periphMemInvBitSet* arguments

pAddr	in	The memory address.

Description: The *periphMemInvBitSet* macro reads the memory content, inverts its value and sets the selected bits in a memory location addressed by parameter pAddr.

Note, that this macro can be used in some special purposes, e.g. for clearing the pending flags.

Example 2-21. periphMemInvBitSet macro usage

```
periphMemInvBitSet(0x0004, &ArchIO.Sim.rststs);
```

This code clears the Power On Reset flag in the RSTSTS register.

2.5.5 periphBitClear - clear selected bits

Call(s):

```
void periphBitClear(UWord16 Mask, UWord16 *pAddr);
```

Arguments:

Table 2-7. *periphBitClear* arguments

Mask	in	Bit mask.
pAddr	in	The memory address.

Description: The *periphBitClear* macro clears the selected bits in a memory location addressed by parameter pAddr.

Example 2-22. periphBitClear macro usage

```
periphBitClear(0xC000, &ArchIO.TimerD.ch0.scr);
```

This code clears bits 15 and 14 in the timer/counter D0 Status and Control Register (SCR).

2.5.6 periphBitGrpSR - set bit group to given value

Call(s):

```
void periphBitGrpSR(UWord16 GroupMask, UWord16 Mask,
                                    UWord16 *pAddr);
```

Arguments:

Table 2-8. *periphBitSet* arguments

GroupMask	in	Group mask
Mask	in	“ones” bit mask.
pAddr	in	The memory address.

Description: The *periphBitGrpSR* macro sets the bit group to a given value in a memory location addressed by parameter pAddr. All bits specified by GroupMask are affected. These bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

This macro uses a single instruction to execute the operation and allows only constants as GroupMask and Mask arguments. If the application requires the variable as argument, the *periphBitGrpSRVar* macro must be used instead.

Example 2-23. periphBitGrpSR macro usage

```
periphBitGrpSR(0x007f, 10, &ArchIO.Pll.plldb);
```

This code sets the lower 7 bits of PLL Divide-By register to the value 10. Other bits in the register are not affected.

2.5.7 periphBitGrpSRVar - set bit group to given value

Call(s):

```
void periphBitGrpSRVar(UWord16 GroupMask, UWord16 Mask,
                                    UWord16 *pAddr);
```

Arguments:

Table 2-9. *periphBitSet* arguments

GroupMask	in	Group mask
Mask	in	“ones” bit mask.
pAddr	in	The memory address.

Description: The *periphBitGrpSRVar* macro sets the bit group to a given value in a memory location addressed by parameter pAddr. All bits specified by GroupMask are affected. These bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

The “SR” variant uses two non-interruptible instructions *bfset* and *bfclr* to accomplish the requested operation. The *bfset* first sets the “one” bits in the destination location, and *bfclr* then clears the “zero” bits there.

Caution: This macro is the optimal way how to set the specified group of bits to given value. However, it must be kept in mind that during the short time between these two bit operations, the target memory location goes through the third state where the bit group might contain invalid value (“ones” already set but “zeroes” not yet cleared).

Example 2-24. periphBitGrpSRVar macro usage

```
periphBitGrpSRVar(0x007f, 10, &ArchIO.Pll.plldb);
```

This code sets the lower 7 bits of PLL Divide-By register to the value 10. Other bits in the register are not affected.

2.5.8 periphBitGrpRS - set bit group to given value

Call(s):

```
void periphBitGrpRS(UWord16 GroupMask, UWord16 Mask,
                                    UWord16 *pAddr);
```

Arguments:

Table 2-10. *periphBitSet* arguments

GroupMask	in	Group mask
Mask	in	“ones” bit mask.
pAddr	in	The memory address.

Description: The *periphBitGrpRS* macro sets the bit group to a given value in a memory location addressed by parameter pAddr. All bits specified by GroupMask are affected. These bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

This macro uses a single instruction to execute the operation and allows only constants as GroupMask and Mask arguments. If the application requires the variable as argument, the *periphBitGrpRSVar* macro must be used instead.

Example 2-25. periphBitGrpRS macro usage

```
periphBitGrpRS(0x0F00, 0x0100, &ArchIO.Adc1.adctl1);
```

This code enables the High Limit exceeded interrupt if the current result value is greater than the high limit. Other bits in the register are not affected.

2.5.9 periphBitGrpRSVar - set bit group to given value

Call(s):

```
void periphBitGrpRSVar(UWord16 GroupMask, UWord16 Mask,
                                    UWord16 *pAddr);
```

Arguments:

Table 2-11. *periphBitSet* arguments

GroupMask	in	Group mask
Mask	in	“ones” bit mask.
pAddr	in	The memory address.

Description: The *periphBitGrpRSVar* macro sets the bit group to a given value in a memory location addressed by parameter pAddr. All bits specified by GroupMask are affected. These bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

The “RS” variant uses two non-interruptible instructions *bfclr* and *bfset* to accomplish the requested operation. The *bfclr* first clears the “zero” bits in the destination location, and *bfclr* then sets the “one” bits there.

Caution: This macro is the optimal way how to set the specified group of bits to given value. However, it must be kept in mind that during the short time between these two bit operations, the target memory location goes through the third state where the bit group might contain invalid value (“ones” already set but “zeroes” not yet cleared).

Example 2-26. periphBitGrpRSVar macro usage

```
periphBitGrpRSVar(0x0F00, 0x0100, &ArchIO.Adc1.adctl1);
```

This code enables the High Limit exceeded interrupt if the current result value is greater than the high limit. Other bits in the register are not affected.

2.5.10 periphBitGrpRS32 - set bit group to given value

Call(s):

```
void periphBitGrpRS32(UWord32 GroupMask, UWord132 Mask,
                                    UWord16 *pAddr);
```

Arguments:

Table 2-12. *periphBitSet* arguments

GroupMask	in	Group mask
Mask	in	“ones” bit mask.
pAddr	in	The memory address.

Description: The *periphBitGrpRS32* macro sets the bit group to a given value in a memory location addressed by parameter pAddr. All bits specified by GroupMask are affected. These bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

The “RS” variant uses two non-interruptible instructions *bfclr* and *bfset* to accomplish the requested operation. The *bfclr* first clears the “zero” bits in the destination location, and *bfclr* then sets the “one” bits there.

Caution: This macro is the optimal way how to set the specified group of bits to given value. However, it must be kept in mind that during the short time between these two bit operations, the target memory location goes through the third state where the bit group might contain invalid value (“ones” already set but “zeroes” not yet cleared).

Example 2-27. periphBitGrpSR macro usage

```
periphBitGrpRS32(0x00000007, 3, &ArchIO.FCan.ctrl1);
```

This code set the length of the Propagation Segment in the bit time. The valid programmable values are 0–7. This field can be written only in Freeze mode because it is blocked by hardware in other modes.Other bits in the register are not affected.

2.5.11 periphBitGrpZS - set bit group to given value

Call(s):

```
void periphBitGrpZS(UWord16 GroupMask, UWord16 Mask,
                                    UWord16 *pAddr);
```

Arguments:

Table 2-13. *periphBitSet* arguments

GroupMask	in	Group mask
Mask	in	“ones” bit mask.
pAddr	in	The memory address.

Description: The *periphBitGrpZS* macro sets the bit group to a given value in a memory location addressed by parameter pAddr. All bits specified by GroupMask are affected. The bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

This macro uses a single instruction to execute the operation and allows only constants as GroupMask and Mask arguments. If the application requires the variable as argument, the *periphBitGrpZSVar* macro must be used instead.

Example 2-28. periphBitGrpZS macro usage

```
periphBitGrpZS(0x007f, 10, &ArchIO.Pll.plldb);
```

This code sets the lower 7 bits of PLL Divide-By register to the value 10. Other bits in the register are not affected.

2.5.12 periphBitGrpZSVar - set bit group to given value

Call(s):

```
void periphBitGrpZSVar(UWord16 GroupMask, UWord16 Mask,
                                    UWord16 *pAddr);
```

Arguments:

Table 2-14. *periphBitSet* arguments

GroupMask	in	Group mask
Mask	in	“ones” bit mask.
pAddr	in	The memory address.

Description: The *periphBitGrpZSVar* macro sets the bit group to a given value in a memory location addressed by parameter pAddr. All bits specified by GroupMask are affected. The bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

The “ZS” variant uses two non-interruptible instructions *bfclr* and *bfset* to accomplish the requested operation. The *bfclr* first clears all bits in GroupMask and *bfset* then sets the “one” bits there.

Caution: This macro is the optimal way how to set the specified group of bits to given value. However, it must be kept in mind that during the short time between these two bit operations, the target memory location goes through the third state where the bit group contains zeroes.

Example 2-29. periphBitGrpZSVar macro usage

```
periphBitGrpZSVar(0x007f, 10, &ArchIO.Pll.plldb);
```

This code sets the lower 7 bits of PLL Divide-By register to the value 10. Other bits in the register are not affected.

2.5.13 periphBitGrpSet - set bit group to given value

Call(s):

```
void periphBitGrpSet(UWord16 GroupMask, UWord16 Mask,
                                    UWord16 *pAddr);
```

Arguments:

Table 2-15. *periphBitSet* arguments

GroupMask	in	Group mask
Mask	in	“ones” bit mask.
pAddr	in	The memory address.

Description: The *periphBitGrpSet* macro sets the bit group to a given value in a memory location addressed by parameter pAddr. All bits specified by GroupMask are affected. The bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

This macro uses a single instruction to execute the operation and allows only constants as GroupMask and Mask arguments. If the application requires the variable as argument, the *periphBitGrpSetVar* macro must be used instead.

Example 2-30. periphBitGrpSet macro usage

```
periphBitGrpSet(0x007f, 10, &ArchIO.Pll.plldb);
```

This code sets the lower 7 bits of PLL Divide-By register to the value 10. Other bits in the register are not affected (but see “Caution” above).

2.5.14 periphBitGrpSetVar - set bit group to given value

Call(s):

```
void periphBitGrpSetVar(UWord16 GroupMask, UWord16 Mask,
                                    UWord16 *pAddr);
```

Arguments:

Table 2-16. *periphBitSet* arguments

GroupMask	in	Group mask
Mask	in	“ones” bit mask.
pAddr	in	The memory address.

Description: The *periphBitGrpSetVar* macro sets the bit group to a given value in a memory location addressed by parameter pAddr. All bits specified by GroupMask are affected. The bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

This variant uses the accumulator and read-modify-write instructions to accomplish the requested operation. The memory location is first read to accumulator, the *bfclr* and *bfset* instructions are performed on accumulator and the result value is then written back to memory location.

Caution: It might seem this macro is the “proper” way how to set the group of bits to certain value as there are no intermediate invalid values written in the target memory location. However, it is quite dangerous to use this macro when interrupts may occur between the read and write operations. If the interrupt service routine would write the other portion of the target memory location, the written value could be overwritten back with its previous state by the write accumulator operation of *periphBitGrpSetVar.*

Example 2-31. periphBitGrpSetVar macro usage

```
periphBitGrpSetVar(0x007f, 10, &ArchIO.Pll.plldb);
```

This code sets the lower 7 bits of PLL Divide-By register to the value 10. Other bits in the register are not affected (but see “Caution” above).

2.5.15 periphBitGrpSet32 - set bit group to given value

Call(s):

```
void periphBitGrpSet(UWord32 GroupMask, UWord32 Mask,
                                UWord16 *pAddr);
```

Arguments:

Table 2-17. *periphBitSet* arguments

GroupMask	in	Group mask
Mask	in	“ones” bit mask.
pAddr	in	The memory address.

Description: The *periphBitGrpSet32* macro sets the bit group to a given value in a memory location addressed by parameter pAddr. All bits specified by GroupMask are affected. The bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

This variant uses the accumulator and read-modify-write instructions to accomplish the requested operation. The memory location is first read to accumulator, the *bfclr* and *bfset* instructions are performed on accumulator and the result value is then written back to memory location.

Caution: It might seem this macro is the “proper” way how to set the group of bits to certain value as there are no intermediate invalid values written in the target memory location. However, it is quite dangerous to use this macro when interrupts may occur between the read and write operations. If the interrupt service routine would write the other portion of the target memory location, the written value could be overwritten back with its previous state by the write accumulator operation of periphBitGrpSet32.

Example 2-32. periphBitGrpSet macro usage

```
periphBitGrpSet32(0x0C0000000, 0x040000000, &ArchIO.crc.ctrl);
```

This code sets the lower TOT bit 30 of CRC Control register. Other bits in the register are not affected (but see “Caution” above).

2.5.16 periphSafeAckByOne - clear (acknowledge) bit flags which are active-high and are cleared by write-one

Call(s):

```
void periphSafeAckByOne(UWord16 GroupMask, UWord16 Mask,
                                    UWord16 *pAddr);
```

Arguments:

Table 2-18. *periphSafeAckByOne* arguments

GroupMask	in	Group mask
Mask	in	“ones” bit mask.
pAddr	in	The memory address.

Description: The *periphSafeAckByOne* macro clears (acknowledges) bit flags which are active-high and are cleared by write-one in a peripheral memory location addressed by parameter pAddr. The GroupMask specifies all flags which might be affected by clearing procedure. The Mask value specifies flag/flags to be cleared.

This macro uses a single instruction to execute the operation and allows only constants as GroupMask and Mask arguments. If the application requires the variable as argument, the *periphSafeAckByOneVar* macro must be used instead.

Example 2-33. periphSafeAckByOne macro usage

```
periphSafeAckByOne(0x8000 | 0x0100 | 0x0010, 0x0100,
                                    &ArchIO.Decoder0.deccr);
```

This code clears the Index Pulse Interrupt Request flag in the Decoder Control Register.

2.5.17 periphSafeAckByOneVar - clear (acknowledge) bit flags which are active-high and are cleared by write-one

Call(s):

```
void periphSafeAckByOneVar(UWord16 GroupMask, UWord16 Mask,
                                   UWord16 *pAddr);
```

Arguments:

Table 2-19. *periphSafeAckByOneVar* arguments

GroupMask	in	Group mask
Mask	in	“ones” bit mask.
pAddr	in	The memory address.

Description: The *periphSafeAckByOneVar* macro clears (acknowledges) bit flags which are active-high and are cleared by write-one in a peripheral memory location addressed by parameter pAddr. The GroupMask specifies all flags which might be affected by clearing procedure. The Mask value specifies flag/flags to be cleared.

Caution: TBD

Example 2-34. periphSafeAckByOneVar macro usage

```
periphSafeAckByOne(0x8000 | 0x0100 | 0x0010, 0x0100,
                                   &ArchIO.Decoder0.deccr);
```

This code clears the Index Pulse Interrupt Request flag in the Decoder Control Register.

2.5.18 periphSafeBitClear - clear bits and keep value of bit flags which are cleared by write-one

Call(s):

```
void periphSafeBitClear(UWord16 FlagGroupMask, UWord16 Mask,
                                   UWord16 *pAddr);
```

Arguments:

Table 2-20. *periphSafeBitClear* arguments

FlagGroupMask	in	Group mask of bit flags which are cleared by write-one
Mask	in	bit mask.
pAddr	in	The memory address.

Description: The *periphSafeBitClear* macro clears the selected bits and keeps value of the bit flags which are cleared by write-one in a peripheral memory location addressed by parameter pAddr. The FlagGroupMask specifies all flags which are cleared by write-one. The Mask value specifies bit/bits to be cleared.

Caution: TBD

Example 2-35. periphSafeBitClear macro usage

```
periphSafeBitClear(0x0002 | 0x0010, 0x0004, &ArchIO.HscmpA.scr);
```

This code disables the falling edge HSCMP A module. The rising edge and falling edge interrupt flags are not cleared

2.5.19 periphSafeBitSet - Set bits and keep value of bit flags which are cleared by write-one

Call(s):

```
void periphSafeBitSet(UWord16 FlagGroupMask, UWord16 Mask,
                                    UWord16 *pAddr);
```

Arguments:

Table 2-21. *periphSafeBitSet* arguments

FlagGroupMask	in	Group mask of bit flags which are cleared by write-one
Mask	in	bit mask.
pAddr	in	The memory address.

Description: The *periphSafeBitSet* macro sets the selected bits and keeps value of the bit flags which are cleared by write-one in a peripheral memory location addressed by parameter pAddr. The FlagGroupMask specifies all flags which are cleared by write-one. The Mask value specifies bit/bits to be set.

This macro uses a single instruction to execute the operation and allows only constants as GroupMask and Mask arguments. If the application requires the variable as argument, the *periphSafeBitSetVar* macro must be used instead.

Example 2-36. periphSafeBitSet macro usage

```
periphSafeBitSet(0x0002 | 0x0004, 0x0010, &ArchIO.HscmpA.scr);
```

This code enables the rising edge HSCMP A module. The rising edge and falling edge interrupt flags are not cleared

2.5.20 periphSafeBitSetVar - Set bits and keep value of bit flags which are cleared by write-one

Call(s):

```
void periphSafeBitSetVar(UWord16 FlagGroupMask, UWord16 Mask,
                                 UWord16 *pAddr);
```

Arguments:

Table 2-22. *periphSafeBitSetVar* arguments

FlagGroupMask	in	Group mask of bit flags which are cleared by write-one
Mask	in	bit mask.
pAddr	in	The memory address.

Description: The *periphSafeBitSetVar* macro sets the selected bits and keeps value of the bit flags which are cleared by write-one in a peripheral memory location addressed by parameter pAddr. The FlagGroupMask specifies all flags which are cleared by write-one. The Mask value specifies bit/bits to be set.

Caution: It might seem this macro is the “proper” way how to set the group of bits to certain value as there are no intermediate invalid values written in the target memory location. However, it is quite dangerous to use this macro when interrupts may occur between the read and write operations. If the interrupt service routine would write the other portion of the target memory location, the written value could be overwritten back with its previous state by the write accumulator operation of *periphBitGrpSet*.

Example 2-37. periphSafeBitSetVar macro usage

```
periphSafeBitSetVar(0x0002 | 0x0004, 0x0010, &ArchIO.HscmpA.scr);
```

This code enables the rising edge HSCMP A module. The rising edge and falling edge interrupt flags are not cleared

2.5.21 periphSafeBitSet32 - Set bits and keep value of bit flags which are cleared by write-one

Call(s):

```
void periphSafeBitSet(UWord32 FlagGroupMask, UWord32 Mask,
                                 UWord16 *pAddr);
```

Arguments:

Table 2-23. *periphSafeBitSet* arguments

FlagGroupMask	in	Group mask of bit flags which are cleared by write-one
Mask	in	bit mask.

Table 2-23. *periphSafeBitSet* arguments

pAddr	in	The memory address.

Description: The *periphSafeBitSet32* macro sets the selected bits and keeps value of the bit flags which are cleared by write-one in a peripheral memory location addressed by parameter pAddr. The FlagGroupMask specifies all flags which are cleared by write-one. The Mask value specifies bit/bits to be set.

Caution: It might seem this macro is the “proper” way how to set the group of bits to certain value as there are no intermediate invalid values written in the target memory location. However, it is quite dangerous to use this macro when interrupts may occur between the read and write operations. If the interrupt service routine would write the other portion of the target memory location, the written value could be overwritten back with its previous state by the write accumulator operation of periphBitGrpSet32.

Example 2-38. periphSafeBitSet macro usage

```
periphSafeBitSet32(0x080808000, 0x000000080,&ArchIO.dma.reqc);
```

Clears the state machine for DMA channel 3.

2.5.22 periphSafeBitGrpSet - set bit group to given value and keep value of bit flags which are cleared by write-one

Call(s):

```
void periphSafeBitGrpSet(UWord16 FlagGroupMask,
                                          UWord16 GroupMask, UWord16 Mask,
                                          UWord16 *pAddr);
```

Arguments:

Table 2-24. *periphSafeBitGrpSet* arguments

FlagGroupMask	in	Group mask of bit flags which are cleared by write-one
GroupMask	in	Group mask
Mask	in	bit mask.
pAddr	in	The memory address.

Description: The *periphSafeBitGrpSet* macro sets bit group to given value and keeps value of the bit flags which are cleared by write-one in a peripheral memory location addressed by parameter pAddr. The FlagGroupMask specifies all flags which are cleared by write-one. All bits specified by GroupMask are affected. The bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

This macro uses a single instruction to execute the operation and allows only constants as GroupMask and Mask arguments. If the application requires the variable as argument, the *periphSafeBitGrpSetVar* macro must be used instead.

Example 2-39. periphSafeBitGrpSet macro usage

```
periphSafeBitGrpSet(0x0002 | 0x0004, 0x00C0, 0x0040, &ArchIO.HscmpA.scr);
```

This code sets the HSCMP A module input hysteresis to 1. The rising edge and falling edge interrupt flags are not cleared

2.5.23 periphSafeBitGrpSetVar - set bit group to given value and keep value of bit flags which are cleared by write-one

Call(s):

```
void periphSafeBitGrpSetVar(UWord16 FlagGroupMask,
                                          UWord16 GroupMask, UWord16 Mask,
                                          UWord16 *pAddr);
```

Arguments:

Table 2-25. *periphSafeBitGrpSetVar* arguments

FlagGroupMask	in	Group mask of bit flags which are cleared by write-one
GroupMask	in	Group mask
Mask	in	bit mask.
pAddr	in	The memory address.

Description: The *periphSafeBitGrpSetVar* macro sets bit group to given value and keeps value of the bit flags which are cleared by write-one in a peripheral memory location addressed by parameter pAddr. The FlagGroupMask specifies all flags which are cleared by write-one. All bits specified by GroupMask are affected. The bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

Caution: It might seem this macro is the “proper” way how to set the group of bits to certain value as there are no intermediate invalid values written in the target memory location. However, it is quite dangerous to use this macro when interrupts may occur between the read and write operations. If the interrupt service routine would write the other portion of the target memory location, the written value could be overwritten back with its previous state by the write accumulator operation of *periphBitGrpSetVar.*

Example 2-40. periphSafeBitGrpSetVar macro usage

```
periphSafeBitGrpSet(0x0002 | 0x0004, 0x00C0, 0x0040, &ArchIO.HscmpA.scr);
```

This code sets the HSCMP A module input hysteresis to 1. The rising edge and falling edge interrupt flags are not cleared

2.5.24 periphSafeBitGrpSet32 - set bit group to given value and keep value of bit flags which are cleared by write-one

Call(s):

```
void periphSafeBitGrpSet(UWord32 FlagGroupMask,
                         UWord32 GroupMask, UWord32 Mask,
                         UWord16 *pAddr);
```

Arguments:

Table 2-26. *periphSafeBitGrpSet* arguments

FlagGroupMask	in	Group mask of bit flags which are cleared by write-one
GroupMask	in	Group mask
Mask	in	bit mask.
pAddr	in	The memory address.

Description: The *periphSafeBitGrpSet32* macro sets bit group to given value and keeps value of the bit flags which are cleared by write-one in a peripheral memory location addressed by parameter pAddr. The FlagGroupMask specifies all flags which are cleared by write-one. All bits specified by GroupMask are affected. The bits are either set if the corresponding bits in Mask value are also set or they are cleared if the corresponding bits in Mask value are cleared.

Caution: It might seem this macro is the “proper” way how to set the group of bits to certain value as there are no intermediate invalid values written in the target memory location. However, it is quite dangerous to use this macro when interrupts may occur between the read and write operations. If the interrupt service routine would write the other portion of the target memory location, the written value could be overwritten back with its previous state by the write accumulator operation of periphBitGrpSet32.

Example 2-41. periphSafeBitGrpSet macro usage

```
periphSafeBitGrpSet32(0x080808080, 0x00F000000, 1 ,&ArchIO.dma.reqc);
```

This code selects the request 1 as the DMA source.

2.5.25 periphBitChange - change selected bits

Call(s):

```
void periphBitChange(UWord16 Mask, UWord16 *pAddr);
```

Arguments:

Table 2-27. *periphBitChange* arguments

Mask	in	Bit mask.
pAddr	in	The memory address.

Description: The *periphBitChange* macro complements the selected bits in a memory location addressed by parameter pAddr.

Example 2-42. periphBitChange macro usage

```
periphBitChange(0xC000, &ArchIO.PortB.dr);
```

This code complements bits 15 and 14 in the Port B Data Register (DR).

2.5.26 periphBitTest - test selected bits

Call(s):

```
UWord16 periphBitTest(UWord16 Mask, UWord16 *pAddr);
```

Arguments:

Table 2-28. *periphBitTest* arguments

Mask	in	Bit mask.
pAddr	in	The memory address.

Description: The *periphBitTest* macro tests the selected bits if they are set in a memory location addressed by parameter pAddr.

Example 2-43. periphBitTest macro usage

```
if (periphBitTest(0x8000, &ArchIO.TimerD.ch0.scr))
{
        periphBitClear(0x8000, &ArchIO.TimerD.ch0.scr);
};
```

This code checks if Timer Compare Flag (Bit 15) in the timer/counter D0 Status and Control Register (SCR) is set.

2.5.27 periphMemDummyRead - memory dummy read

Call(s):

```
void periphMemDummyRead(UWord16 *pAddr);
```

Arguments:

Table 2-29. *periphMemDummyRead* arguments

pAddr	in	The memory address from which to read a 16-bit word.

Description: The *periphMemDummyRead* macro reads a 16-bit word from the memory location addressed by parameter pAddr. The result is thrown away.

Example 2-44. periphMemDummyRead macro usage

```
periphMemDummyRead(&ArchIO.Sci.scisr);
```

This code reads the SCI status register to clear SCI flags.

2.5.28 periphMemForcedRead- memory force read (Never optimized out)

Call(s):

```
UWord16 periphMemForcedRead(UWord16 *pAddr);
```

Arguments:

Table 2-30. *periphMemForcedRead* arguments

pAddr	in	The memory address from which to read a 16-bit word.

Description: The *periphMemForcedRead* macro reads a 16-bit word from the memory location addressed by parameter pAddr. This macro is never optimized out.

Example 2-45. periphMemForcedRead macro usage

```
periphMemForcedRead(&ArchIO.Sci.scisr);
```

This code reads the SCI status register to clear SCI flags.

2.5.29 Miscellaneous Routines

This section describes some additional routines provided by the 56800EX_Quick_Start tool.

2.5.29.1 impyuu - integer multiply unsigned 16b x unsigned 16b

Call(s):

```
UWord32 impyuu(UWord16 unsigA, UWord16 unsigB);
```

Arguments:

Table 2-31. impyuu arguments

unsigA	in	first argument
unsigB	in	second argument

Description: The *impyuu* inline function multiplies a 16-bit unsigned integer with a 16-bit unsigned integer and returns the 32-bit unsigned integer result.

Returns: result of multiplication $\text{unsigA} \cdot \text{unsigB}$

Example 2-46. impyuu function usage

```
UWord16 var1 = 65535U;
UWord16 var2 = 65535U;
UWord32 result;

result = impyuu(var1, var2); /* returns 4294836225 */
```

This code multiplies variables *var1* and *var2* and returns the result in *result* variable.

2.5.29.2 impysu - integer multiply signed 16b x unsigned 16b

Call(s):

```
Word32 impysu(Word16 sig, UWord16 unsig);
```

Arguments:

Table 2-32. impysu arguments

sig	in	first argument (signed)
unsig	in	second argument (unsigned)

Description: The *impysu* function multiplies 16-bit signed integer and 16-bit unsigned integer as an and returns the 32-bit signed integer result.

Returns: result of multiplication $\text{sig} \cdot \text{unsig}$

Example 2-47. impysu function usage

```
Word16 var1 = -32768;
```

```
UWord16 var2 = 65535U;
Word32 result;

result = impysu(var1, var2); /* returns -2147450880 */
```

This code multiplies variables *var1* and *var2* and returns the result in *result* variable.

2.5.29.3 shl2 - optimized version of *shl* intrinsic function

Call(s):

```
Word16 shl2(Word16 num, UWord16 shifts);
```

Arguments:

Table 2-33. shl2 arguments

num	in	parameter to be shifted
shifts	in	number of shifts

Description: The *shl2* function performs a multi-bit arithmetic shift of the first parameter to the left by the amount specified in the second parameter. The result is returned as a 16-bit integer. This function is the optimized version of the *shl* intrinsic function (see CodeWarrior Help for more information on *shl*).

Returns: *num* parameter shifted *shifts* times to the left

Example 2-48. shl2 function usage

```
Word16 var1 = 1;
UWord16 var2 = 15;
Word16 result;

result = shl2(var1, var2); /* returns 0x8000 */
```

This code shifts *var1* variable *var2* times to the left and returns the result in *result* variable.

2.5.29.4 shr2 - optimized version of *shr* intrinsic function

Call(s):

```
Word16 shr2(Word16 num, UWord16 shifts);
```

Arguments:

Table 2-34. shr2 arguments

num	in	parameter to be shifted

Table 2-34. shr2 arguments

shifts	in	number of shifts

Description: The *shr2* function performs a multi-bit arithmetic shift of the first parameter to the right by the amount specified in the second parameter. The result is returned as a 16-bit integer. This function is the optimized version of the *shr* intrinsic function (see CodeWarrior Help for more information on *shr*).

Returns: *num* parameter shifted *shifts* times to the right

Example 2-49. shr2 function usage

```
Word16 var1 = 16;
Word16 result;

result = shr2(var1, 3); /* returns 0x0002 */
```

This code shifts *var1* variable three times to the right and returns the result in the *result* variable.

2.5.30 Intrinsic Functions

The 56800EX_Quick_Start tool can exploit the system intrinsic functions defined in *intrinsics_56800E.h* header file distributed with the CodeWarrior Development Studio 56800/EX Hybrid Controllers.

To preserve compatibility with the DSP56800_Quick_Start tool, the *intrinsics_56800E.h* is included in *core.h* header file, if the macro __MWERKS__ is defined.

2.6 Interrupts

This section describes interrupt processing and interrupt configuration using the 56800EX_Quick_Start tool. For detailed information on interrupts and interrupt processing for the 56F800EX, please see the **DSP56800E and DSP56800EX Reference Manual** and the **target processor's Reference Manual**.

2.6.1 Processing Interrupts

An interrupt is an event that is generated by a condition inside the microcontroller or from external sources. When such event occurs, the interrupt processing transfers control from the currently executing program to an interrupt service routine (ISR), with the ability to later return to the current program upon completion of the ISR. Among the main uses of interrupts we can have data transfers between microcontroller memory and a peripheral device, or begin of execution of an algorithm upon reception of a new sample. An interrupt can also be used, for example, to exit the microcontroller's low-power wait processing state.

2.6.1.1 Interrupt Vector Table

The interrupt system on 56F800E can be defined as vectored. Each interrupt source has its own program memory location at a fixed address, to which program control is passed when an interrupt occurs. This

program memory location must contain a JSR instruction with the address of the interrupt service routine (ISR). When this interrupt occurs, the JSR instruction is executed and the program control is passed to the ISR. The program memory containing the JSR instructions with the addresses of the ISR is called interrupt vector table.

The interrupt vector table might be located at base address 0x0000. During the code execution, the interrupt vector table base address can be changed by modifying the VBA register of interrupt controller unit (INTC).

In the 56800EX_Quick_Start tool, the full interrupt vector table is always located at address 0x0000. The VBA register is set to zero during the startup code. See Section 2.1.1 on page -2 for closer description of the booting process.

In the 56800EX_Quick_Start tool, the interrupt vector table is implemented in C code which enables to effectively use the C preprocessor. The special macros defined in the global application configuration file (*appconfig.h*) can be used to setup the interrupt vector and to assign the interrupt priorities.

The interrupt controller and its configuration are described in more details later in Section .

2.6.1.2 Interrupt Processing Flow

Figure 2-2 shows an interrupt processing flow. The 56800EX_Quick_Start tool does not provide any intermediate step when calling the ISR. When an interrupt occurs, the currently executed program is interrupted and the JSR instruction from the interrupt vector table is fetched. Executing the JSR instruction results in the program changing its flow directly to an ISR. Also the status register and the program counter are pushed onto the stack. When the user ISR finishes, it executes a Return from Interrupt (RTI) instruction, which pops the program counter and the status register from the hardware stack. It puts the User Code back into the same state as it was in before execution, assuming that the User ISR saved and restored all the registers it had used.

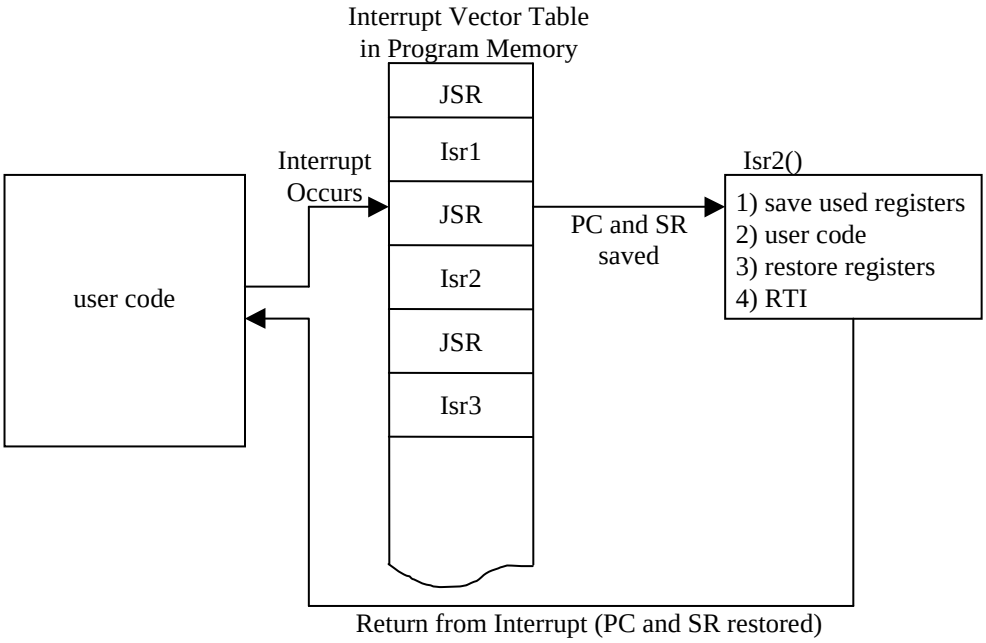


Figure 2-2. Interrupt Processing Flow

2.6.1.3 ISRs

An ISR is a program code that is executed when an interrupt is detected. An ISR is responsible for servicing the cause of the interrupt, such as reading a sample from a port when it is full or transmitting a sample to a port when it is empty. When an interrupt occurs, all other interrupts of the same or of a lower priority are disabled from executing, until the current ISR finishes executing. For this reason, an ISR should be as fast as possible to prevent any overflow or under run condition.

Inside the ISR it is necessary to save, and upon servicing the interrupt, to restore all used registers, including registers from the register bank used by the compiler. The 56800EX_Quick_Start tool does not provide any automatic saving/restoring of used registers.

The last instruction of an ISR must be “Return from Interrupt” (RTI) instruction. This instruction restores the SR and the PC from the stack.

Both saving/restoring registers and using RTI instead of RTS are provided by the compiler directive *#pragma interrupt*. *#pragma interrupt* is used when declaring a C function and it instructs the compiler to save all registers used within a C function and to restore those register values upon exiting. Also it places an RTI instruction instead of an RTS at the end of the function. See Section 2.6.3.

2.6.1.4 Interrupt Priority Levels

On 56F800EX hybrid microcontroller family, each interrupt can be assigned the interrupt priority level (IPL). It is the number from 0 (lowest priority) to 3 (highest priority). When servicing the interrupt, until the RTI instruction is executed, the other interrupts of the same and lower priority levels are masked

(temporarily disabled). If there is an interrupt request of the masked priority level, its processing is postponed until the level is unmasked again.

This model assures that the interrupts of the same level can not “nest” one to each other. On the other hand, the higher priority interrupts do nest to the lower priority interrupts.

2.6.1.5 Fast Interrupts

Up to 2 interrupt sources can be declared as Fast Interrupts. The Fast Interrupts jump directly to a service routine based on values in the Fast Interrupt Vector Address registers without having to go to a jump table first.

IRQs used as fast interrupts MUST be set to priority level 2. Unexpected results can occur if a fast interrupt vector is set to any other priority.

Caution: A special Fast Interrupt Return instruction (*frtid*) must be used in order to return from the Fast Interrupt service routine. There are also several limitations in the way how the Fast Interrupt service routine can be coded. See the **56800E and 56800EX Reference Manual** for more details.

2.6.1.6 Clearing Interrupt Flags

Each on-chip peripheral interrupt source has its own interrupt flag, which must be cleared after the interrupt is serviced. For each peripheral module, the method of clearing the interrupt flag is different. As the 56800EX_Quick_Start tool does not add any infrastructure code to the interrupt service routines, it also does not clear the interrupt flag inside the ISR. See Example 2-50.

Example 2-50. Clearing Interrupt Flags inside ISR

```
/*************************************************************************
        PWM A Reload Interrupt Service Routine
*************************************************************************/
#pragma interrupt
void pwmAReloadISR(void)
{
        /* ISR code */
        ...
        /* clear Reload interrupt flag */
        ioctl(PWM_A, PWM_CLEAR_RELOAD_FLAG, NULL);
}
```

This example shows the PWMA Reload Interrupt Service Routine. Note that the `PWM_CLEAR_RELOAD_FLAG` ioctl() command is used to clear the Reload Interrupt Flag (Bit 5) in the PWM Control Register and that this is the user’s responsibility.

2.6.2 Configuring Interrupts

This section describes the configuration of interrupts using the 56800EX_Quick_Start tool. Interrupt configuration consists of installing the interrupt service routine (ISR) at the specified interrupt vector, enabling the interrupt and setting the interrupt priority level.

Installing ISRs

The 56800EX_Quick_Start tool supports static (compile-time) installation of the ISRs, dynamic installation (run-time) is not supported. In general, static installation of ISRs requires less program memory and has a lower (or even no) time overhead.

The static installation of ISRs consists of writing the address of the ISR to the interrupt vector table for given interrupt source at compilation time. The interrupt vector table is located in the *vectors.c* file. By default all interrupt vectors are initialized with the address of the *unhandled_interrupt()* function in the *vectors.c* file, which contains the *debughlt* instruction and provides an alarm to the user, that this interrupt was not installed but has occurred, which is very useful when debugging. One exception to this is the Hardware Reset vector, which contains the address of the startup code - *Start()* routine in the *startup.c* file.

To install a user's ISR at the xxth interrupt vector add the following *#define* in *appconfig.h*:

```
#define  INT_VECTOR_ADDR_xx  userISRname
```

The conditional compilation then forces the compiler to use the *userISRname()* ISR instead of the default *unhandled_interrupt()* at the position of the xxth interrupt vector in the interrupt vector table. The *userISRname* is the placeholder for the name of interrupt service routine with prototype of

```
void userISRroutine (void)
```

In your source code, you then put the following code:

```
#pragma interrupt
void userISRname(void)
{
        /* ISR code */
}
```

The range of interrupt vectors which can be installed (xx) is 1 to 80. Vector 0 is the Hardware Reset vector and always refers to the *Start()* code.

2.6.2.1 Assigning Interrupt Priority Levels

As described in Section 2.6.1.4 on page -34, each enabled interrupt can be assigned to one interrupt priority level in range from 0 to 3.

There are some exceptions from this rule for the particular interrupt sources which has assigned a fixed priority levels. Also, as there are only two bits (four combinations) to encode five different states of the interrupt source (disabled, level 0,..., level 3) there is always one priority level, which cannot be set for any interrupt.

The 56800EX_Quick_Start tool hides these difficulties and implementation details described above and simplifies the configuration of the interrupt priority levels to the maximal extent (while keeping the generated code optimal).

To enable the interrupt servicing and to assign a certain priority level, the user defines the macro:

```
INT_PRIORITY_LEVEL_xx INTC_LEVELn
```

To explicitly disable the interrupt, the user can define the macro as

```
INT_PRIORITY_LEVEL_xx INTC_DISABLED
```

where xx is the interrupt number (from 1 to 110) and n is the interrupt level (from 0 to 3). The interrupt sources configurations are then applied to a processor core by issuing the `INTC_INIT` ioctl command, for example in the *main* function.

The C preprocessor and compiler check the validity of the selected priority level early during the compilation and issues compilation errors if invalid combination of interrupt source number and interrupt priority level is requested (or if priority level is requested to be set for the source with fixed priority level).

2.6.2.2 Installing Fast Interrupts

As described in Section 2.6.1.5 on page -35, two interrupt sources can be selected as “Fast Interrupts”. For the fast interrupts, the interrupt controller does not fetch the *jsr* instruction from the vector table and directly loads the program counter (PC) with address specified in dedicated Fast Interrupt Vector Address (`FIVA`) registers.

In the 56800EX_Quick_Start tool, the fast interrupts are automatically configured by the `INTC_INIT` code if the user defines the macros:

```
INTC_FIM0_INIT xx
```

or

```
INTC_FIM1_INIT xx
```

where xx specifies what interrupt source is to be selected as fast interrupt (0 or 1).

By default, the address of interrupt service routine defined by `INT_VECTOR_ADDR_xx` is then automatically loaded into the `FIVA` registers during the `INTC_INIT` command. The preprocessor also verifies the interrupt identified for a fast interrupt is configured to priority level 2 (which is required for the proper operation).

Caution: A special Fast Interrupt Return instruction (*frtid*) must be used in order to return from the Fast Interrupt service routine.

If there is another vector address to be used for the fast interrupt processing, instead of the default `INT_VECTOR_ADDR_xx`, the following macros can be defined in *appconfig.h*

```
INTC_FIVA0_INIT fastint0ISR
```

or

```
INTC_FIVA1_INIT fastint1ISR
```

where `fastint0ISR` and `fastint1ISR` are the placeholders for the fast interrupt service routine names.

2.6.2.3 Enabling Interrupts

In addition to the interrupt controller peripheral described above, the 56800EX core has its own method how to enable and disable the interrupts of certain priority levels. So, regardless the interrupt setting defined by macros in *appconfig.h* and initialization done by the INTC_INIT command, there is another step to do to enable interrupt servicing in the application.

At the core level, the interrupts can be in four states:

- All interrupts disabled (default state) - use archDisableInt() macro
- All interrupts enabled - use archEnableInt() macro
- Priority levels 1, 2 and 3 enabled, level 0 disabled - use archEnableIntLvl123() macro
- Priority levels 2 and 3 enabled, levels 0 and 1 disabled - use archEnableIntLvl23() macro

2.6.3 Code Example

The following example shows the installation of the ISR into the interrupt vector table and shows how to enable interrupts using the 56800EX_Quick_Start tool.

The following example shows the installation of the external interrupt $\overline{\text{IRQA}}$, the timer/counter D2 interrupt and the PWM A reload interrupt. The example shows a part of the code, which must be included in *appconfig.h*, all three ISRs and the initialization code. ISRs are declared as *#pragma interrupt* to instruct the compiler to save/restore all used registers and to terminate the ISRs with an RTI instruction. Inside the *appconfig.h* file, INT_VECTOR_ADDR_xx and ITCN_INT_PRIORITY_xx define statements are used to install the ISR at the specified interrupt vector and to define the interrupt priority level. The *achEnableInt()* macro and the ITCN driver commands ITCN_INIT_GPRS and ITCN_INIT_IPR are used to enable interrupts.

Example 2-51. Installing ISRs and enabling interrupts

1) *appconfig.h* file

```
/*************************************************************************
*
* File Name: appconfig.h
*
* Description: file for static configuration of the application
*              (initial values, interrupt vectors)
*
*************************************************************************/

#ifndef __APPCONFIG_H
#define __APPCONFIG_H

/*.**********************************************************************
*
*  File generated by Graphical Configuration Tool Thu, 18/Apr/2013, 10:30:51
*
**********************************************************************.*/

#define MC56F82748
#define EXTCLK 8000000L
#define APPCFG_DFLTS_OMITTED 1
#define APPCFG_GCT_VERSION 0x02060200L

/*.
    OCCS Configuration
----------------------------------------
    Use Factory Trim Value: Yes
```

```
    Enable internal 32 kHz oscillator: No
    Power Down crystal oscillator: Yes
    Core frequency: 50 MHz
    VCO frequency: 200 MHz
    Loss of lock interrupt 0: Disable
    Loss of lock interrupt 1: Disable
    Loss of reference clock Interrupt: Disable
.*/
#define OCCS_CTRL_INIT                    0x0081U
#define OCCS_DIVBY_INIT                   0x2018U
#define OCCS_USE_FACTORY_TRIM             1
#define OCCS_USE_FACTORY_TRIM_TEMP        1

/*.
    SYS Configuration
----------------------------------------
    SIM: Power Saving Modes: Stop enabled
    Wait enabled
         OnCE clock to processor core: Enabled when core TAP enabled
    DMA Enable in RUN and WAIT modes: DMA enabled in all power modes
   Enable External Reset Padcell Input Filter : No , SIM - Clock on GPIO: Enable CLKO_0: No
    SIM - Clock on GPIO: Enable CLKO_1: No
    SIM - HS_PERF Peripheral Clk: PWM
    SIM - Peripheral Clock Enable: GPIO F: Yes, GPIO E: Yes, GPIO D: No , GPIO C: Yes,
GPIO B: No , GPIO A: No , TMR A0: No
                                  TMR A1: No , TMR A2: No , TMR A3: No , SCI0: No , SCI1:
No , QSPI0: No , QSPI1: No , IIC: No , MSCAN: No
                                    CMP A: No , CMP B: No , CMP C: No , CMP D: No , CYC
ADC: No , CRC: No , QDC: No , PIT0: No , PIT1: No , DACA: No , DACB: No
                                    PWMCH0: No , PWMCH1: No , PWMCH2: No , PWMCH3: No ,
SIM - Modules Enabled in Stop: GPIO F: No , SIM - Modules Enabled in Stop: GPIO E: No ,
SIM - Modules Enabled in Stop: GPIO D: No , SIM - Modules Enabled in Stop: GPIO C: No ,
SIM - Modules Enabled in Stop: GPIO B: No , SIM - Modules Enabled in Stop: GPIO A: No
    SIM - Modules Enabled in Stop: TMR A0: No , TMR A1: No , TMR A2: No , TMR A3: No ,
                           SCI0: No , SCI1: No , QSPI0: No , QSPI1: No , IIC: No , MSCAN: No
                                    CMP A: No , CMP B: No , CMP C: No , CMP D: No , CYC
ADC: No , CRC: No , QDC: No , PIT0: No , PIT1: No , DACA: No , DACB: No
                                    PWMCH0: No , PWMCH1: No , PWMCH2: No , PWMCH3: No
    Protection of IPS and GPSxx  : Registers not protected
    Protection of PCE, SD and PCR: Registers not protected
    Protection of GPIO Port D: Registers not protected
    Protection of PWRMODE: Registers not protected
    GPIO Peripheral select registers (GPSn): ANA0/CMPA3
                                             ANB1/CMPB_IN0
                                             EXTAL
                                             TXD0
                                             TA0
                                             TA1
                                             DACA
                                             TA2
                                             SS0_B
                                             MOSI0
                                             SCLK0
                                             MOSI0
                                             Reserved
                                             Reserved
                                             TA3
```

```
                                                SDA0
                                                SCL0
                                                PWMA_2B
                                                PWMA_2A
                                                PWMA_3B
                                                PWMA_3A
                                                XB_IN6
                                                CLKOUT1
                                                SCL0
                                                SDA0
                                                TXD1
                                                RXD1
                                                Reserved
                                                CMPC_O
                                                RXD0
    Internal Peripheral Select Register 0 (IPS0): GPIOC3
                                                  GPIOC4
                                                  GPIOC6
                                                  GPIOC13
                                                  GPIOC3/GPIOC8/GPIOF8
                                                  GPIOC12/GPIOF5
    Miscellaneous Register 0 (SIM_MISC0): Disable
                                          Disable
                                          CLKIN0 (GPIOC0 alt1)
                                          PIT0 master, PIT1 slave
    SIM - Interrupts: Low voltage 2.2V: Disable
                      Low voltage 2.7V: Disable
                      High voltage 2.2V: Disable
                      High voltage 2.7V: Disable
    Enable Voltage Reference Buffer: No
    Bandgap trim: 7, Use Factory Trim Value: No
.*/
#define SIM_CLKOSR_INIT                   0xD020U
#define SIM_PCE0_INIT                     0x0016U
#define SIM_PCE1_INIT                     0x0002U
#define SIM_PCE2_INIT                     0x0000U
#define SIM_PCE3_INIT                     0x0000U

/*.
    INTC Configuration
-------------------------------------------
.*/
#define INTC_ICTL_INIT                    0x0000U
#define INT_VECTOR_ADDR_102               gpio_f_isr
#define INT_PRIORITY_LEVEL_102            INTC_LEVEL0
#define INT_VECTOR_ADDR_105               gpio_c_isr
#define INT_PRIORITY_LEVEL_105            INTC_LEVEL0

/*.
    GPIO_C Configuration
-------------------------------------------
    Pin  0: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  1: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  2: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Enable ,
Int.Polarity: Active high ,
```

```
    Pin  3: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  4: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  5: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  6: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  7: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  8: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  9: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin 10: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin 11: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin 12: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin 13: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin 14: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin 15: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
.*/
#define GPIO_C_PER_INIT                 0x0000U
#define GPIO_C_IENR_INIT                0x0004U

/*.
    GPIO_E Configuration
-----------------------------------------
   Pin  0: Function: GPIO , Direction: Output , Init.Value: Low - 0 , Interrupt: Disable,
Int.Polarity: Active high , Output-Mode: Push-pull ,
   Pin  1: Function: GPIO , Direction: Output , Init.Value: Low - 0 , Interrupt: Disable,
Int.Polarity: Active high , Output-Mode: Push-pull ,
   Pin  2: Function: GPIO , Direction: Output , Init.Value: Low - 0 , Interrupt: Disable,
Int.Polarity: Active high , Output-Mode: Push-pull ,
   Pin  3: Function: GPIO , Direction: Output , Init.Value: Low - 0 , Interrupt: Disable,
Int.Polarity: Active high , Output-Mode: Push-pull ,
   Pin  4: Function: GPIO , Direction: Output , Init.Value: Low - 0 , Interrupt: Disable,
Int.Polarity: Active high , Output-Mode: Push-pull ,
   Pin  5: Function: GPIO , Direction: Output , Init.Value: Low - 0 , Interrupt: Disable,
Int.Polarity: Active high , Output-Mode: Push-pull ,
   Pin  6: Function: GPIO , Direction: Output , Init.Value: Low - 0 , Interrupt: Disable,
Int.Polarity: Active high , Output-Mode: Push-pull ,
   Pin  7: Function: GPIO , Direction: Output , Init.Value: Low - 0 , Interrupt: Disable,
Int.Polarity: Active high , Output-Mode: Push-pull ,
.*/
#define GPIO_E_DDR_INIT                 0x00FFU
#define GPIO_E_PER_INIT                 0x0000U

/*.
    GPIO_F Configuration
-----------------------------------------
```

```
    Pin  0: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  1: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  2: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  3: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  4: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
```

2) application code (*main.c* file)

```
/*****************************************************************************
*
* File Name: main.c
*
* Description: Main application file generated automatically from the
*              DSP56800EX_Quick_Start stationery
*
* Target: MC56F82748 device
*
*****************************************************************************/

/* required DSP56F800E_Quick_Start header */
#include "qs.h"

/* low-level driver headers for each module used */
#include "sys.h"
#include "intc.h"
#include "gpio.h"
#include "cop.h"

/* few Tower Board 56F8200 specific defines */
/* three basic LEDs on a single port */
#define GPIO_LEDS   GPIO_E
#define LED_G       BIT_0
#define LED_Y       BIT_1
/* alternate LEDs, each may be on a separate port */
#define GPIO_LED_R2 GPIO_F
#define LED_R2      BIT_6
#define GPIO_LED_Y2 GPIO_E
#define LED_Y2      BIT_7
#define GPIO_LED_G2 GPIO_E
#define LED_G2      BIT_6
/* GPIO active-low buttons */
/* jumper J5 2-3 */
#define GPIO_BTN_0  GPIO_F
#define BTN_0       BIT_7
/* jumper J4 1-2 */
#define GPIO_BTN_1  GPIO_C
#define BTN_1       BIT_2
/* jumper J5 2-3 */
#define GPIO_BTN_0  GPIO_F
#define BTN_0       BIT_7
```

```
/* local prototypes */
void init_gpio(void);

/*
 *  The main function
 */

void main (void)
{
    UWord16 i;

  /* initialise SYS module */
    ioctl(SYS, SYS_INIT, NULL);

    /* configure COP module */
    ioctl(COP, COP_INIT, NULL);

    /* configure all GPIO modules */
    ioctl(GPIO, GPIO_INIT_ALL, NULL);

    /* initialize and configure GPIO ports */
    init_gpio();

    /* configure Interrupt Controller */
    ioctl(INTC, INTC_INIT, NULL);

    /* enable interrupts in SR */
    archEnableInt();

    while(1)
    {
      /* wait a while */
      for(i=0; i<100; i++)
          archDelay(0xffff);

      /* toggle green indicator D8 */
      ioctl(GPIO_LED_G2, GPIO_TOGGLE_PIN, LED_G2);

      /* service COP */
      ioctl(COP, COP_CLEAR_COUNTER, NULL);
    }
}


/*
 *  GPIO port C  interrupt service routine - toggles LED_Y2
 */

#pragma interrupt on

void gpio_c_isr(void)
{
    UWord16 irqs = ioctl(GPIO_BTN_1, GPIO_READ_INT_PENDING_REG, NULL);

    /* toggle LEDs */
    if(irqs & BTN_1)
        ioctl(GPIO_LED_Y2, GPIO_TOGGLE_PIN, LED_Y2);
```

```
    /* clear interrupt flags */
    ioctl(GPIO_BTN_1, GPIO_CLEAR_INT_PENDING, irqs);
}

#pragma interrupt off

/*
 *  GPIO port F  interrupt service routine - toggles LED_R2
 */
#pragma interrupt on

void gpio_f_isr(void)
{
    UWord16 irqs = ioctl(GPIO_BTN_0, GPIO_READ_INT_PENDING_REG, NULL);

    /* toggle LEDs */
    if(irqs & BTN_0)
        ioctl(GPIO_LED_R2, GPIO_TOGGLE_PIN, LED_R2);

    /* clear interrupt flags */
    ioctl(GPIO_BTN_0, GPIO_CLEAR_INT_PENDING, irqs);
}

#pragma interrupt off

/*
 *  Initialize the GPIO ports
 */

void init_gpio(void)
{
    /* pins are already configured from the device_init;
       this is an example of run-time configuration of LEDs outputs */
    ioctl(GPIO_LED_R2, GPIO_SETAS_GPIO, LED_R2);
    ioctl(GPIO_LEDS,   GPIO_SETAS_GPIO, LED_Y2 | LED_G2);

    ioctl(GPIO_LED_R2, GPIO_SETAS_OUTPUT, LED_R2);
    ioctl(GPIO_LEDS,   GPIO_SETAS_OUTPUT, LED_Y2 | LED_G2);

    /* run-time configuration of button inputs */
    ioctl(GPIO_BTN_0, GPIO_SETAS_GPIO, BTN_0);
    ioctl(GPIO_BTN_1, GPIO_SETAS_GPIO, BTN_1);

    ioctl(GPIO_BTN_0, GPIO_SETAS_INPUT, BTN_0);
    ioctl(GPIO_BTN_1, GPIO_SETAS_INPUT, BTN_1);

    ioctl(GPIO_BTN_0, GPIO_PULLUP_ENABLE, BTN_0);
    ioctl(GPIO_BTN_1, GPIO_PULLUP_ENABLE, BTN_1);

    ioctl(GPIO_BTN_0, GPIO_INT_ENABLE, BTN_0);
    ioctl(GPIO_BTN_1, GPIO_INT_ENABLE, BTN_1);
}
```

2.7 Advanced Topics

This section describes the implementation details and the system code of each project created from the 56800EX_Quick_Start tool stationery for the 56F82xxx and 56F84xxx hybrid controllers.

2.7.1 Project Targets

Each created project contains several targets for different hardware configurations of the microcontroller system. All targets are briefly described in the following tables:

Table 2-35. Targets of the MC56F82748EVM project.

Target Name	Data Model	Memory Used					EVM Board Jumpers	Target Description
		Code	Boot Location	Data	Initial Data	Constant Data		
FLASH_SDM	Small	pFlash (0x0000)	0x0000	Int xRAM (0x0000)	Int xRAM	Int xRAM	n/a	Stand Alone application
FLASH_LDM	Large	pFlash (0x0000)	0x0000	Int xRAM (0x0000)	Int xRAM	Int xRAM	n/a	Stand Alone application

There is a different linker command file (LCF) for each target, which defines the destination memory ranges used by the linker. Although the syntax of the LCF and C header files are completely different. The LCF for each target is also used as prefix[1] header file in its target configuration. The macros defined in the LCF identify the target for further conditional compilation of the project source files.

The trick which enables using a file with the LCF syntax as a header file is shown on Example 2-52. It successfully exploits the fact that the '#' sign is treated as a start of comment line in LCF syntax, so the C-like #define statements do not cause the LCF syntax errors. On the other side, the #if 0 ... #endif block excludes the LCF part of the file from C compilation.

Example 2-52. Internal_PFlash_SDM.cmd linker command file

```
#include "version.h"
#include "hawkcpu.h"

#define TARGET_SDM                  /* Small Data Model */
#define TARGET_CODE_PFLASH          /* Code located in internal flash */
#define TARGET_CONSTDATA_INTRAM     /* Constants and const variables located in x RAM */
#define TARGET_INITDATA_PFLASH      /* Initialization values for global variables located in
pFlash */
#define TARGET_DATA_INTRAM          /* Variables located in internal RAM */

#pragma define_section fardata  "fardata.data" "fardata.bss" RW  /* can be used to put far data
(after 0x10000) */
#pragma define_section pramcode "pramcode.text" RWX  /* can be used to put code to program ram */
#pragma define_section fast_interrupt "fast_interrupt.text"  RX/*  */
```

1. Prefix file is unconditionaly included at the begining of every compiled C file.

```
#if 0   /*

MEMORY
{
...
}

SECTIONS
{
...
}

...

#endif  /* end of code excluded by C-compiler */
```

2.7.2 Inside Startup Code

This section goes step-by-step through the processor initialization code described briefly in Section 2.1.2 on page -2. The startup code described here can be found in the *startup.c* file, located in the *SystemConfig* subdirectory of any project created using the 56800EX_Quick_Start tool stationery.

2.7.2.1 Symbols Used in Startup Code

2.7.2.1.1 Included Header Files

The master Quick_Start header file *qs.h* is included in the startup code. This file further includes other critical system files to define common C types, peripheral module base addresses and other types and macros required by the startup code. The application configuration header file *appconfig.h* is also included so the startup code is able to configure system modules like OCCS (PLL) and GPIO.

```
#include “qs.h”
```

2.7.2.1.2 Initial Value of Operation Mode Register (OMR)

Although it is not very common, the initial value of the Operation Mode Register (OMR) can be specified in *appconfig.h* using the `OMR_INIT` macro.

The following *startup.c* statements define the default initial OMR value for the cases when the user had not defined the `OMR_INIT` in *appconfig.h*:

```
#ifndef TARGET_OMR_INIT
#define TARGET_OMR_INIT 0
#endif

#ifndef OMR_INIT
#define OMR_INIT 0|(TARGET_OMR_INIT)
#endif
```

The default initialization value of the OMR is based on the `TARGET_OMR_INIT` value, which might be defined in the prefix file (LCF) within the active compilation target. Currently, the `TARGET_OMR_INIT` is not defined in the prefix file of any target, leaving the initial OMR value on 0x0000.

The following OMR bits are important for the proper operation of the C application:

- CM = 0 - optional for C application
- XP = 0 - enabling separate program and data buses (Harvard Architecture)
- R = 0 - rounding off, required for C applications
- SA = 0 - saturation off, required for C applications
- EX = 0 - complete X memory space as external, required by CodeWarrior debugger

The critical OMR bits are checked by the C preprocessor directive, issuing the compile-time warning when found in the OMR_INIT value:

```
#if (OMR_INIT & (OMR_CM|OMR_XP|OMR_R|OMR_SA))
#warning Initial OMR value might be invalid for the C project
#endif
#if (OMR_INIT) & OMR_EX
#warning  CodeWarrior cannot debug projects with OMR.EX bit set
#endif
```

2.7.2.1.3 Other appconfig.h Symbols

Using the `OCCS_REQUIRED_LOCK_MODE` macro, the user specifies in which lock state of the PLL the setup code continues to the rest of the startup code:

- 0x20 (default) - continue when “coarse” lock mode is reached (bit LCK0 in PLLSR)
- 0x40 - continue when “fine” lock mode is reached (bit LCK1 in PLLSR)

```
#ifndef OCCS_REQUIRED_LOCK_MODE
#define OCCS_REQUIRED_LOCK_MODE 0x20 /* coarse (LCK0) by default */
#endif
#if (OCCS_REQUIRED_LOCK_MODE != 0x40) && (OCCS_REQUIRED_LOCK_MODE != 0x20)
#error OCCS_REQUIRED_LOCK_MODE must be one of 0x20 (coarse) or 0x40 (LCK1-fine)
#endif
```

One of the startup code optional features is to perform the internal data RAM checking. The checking algorithm, fully described later in Section 2.7.2.2.6, uses two values which writes, reads and verifies to check each memory location. By default the two values are 0xAAAA and 0x5555. If there is any reason to change the values, the user can define the macros `CONFIG_INTRAM_CHECKVALUE1` and `CONFIG_INTRAM_CHECKVALUE2` in the *appconfig.h* file.

```
#ifndef CONFIG_INTRAM_CHECKVALUE1
#define CONFIG_INTRAM_CHECKVALUE1 0xaaaa
#endif
#ifndef CONFIG_INTRAM_CHECKVALUE2
#define CONFIG_INTRAM_CHECKVALUE2 0x5555
#endif
```

2.7.2.1.4 Linker Command File Symbols

While linking, the linker replaces any zeros generated by compiler for *external* symbols with proper values calculated during linking process when the physical addresses of the symbols are known. Some values of external symbols can be also specified directly by the directives in the linker command file.

The following symbols are specified by the LCF and provide physical address of memory segments used in the startup code:

```
/* external constants defined in LCF */
extern _Lstack_addr;
extern _Ldata_size;
extern _Ldata_ROM_addr;
extern _Ldata_RAM_addr;
extern _Ldata2_size;
extern _Ldata2_ROM_addr;
extern _Ldata2_RAM_addr;
extern _Ldatap_size;
extern _Ldatap_ROM_addr;
extern _Ldatap_RAM_addr;
extern _Lbss_size;
extern _Lbss_start;
extern _Lbss2_size;
extern _Lbss2_start;
extern _Lbssp_size;
extern _Lbssp_start;
extern _Linternal_RAM_addr;
extern _Linternal_RAM_size;
extern _Linterrupt_vectors_addr;
```

2.7.2.2 Startup Source Code

The following subsections describe the source code of the Start assembly function.

```
asm void Start(void)
{
```

2.7.2.2.1 Initialize Interrupt Vectors Base Address

The vector table is located at the beginning of the Program Flash at the beginning of the Program RAM. The startup code always updates the Vector Table Base Address (VBA) to beginning of ".interrupt_vectors" section where the Quick_Start vector table is located. By default this table is always put to the beginning of the Program RAM anyway.

By defining the ARCH_VECTBL_ADDR macro in the *appconfig.h* configuration file, the VBA may be forced to a custom value.

```
/* relocate vector table properly */
    #ifdef ARCH_VECTBL_ADDR
    move.l ARCH_VECTBL_ADDR,A
    #else
    move.l #_Linterrupt_vectors_addr,A
    #endif
#if (MC56F824x || MC56F825x || MC56F84xxx || MC56F82xxx)
    asrr.l #8,A
```

```
#else
    asrr.l #7,A
#endif
/* initialize Vector Base Address */
#if defined(INTC_VERSION)
    move.w A0,ArchIO.Intc.vba
#elif defined(WINTC_VERSION)
    move.w A0,ArchIO.Wintc.vba
#else
    #warning Vector Base Address is not initialized
#endif
```

2.7.2.2.2 Clear COP Counter and Keep Clearing Values in Registers

On the newer 56F800EX-based devices, the COP Watchdog counter is enabled after reset, so it is necessary to clear this counter periodically during any lengthy operation in the startup code. Early in the startup, the COP counter is initially cleared and the clearing values are preserved in registers. The R5, C1 and D1 registers are not changed anywhere in the rest of the startup code and are used to clear the COP without loading the constant values again.

```
/* clear COP watchdog counter, keep clearing values in registers C1,D1,R5 */
    moveu.w #ArchIO.Cop.copctr,R5
    move.w 0x5555,C1
    move.w 0xAAAA,D1
    move.w C1,X:(R5)
    move.w D1,X:(R5)
```

2.7.2.2.3 Setup the Operation Mode Register (OMR)

The “one” bits in the OMR_INIT value are set in the Operating Mode Register.

```
/* setup the OMR */
bfset OMR_INIT,omr
nop
nop
```

2.7.2.2.4 Other Initialization

The M01 register is initialized to -1 to activate linear addressing mode with R0 and R1 registers.

```
/* setup the m01 register for linear addressing */
move.w   #-1,x0
moveu.w  x0,m01
```

The values on the Hardware Stack are cleared (for proper debugger behavior).

```
/* clear (read-out) the hardware stack */
moveu.w   hws,la
moveu.w   hws,la
nop
nop
```

2.7.2.2.5 Core Clock Setup (OCCS)

The PLL Oscillator Control Register and the Divide-By Register are initialized with the *appconfig.h* values if defined. The value in the Divide-By Register controls the prescaler and postscaler frequency divisors and also multiplication factor of the PLL. Note that before the PLLCR register is written, the PLL

remains turned off and the system clock is still taken from a default clock source (now divided by prescaler value). The default clock source is an external oscillator or an internal relaxation oscillator on some devices.

```
/* configure external oscillator and clock mode */

#ifdef OCCS_OSCTL_INIT
#define OSCTL_TEMP (OCCS_OSCTL_INIT & 0x3fff) /* keep internal osc. enabled */
    move.w  #OSCTL_TEMP,ArchIO.Pll.osctl      /* OSCTL,even if PLL not used */
    nop
    nop
#endif

/* setup the PLL according to appconfig.h values */

#ifdef OCCS_PLLDB_INIT
    move.w  OCCS_PLLDB_INIT,ArchIO.Pll.plldb  /* PLLDB, even if PLL not used */
    nop
    nop
#endif
```

On the devices equipped with an internal relaxation oscillator, a user may want to initialize the trimming value in the Oscillator Control Register by the factory-measured value which is saved in the SIM Non-Volatile Memory Option Register 2 (High). For the new devices (e.g. 56F82xxx/56F84xxx) the OCCS version 6 or 7 is valid.

```
/* load factory trimming value of the internal relaxation oscillator? */
#if OCCS_USE_FACTORY_TRIM
/* first move factory value to Y1 */
#if OCCS_VERSION <= 4
    move.w  ArchIO.Hfm.fmopt1,y1
#elif OCCS_VERSION <= 5  /* OCCS_VERSION == 5 */
    move.w  ArchIO.Hfm.fmopt0,y1
#else  /* OCCS_VERSION >= 6 */
    move.w  ArchIO.Sim.sim_nvmopt2h,y1
#endif
    bfclr   #0xfc00,y1
```

Then, if the PLL Control Register initial value is defined in *appconfig.h*, the PLL setup code is executed:

```
#ifdef OCCS_PLLCR_INIT
```

On the new devices (e.g. 56F82xxx/56F84xxx), all pins are in the GPIO mode after reset, including the pins which may be needed as an external clock or crystal source. The startup code automatically re-configures these pins to the required clock-related mode before switching to an external clock. The new devices are identified by OCCS version 6 or 7 and SIM version 7 or 8 in the new code.

NOTE

The peripheral module version identifiers are defined in the *arch.h* file for each device purely for an internal use in the DSP56800EX_Quick_Start code. The version numbers **do not** rely to chip or silicon version.

```
/* on new devices, some external pins may be needed if PLLCR.PRESC=1 */

#if (defined(OCCS_VERSION_6) || defined(OCCS_VERSION_7)) &&
(defined(SIM_VERSION_7)||defined(SIM_VERSION_8)) && (OCCS_PLLCR_INIT & 0x4)

    /* first get EXT_SEL and CLK_MODE values (see OSCTL register) */
    #ifdef OCCS_OSCTL1_INIT
    #define _OCCS_EXTSEL  (((OCCS_OSCTL1_INIT) >> 10) & 0x1)
    #define _OCCS_CLKMODE (((OCCS_OSCTL1_INIT) >> 12) & 0x1)
    #else
    #define _OCCS_EXTSEL  1 /* reset value is 1 */
    #define _OCCS_CLKMODE 1 /* reset value is 1 */
    #endif

    #ifdef SIM_MISC0_INIT
    #define _SIM_CLK1 (((SIM_MISC0_INIT) >> 1) & 0x1)
    #else
    #define _SIM_CLK1 0
    #endif


   //todo optimalise, check correct functionality (test all cases  - CLKIN/EXTAL/CRYSTAL)
    /* external clock on CLKIN (GPIO_C0) */   // EXTAL for black GPIOC1, XTAL=C0, EXTAL
for black GPIOC0, XTAL=C1
    #if _OCCS_EXTSEL == 1
    /* enable clock for GPIO_C*/
    bfset 0x0010, ArchIO.Sim.sim_pce0
    //enable CLKIN_0 or CLKIN_1
    #if _SIM_CLK1
    bfset 0x0002, ArchIO.Sim.sim_misc0
    bfset 0x00C0, ArchIO.Sim.sim_gpscl
    bfset 0x0008, ArchIO.PortC.per

    #else
    bfset 0x0001, ArchIO.Sim.sim_gpscl
    bfset 0x0001, ArchIO.PortC.per
    bfclr 0x0002, ArchIO.Sim.sim_misc0
    #endif

    /* external clock on XTAL (GPIO_C0)*/
#else
    /* enable clock for GPIO_C*/
    bfset 0x0010, ArchIO.Sim.sim_pce0
    bfclr 0x0001, ArchIO.Sim.sim_gpscl
    bfset 0x0001, ArchIO.PortC.per
/* crystal on EXTAL and XTAL pins (GPIO_C1 and GPIO_C0)*/
 #if _OCCS_CLKMODE == 0
    bfset 0x0002, ArchIO.PortC.per

    /* give it some time until crystal/resonator stabilizes */
    /* we now run from internal relaxation oscillator / 2 (i.e. 4MHz) */
    move.w #5000,x0   /* wait 50ms */
    do x0,waitosc
    rep 36; nop;      /* sigle loop pass takes 40 cycles */
    move.w C1,X:(R5)  /* and also clears the watchdog */
    move.w D1,X:(R5)
waitosc:
```

```
 #endif  /* _OCCS_CLKMODE == 0 */
#endif   /* _OCCS_EXTSEL == 0 */

    /* switch to external clock source (set PRESC=1) */

    nop;
    bfset 0x4,ArchIO.Pll.pllcr
    nop
    nop

#ifdef OCCS_OSCTL1_INIT
#define OSCTL_TEMP2 (OCCS_OSCTL1_INIT & 0xC000) /* shut down internal oscillator if
required */
    bfset  #OSCTL_TEMP2,ArchIO.Pll.osctl1
    nop
    nop
#endif

skip_set_ext:
#endif /* (defined(OCCS_VERSION_6) || defined(OCCS_VERSION_7)) &&
(defined(SIM_VERSION_7)||defined(SIM_VERSION_8)) && (OCCS_PLLCR_INIT & 0x4) */
```

When the PLL is to be turned on, it is first decided whether the code is running on real chip or in software simulator. The simulator mode is identified by looking at the “clock source” bit-field value in the PLLCR register. In the simulator mode, the PLL setup is skipped because the loop waiting for the PLL lock would never finish.

```
#if (OCCS_PLLCR_INIT & 1) /* PLL active ? */

#define PLLCR_TEMP (OCCS_PLLCR_INIT & 0xfe) /* interrupts off and PLL bypassed */

    brset 0,ArchIO.Pll.pllcr,skip_pll_lock /* skip PLL in simulator mode */
```

While still running from an external oscillator, the PLL lock detector is activated and it is waiting until the PLL lock is detected. According to *appcofing.h* setting, the required lock state is either “coarse” or “fine” - which corresponds to the PLLSR bits LCK1 and LCK0. Note that the COP counter is periodically cleared while waiting in the loop.

```
move.w  #PLLCR_TEMP,ArchIO.Pll.pllcr   /* PLL lock detector ON, core still on prescaler */

pll_lock:
    move.w C1,X:(R5)  /* clear COP watchdog counter while waiting in the loop*/
    move.w D1,X:(R5)

    brclr   OCCS_REQUIRED_LOCK_MODE,ArchIO.Pll.pllsr,pll_lock   /* test lock (LCK1 or
LCK0) */
```

When the PLL is locked, the system clock is switched to PLL and the PLLCR is finally initialized with the user defined value. As the last, the pending PLL interrupts are cleared.

```
    nop
    nop
    move.w  OCCS_PLLCR_INIT,ArchIO.Pll.pllcr  /* PLL locked: final PLL setup */
```

```
skip_pll_lock:
    move.w  ArchIO.Pll.pllsr,x0     /* clear pending clkgen interrupts */
    move.w  x0,ArchIO.Pll.pllsr
    nop
```

If the PLL is not to be enabled, the initial value of the PLL Control Register is simply written.

```
#else /* (OCCS_PLLCR_INIT & 1) PLL not active */

    move.w  OCCS_PLLCR_INIT,ArchIO.Pll.pllcr

#endif /* (OCCS_PLLCR_INIT & 1) */
```

2.7.2.2.6 Internal Memory Checking

Checking the internal data RAM is an optional feature of the startup code. When the `INTXRAM_CHECK_ENABLED` macro is defined in *appconfig.h*, this feature is activated.

The memory checking process consists of tree parts:

- Complete memory fill (value 0xAAAA) & read + compare
- Single write, read & compare for each memory location
- Two immediate reads from different memory locations & compare

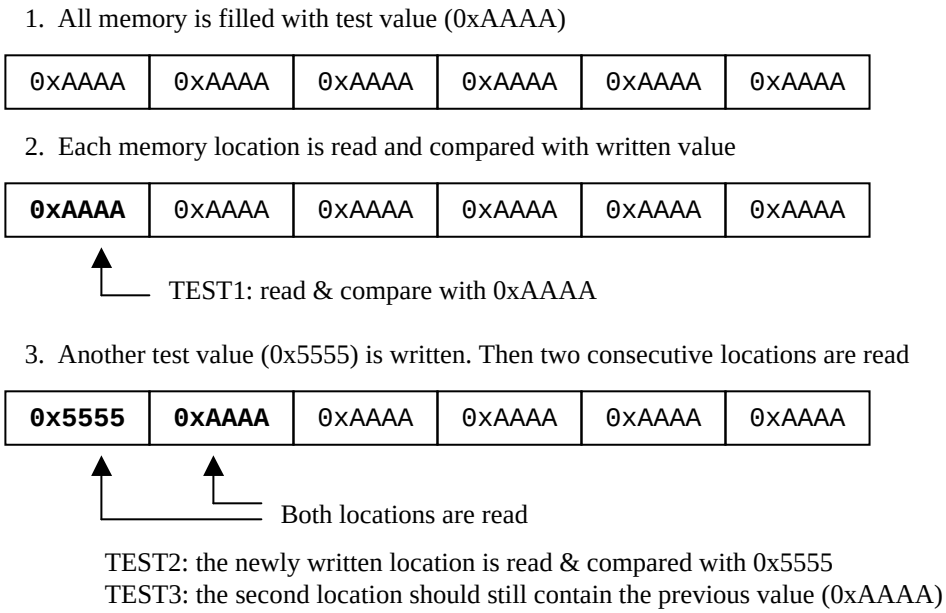


Figure 2-3. Memory Checking Process

In case if any of the three tests fails, the application execution is halted by *debughlt* and *stop* instructions.

The compile-time warning is issued when the internal memory checking is activated in targets that do not use the internal memory.

```
/* internal RAM memory test */

#ifdef INTXRAM_CHECK_ENABLED
#ifndef TARGET_DATA_INTRAM
#warning Internal Memory Checking is active but variables go elsewhere
#endif

move.l  #>>_Linternal_RAM_addr,r1                          /* memory pointer */
move.l  #>>_Linternal_RAM_size,r2                             /* memory size */
move.w  CONFIG_INTRAM_CHECKVALUE1, x0                /* x0=write/test value 1 */
move.w  CONFIG_INTRAM_CHECKVALUE2, y0               /* y0=write/test value 2; */
move.w  #0,b                                     /* b0=0, b1 will be used as "b" */

rep r2; move.w x0,x:(r1)+                        /* fill memory with value test1 */

move.l  #>>_Linternal_RAM_addr,r1          /* initialize verify memory pointer */
do      r2,end_intramcheck1                                 /* start verify loop */


    move.w C1,X:(R5)                          /* clear COP watchdog counter */
    move.w D1,X:(R5)

cmp.w   x:(r1),x0                                    /* TEST1: read & compare */
beq <t1passed                                                /* TEST1: OK ? */
debughlt

t1passed:
move.w  y0,x:(r1)                                       /* TEST2: write test2 */
move.wx:(r1+1),y1                 /* read from incremented address (see TEST3) */
cmp.w   x:(r1),y0           /* read written value & compare (should be test2) */
beq <t2passed                                                /* TEST2: OK ? */

nop
debughlt /* !! MEMORY TEST FAILED !! */
stop

t2passed:
move.w  lc,b              /* skip TEST3 for the last memory cell (when LC==1) */
cmp.w   #1,b
ble <t3passed
cmp.wy1,x0           /* TEST3: value from incremented addr. should be ==test1 */
beq <t3passed                                                /* TEST3: OK ? */

nop
debughlt /* !! MEMORY TEST FAILED !! */
stop

t3passed:
move.w  b0,x:(r1)+                            /* clear checked memory location */
nop
nop                               /* without nops, the branch to t3passed above */
nop                                    /* could confuse the hardware loop unit */

end_intramcheck1:
#endif
```

2.7.2.2.7 Stack Pointer Initialization

The stack pointer (SP) register is initialized to the first odd value after _Lstack_addr symbol generated by linker command file. The first stack location is then initialized to NULL.

```
/* initialize stack */

move.l #>>_Lstack_addr,r0
bftsth #$0001,r0
bcc <noinc
adda #1,r0
noinc:
tfra     r0,sp
move.w   #0,r1
nop
move.w   r1,x:(sp)
adda     #1,sp
```

2.7.2.2.8 Clearing .bss, .bss.pmem and fardata.bss Segments

The *.bss* is the memory segment containing the global or static C variables to which are not assigned initial values (or the initial value is 0). This segment is cleared by the startup code so the global and static C variables are initialized to 0.

Note that the COP counter is periodically cleared in all loops below.

```
/* clear BSS segment (can't use 'do' and its 16 bit loop counter) */

move.l  #>>_Lbss_size,r2                                        /* bss size */
tsta.l  r2
beq <end_clearbss;                                      /* skip if size is 0 */
move.l  #>>_Lbss_start,r1                                    /* dest address */
move.w  #0,x0
loop_clearbss:
move.w  C1,X:(R5)              /* clear COP watchdog counter */
move.w  D1,X:(R5)
move.w  x0,x:(r1)+                                      /* clear value at r1 */
dectsta r2;                                             /* long loop counter */
bne <loop_clearbss;
end_clearbss:
```

The same is done with the *.bss* segment of the fardata section (addresses after 0x10000). The full name of segment is *.fardata.bss*. In the startup code it is referenced as *bss2*.

```
/* clear BSS2 segment (can't use 'do' and its 16 bit loop counter) */

move.l  #>>_Lbss2_size,r2 /* bss size */
tsta.l  r2
beq <end_clearbss2;                                     /* skip if size is 0 */
move.l  #>>_Lbss2_start,r1 /* dest address */
move.w  #0,x0
loop_clearbss2:
move.w  C1,X:(R5)              /* clear COP watchdog counter */
move.w  D1,X:(R5)
move.w  x0,x:(r1)+                                      /* clear value at r1 */
dectsta r2;                                             /* long loop counter */
```

```
bne <loop_clearbss2;
end_clearbss2:
```

And again the process is repeated for the Program RAM-based variables. In the startup code, this *.bss.pmem* segment is referenced as *bssp*. Note that the move instruction accesses the P (program) space.

```
/* clear BSSP (program RAM) segment (can't use 'do' and its 16 bit loop counter) */

move.l  #>>_Lbssp_size,r2                                       /* bssp size */
tsta.l  r2
beq <end_clearbssp;                                        /* skip if size is 0 */
move.l  #>>_Lbssp_start,r1                                      /* dest address */
move.w  #0,x0
loop_clearbssp:
move.w  C1,X:(R5)              /* clear COP watchdog counter */
move.w  D1,X:(R5)
move.w  x0,p:(r1)+                                         /* clear value at r1 */
dectsta r2;                                                /* long loop counter */
bne <loop_clearbssp;
end_clearbssp:
```

2.7.2.2.9 Initializing Global Variables

The C variables to which are assigned a non-zero initial values must be initialized using the data from a non-volatile memory. Using the directives in the linker command file, the initial data are stored in the internal Flash memory. The source and destination addresses are calculated by the linker and exported as symbols. The P-Flash memory is used and the appropriate code is compiled.

Note that the COP counter is periodically cleared in all loops below.

```
/* copy variable initialization data from pFlash to destination (long loop) */

#ifdef TARGET_INITDATA_PFLASH
    move.l  #>>_Ldata_size,r2/* set data size */
    tsta.l  r2
    beq <end_prom2xram
    move.l  #>>_Ldata_ROM_addr,r3/* src address -- xROM data start */
    move.l  #>>_Ldata_RAM_addr,r1/* dest address -- xRAM data start */
loop_prom2xram:
    move.w  C1,X:(R5)              /* clear COP watchdog counter */
    move.w  D1,X:(R5)
    move.w  p:(r3)+,x0                          /* fetch value at address r3 */
    move.w  x0,x:(r1)+                          /* stash value at address r1 */
    dectsta r2
    bne <loop_prom2xram
end_prom2xram:
```

Next, the initialized program-RAM variables (those not in *.bss.pmem* section) and also the program-RAM-based code (from the Quick_Start-specific *pramcode* section) is initialized using the values from the program Flash.

```
/* in any flash-based target, do copy pram-variable initialization data
   (and ram-based code) from pFlash storage to destination in program-ram */

#ifdef TARGET_CODE_PFLASH
    move.l  #>>_Ldatap_size,r2/* set data size */
```

```
    tsta.l  r2
    beq <end_prom2pram
    move.l  #>>_Ldatap_ROM_addr,r3/* src address -- pROM data start */
    move.l  #>>_Ldatap_RAM_addr,r1/* dest address -- pRAM data start */
loop_prom2pram:
    move.w  C1,X:(R5)               /* clear COP watchdog counter */
    move.w  D1,X:(R5)
    move.w  p:(r3)+,x0                          /* fetch value at address r3 */
    move.w  x0,p:(r1)+                          /* stash value at address r1 */
    dectsta r2
    bne <loop_prom2pram
end_prom2pram:
#endif
```

2.7.2.2.10 Calling the main()

As the last step of the startup code, the *userPreMain* file and the *main* functions are called. The *userPreMain* can be found in the *arch.c* file and contains architecture and peripheral specific initialization code. It is empty in the current implementation.

In the case the *main* is prototyped with standard *argc* and *argv* arguments, the 0 and NULL values are passed - as it makes no sense to use them in the embedded application.

```
/* call userPreMain() from appconfig.c */
jsr userPreMain

/* call main() */
move.w   #0,y0                                  /* pass parameters to main() */
move.w   #0,R2
move.w   #0,R3

jsr main                                            /* call the user program */
```

2.7.2.2.11 Never-Reached Finish Code

In case that the main ever returns - which would be very uncommon case - the *userPostMain* de-initialization code (empty) from *arch.c* is called and the processor is halted.

If any of the debugging console I/O operations are used in the application, the calling of the internal *fflush* and *fflush_console* functions can be un-commented to assure the internal console buffers get flushed.

```
/* call userPostMain() from appconfig.c */
jsr userPostMain

/*   The fflush calls where removed because they added code */
/*   growth in cases where the user is not using any debugger IO. */
/*   Users should make these calls at the end of main if they use debugger IO */

/*move.w #0,r2 */
/*jsr    fflush                                                ; flush file IO */
/*jsr    fflush_console                                      ; flush console IO */

/*end of program; halt CPU */
```

```
nop
debughlt
stop
}
```

Chapter 3
Directory Structure

This section describes the directory structure of the Freescale DSP56800EX_Quick_Start tool, located in the **<...>\Freescale\DSC56800EX_Quick_Start_r2.6** directory. Note that the root directory of the DSP56800EX_Quick_Start may be changed during installation by the user. In general, the DSP56800EX_Quick_Start software is organized by supported devices as it is explained in this chapter.

3.1 Root Directory

The root, or main, directory is organized as shown in Figure 3-1.

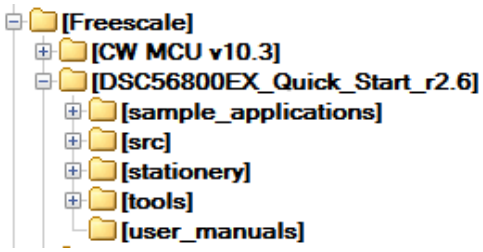


Figure 3-1. Root Directory Structure

Where:

- ***sample_applications*** contains simple application examples to demonstrate the usage of the DSP56800EX_Quick_Start tool as well as the use of device or on-chip peripherals; see also Section 3.2.
- ***src*** contains the C source files; see also Section 3.4.
- ***stationery*** contains the templates for the newly created projects. Note: this directory is also installed directly into the CodeWarrior development tool, if the path to this tool was specified by user.
- ***tools*** contains the Graphical Configuration Tool, its configuration files, device data sheets and peripheral user manuals which can be opened directly from the GCT.
- ***user_manuals*** contains the DSP56800EX_Quick_Start User's Manual and other documentation.

3.2 Sample Applications Directory

This directory contains simple application examples to demonstrate usage of the DSP56800EX_Quick_Start tool as well as the usage of device or on-chip peripherals. The structure of the ***sample_applications*** directory is illustrated in Figure 3-2.

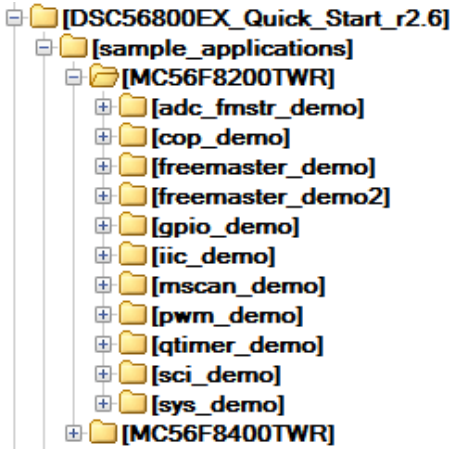


Figure 3-2. Sample Applications Directory Structure

The sample applications reside on the directory corresponding to the target hardware - Freescale Tower System boards. There are two Tower System boards used in examples:

- MC56F8200TWR based on MC56F82748 device
- MC56F8400TWR based on MC56F84789 device

Note: the individual application directories are further structured with project specific folders which hold the configuration files, the project build files and the CodeWarrior private data files. The specific board configuration is stored in board.h header files placed in MC56F8200TWR or MC56F8400TWR directory.

3.3 Tools Directory

The ***tools*** directory contains the Graphical Configuration Tool executable application, the needed *.dll* libraries and the help files.

3.4 Src Directory

The ***src*** or “source” directory is intended to hold all source files. Its structure is shown in Figure 3-3. The ***src*** directory is further divided into the following subdirectories:

- ***algorithms*** (optional) can contain the distributed algorithms and the user algorithms
- ***MC56F8xxxx*** is the directory specific for each of the supported devices. The subdirectory ***peripheral*** contains the source code for all on-chip peripheral drivers and the ***system*** subdirectory contains the device specific source files
- ***include*** contains the common DSP56800EX_Quick_Start header files, which define APIs and the implementation of generally used macro’s
- ***support*** contains other common DSP56800EX_Quick_Start source files. The subdirectory ***freemaster*** contains the source files to enable the FreeMASTER operation on the target board application. The directory ***compat*** is there because of compatibility with older DSP56800E_Quick_Start releases

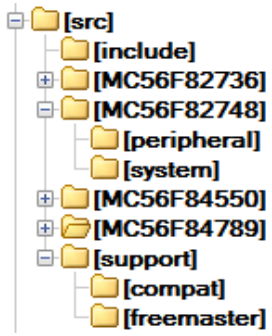


Figure 3-3. Src Directory Structure

3.5 Stationery Directory

The ***stationery*** directory contains the templates for the newly created DSP56800EX_Quick_Start projects. This directory is also copied into the CodeWarrior development tool directory if a proper path was specified by the user. This directory is needed to be copied manually or import into CodeWarrior present on the host computer.

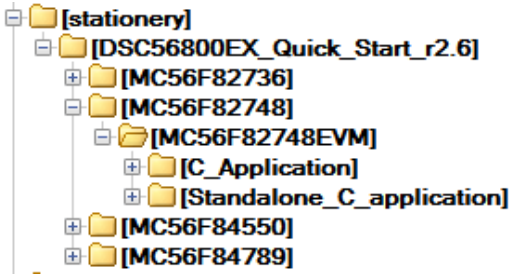


Figure 3-4. Stationery Directory Structure

The device specific subdirectories ***MC56F8xxxx*** are covered by the DSP56800EX_Quick_Start directory with the release version number. The device specific subdirectory contains all needed support files for the proper memory, system and application configuration and initialization.

3.6 User_manuals Directory

The ***user_manuals*** directory contains this DSP56800EX_Quick_Start User's Manual as well as other relevant documentation.

Chapter 4
Developing Software

This chapter describes in detail how to develop the applications using the DSC56800EX_Quick_Start. It describes how to create new applications using the DSC56800EX_Quick_Start tool, how to initialize on-chip peripheral modules, how to access them in run-time by application code and an application configuration by an application specific configuration file *appconfig.h*. At this point it is assumed that CodeWarrior for Microcontrollers Development Tools and DSC56800EX_Quick_Start are successfully installed and running (see Section 1.2.1 and Section 1.2.2 if you need information about installation of these tools).

4.1 Creating a new project

To create a new project based on the DSC56800EX_Quick_Start project templates (stationery), two options are available:

- Standalone C-application - all essential driver files are located in the project folder.
- C-application - driver files are linked to the project from DSC56800EX_Quick_Start depository.

Following steps suppose DSC56800EX_Quick_Start to be installed in a default installation folder *c:\Freescale\DSC56800EX_Quick_Start_X_Y* to link properly driver files when the new project is based on C-application template.

Creating a new project based on QuickStart C-application template:

1. Launch CodeWarrior IDE from the Start->Programs->Freescale CodeWarrior menu and open existing or create new *Workspace*.
2. Choose *File->Import* command and select *General->Existing Projects into Workspace* and click on *Next.*

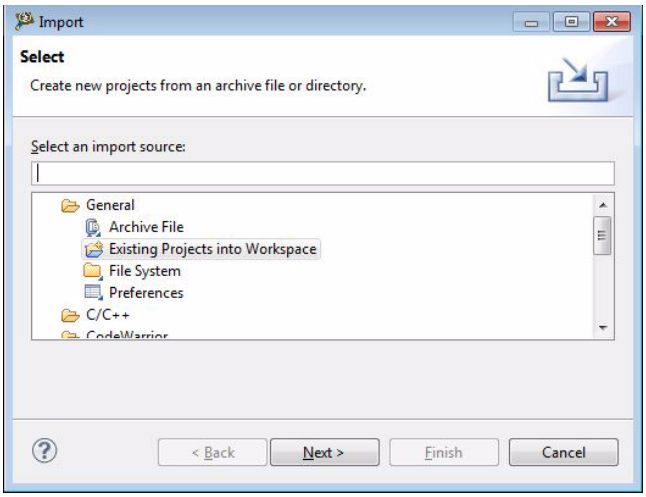


Figure 4-1. Import Dialog Box

3. Select root directory of the project stationary, e.g. *..\DSC56800EX_Quick_Start r2.6\stationary\DSC56800EX_Quick_Start_r2.6\MC56F82748\Standalone_C_application*. The project template have to be copied into the CodeWarrior Workspace by ticking *Copy project into workspace* tick box and click on *Finish.*

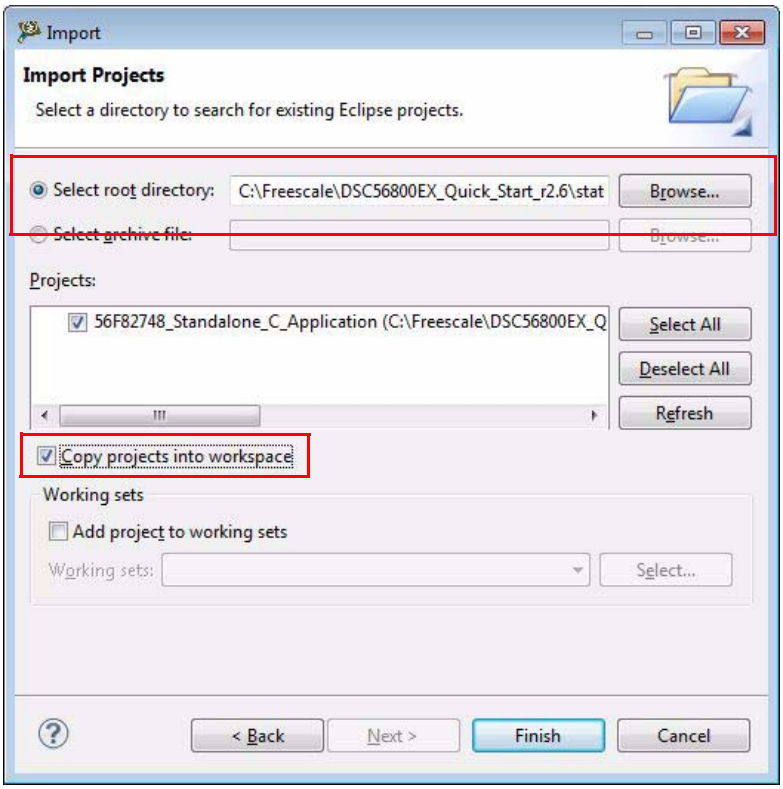


Figure 4-2. Project Import Settings

4. Other method to add the project template to the Workspace is to copy *..\DSC56800EX_Quick_Start_r2.6\stationary\DSC56800EX_Quick_Start_r2.6\MC56F82748\Standalone_C_application* folder to your workspace directory and drag and drop *.project* file to the CodeWarrior Workspace Project Tab.

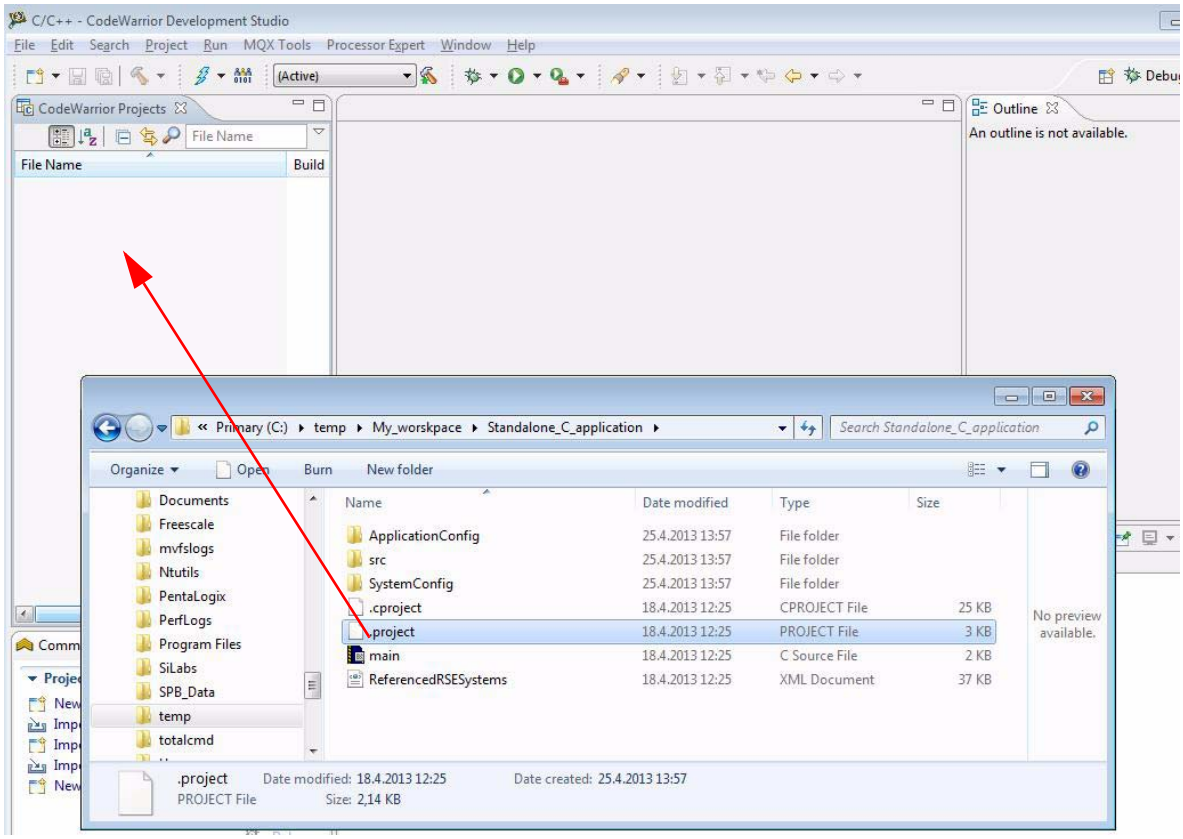


Figure 4-3. Drag & Drop CodeWarrior Project File

NOTE

It is recommended to rename the new project directory something other than default names (C_application or Standalone_C_application) to be able to add other new projects later to the same workspace folder. This step has to be done either prior to the project import or using drag & drop method to add the project to the workspace.

5. Rename the project in CodeWarriror Project tab by right clicking the project and select *Rename* command.
6. If a different directory path is used, the internal variable need to be modified in CodeWarrior preferences. Open project properties Project->Properties.
7. Select Resource->Linked Reources
8. Modify the variable *DSP56800_QS_SRC_260* according to the DSC56800EX_Quick_Start installation folder location and click *OK*.

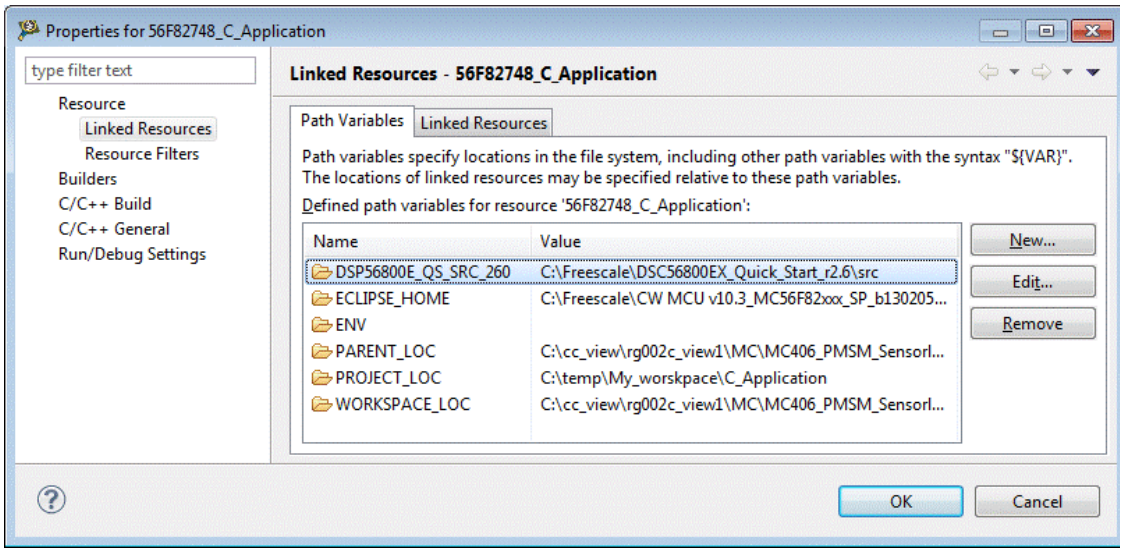


Figure 4-4. DSC56800EX_Quick_Start Variable

9. Clean the project right clicking on the project a choosing *Clean* command.
10. Build the application code by pressing Ctrl+B or choosing Project->Build All command. Check if there is zero errors after the application building.
11. Run the application by pressing the green arrow (Run) or choose the *Run->Run* command from the menu. Select a proper debug interface.

Upon completing all these actions the project window is displayed. The project window contains the predefined file groups as follows:

- **ApplicationConfig** - contains the *appconfig.h* header file.
- **SystemConfig** - contains *startup.c*, *appconfig.c*, *vectors.c*, *linker files* and *debug interface configuration* files.
  - **LinkerFiles** - contains the target specific linker command files *Internal_PFlash_LDM.cmd, Internal_PFlash_SDM.cmd,*
- **src**
  - **Include**- contains header files for the driver source files.
  - MC56F8xxx
    - **Peripheral** - contains chip specific driver source files.
    - **System** - contains *arch.c* and *arch.h* files
  - Support
    - **FreeMASTER** - contains FreeMASTER software support files.

Now, you can start writing your code in the C source file *main.c* and configuring the on-chip peripherals into the include file *appconfig.h*, either manually or by using the Graphical Configuration Tool (GCT). See Chapter 7 for GCT usage.

4.2 On-chip peripheral initialization

The DSC56800EX_Quick_Start provides a very effective mechanism on how to initialize statically all on-chip peripherals. The static configuration of on-chip peripherals is provided by the application specific configuration file *appconfig.h*, in cooperation with the *ioctl* driver commands xx_INIT (xx is the peripheral prefix used in all *ioctl* commands). These commands are for example QT_INIT for Quad Timer, EFPWM_INIT for Pulse Width Modulator, etc.

The configuration file *appconfig.h* is used to define the configuration items, which determine the configuration of the on-chip peripheral. Each configuration item corresponds to one register of the respective on-chip peripheral. The defined configuration items are written to peripheral registers by the *ioctl* driver commands xx_INIT, which are called by the user somewhere in the initialization code of the application.

The step by step procedure to statically initialize the on-chip peripheral, using the DSC56800EX_Quick_Start, is the following:

1. Define configuration items (register values) in the configuration file *appconfig.h*. You can edit the *appconfig.h* file manually or with the Graphical Configuration Tool (GCT). For more information on the GCT, refer to Chapter 7, “Graphical Configuration Tool,” and predefined names of all configuration items can be found in Chapter 5, “On-chip Drivers,” .
2. Initialize the selected on-chip peripheral by calling the xx_INIT *ioctl* command (xx is the peripheral prefix, for example QT_INIT for Quad Timer, EFPWM_INIT for Pulse Width Modulator etc.)

The DSC56800EX_Quick_Start also enables to dynamically initialize on-chip peripherals. The dynamic configuration is fully supported by the *ioctl* commands. See Chapter 5, “On-chip Drivers,” where all *ioctl* commands are described.

Tip: If you are editing the configuration file *appconfig.h* manually, you can copy the template of all configuration items, intended for the *appconfig.h* file from the peripheral module header file *<name_of_driver>.h* (e.g. *intc.h* - Interrupt Controller driver include file, *pwm.h* - Pulse Width Modulation driver include file, etc.). See Example 4-1 where this template for interrupt controller, extracted from the include file *intc.h*, is shown.

Example 4-1. Configuration items for interrupt controller- extract from the driver header file

```
*************************************************************************
    Defines for appconfig.h
*************************************************************************/
/*
    #define INT_VECTOR_ADDR_n       interrupt handler for interrupt n
    #define INT_PRIORITY_LEVEL_n    one of the INTC_DISABLED, INTC_LEVEL0,
                                          INTC_LEVEL1, INTC_LEVEL2 or INTC_LEVEL3

    #define INTC_ICTL_INIT  // initial value of INTC Control Register

    #define INTC_FIM0_INIT  // initial value for Fast Interrupt Match register 0
                               (interrupt number 1-80)
    #define INTC_FIM1_INIT  // initial value for Fast Interrupt Match register 1
                               (interrupt number 1-80)
```

```
        #define INTC_FIVA0_INIT // [optional] addr of fast int. 0 handler
                                // - appropriate INT_VECTOR_ADDR_n used if this is not
                                     specified
        #define INTC_FIVA1_INIT // [optional] addr of fast int. 1 handler
                                // - appropriate INT_VECTOR_ADDR_n used if this is not
                                     specified

    */
```

4.3 On-chip drivers - interface description

The DSC56800EX_Quick_Start includes a set of on-chip drivers which are used to initialize, to configure and to access the on-chip peripherals. The on-chip drivers provide a C language Application Programming Interface (API) to the peripheral module (see Figure 4-5). This interface is common for all input/output operations.

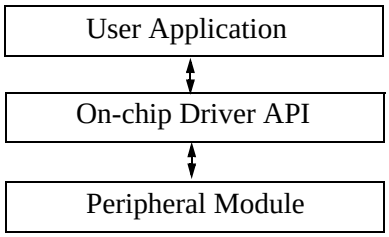


Figure 4-5. User Interface

This interface provides the following API statements:

ioctl - to initialize and to access peripheral module

read - e.g. to receive data

write - e.g. to transmit data

The philosophy of all input/output operations resides in these three statements (commands). These commands provide better code portability between the processors from the same family, where the base addresses of the peripheral modules are different. Therefore it is preferred to use *ioctl*, *read* and *write* commands instead of the direct access to the peripheral module registers. The direct access to the peripheral registers is performed by *periphMemWrite*, *periphMemRead* and other predefined macros described in Section 2.5.

4.3.1 ioctl()

The **ioctl** command is used to initialize a peripheral module (see Section 4.2) and to access a peripheral module. Use of the *ioctl* command provides a very efficient and easy way to access a peripheral module. It increases the code portability and readability and, thus, decrease the number of bugs in the developed code.

The general syntax of the **ioctl** command is as follows:

```
ioctl(peripheral_module_identifier, command, command_specific_parameter);
```

or (if *ioctl* command returns a value):

```
var = ioctl(peripheral_module_identifier, command, command_specific_parameter);
```

Where:

- *Peripheral_module_identifier* parameter is the base address of the peripheral module. Instead of passing the raw base address (e.g. 0xF2D0) you can use the predefined symbolic constants OCCS, QTIMER, INTC etc.
- *Command* parameter specifies the action, which will be performed on the peripheral module. The list of all commands available can be found in Chapter 5, “On-chip Drivers,” .
- *Command_specific_parameter* parameter specifies other data required to execute the command.

Example 4-2. Using ioctl

```
ioctl(GPIO_B, GPIO_SET_PIN, BIT_1 | BIT_2);
ioctl(ADC_A, ADC_START, NULL);
ioctl(QTIMER_A1, QT_CLEAR_FLAG, QT_COMPARE_FLAG);
```

This example shows a miscellaneous ioctl commands. Note, the parameters are: the first one specifies the peripheral module (GPIO_B - General Purpose Input Output B, ADC_A - Analog to Digital Converter A, QTIMER_A1 - timer/counter A1), the second one is the command (GPIO_SET_PIN - to set pin, ADC_START - to start A/D conversion, QT_CLEAR_FLAG - to clear flag) and the third one is the command specific parameter (BIT_1 | BIT_2 - to specify that bits 1 and 2 will be set, NULL - no parameter is used, QT_COMPARE_FLAG - to clear timer compare flag).

See Chapter 5, “On-chip Drivers,” where all *ioctl* commands and their detailed descriptions can be found.

Tip: To see all available ioctl commands and their parameters from within CodeWarrior IDE, just open the appropriate <*name_of_driver*>.*h* include file (e.g. *intc.h* - Interrupt Controller driver include file, *pwm.h* - Pulse Width Modulation driver include file, etc.) and, at the beginning of the file, there is a list of all implemented *ioctl* commands.

4.3.2 read()

The **read()** function reads a specified number of words from the SCI or SPI module to an user allocated buffer. This function can operate in Blocking mode (it waits till end of operation), NonBlocking mode (it exits from the function immediately and the end of operation can be checked by testing the status word) or in Buffered mode (characters are copied from the internal circular buffer).

The syntax of **read()** function call is as follows:

```
read(peripheral_module_identifier, mode_identifier, buffer_pointer, number_of_words);
```

Where:

- *Peripheral_module_identifier* parameter is the same as in *ioctl()*, i.e. the base address of the peripheral module, which can be either SCI or SPI (because only these two peripheral modules can transmit/receive data). The predefined symbolic constants SCI or SPI can be used.
- *Mode_identifier* parameter specifies the mode of operation, which can be BLOCKING, NON_BLOCKING. or BUFFERED.
- *Buffer_pointer* and *number_of_words* parameters specifies the buffer pointer and the number of words, which will be read.

4.3.3 write()

The **write()** function writes a specified number of words to the SCI or SPI module from the user allocated buffer. This function can operate in Blocking mode (it waits for end of operation), NonBlocking mode (it exits from the function immediately and the end of operation can be checked by testing the status word) or in Buffered mode (characters are copied into the internal circular buffer).

The syntax of the **write()** function call is as follows:

```
write(peripheral_module_identifier, mode_identifier, buffer_pointer,
        number_of_words);
```

Where:

- *Peripheral_module_identifier* parameter is the same as in *ioctl()*, i.e. the base address of the peripheral module, which can be either SCI or SPI (because only these two peripheral modules can transmit/receive data). The predefined symbolic constants SCI or SPI can be used.
- *Mode_identifier* parameter specifies the mode of operation, which can be BLOCKING, NON_BLOCKING. or BUFFERED.
- *Buffer_pointer* and *number_of_words* parameters specifies the buffer pointer and the number of words which will be transmitted.

4.4 Interrupts and Interrupt Service Routines

Handling interrupts using the DSC56800EX_Quick_Start is described in detail in Section 2.6. This section contains also a practical guide on how to write a user interrupt service routine.

4.5 *appconfig.h* file

The *appconfig.h* (see the full listing in Example 4-3) include file is the application specific configuration file. It is used to define configuration items and the addresses of the user interrupt service routines (ISRs). The defined configuration items are then used by the *ioctl()* commands xx_INIT to initialize statically the xx peripheral module (e.g. OCCS_INIT to initialize On-chip Clock Synthesis module, QT_INIT to initialize quad timer/counter, etc.). The defined addresses of ISRs are used to install the ISR into the desired interrupt vector, at compilation time.

See Section 4.2 to find out how to initialize on-chip peripheral modules using the *appconfig.h* file and the respective ioctl xx_INIT command.

See Section 2.6.2, “Configuring Interrupts,” for information on installing ISRs and defining the interrupt priorities through the *appconfig.h* file.

Example 4-3. *appconfig.h* from sample application

```
/*****************************************************************************
*
* File Name: appconfig.h
*
* Description: file for static configuration of the application
*              (initial values, interrupt vectors)
*
*****************************************************************************/

#ifndef __APPCONFIG_H
#define __APPCONFIG_H

/*.************************************************************************
*
*  File generated by Graphical Configuration Tool Wed, 06/Mar/2013, 17:23:57
*
************************************************************************.*/

#define MC56F82748
#define EXTCLK 8000000L
#define APPCFG_DFLTS_OMITTED 1
#define APPCFG_GCT_VERSION 0x02060100L

/*.
    OCCS Configuration
----------------------------------------
    Use Factory Trim Value: Yes
    Enable internal 32 kHz oscillator: No
    Power Down crystal oscillator: Yes
    Core frequency: 50 MHz
    VCO frequency: 200 MHz
    Loss of lock interrupt 0: Disable
    Loss of lock interrupt 1: Disable
    Loss of reference clock Interrupt: Disable
.*/
#define OCCS_CTRL_INIT                  0x0081U
#define OCCS_DIVBY_INIT                 0x2018U
#define OCCS_USE_FACTORY_TRIM           1
#define OCCS_USE_FACTORY_TRIM_TEMP      1

/*.
    SYS Configuration
----------------------------------------
    SIM: Power Saving Modes: Stop enabled
    Wait enabled
         OnCE clock to processor core: Enabled when core TAP enabled
    DMA Enable in RUN and WAIT modes: DMA enabled in all power modes
    Enable External Reset Padcell Input Filter : No , SIM - Clock on GPIO: Enable CLKO_0:
    No
    SIM - Clock on GPIO: Enable CLKO_1: No
    SIM - Peripheral Clock Enable: GPIO F: Yes, GPIO E: Yes, GPIO D: No , GPIO C: No , GPIO
    B: No , GPIO A: No , TMR A0: No
    TMR A1: No , TMR A2: No , TMR A3: No , SCI0: No , SCI1: Yes, QSPI0: No , QSPI1: No , IIC0:
    No , FLEXCAN: No
    CMP A: No , CMP B: No , CMP C: No , CMP D: No , CYC ADC: No , CRC: No , QDC: No , PIT0:
    No , PIT1: No , DACA: No , DACB: No
    PWMCH0: Yes, PWMCH1: Yes, PWMCH2: Yes, PWMCH3: Yes, SIM - Modules Enabled in Stop: GPIO
    F: No , SIM - Modules Enabled in Stop: GPIO E: No , SIM - Modules Enabled in Stop: GPIO
    D: No , SIM - Modules Enabled in Stop: GPIO C: No , SIM - Modules Enabled in Stop: GPIO
    B: No , SIM - Modules Enabled in Stop: GPIO A: No
    SIM - Modules Enabled in Stop: TMR A0: No , TMR A1: No , TMR A2: No , TMR A3: No ,
    SCI0: No , SCI1: No , QSPI0: No , QSPI1: No , IIC0: No , FLEXCAN: No
```

```
    CMP A: No , CMP B: No , CMP C: No , CMP D: No , CYC ADC: No , CRC: No , QDC: No , PIT0:
    No , PIT1: No , DACA: No , DACB: No
                                  PWMCH0: No , PWMCH1: No , PWMCH2: No , PWMCH3: No
    Protection of IPS and GPSxx  : Registers not protected
    Protection of PCE, SD and PCR: Registers not protected
    Protection of GPIO Port D: Registers not protected
    Protection of PWRMODE: Registers not protected
    GPIO Peripheral select registers (GPSn): ANA0/CMPA3
                                             ANB1/CMPB_IN0
                                             EXTAL
                                             TXD0
                                             TA0
                                             TA1
                                             DACA
                                             TA2
                                             SS0_B
                                             MOSI0
                                             SCLK0
                                             MOSI0
                                             Reserved
                                             Reserved
                                             TA3
                                             SDA0
                                             SCL0
                                             PWMA_2B
                                             PWMA_2A
                                             PWMA_3B
                                             PWMA_3A
                                             XB_IN6
                                             CLKOUT1
                                             SCL0
                                             SDA0
                                             TXD1
                                             RXD1
                                             Reserved
                                             CMPC_O
                                             RXD0
    Internal Peripheral Select Register 0 (IPS0): GPIOC3
                                                  GPIOC4
                                                  GPIOC6
                                                  GPIOC13
                                                  GPIOC3/GPIOC8/GPIOF8
                                                  GPIOC12/GPIOF5
    Miscellaneous Register 0 (SIM_MISC0): Disable
                                          Disable
                                          CLKIN0 (GPIOC0 alt1)
                                          PIT0 master, PIT1 slave
    SIM - Interrupts: Low voltage 2.2V: Disable
                      Low voltage 2.7V: Disable
                      High voltage 2.2V: Disable
                      High voltage 2.7V: Disable
    Enable Voltage Reference Buffer: No
    Bandgap trim: 7, Use Factory Trim Value: No
.*/
#define SIM_CLKOSR_INIT                  0x1020U
#define SIM_PCE0_INIT                    0x0006U
#define SIM_PCE1_INIT                    0x0802U
#define SIM_PCE2_INIT                    0x0000U
#define SIM_PCE3_INIT                    0x00F0U

/*.
    INTC Configuration
-----------------------------------------
```

```
.*/
#define INTC_ICTL_INIT                  0x0000U
#define INT_VECTOR_ADDR_86              pwm_reload_isr
#define INT_PRIORITY_LEVEL_86           INTC_LEVEL0

/*.
    GPIO_E Configuration
-----------------------------------------
    Pin  0: Function: PWM0B , PullUp: Disable ,
    Pin  1: Function: PWM0A , PullUp: Disable ,
    Pin  2: Function: PWM1B , PullUp: Disable ,
    Pin  3: Function: PWM1A , PullUp: Disable ,
    Pin  4: Function: PWM2B , PullUp: Disable ,
    Pin  5: Function: PWM2A , PullUp: Disable ,
    Pin  6: Function: PWM3B , PullUp: Disable ,
    Pin  7: Function: PWM3A , PullUp: Disable ,
.*/
#define GPIO_E_PER_INIT                 0x00FFU

/*.
    GPIO_F Configuration
-----------------------------------------
    Pin  0: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  1: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  2: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  3: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  4: Function: TXD1 , PullUp: Disable ,
    Pin  5: Function: RXD1 , PullUp: Disable ,
    Pin  6: Function: GPIO , Direction: Output , Init.Value: Low - 0 , Interrupt: Disable,
Int.Polarity: Active high , Output-Mode: Push-pull ,
    Pin  7: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  8: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
.*/
#define GPIO_F_DDR_INIT                 0x0040U
#define GPIO_F_PER_INIT                 0x0030U

/*.
    PWM_A_Common Configuration
-----------------------------------------
    Monitor PLL State: Not locked. No PLL check
    Fault0 Level: Low
    Fault1 Level: Low
    Fault2 Level: Low
    Fault3 Level: Low
    Fault0 Clearing: Manual
    Fault1 Clearing: Manual
    Fault2 Clearing: Manual
    Fault3 Clearing: Manual
    Fault0 Safety Mode: Normal
    Fault1 Safety Mode: Normal
    Fault2 Safety Mode: Normal
    Fault3 Safety Mode: Normal
    Fault Enable Mode: None
    None: None
          None
          None
    Fault Glitch Stretching: Enabled
```

```
Fault Filter Period: 0
Fault Filter Count: 3
Fault 0 Pin: Disable
Fault 1 Pin: Disable
Fault 2 Pin: Disable
Fault 3 Pin: Disable
Submodule 0: Disable Pins PWMA by Fault: Fault 0: No
             Disable Pins PWMA by Fault: Fault 1: No
             Disable Pins PWMA by Fault: Fault 2: No
             Disable Pins PWMA by Fault: Fault 3: No
             Disable Pins PWMB by Fault: Fault 0: No
             Disable Pins PWMB by Fault: Fault 1: No
             Disable Pins PWMB by Fault: Fault 2: No
             Disable Pins PWMB by Fault: Fault 3: No
             Disable Pins PWMX by Fault: Fault 0: No
             Disable Pins PWMX by Fault: Fault 1: No
             Disable Pins PWMX by Fault: Fault 2: No
             Disable Pins PWMX by Fault: Fault 3: No
             Disable Pins PWMX by Fault: PWMA Fault State: Logic 0
             Disable Pins PWMX by Fault: PWMB Fault State: Logic 0
             Disable Pins PWMX by Fault: PWMX Fault State: Logic 0
Submodule 1: Disable Pins PWMA by Fault: Fault 0: No
             Disable Pins PWMA by Fault: Fault 1: No
             Disable Pins PWMA by Fault: Fault 2: No
             Disable Pins PWMA by Fault: Fault 3: No
             Disable Pins PWMB by Fault: Fault 0: No
             Disable Pins PWMB by Fault: Fault 1: No
             Disable Pins PWMB by Fault: Fault 2: No
             Disable Pins PWMB by Fault: Fault 3: No
             Disable Pins PWMX by Fault: Fault 0: No
             Disable Pins PWMX by Fault: Fault 1: No
             Disable Pins PWMX by Fault: Fault 2: No
             Disable Pins PWMX by Fault: Fault 3: No
             Disable Pins PWMX by Fault: PWMA Fault State: Logic 0
             Disable Pins PWMX by Fault: PWMB Fault State: Logic 0
             Disable Pins PWMX by Fault: PWMX Fault State: Logic 0
Submodule 2: Disable Pins PWMA by Fault: Fault 0: No
             Disable Pins PWMA by Fault: Fault 1: No
             Disable Pins PWMA by Fault: Fault 2: No
             Disable Pins PWMA by Fault: Fault 3: No
             Disable Pins PWMB by Fault: Fault 0: No
             Disable Pins PWMB by Fault: Fault 1: No
             Disable Pins PWMB by Fault: Fault 2: No
             Disable Pins PWMB by Fault: Fault 3: No
             Disable Pins PWMX by Fault: Fault 0: No
             Disable Pins PWMX by Fault: Fault 1: No
             Disable Pins PWMX by Fault: Fault 2: No
             Disable Pins PWMX by Fault: Fault 3: No
             Disable Pins PWMX by Fault: PWMA Fault State: Logic 0
             Disable Pins PWMX by Fault: PWMB Fault State: Logic 0
             Disable Pins PWMX by Fault: PWMX Fault State: Logic 0
Submodule 3: Disable Pins PWMA by Fault: Fault 0: No
             Disable Pins PWMA by Fault: Fault 1: No
             Disable Pins PWMA by Fault: Fault 2: No
             Disable Pins PWMA by Fault: Fault 3: No
             Disable Pins PWMB by Fault: Fault 0: No
             Disable Pins PWMB by Fault: Fault 1: No
             Disable Pins PWMB by Fault: Fault 2: No
             Disable Pins PWMB by Fault: Fault 3: No
             Disable Pins PWMX by Fault: Fault 0: No
             Disable Pins PWMX by Fault: Fault 1: No
             Disable Pins PWMX by Fault: Fault 2: No
             Disable Pins PWMX by Fault: Fault 3: No
```

```
                Disable Pins PWMX by Fault: PWMA Fault State: Logic 0
                Disable Pins PWMX by Fault: PWMB Fault State: Logic 0
                Disable Pins PWMX by Fault: PWMX Fault State: Logic 0
.*/
#define PWM_A_MCTRL_INIT                  0x0F01U
#define PWM_A_MCTRL2_INIT                 0x0000U
#define PWM_A_OUTEN_INIT                  0x0FF0U

/*.
    PWM_A_0 Configuration
-----------------------------------------
    Debug Mode Operation: Stop
    Wait Mode Operation: Stop
    Load Mode: End cycle
    Load OK: Yes
    PWM Clock Enable: Yes
    Clock Source: IPBus Clock
    Prescaler: fclk/1
    INIT register: -1700
    VAL1 register: 1699
    Fraction (FRACVAL1): 0
    Sync. source: Local sync (PWMX)
    Reload source: This module
    Reload Frequency: Every 16 opportunity
    Half Cycle Reload: Disable
    Full Cycle Reload: Enable
    PWMA Mask: Normal
    PWMB Mask: Normal
    PWMX Mask: Normal
    PWMA Output Polarity: Active High
    PWMB Output Polarity: Active High
    PWMX Output Polarity: Active High
    PWMA Output enable: Enabled
    PWMB Output enable: Enabled
    PWMX Output enable: Disabled
    PWMA and PWMB Pair Operation: Complementary
    Initialize value registers: Disable
    Value 0: Disable
    Value1: Disable
    Value 2: Disable
    Value3: Disable
    Value 4: Disable
    Value5: Disable
    Double Switching: PWM23
    Deadtime count 1: 0
    Software Controlled Output: Logic 0
                                Logic 0
    Force Initialization Enable: No
    Source of FORCE OUTPUT signal: Local force CTRL2[FORCE]
    Dead Time Source 23: PWM23
    Dead Time Source 45: PWM45
    PWM45 Initial Value: Logic 0
                         Logic 0
    PWMX Initial Value: Logic 0
    Reload: Enable
    Reload Error: Disable
    Value 0 Compare: Disable
    Value 1 Compare: Disable
    Value 2 Compare: Disable
    Value 3 Compare: Disable
    Value 4 Compare: Disable
    Value 5 Compare: Disable
    Capture A0: Disable
```

```
    Capture A1: Disable
    Capture B0: Disable
    Capture B1: Disable
    Capture X0: Disable
    Capture X1: Disable
    Capture A Input select: Raw PWMA input
    Capture B Input select: Raw PWMA input
    Capture X Input select: Raw PWMA input
    One Shot mode enable: Disable
                          Disable
                          Disable
    Edge Counter Enable: Disable
                         Disable
                         Disable
    Edge Compare A Value: 0
    Edge Compare B Value: 0
    Edge Compare X Value: 0
    Capture A0 Edge Select: Disabled
    Capture A1 Edge Select: Disabled
    Capture B0 Edge Select: Disabled
    Capture B1 Edge Select: Disabled
    Capture X0 Edge Select: Disabled
    Capture X1 Edge Select: Disabled
    PWMX Double Switching Enable: Disable
    Capture A0: Disable
    Capture A1: Disable
    Capture B0: Disable
    Capture B1: Disable
    Capture X0: Disable
    Capture X1: Disable
    Source of capture DMA: DMA disabled
    Enable DMA Write Requests For alue Registers: No
    Output Trigger 0 Source: PWM_OUT_TRIG0
    Output Trigger 1 Source: PWM_OUT_TRIG1
.*/
#define PWM_A_0_CTRL_INIT                0xF400U
#define PWM_A_0_CTRL2_INIT               0x0000U
#define PWM_A_0_INIT_INIT                0xF95CU
#define PWM_A_0_VAL1_INIT                0x06A3U
#define PWM_A_0_VAL0_INIT                0x0000U
#define PWM_A_0_VAL2_INIT                0x0000U
#define PWM_A_0_VAL3_INIT                0x0000U
#define PWM_A_0_VAL4_INIT                0x0000U
#define PWM_A_0_VAL5_INIT                0x0000U
#define PWM_A_0_FRACVAL2_INIT            0x0000U
#define PWM_A_0_FRACVAL3_INIT            0x0000U
#define PWM_A_0_FRACVAL4_INIT            0x0000U
#define PWM_A_0_FRACVAL5_INIT            0x0000U
#define PWM_A_0_DTCNT0_INIT              0x0000U
#define PWM_A_0_DTCNT1_INIT              0x0000U
#define PWM_A_0_INTEN_INIT               0x1000U
#define PWM_A_0_DISMAP0_INIT             0xF000U

/*.
    PWM_A_1 Configuration
-------------------------------------------
    Debug Mode Operation: Stop
    Wait Mode Operation: Stop
    Load Mode: End cycle
    Load OK: No
    PWM Clock Enable: Yes
    Clock Source: PWM_0 clock
    Prescaler: fclk/1
```

```
INIT register: -1700
VAL1 register: 1699
Fraction (FRACVAL1): 0
Sync. source: Master sync (PWM_0)
Reload source: PWM_0 module
Reload Frequency: Every opportunity
Half Cycle Reload: Disable
Full Cycle Reload: Enable
PWMA Mask: Normal
PWMB Mask: Normal
PWMX Mask: Normal
PWMA Output Polarity: Active High
PWMB Output Polarity: Active High
PWMX Output Polarity: Active High
PWMA Output enable: Enabled
PWMB Output enable: Enabled
PWMX Output enable: Disabled
PWMA and PWMB Pair Operation: Complementary
Initialize value registers: Disable
Value 0: Disable
Value1: Disable
Value 2: Disable
Value3: Disable
Value 4: Disable
Value5: Disable
Double Switching: PWM23
Deadtime count 1: 0
Software Controlled Output: Logic 0
                            Logic 0
Force Initialization Enable: No
Source of FORCE OUTPUT signal: Local force CTRL2[FORCE]
Dead Time Source 23: PWM23
Dead Time Source 45: PWM45
PWM45 Initial Value: Logic 0
                     Logic 0
PWMX Initial Value: Logic 0
Reload: Disable
Reload Error: Disable
Value 0 Compare: Disable
Value 1 Compare: Disable
Value 2 Compare: Disable
Value 3 Compare: Disable
Value 4 Compare: Disable
Value 5 Compare: Disable
Capture A0: Disable
Capture A1: Disable
Capture B0: Disable
Capture B1: Disable
Capture X0: Disable
Capture X1: Disable
Capture A Input select: Raw PWMA input
Capture B Input select: Raw PWMA input
Capture X Input select: Raw PWMA input
One Shot mode enable: Disable
                       Disable
                       Disable
Edge Counter Enable: Disable
                     Disable
                     Disable
Edge Compare A Value: 0
Edge Compare B Value: 0
Edge Compare X Value: 0
Capture A0 Edge Select: Disabled
```

```
    Capture A1 Edge Select: Disabled
    Capture B0 Edge Select: Disabled
    Capture B1 Edge Select: Disabled
    Capture X0 Edge Select: Disabled
    Capture X1 Edge Select: Disabled
    PWMX Double Switching Enable: Disable
    Capture A0: Disable
    Capture A1: Disable
    Capture B0: Disable
    Capture B1: Disable
    Capture X0: Disable
    Capture X1: Disable
    Source of capture DMA: DMA disabled
    Enable DMA Write Requests For alue Registers: No
    Output Trigger 0 Source: PWM_OUT_TRIG0
    Output Trigger 1 Source: PWM_OUT_TRIG1
.*/
#define PWM_A_1_CTRL_INIT                0x0400U
#define PWM_A_1_CTRL2_INIT               0x0206U
#define PWM_A_1_INIT_INIT                0xF95CU
#define PWM_A_1_VAL1_INIT                0x06A3U
#define PWM_A_1_VAL0_INIT                0x0000U
#define PWM_A_1_VAL2_INIT                0x0000U
#define PWM_A_1_VAL3_INIT                0x0000U
#define PWM_A_1_VAL4_INIT                0x0000U
#define PWM_A_1_VAL5_INIT                0x0000U
#define PWM_A_1_FRACVAL2_INIT            0x0000U
#define PWM_A_1_FRACVAL3_INIT            0x0000U
#define PWM_A_1_FRACVAL4_INIT            0x0000U
#define PWM_A_1_FRACVAL5_INIT            0x0000U
#define PWM_A_1_DTCNT0_INIT              0x0000U
#define PWM_A_1_DTCNT1_INIT              0x0000U
#define PWM_A_1_DISMAP0_INIT             0xF000U

/*.
    PWM_A_2 Configuration
-------------------------------------------
    Debug Mode Operation: Stop
    Wait Mode Operation: Stop
    Load Mode: End cycle
    Load OK: No
    PWM Clock Enable: Yes
    Clock Source: PWM_0 clock
    Prescaler: fclk/1
    INIT register: -1700
    VAL1 register: 1699
    Fraction (FRACVAL1): 0
    Sync. source: Master sync (PWM_0)
    Reload source: PWM_0 module
    Reload Frequency: Every opportunity
    Half Cycle Reload: Disable
    Full Cycle Reload: Enable
    PWMA Mask: Normal
    PWMB Mask: Normal
    PWMX Mask: Normal
    PWMA Output Polarity: Active High
    PWMB Output Polarity: Active High
    PWMX Output Polarity: Active High
    PWMA Output enable: Enabled
    PWMB Output enable: Enabled
    PWMX Output enable: Disabled
    PWMA and PWMB Pair Operation: Complementary
    Initialize value registers: Disable
```

```
    Value 0: Disable
    Value1: Disable
    Value 2: Disable
    Value3: Disable
    Value 4: Disable
    Value5: Disable
    Double Switching: PWM23
    Deadtime count 1: 0
    Software Controlled Output: Logic 0
                                Logic 0
    Force Initialization Enable: No
    Source of FORCE OUTPUT signal: Local force CTRL2[FORCE]
    Dead Time Source 23: PWM23
    Dead Time Source 45: PWM45
    PWM45 Initial Value: Logic 0
                         Logic 0
    PWMX Initial Value: Logic 0
    Reload: Disable
    Reload Error: Disable
    Value 0 Compare: Disable
    Value 1 Compare: Disable
    Value 2 Compare: Disable
    Value 3 Compare: Disable
    Value 4 Compare: Disable
    Value 5 Compare: Disable
    Capture A0: Disable
    Capture A1: Disable
    Capture B0: Disable
    Capture B1: Disable
    Capture X0: Disable
    Capture X1: Disable
    Capture A Input select: Raw PWMA input
    Capture B Input select: Raw PWMA input
    Capture X Input select: Raw PWMA input
    One Shot mode enable: Disable
                          Disable
                          Disable
    Edge Counter Enable: Disable
                         Disable
                         Disable
    Edge Compare A Value: 0
    Edge Compare B Value: 0
    Edge Compare X Value: 0
    Capture A0 Edge Select: Disabled
    Capture A1 Edge Select: Disabled
    Capture B0 Edge Select: Disabled
    Capture B1 Edge Select: Disabled
    Capture X0 Edge Select: Disabled
    Capture X1 Edge Select: Disabled
    PWMX Double Switching Enable: Disable
    Capture A0: Disable
    Capture A1: Disable
    Capture B0: Disable
    Capture B1: Disable
    Capture X0: Disable
    Capture X1: Disable
    Source of capture DMA: DMA disabled
    Enable DMA Write Requests For alue Registers: No
    Output Trigger 0 Source: PWM_OUT_TRIG0
    Output Trigger 1 Source: PWM_OUT_TRIG1
.*/
#define PWM_A_2_CTRL_INIT                0x0400U
#define PWM_A_2_CTRL2_INIT               0x0206U
```

```
#define PWM_A_2_INIT_INIT                0xF95CU
#define PWM_A_2_VAL1_INIT                0x06A3U
#define PWM_A_2_VAL0_INIT                0x0000U
#define PWM_A_2_VAL2_INIT                0x0000U
#define PWM_A_2_VAL3_INIT                0x0000U
#define PWM_A_2_VAL4_INIT                0x0000U
#define PWM_A_2_VAL5_INIT                0x0000U
#define PWM_A_2_FRACVAL2_INIT            0x0000U
#define PWM_A_2_FRACVAL3_INIT            0x0000U
#define PWM_A_2_FRACVAL4_INIT            0x0000U
#define PWM_A_2_FRACVAL5_INIT            0x0000U
#define PWM_A_2_DTCNT0_INIT              0x0000U
#define PWM_A_2_DTCNT1_INIT              0x0000U
#define PWM_A_2_DISMAP0_INIT             0xF000U

/*.
    PWM_A_3 Configuration
-------------------------------------------
    Debug Mode Operation: Stop
    Wait Mode Operation: Stop
    Load Mode: End cycle
    Load OK: No
    PWM Clock Enable: Yes
    Clock Source: IPBus Clock
    Prescaler: fclk/1
    INIT register: 0
    VAL1 register: 3700
    Fraction (FRACVAL1): 0
    Sync. source: Master sync (PWM_0)
    Reload source: PWM_0 module
    Reload Frequency: Every opportunity
    Half Cycle Reload: Disable
    Full Cycle Reload: Enable
    PWMA Mask: Normal
    PWMB Mask: Normal
    PWMX Mask: Normal
    PWMA Output Polarity: Active High
    PWMB Output Polarity: Active High
    PWMX Output Polarity: Active High
    PWMA Output enable: Enabled
    PWMB Output enable: Enabled
    PWMX Output enable: Disabled
    PWMA and PWMB Pair Operation: Independent
    Initialize value registers: Disable
    Value 0: Disable
    Value1: Disable
    Value 2: Disable
    Value3: Disable
    Value 4: Disable
    Value5: Disable
    Software Controlled Output: Logic 0
                                Logic 0
    Force Initialization Enable: No
    Source of FORCE OUTPUT signal: Local force CTRL2[FORCE]
    Dead Time Source 23: PWM23
    Dead Time Source 45: PWM45
    PWM45 Initial Value: Logic 0
                         Logic 0
    PWMX Initial Value: Logic 0
    Reload: Disable
    Reload Error: Disable
    Value 0 Compare: Disable
    Value 1 Compare: Disable
```

```
    Value 2 Compare: Disable
    Value 3 Compare: Disable
    Value 4 Compare: Disable
    Value 5 Compare: Disable
    Capture A0: Disable
    Capture A1: Disable
    Capture B0: Disable
    Capture B1: Disable
    Capture X0: Disable
    Capture X1: Disable
    Capture A Input select: Raw PWMA input
    Capture B Input select: Raw PWMA input
    Capture X Input select: Raw PWMA input
    One Shot mode enable: Disable
                          Disable
                          Disable
    Edge Counter Enable: Disable
                         Disable
                         Disable
    Edge Compare A Value: 0
    Edge Compare B Value: 0
    Edge Compare X Value: 0
    Capture A0 Edge Select: Disabled
    Capture A1 Edge Select: Disabled
    Capture B0 Edge Select: Disabled
    Capture B1 Edge Select: Disabled
    Capture X0 Edge Select: Disabled
    Capture X1 Edge Select: Disabled
    PWMX Double Switching Enable: Disable
    Capture A0: Disable
    Capture A1: Disable
    Capture B0: Disable
    Capture B1: Disable
    Capture X0: Disable
    Capture X1: Disable
    Source of capture DMA: DMA disabled
    Enable DMA Write Requests For alue Registers: No
    Output Trigger 0 Source: PWM_OUT_TRIG0
    Output Trigger 1 Source: PWM_OUT_TRIG1
.*/
#define PWM_A_3_CTRL_INIT                0x0400U
#define PWM_A_3_CTRL2_INIT               0x2204U
#define PWM_A_3_INIT_INIT                0x0000U
#define PWM_A_3_VAL1_INIT                0x0E74U
#define PWM_A_3_VAL0_INIT                0x0000U
#define PWM_A_3_VAL2_INIT                0x0000U
#define PWM_A_3_VAL3_INIT                0x0000U
#define PWM_A_3_VAL4_INIT                0x0000U
#define PWM_A_3_VAL5_INIT                0x0000U
#define PWM_A_3_FRACVAL2_INIT            0x0000U
#define PWM_A_3_FRACVAL3_INIT            0x0000U
#define PWM_A_3_FRACVAL4_INIT            0x0000U
#define PWM_A_3_FRACVAL5_INIT            0x0000U
#define PWM_A_3_DISMAP0_INIT             0xF000U

/*.
    SCI_1 Configuration
-----------------------------------------
    Baudrate: 9601 bps
    Enable Receiver: Enable
    Enable Transmitter: Enable
    Data word length: 8 bits
    Parity: None
```

```
    Polarity: True polarity
    Loop mode: Disable
    Function in Wait Mode: SCI module enabled in Wait Mode
    Interrupts: RX Full: Disable
                RX Error: Disable
                TX Empty: Disable
                TX Empty: Disable
    Enable RX and TX FIFO Queues: Disable
    RX Active Edge: Disable
    Enable TX DMA: Disable
    Enable RX DMA: Disable
    Hold off entry to stop mode: No
    Rx Idle Interrupt enabled: Disable
.*/
#define SCI_1_SCIBR_INIT                    0x0A2CU
#define SCI_1_SCICR_INIT                    0x000CU
#define SCI_1_SCICR2_INIT                   0x0000U
#define SCI_1_RX_BUFFER_OKLIMIT             0x000FU
#define SCI_1_RX_BUFFER_LOWLIMIT            0x000AU
#define SCI_1_SCICR3_INIT                   0x0000U

/*.
    FMSTR Configuration
-----------------------------------------
.*/
#define FMSTR_COMM_INTERFACE                2
#define FMSTR_LONG_INTR                     0
#define FMSTR_SHORT_INTR                    0
#define FMSTR_POLL_DRIVEN                   1
#define FMSTR_USE_SCOPE                     1
#define FMSTR_USE_RECORDER                  1


/*.         End of autogenerated code
********************************************************************** ..*/

#endif
```

Chapter 5 On-chip Drivers

One of the DSP56800EX_Quick_Start tool strengths is that it provides a high degree of architectural and hardware independence for the application code. This portability is achieved by the modular design of DSP56800EX_Quick_Start, which in this case, isolates all chip-specific functionality into a set of defined, tested, and documented Application Programming Interface (API).

This chapter describes the API for on-chip drivers, forming the interface between hardware and application software. The source code - implementation can be found at ***<...>\src\MC56F8xxx\peripheral*** of the DSP56800EX_Quick_Start. It defines the API by identifying all public interface functions-commands and data structures.

The DSP56800EX_Quick_Start on-chip driver's API is implemented as a *low level device driver interface*. The low level device driver interface was chosen mainly for its efficiency and also because it enables the complete use of the hardware functionality. Yet another reason is the non standardized approach regarding the usage of most of the on-chip peripheral modules. The portability of the low level device driver interface is not influenced so much by the lower abstraction level, but mainly by the capability of the peripheral module hardware. In other words, the portability between devices is ensured, and involves the same or a very similar implementation of the peripheral module hardware. When the peripheral modules on target devices are significantly different, the portability is much lower. Nevertheless, even in this case, the overall application might be built differently to reflect the hardware capability.

The general introductory description of on-chip drivers can be found in Section 4.3. The following list contains useful tips.

On-chip drivers usage considerations:

- ***Peripheral module hardware and functionality knowledge.***
  The only efficient and, in some cases, safe usage of the on-chip peripheral module is based on the user knowledge about the module itself. A comprehensive description can be found in the **MC56F8xxx Reference Manual**, **MC56F8xxx Data Sheet** and in various Freescale Application Notes (ANs). The way in which the on-chip driver's API is designed takes into consideration the entire hardware capability. The self-explaining names of the driver commands help users find the desired hardware feature.
- ***On-chip driver commands implemented as macros.***
  Almost all commands are implemented as efficient C function-like macros. The exceptions are the initialization commands and the read/write commands of the SPI and the SCI, which are implemented as regular functions. This is documented in every detailed description of each command.
  Implementation of most commands as macros is not only done for the sake of efficiency. The other advantage is ease of use within the interrupt service routine, where the unwanted overhead (i.e. jump/return to/from function plus context store/restore) is eliminated. Further, the consistent implementation of commands takes care of the used instructions, mainly as a result of the proper usage of the read-modify-write instructions. These uninterruptible instructions are essential for safety when accessing the control and peripheral registers.

- ***Efficient use of the driver commands.***
  The general form of the driver command is the following:

  ```
  ioctl(peripheral_module_identifier,command,command_specific_parameter);
  ```

  Where, the *Peripheral_module_identifier* parameter is the base address of the peripheral module. The predefined symbolic constants, like OCCS, PWM_A, INTC, ENC etc., should be used.
  The *Command* parameter specifies the action, which will be performed on the peripheral module. It represents the command name as it is implemented for each on-chip driver.
  The *Command_specific_parameter* parameter specifies other data required to execute the command. Generally speaking, it can be a pointer to the structure, the NULL value, or a variable-value depending on the specific command. If the required parameter is a variable-value, users should make use of a constant value if possible, because it affects the efficiency of the resulting code. The efficiency is illustrated by the following examples:

  ```
  ioctl( PWM_A, PWM_SET_MODULO, 0x30ff ); //constant used
  ```

results in:

```
move.l   0xf145,R0                        or:
move.w   #12543,X:(R0)                    move.w   #12543,X:0xf145
```

while the following code sequence

```
val = 32767;
...
ioctl( PWM_A, PWM_SET_MODULO, val ); //variable used
```

results in:

```
move.w   #32767,X:0x003012
...
move.l   0x003012,R1
move.l   0xf145,R0                        or:
move.w   X:(R1),A                         move.w   #32767,A
move.w   A1,X:(R0)                        move.w   A1,X:0xf145
```

Another possibility is to use the predefined symbolic constants to express the desired action, like:

```
ioctl( PWM_A, PWM_RELOAD_INT, PWM_ENABLE );
```

which results in:

```
move.l   0xf140,R0                        or:
bfset   #0x20,X:(R0)                      bfset   #0x20,X:0xf140
```

The predefined symbols or constants should be used whenever possible.

NOTE

Some macros expand to a single assembly instruction (as illustrated above). Other macros expand to a more assembly instructions, e.g. the different mode setting where it is necessary to clear the previous setting and then, to set the new mode. Assembly insructions are illustrated by the following example:

```
ioctl( PWM_A, PWM_SET_PRESCALER, PWM_PRESCALER_DIV_2 );

        move.l   0xf140,R0                      or:
        bfclr   #0xc0,X:(R0)                    bfclr   #0xc0,X:0xf140
        bfset   #0x40,X:(R0)                    bfset   #0x40,X:0xf140
```

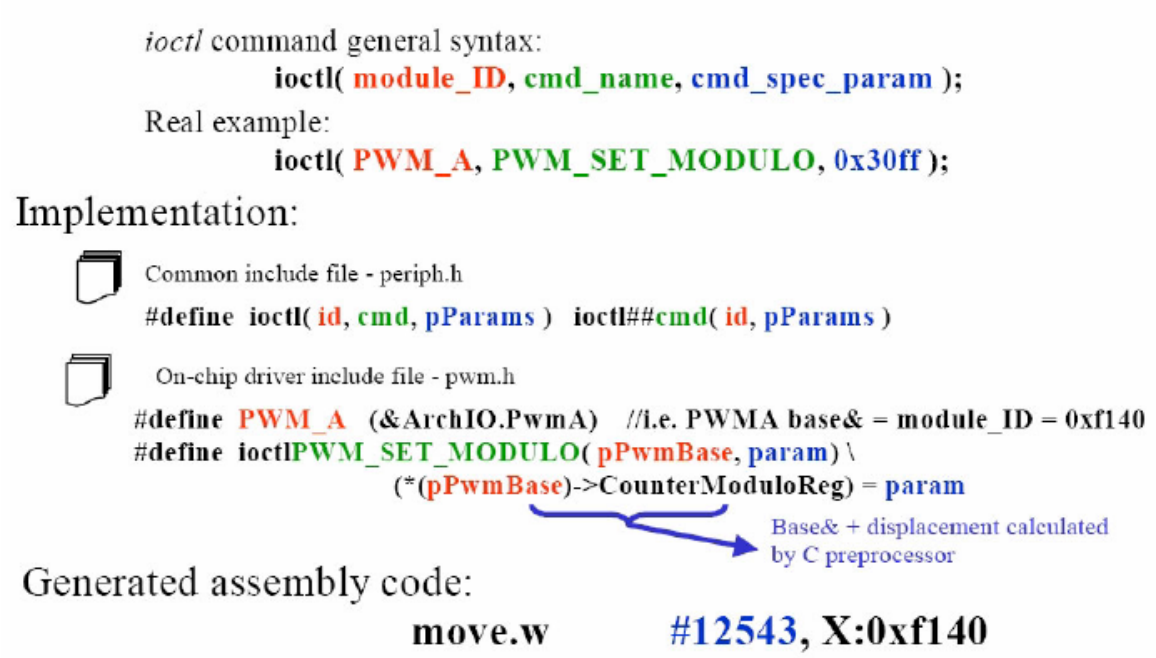
Note that the generated code depends on the selected compiler optimizations, on the rest of the source code, and on the selected target.

Even longer commands can be implemented. These commands incorporate a functionality that is higher than a simple access to the peripheral registers. An example of a higher functionality are commands which perform the mathematical calculations for data scaling to fit the results into the desired data range. Specifically, a higher functionality is exemplified by recounting of the PWM duty cycle in percentage of the actual value to be written to the PWM Value register.

Example 5-1. Implementation details

Figure 5-1 is intended to illustrate the macro expansion process. In this example, each corresponding item is represented by its matching color.

Figure 5-1. Macro Expansion Process



5.1 API Specification

This section briefly describes API macros and functions.

Function arguments for each routine are described as *in*, *out*, or *inout*.

1. *in* argument means that the parameter value is an input to the function only.
2. *out* argument means that the parameter value is an output from the function only.
3. *inout* argument means that a parameter value is an input to the function, but the same parameter is also an output from the function.

Note: *inout* parameters are typically input pointer variables in which the caller passes the address of a pre-allocated data structure to a function. The function stores its results within that data structure. The actual value of the *inout* pointer parameter is not changed.

ioctl call(s):

The *ioctl* call is generally represented by the following form:

```
UWord16 ioctl(const int *pModuleBase, void cmd, UWord16 param);
UWord16 ioctl(const int *pModuleBase, void cmd, void *pParam);
```

Description: The *ioctl* call “changes” peripheral module modes or accesses the module register(s). Keep in mind that *ioctl* is treated as macro and that in result it is mostly compiled to an optimal inline code.

NOTE

There are three types of ioctl commands:

1. Single-Instruction ioctl commands are translated into one assembler instruction. These commands write parameter configuration directly into the peripheral register.
2. Multi-Instruction ioctl commands are translated into several assembler instructions. The performing of these commands can be broken by the interrupt occurrence. These commands write parameter configuration directly into the peripheral register.
3. Software Layer ioctl commands are translated into several assembler instructions. The performing of these commands can be broken by the interrupt occurrence. These commands represent additional software functionality for complex peripheral control.

Arguments:

Table 5-1. Driver Arguments - ioctl

pModuleBase	in	Module identifier e.g. OCCS.
cmd	in	Command name
pParam	in, inout	Used to pass the relevant data to ioctl function call.

Items Separators Convention:

```
/  only one of the specified items is allowed
```

```
|  consolidation of items is allowed ( item1 | item2 | item3 ) &  intersection of items is
allowed ( item1 & item2 & item3 )
```

Device Driver Support

Command tables contain two columns **“56F82xxx”** and **“56F84xxx”.** The tick defines the command support for particular DSC members.

5.1.1 12-bit Cyclic Analog-to-Digital Converter (ADC) Driver

The analog-to-digital (ADC) converter function consists of two separate analog-to-digital converters, each with eight analog inputs and its own sample and hold circuit. A common digital control module configures and controls the functioning of the converters.

The Table 5-2 shows module identifiers for ADC Driver.

Table 5-2. Identifiers for ADC Driver

Module identifier	56F82xxx	56F84xxx
ADC	✓	
ADC_1		✓

The Table 5-3 shows all commands dedicated for ADC Driver.

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_AUTO_POWERDOWN_MODE	ADC_ON/ADC_OFF	Switch on/off ADC Auto Power Down saving mode in the Power Control Register.	✓	✓
ADC_AUTO_STANDBY_MODE	ADC_ON/ADC_OFF	Enable/disable Auto Standby Mode in the Power Control Register	✓	✓
ADC_CLEAR_HIGH_LIMIT_STATUS12_BITS	UWord32; any combination of ADC_HLSx bits (x=0-19)	Clear selected bits in the ADC High Limit Status Registers 1 and 2.	✓	
ADC_CLEAR_HIGH_LIMIT_STATUS2_BITS	UWord16; any combination of ADC_HLSx bits (x=16-19)	Clear selected bits in the ADC High Limit Status Register 2.	✓	
ADC_CLEAR_LIMIT_STATUS_HLS	UWord16 sample number 0-15	Clear the Low Limit Status Register LLSx bit (Low Limit Sample x flag).	✓	✓
ADC_CLEAR_LIMIT_STATUS_LLS	UWord16 sample number 0-15	Clear the High Limit Status Register HLSx bit (High Limit Sample x flag).	✓	✓
ADC_CLEAR_LIMIT_STATUS12_HLS	UWord16 sample number 0-19	Clear all bits of the ADC high limit status register 1 and 2	✓	
ADC_CLEAR_LIMIT_STATUS12_LLS	UWord16 sample number 0-19	Clear all bits of the ADC low limit status register 1 and 2	✓	
ADC_CLEAR_LIMIT_STATUS2_HLS	UWord16 sample number 16-19	Clear the High Limit Status Register HLSx bit (High Limit Sample x flag).	✓	
ADC_CLEAR_LIMIT_STATUS2_LLS	UWord16 sample number 16-19	Clear the Low Limit Status Register LLSx bit (Low Limit Sample x flag).	✓	

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_CLEAR_LOW_LIMIT_STATUS12_BITS	UWord32; any combination of ADC_LLSx bits (x=0-19)	Clear selected bits in the ADC Low Limit Status Registers 1 and 2.	✓	
ADC_CLEAR_LOW_LIMIT_STATUS2_BITS	UWord16; any combination of ADC_LLSx bits (x=16-19)	Clear selected bits in the ADC Low Limit Status Register 2.	✓	
ADC_CLEAR_STATUS_EOSI	NULL / ADC_CONVERTER_0|ADC_CONVERTER_1	Clear selected ADC EOSI status in the Control Register.	✓	✓
ADC_CLEAR_STATUS_HLMTI	NULL	Clear all HILIM status bits in the High Limit Status Register.	✓	✓
ADC_CLEAR_STATUS_LLMTI	NULL	Clear all LOLIM status bits in the Low Limit Status Register.	✓	✓
ADC_CLEAR_STATUS_ZCI	NULL	Clear all ZCI status bits in the Zero Crossing Status Register.	✓	✓
ADC_CLEAR_STATUS12_HLMTI	NULL	Clear all HILIM status bits for all samples 0-19 in the High Limit Status Registers 1 and 2.	✓	
ADC_CLEAR_STATUS12_LLMTI	NULL	Clear all LOLIM status bits for all samples 0-19 in the Low Limit Status Registers 1 and 2.	✓	
ADC_CLEAR_STATUS12_ZCI	NULL	Clear all ZCI status bits for all samples 0-19 in the Zero Crossing Status Registers 1 and 2.	✓	
ADC_CLEAR_STATUS2_HLMTI	NULL	Clear all HILIM status bits for samples 16-19 in the High Limit Status Register 2.	✓	
ADC_CLEAR_STATUS2_LLMTI	NULL	Clear all LOLIM status bits for samples 16-19 in the Low Limit Status Register 2.	✓	
ADC_CLEAR_STATUS2_ZCI	NULL	Clear all ZCI status bits for samples 16-19 in the Zero Crossing Status Register 2.	✓	
ADC_CLEAR_ZERO_CROSS_STATUS_ZCS	UWord16 sample number 0-15	Clear the High Limit Status Register ZCSx bit (Zero Crossing x flag).	✓	✓
ADC_CLEAR_ZERO_CROSS_STATUS12_ZCS	UWord16 sample number 0-19	Clear all bits of the ADC zero crossing status register 2	✓	
ADC_CLEAR_ZERO_CROSS_STATUS2_ZCS	UWord16 sample number 16-19	Clear the Zero Cross Status Register ZCSx bit (Zero Cross Sample x flag).	✓	

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_DMAEN	ADC_CONVERTER_0/ADC_CONVERTER_1	Enable ADC DMA in the Control Register.	✓	✓
ADC_END_OF_SCAN_INT	ADC_ENABLE_CONVERTER_0/ADC_DISABLE_CONVERTER_0/ADC_ENABLE_CONVERTER_1/ADC_DISABLE_CONVERTER_1	Enable/disable the ADC End of Scan interrupt; this command has no effect in loop mode.	✓	✓
ADC_GET_LIMIT_STATUS_HLS	UWord16 sample number 0-15	Read the High Limit Status Register HLSx bit (High Limit Sample x flag).	✓	✓
ADC_GET_LIMIT_STATUS_LLS	UWord16 sample number 0-15	Read the Low Limit Status Register LLSx bit (Low Limit Sample x flag).	✓	✓
ADC_GET_LIMIT_STATUS12_HLS	UWord16 sample number 0-19	Read the Low Limit Status Register HLSx bit (High Limit Sample x flag).	✓	
ADC_GET_LIMIT_STATUS12_LLS	UWord16 sample number 0-19	Read the Low Limit Status Register LLSx bit (Low Limit Sample x flag).	✓	
ADC_GET_LIMIT_STATUS2_HLS	UWord16 sample number 16-19	Read the Low Limit Status Register HLSx bit (High Limit Sample x flag).	✓	
ADC_GET_LIMIT_STATUS2_LLS	UWord16 sample number 16-19	Read the Low Limit Status Register LLSx bit (Low Limit Sample x flag).	✓	
ADC_GET_POWER_STATUS	ADC_CONVERTER_0|ADC_CONVERTER_1	Read and test the power status of selected ADC converters.	✓	✓
ADC_GET_STATUS_CIP	NULL	Read the Status Register CIP bit in the Status Register.	✓	✓
ADC_GET_STATUS_EOSI	NULL / ADC_CONVERTER_0|ADC_CONVERTER_1	Read the Status Register EOSI bit in the Status Register.	✓	✓
ADC_GET_STATUS_HLMTI	NULL	Read the Status Register HLMTI bit in the Status Register.	✓	✓
ADC_GET_STATUS_LLMTI	NULL	Read the Status Register LLMTI bit in the Status Register.	✓	✓
ADC_GET_STATUS_RDY	UWord16 sample number 0-15	Read the Status Register 1 RDYx bit (Ready Sample 0-15 flag).	✓	✓
ADC_GET_STATUS_RDY12	UWord16 sample number 0-19	Read the Status Register 1 and 2 RDYx bit (Ready Sample 0-19 flag).	✓	✓
ADC_GET_STATUS_RDY2	UWord16 sample number 16-19	Read the Status Register 2 RDYx bit (Ready Sample 16-19 flag).	✓	

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_GET_STATUS_RDY2	UWord16 sample number 16-19	Read the Status Register 2 RDYx bit (Ready Sample 16-19 flag).	✓	
ADC_GET_STATUS_ZCI	NULL	Read the Status Register ZCI bit in the Status Register.	✓	✓
ADC_GET_ZERO_CROSS_STATUS_ZCS	UWord16 sample number 0-15	Read the Zero Crossing Status Register ZCSx bit (Zero Crossing x flag).(ADC_ZXSTAT->_)	✓	✓
ADC_GET_ZERO_CROSS_STATUS12_ZCS	UWord16 sample number 0-19	Read the Zero Crossing Status Register ZCSx bit (Zero Crossing x flag).	✓	
ADC_GET_ZERO_CROSS_STATUS2_ZCS	UWord16 sample number 16-19	Read the Zero Crossing Status Register ZCSx bit (Zero Crossing x flag).	✓	
ADC_INIT	NULL	Initialize ADC periheral registers using the appconfig.h _INIT values.	✓	✓
ADC_INT_DISABLE	ADC_END_OF_SCAN|ADC_ZERO_CROSS|ADC_LOW_LIMIT|ADC_HIGH_LIMIT|ADC_END_OF_SCAN_CONVERTER_0|ADC_END_OF_SCAN_CONVERTER_1	Disable selected ADC interrupts.	✓	✓
ADC_INT_ENABLE	ADC_END_OF_SCAN|ADC_ZERO_CROSS|ADC_LOW_LIMIT|ADC_HIGH_LIMIT|ADC_END_OF_SCAN_CONVERTER_0|ADC_END_OF_SCAN_CONVERTER_1	Enable selected ADC interrupts.	✓	✓
ADC_POWER_DOWN	ADC_CONVERTER_0|ADC_CONVERTER_1	Power down the selected ADC converters and the voltage reference.	✓	✓
ADC_POWER_UP	ADC_CONVERTER_0|ADC_CONVERTER_1	Power up the selected ADC converters and the voltage reference.	✓	✓
ADC_READ_ALL_SAMPLES	adc_tBuff* (pointer to results buffer)	Read the first 16 sample results at a time. Sample results are copied to user allocated 16 word buffer.	✓	✓
ADC_READ_ALL_SAMPLES2	adc_tBuff* (pointer to results buffer)	Read sample results 16-19 at a time. Sample results are copied to user allocated 4 word buffer.	✓	
ADC_READ_GAIN_CONTROL_1_REG	NULL	Read and return the value of Gain Control Register 1.	✓	✓

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_READ_GAIN_CONTROL_2_REG	NULL	Read and return the value of Gain Control Register 2.	✓	✓
ADC_READ_GAIN_CONTROL_3_REG	NULL	Read and return the value of Gain Control Register 3.	✓	
ADC_READ_HIGH_LIMIT	UWord16 sample number 0-15	Read and return the value of ADC High Limit Register for sample defined by parameter.	✓	✓
ADC_READ_HIGH_LIMIT_STATUS12	NULL	Read and return values of ADC High Limit Status registers 1 and 2	✓	
ADC_READ_HIGH_LIMIT_STATUS2	NULL	Read and return the value of High Limit Status Register 2	✓	
ADC_READ_HIGH_LIMIT12	UWord16 sample number 0-19	Read and return the value of ADC High Limit Register for sample defined by parameter.	✓	
ADC_READ_HIGH_LIMIT2	UWord16 sample number 16-19	Read and return the value of ADC High Limit Register for sample defined by parameter.	✓	
ADC_READ_LOW_LIMIT	UWord16 sample number 0-15	Read and return the value of ADC Low Limit Register for sample defined by parameter.	✓	✓
ADC_READ_LOW_LIMIT_STATUS12	NULL	Read and return values of ADC Low Limit Status registers 1 and 2	✓	
ADC_READ_LOW_LIMIT_STATUS2	NULL	Read and return the value of Low Limit Status Register 2	✓	
ADC_READ_LOW_LIMIT12	UWord16 sample number 0-19	Read and return the value of ADC Low Limit Register for sample defined by parameter.	✓	
ADC_READ_LOW_LIMIT2	UWord16 sample number 16-19	Read and return the value of ADC Low Limit Register for sample defined by parameter.	✓	
ADC_READ_OFFSET	UWord16	Read and return the value of ADC Offset Register. The number of the sample which the offset value belongs to is determined by the parameter.	✓	✓
ADC_READ_OFFSET12	UWord16 sample number 0-19	Read and return the value of ADC Offset Register for sample defined by parameter.	✓	

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_READ_OFFSET2	UWord16 sample number 16-19	Read and return the value of ADC Offset Register for sample defined by the parameter.	✓	
ADC_READ_POWER_CONTROL_2_REG	NULL	Read and return value of Power Control Register 2.	✓	✓
ADC_READ_POWER_CONTROL_REG	NULL	Read and return the value of ADC Power Control Register.	✓	✓
ADC_READ_SAMPLE	UWord16 sample number (0-15)	Read Result Register. The sample number is determined by parameter 0-15.	✓	✓
ADC_READ_SAMPLE12	UWord16 sample number (0-19)	Read Result Register. This is universal command and works for samples 0-19.	✓	✓
ADC_READ_SAMPLE2	UWord16 sample number (16-19)	Read Result Register for extended sample numbers. The sample number is determined by parameter 16-19.	✓	✓
ADC_READ_SCAN_CONTROL_REG	NULL	Read and return the value of Scan Control Register.	✓	✓
ADC_READ_SCAN_CONTROL_REG2	NULL	Read and return the value of Scan Control Register 2.	✓	
ADC_READ_SCAN_HALTED_INTERRUPT_REG	NULL	Read and return the value of Scan Halted Interrupt Enable Register.	✓	✓
ADC_READ_SCAN_HALTED_INTERRUPT_REG2	NULL	Read and return the value of Scan Halted Interrupt Enable Register 2.	✓	
ADC_READ_STATUS	NULL	Read and return the value of ADC Status Register.	✓	✓
ADC_READ_ZERO_CROSS_STATUS	NULL	Read the ADC Zero Crossing Status Register.	✓	✓
ADC_READ_ZERO_CROSS_STATUS12	NULL	Read and return values of ADC Zero Cross Status registers 1 and 2	✓	
ADC_READ_ZERO_CROSS_STATUS2	NULL	Read and return the value of Zero Cross Status Register 2	✓	
ADC_SET_ADCA6_INPUT	ADC_ANALOG_INPUT|ADC_NORMAL_OPERATION	Set On-Chip Analog Input Alternate Source.	✓	

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_SET_ADCA7_INPUT	ADC_TEMPERATURE_SENSOR|ADC_NORMAL_OPERATION	Set On-Chip Analog Input Alternate Source.	✓	
ADC_SET_ADCB_DIVISOR_PARALEL_MODE	UWord16 or one of ADC_DIVx	Set ADC module ANB clock divisor in parallel mode which determines ADC conversion speed.		✓
ADC_SET_ADCB6_INPUT	ADC_ANALOG_INPUT|ADC_NORMAL_OPERATION	Set On-Chip Analog Input Alternate Source.	✓	
ADC_SET_ADCB7_INPUT	ADC_TEMPERATURE_SENSOR|ADC_NORMAL_OPERATION	Set On-Chip Analog Input Alternate Source.	✓	
ADC_SET_ANA0_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANA0 input.	✓	✓
ADC_SET_ANA1_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANA1 input.	✓	✓
ADC_SET_ANA10_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANA10 input.	✓	
ADC_SET_ANA16_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANA16 input.	✓	
ADC_SET_ANA17_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANA17 input.	✓	
ADC_SET_ANA2_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANA2 input.	✓	✓
ADC_SET_ANA3_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANA3 input.	✓	✓
ADC_SET_ANA4_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANA4 input.	✓	✓
ADC_SET_ANA5_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANA5 input.	✓	✓
ADC_SET_ANA6_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANA6 input.	✓	✓
ADC_SET_ANA7_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANA7 input.	✓	✓
ADC_SET_ANA9_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANA9 input.	✓	
ADC_SET_ANB0_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANB0 input.	✓	✓
ADC_SET_ANB1_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANB1 input.	✓	✓
ADC_SET_ANB10_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANB10 input.	✓	
ADC_SET_ANB18_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANB18 input.	✓	

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_SET_ANB19_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANB19 input.	✓	
ADC_SET_ANB2_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANB2 input.	✓	✓
ADC_SET_ANB3_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANB3 input.	✓	✓
ADC_SET_ANB4_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANB4 input.	✓	✓
ADC_SET_ANB5_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANB5 input.	✓	✓
ADC_SET_ANB6_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANB6 input.	✓	✓
ADC_SET_ANB7_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANB7 input.	✓	✓
ADC_SET_ANB9_GAIN	ADC_GAIN_x (x=1/2/4)	Selects channel gain for ANB9 input.	✓	
ADC_SET_CALIB_SOURCE	ADC_ANA7_xxx or ADC_ANB7_xxx (xxx=NORMAL/FROM_DAC0/FROM_DAC0_PASSTHRU)	Select internal source of ANA7 and ANB7 inputs in the ADC Calibration Register.	✓	✓
ADC_SET_CHANNEL_CONFIG	ADC_ANAx_ANAy_zzz (xy=01|23|45|67; zzz=SE|DIFF)	Configure the analog inputs for either single ended or differential conversions.	✓	✓
ADC_SET_DIVISOR	UWord16 5-bit value or one of ADC_DIVxx	Clock Divisor Select.	✓	✓
ADC_SET_DMA_TRIGGER	ADC_DMA_TRIGGER_END_SCAN/ADC_DMA_TRIGGER_RDY	Select between EOSI0 and RDY bits as the DMA source.	✓	✓
ADC_SET_LIST_SAMPLE0	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 0.	✓	✓
ADC_SET_LIST_SAMPLE1	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 1.	✓	✓
ADC_SET_LIST_SAMPLE10	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 10.	✓	✓
ADC_SET_LIST_SAMPLE11	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 11.	✓	✓
ADC_SET_LIST_SAMPLE12	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 12.	✓	✓
ADC_SET_LIST_SAMPLE13	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 13.	✓	✓

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_SET_LIST_SAMPLE14	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 14.	✓	✓
ADC_SET_LIST_SAMPLE15	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 15.	✓	✓
ADC_SET_LIST_SAMPLE16	ADCx_TEMPERATURE_SENSOR|ADCx_ANALOG_INPUT (x=A,B)	Set mapping of the physical ADC input to the sample 16.	✓	
ADC_SET_LIST_SAMPLE17	ADCx_TEMPERATURE_SENSOR|ADCx_ANALOG_INPUT (x=A,B)	Set mapping of the physical ADC input to the sample 17.	✓	
ADC_SET_LIST_SAMPLE18	ADCx_TEMPERATURE_SENSOR|ADCx_ANALOG_INPUT (x=A,B)	Set mapping of the physical ADC input to the sample 18.	✓	
ADC_SET_LIST_SAMPLE19	ADCx_TEMPERATURE_SENSOR|ADCx_ANALOG_INPUT (x=A,B)	Set mapping of the physical ADC input to the sample 19.	✓	
ADC_SET_LIST_SAMPLE2	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 2.	✓	✓
ADC_SET_LIST_SAMPLE3	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 3.	✓	✓
ADC_SET_LIST_SAMPLE4	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 4.	✓	✓
ADC_SET_LIST_SAMPLE5	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 5.	✓	✓
ADC_SET_LIST_SAMPLE6	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 6.	✓	✓
ADC_SET_LIST_SAMPLE7	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 7.	✓	✓
ADC_SET_LIST_SAMPLE8	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 8.	✓	✓
ADC_SET_LIST_SAMPLE9	one of ADC_ANAx/ADC_ANBx	Set mapping of the physical ADC input to the sample 9.	✓	✓
ADC_SET_MAX_SPEED_ADCA	ADC_SPEED_xxx (xxx=5MHZ/10MHZ/15MHZ/20MHZ)	Set maximum clock speed of the part ADCA		✓

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_SET_MAX_SPEED_ADCB	ADC_SPEED_xxx (xxx=5MHZ/10MHZ/15MHZ/ 20MHZ)	Set maximum clock speed of the part ADCB		✓
ADC_SET_POWER_UP_DELAY	UWord16 value 0-63	Set power up delay in Power Control Register.	✓	✓
ADC_SET_SAMPLE_BY_SYNC	ADC_SAMPLEx (x=0-15)	Set converter to delay sample x until a new sync signal occurs.	✓	✓
ADC_SET_SAMPLE_BY_SYNC12	ADC_SAMPLEx (x=0-19)	Set converter to delay sample x until a new sync signal occures.	✓	
ADC_SET_SAMPLE_BY_SYNC2	ADC_SAMPLEx (x=16-19)	Set converter to delay sample x until a new sync signal occures.	✓	
ADC_SET_SAMPLE_IMMEDIATELY	ADC_SAMPLEx (x=0-15)	Clear the delay condition and set converter to immediately take the sample x after completion of previous sample.	✓	✓
ADC_SET_SAMPLE_IMMEDIATELY12	ADC_SAMPLEx (x=0-19)	Clear the delay condition and set converter to immediately take the sample x after completion of previous sample.	✓	
ADC_SET_SAMPLE_IMMEDIATELY2	ADC_SAMPLEx (x=16-19)	Clear the delay condition and set converter to immediately take the sample x after completion of previous sample.	✓	
ADC_SET_SCAN_HALTED_INTERRUPT_DISABLE	Any combination of ADC_SAMPLEx (x=0-15)	Disable Scan Halted Interrupt for selected samples.	✓	✓
ADC_SET_SCAN_HALTED_INTERRUPT_DISABLE12	Any combination of ADC_SAMPLEx (x=0-19)	Disable Scan Halted Interrupt for selected samples.	✓	
ADC_SET_SCAN_HALTED_INTERRUPT_DISABLE2	Any combination of ADC_SAMPLEx (x=16-19)	Disable Scan Halted Interrupt for selected samples.	✓	
ADC_SET_SCAN_HALTED_INTERRUPT_ENABLE	Any combination of ADC_SAMPLEx (x=0-15)	Enable Scan Halted Interrupt for selected samples.	✓	✓
ADC_SET_SCAN_HALTED_INTERRUPT_ENABLE12	Any combination of ADC_SAMPLEx (x=0-19)	Enable Scan Halted Interrupt for selected samples.	✓	
ADC_SET_SCAN_HALTED_INTERRUPT_ENABLE2	Any combination of ADC_SAMPLEx (x=16-19)	Enable Scan Halted Interrupt for selected samples.	✓	

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_SET_SCAN_MODE	ADC_SCAN_xxx (xxx=ONCE_SEQUENTIAL/ ONCE_SIMULTANEOUS/LO OP_SEQUENTIAL/LOOP_SI MULTA-NEOUS/TRIG_SEQUENTIA L/TRIG_SIMULTANEOUS)	Set Scan Mode Control.	✓	✓
ADC_SET_UNIPOLAR_CHANNEL	ADC_ANAx_ANAy_zzz_DIF F (xy=01|23|45|67; zzz=FULLY/UNIPOLAR)	Enable the Unipolar differential or Fully differential mode according to the parameter.	✓	
ADC_SIMULT	ADC_ON/ADC_OFF	Select simultaneous or independent parallel scan mode in the Control Reg-ister 2.	✓	✓
ADC_START	NULL/ADC_CONVERTER_0 /ADC_CONVERTER_1	Start ADC conversion in software.	✓	✓
ADC_STOP	ADC_ON/ADC_OFF/ADC_O N_CONVERTER_0/ADC_O N_CONVERTER_1/ADC_OF F_CONVERTER_0/ADC_OF F_CONVERTER_1	Set the ADC to normal operation (ADC_ON) or to stop mode (ADC_OFF).	✓	✓
ADC_SYNC	ADC_ON/ADC_OFF/ADC_O N_CONVERTER_0/ADC_O N_CONVERTER_1/ADC_OF F_CONVERTER_0/ADC_OF F_CONVERTER_1	Select the ADC conversion START source - SYNC input (ADC_ON) or ADC_START command (ADC_OFF).	✓	✓
ADC_TEST_INT_ENABLED	ADC_END_OF_SCAN/ADC_ ZERO_CROSS/ADC_LOW_ LIMIT/ADC_HIGH_LIMIT/AD C_END_OF_SCAN_CONVE RTER_0/ADC_END_OF_SC AN_CONVERTER_1	Return non-zero if any of interrupts specified in parameter are enabled.	✓	✓
ADC_WRITE_CHANNEL_LIST1	ADC_ANAx_Sy (x=0-7; y=0-3) | ADC_ANBx_Sy(x=0-7; y=0-3)	Configures mapping of the physical inputs ANA0-ANA7 or ANA0-ANA7 to samples 0-3.	✓	✓
ADC_WRITE_CHANNEL_LIST2	ADC_ANAx_Sy (x=0-7; y=4-7) | ADC_ANBx_Sy(x=0-7; y=4-7)	Configures mapping of the physical inputs ANA0-ANA7 or ANA0-ANA7 to samples 4-7.	✓	✓

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_WRITE_CHANNEL_LIST3	ADC_ANAx_Sy (x=0-7; y=8-11) | ADC_ANBx_Sy(x=0-7; y=8-11)	Configures mapping of the physical inputs ANA0-ANA7 or ANA0-ANA7 to samples 8-11.	✓	
ADC_WRITE_CHANNEL_LIST4	ADC_ANAx_Sy (x=0-7; y=12-15) | ADC_ANBx_Sy(x=0-7; y=12-15)	Configures mapping of the physical inputs ANA0-ANA7 or ANA0-ANA7 to samples 12-15.	✓	
ADC_WRITE_CHANNEL_LIST5	ADCx_yyy_Sz (x=A,B; yyy=TEMPERATURE_SENSOR/ANALOG_INPUT; z=16-19)	Write ADC channel list 5 register. Modify the ADC Channel List Register 5	✓	
ADC_WRITE_GAIN_CONTROL_1_REG	UWord16	Write the Gain Control Register 1.	✓	✓
ADC_WRITE_GAIN_CONTROL_2_REG	UWord16	Write the Gain Control Register 2.	✓	✓
ADC_WRITE_GAIN_CONTROL_3_REG	UWord16	Write the Gain Control Register 3.	✓	
ADC_WRITE_HIGH_LIMIT0	UWord16	Write High Limit Register for sample 0.	✓	✓
ADC_WRITE_HIGH_LIMIT1	UWord16	Write High Limit Register for sample 1.	✓	✓
ADC_WRITE_HIGH_LIMIT10	UWord16	Write High Limit Register for sample 10.	✓	✓
ADC_WRITE_HIGH_LIMIT11	UWord16	Write High Limit Register for sample 11.	✓	✓
ADC_WRITE_HIGH_LIMIT12	UWord16	Write High Limit Register for sample 12.	✓	✓
ADC_WRITE_HIGH_LIMIT13	UWord16	Write High Limit Register for sample 13.	✓	✓
ADC_WRITE_HIGH_LIMIT14	UWord16	Write High Limit Register for sample 14.	✓	✓
ADC_WRITE_HIGH_LIMIT15	UWord16	Write High Limit Register for sample 15.	✓	✓
ADC_WRITE_HIGH_LIMIT16	UWord16	Write High Limit Register for sample 16.	✓	
ADC_WRITE_HIGH_LIMIT17	UWord16	Write High Limit Register for sample 17.	✓	

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_WRITE_HIGH_LIMIT18	UWord16	Write High Limit Register for sample 18.	✓	
ADC_WRITE_HIGH_LIMIT19	UWord16	Write High Limit Register for sample 19.	✓	
ADC_WRITE_HIGH_LIMIT2	UWord16	Write High Limit Register for sample 2.	✓	✓
ADC_WRITE_HIGH_LIMIT3	UWord16	Write High Limit Register for sample 3.	✓	✓
ADC_WRITE_HIGH_LIMIT4	UWord16	Write High Limit Register for sample 4.	✓	✓
ADC_WRITE_HIGH_LIMIT5	UWord16	Write High Limit Register for sample 5.	✓	✓
ADC_WRITE_HIGH_LIMIT6	UWord16	Write High Limit Register for sample 6.	✓	✓
ADC_WRITE_HIGH_LIMIT7	UWord16	Write High Limit Register for sample 7.	✓	✓
ADC_WRITE_HIGH_LIMIT8	UWord16	Write High Limit Register for sample 8.	✓	✓
ADC_WRITE_HIGH_LIMIT9	UWord16	Write High Limit Register for sample 9.	✓	✓
ADC_WRITE_LOW_LIMIT0	UWord16	Write Low Limit Register for sample 0.	✓	✓
ADC_WRITE_LOW_LIMIT1	UWord16	Write Low Limit Register for sample 1.	✓	✓
ADC_WRITE_LOW_LIMIT10	UWord16	Write Low Limit Register for sample 10.	✓	✓
ADC_WRITE_LOW_LIMIT11	UWord16	Write Low Limit Register for sample 11.	✓	✓
ADC_WRITE_LOW_LIMIT12	UWord16	Write Low Limit Register for sample 12.	✓	✓
ADC_WRITE_LOW_LIMIT13	UWord16	Write Low Limit Register for sample 13.	✓	✓
ADC_WRITE_LOW_LIMIT14	UWord16	Write Low Limit Register for sample 14.	✓	✓
ADC_WRITE_LOW_LIMIT15	UWord16	Write Low Limit Register for sample 15.	✓	✓
ADC_WRITE_LOW_LIMIT16	UWord16	Write Low Limit Register for sample 16.	✓	

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_WRITE_LOW_LIMIT17	UWord16	Write Low Limit Register for sample 17.	✓	
ADC_WRITE_LOW_LIMIT18	UWord16	Write Low Limit Register for sample 18.	✓	
ADC_WRITE_LOW_LIMIT19	UWord16	Write Low Limit Register for sample 19.	✓	
ADC_WRITE_LOW_LIMIT2	UWord16	Write Low Limit Register for sample 2.	✓	✓
ADC_WRITE_LOW_LIMIT3	UWord16	Write Low Limit Register for sample 3.	✓	✓
ADC_WRITE_LOW_LIMIT4	UWord16	Write Low Limit Register for sample 4.	✓	✓
ADC_WRITE_LOW_LIMIT5	UWord16	Write Low Limit Register for sample 5.	✓	✓
ADC_WRITE_LOW_LIMIT6	UWord16	Write Low Limit Register for sample 6.	✓	✓
ADC_WRITE_LOW_LIMIT7	UWord16	Write Low Limit Register for sample 7.	✓	✓
ADC_WRITE_LOW_LIMIT8	UWord16	Write Low Limit Register for sample 8.	✓	✓
ADC_WRITE_LOW_LIMIT9	UWord16	Write Low Limit Register for sample 9.	✓	✓
ADC_WRITE_OFFSET0	UWord16	Write Offset Register for sample 0.	✓	✓
ADC_WRITE_OFFSET1	UWord16	Write Offset Register for sample 1.	✓	✓
ADC_WRITE_OFFSET10	UWord16	Write Offset Register for sample 10.	✓	✓
ADC_WRITE_OFFSET11	UWord16	Write Offset Register for sample 11.	✓	✓
ADC_WRITE_OFFSET12	UWord16	Write Offset Register for sample 12.	✓	✓
ADC_WRITE_OFFSET13	UWord16	Write Offset Register for sample 13.	✓	✓
ADC_WRITE_OFFSET14	UWord16	Write Offset Register for sample 14.	✓	✓
ADC_WRITE_OFFSET15	UWord16	Write Offset Register for sample 15.	✓	✓
ADC_WRITE_OFFSET16	UWord16	Write Offset Register for sample 16.	✓	
ADC_WRITE_OFFSET17	UWord16	Write Offset Register for sample 17.	✓	

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_WRITE_OFFSET18	UWord16	Write Offset Register for sample 18.	✓	
ADC_WRITE_OFFSET19	UWord16	Write Offset Register for sample 19.	✓	
ADC_WRITE_OFFSET2	UWord16	Write Offset Register for sample 2	✓	✓
ADC_WRITE_OFFSET3	UWord16	Write Offset Register for sample 3.	✓	✓
ADC_WRITE_OFFSET4	UWord16	Write Offset Register for sample 4.	✓	✓
ADC_WRITE_OFFSET5	UWord16	Write Offset Register for sample 5.	✓	✓
ADC_WRITE_OFFSET6	UWord16	Write Offset Register for sample 6.	✓	✓
ADC_WRITE_OFFSET7	UWord16	Write Offset Register for sample 7.	✓	✓
ADC_WRITE_OFFSET8	UWord16	Write Offset Register for sample 8.	✓	✓
ADC_WRITE_OFFSET9	UWord16	Write Offset Register for sample 9.	✓	✓
ADC_WRITE_POWER_CONTROL_2_REG	UWord16	Write Power Control Register 2.	✓	✓
ADC_WRITE_SAMPLE_DISABLE	UWord16 0-15 or any combination of ADC_SAMPLEx (x=0-15)	Set the number of samples in scan sequence.	✓	✓
ADC_WRITE_SAMPLE_DISABLE12	UWord16 0-19 or any combination of ADC_SAMPLEx (x=0-19)	Set the number of samples in scan sequence.	✓	
ADC_WRITE_SAMPLE_DISABLE2	UWord16 16-19 or any combination of ADC_SAMPLEx (x=15-19)	Set the number of samples in scan sequence.	✓	
ADC_WRITE_SCAN_CONTROL_REG	UWord16	Write Scan Control Register.	✓	✓
ADC_WRITE_SCAN_CONTROL_REG2	UWord16	Write Scan Control Register 2.	✓	
ADC_WRITE_SCAN_HALTED_INTERRUPT_REG	UWord16	Write Scan Halted Interrupt Enable Register.	✓	✓
ADC_WRITE_SCAN_HALTED_INTERRUPT_REG2	UWord16	Write Scan Halted Interrupt Enable Register 2.	✓	

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_WRITE_ZERO_CROSS_CNTRL	ADC_Sx_ZC_xxx (x=0-7; xxx=DISABLE/POSITIVE_NEGATIVE/NEGATIVE_POSITIVE/ANY_CROSS)	Configure zero crossing detection logic for selected samples.	✓	✓
ADC_WRITE_ZERO_CROSS_CNTRL1	ADC_Sx_ZC1_xxx (x=0-7; xxx=DISABLE/POSITIVE_NEGATIVE/NEGATIVE_POSITIVE/ANY_CROSS)	Configure zero crossing detection logic for selected samples.	✓	✓
ADC_WRITE_ZERO_CROSS_CNTRL2	ADC_Sx_ZC2_xxx (x=8-15; xxx=DISABLE/POSITIVE_NEGATIVE/NEGATIVE_POSITIVE/ANY_CROSS)	Configure zero crossing detection logic for selected samples.	✓	✓
ADC_ZERO_CROSS_CH0	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 0.	✓	✓
ADC_ZERO_CROSS_CH1	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 1.	✓	✓
ADC_ZERO_CROSS_CH10	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 10.	✓	✓
ADC_ZERO_CROSS_CH11	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 11.	✓	✓
ADC_ZERO_CROSS_CH12	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 12.	✓	✓
ADC_ZERO_CROSS_CH13	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 13.	✓	✓
ADC_ZERO_CROSS_CH14	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 14.	✓	✓
ADC_ZERO_CROSS_CH15	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 15.	✓	✓

Table 5-3. ADC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC_ZERO_CROSS_CH2	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 2.	✓	✓
ADC_ZERO_CROSS_CH3	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 3.	✓	✓
ADC_ZERO_CROSS_CH4	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 4.	✓	✓
ADC_ZERO_CROSS_CH5	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 5.	✓	✓
ADC_ZERO_CROSS_CH6	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 6.	✓	✓
ADC_ZERO_CROSS_CH7	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 7.	✓	✓
ADC_ZERO_CROSS_CH8	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 8.	✓	✓
ADC_ZERO_CROSS_CH9	ADC_ZC_xxx (xxx=DISABLE/POS2NEG/NEG2POS/BOTH)	Configure zero crossing detection logic for sample 9.	✓	✓

5.1.2 16-bit SAR Analog-to-Digital Converter (ADC16)

The 16-bit analog-to-digital (ADC16) converter is based on the linear successive approximation algorithm with up to 16-bit resolution. The ADC16 resolution can be set to 16-bit, 12-bit, 10-bit, and 8-bit modes. The results are right-justified unsigned format for single-ended. The converter includes up to 24 single-ended external analog inputs.

The ADC16 provides the following features:

- Single or continuous conversion which means the automatic return to idle after a single conversion
- Configurable sample time and conversion speed/power
- Conversion complete/hardware average complete flag and interrupt
- Input clock selectable from up to four sources
- Operation in Low-Power modes for lower noise
- Asynchronous clock source for lower noise operation with option to output the clock
- Selectable hardware conversion trigger with hardware channel select
- Automatic compare with interrupt for less-than, greater-than or equal-to, within range, or out-of-range, programmable value
- Temperature sensor
- Hardware average function
- Selectable voltage reference: external or alternate
- Self-Calibration mode

The Table 5-4 shows module identifiers for ADC16 Driver.

Table 5-4. Identifiers for ADC16 Driver

Module identifier	56F82xxx	56F84xxx
ADC16		✓

The Table 5-5 shows all commands dedicated for ADC16 Driver.

Table 5-5. ADC16 Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC16_CALIBRATION_START	NULL	Start the calibration sequence.		✓
ADC16_CLEAR_CALIBRATION_FAILED_FLAG	NULL	Clear the Calibration Failed flag.		✓

Table 5-5. ADC16 Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC16_INIT	NULL	Initialize the ADC16 peripheral registers using the appconfig.h _INIT values.		✓
ADC16_READ_CFG1_REG	NULL	Read and return value of the Configuration register 1 as UWord16.		✓
ADC16_READ_CFG2_REG	NULL	Read and return value of the Configuration register 2 as UWord16.		✓
ADC16_READ_CLP0_REG	NULL	Read and return the Plus-Side General Calibration Value 0 register as Uword16.		✓
ADC16_READ_CLP1_REG	NULL	Read and return the Plus-Side General Calibration Value 1 register as UWord16.		✓
ADC16_READ_CLP2_REG	NULL	Read and return the Plus-Side General Calibration Value 2 register as UWord16.		✓
ADC16_READ_CLP3_REG	NULL	Read and return the Plus-Side General Calibration Value 3 register as UWord16.		✓
ADC16_READ_CLP4_REG	NULL	Read and return the Plus-Side General Calibration Value 4 register as UWord16.		✓
ADC16_READ_CLPD_REG	NULL	Read and return the Plus-Side General Calibration Value register as UWord16.		✓
ADC16_READ_CLPS_REG	NULL	Read and return the Plus-Side General Calibration Value register as UWord16.		✓
ADC16_READ_CV1_REG	NULL	Read and return value of Compare Value 1 register as UWord16.		✓
ADC16_READ_CV2_REG	NULL	Read and return value of Compare Value 2 register as UWord16.		✓
ADC16_READ_OFS_REG	NULL	Read and return the Offset register as UWord16.		✓
ADC16_READ_PLUS_SIDE_GAIN_REG	NULL	Read and return the Plus-Side Gain register as UWord16.		✓

Table 5-5. ADC16 Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC16_READ_RESULT	NULL	Read and return the ADC data result (RA register) as UWord16. The return value contains the result of an ADC conversion of the channel selected by the ADC16_SET_INPUT_CHANNEL ioctl command.		✓
ADC16_READ_SC1_REG	NULL	Read and return value of the Status and Control register 1 as UWord16.		✓
ADC16_READ_SC2_REG	NULL	Read and return value of the Status and Control register 2 as UWord16.		✓
ADC16_READ_SC3_REG	NULL	Read and return value of the Status and Control register 3 as UWord16.		✓
ADC16_SELECT_LONG_SAMPLE_TIME	ADC16_xxx (xxx=24ADCK/16ADCK/10ADCK/6ADCK)	Select between the extended sample times when long sample time is enabled by using ADC16_SET_LONG_SAMPLE_TIME ioctl command.		✓
ADC16_SET_ASSIST_TRIGGER	ADC16_ENABLE/ADC16_DISABLE	Enable/disable writes to ADCSC1 COCO bit to be reflected on ADTRG register bit.		✓
ADC16_SET_ASYNCH_CLOCK_OUT	ADC16_ENABLE/ADC16_DISABLE	Enable/disable the asynchronous clock source and output regardless of the conversion and status of CFG1[ADICLK]. Based on MCU configuration, the asynchronous clock may be used by other modules. See the chip configuration information.		✓
ADC16_SET_CLOCK_INPUT	ADC16_CLOCK_SEL_xxx (xxx=BUS/BUS_DIV2/ALTCLK/ADATCK)	Select the ADC input clock source to generate the internal ADCK clock.		✓
ADC16_SET_COMPARE_FUNCTION	ADC16_ENABLE/ADC16_DISABLE	Enable/disable the compare function of the conversion result.		✓
ADC16_SET_COMPARE_FUNCTION_MODE	ADC16_xxx (xxx=LESS_THAN/GREATER_THAN_OR_EQUAL/RANGE_NON_INCLUSIVE/RANGE_INCLUSIVE)	Set compare function mode. For the RANGE modes, the selection whether inside or outside of range is compared depends on relation of CV1 and CV2 values.		✓
ADC16_SET_CONVERSION_MODE	ADC16_CONV_xxx (xxx=SINGLE/CONTINUOUS)	Select the conversion mode. When the HW average is enabled, the conversion is completed when the average is calculated and COCO is set.		✓

Table 5-5. ADC16 Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC16_SET_CONVERSION_TRIGGER	ADC16_SW_TRIGGER/ADC16_HW_TRIGGER	Set the type of trigger used for initiating a conversion. Use ADC16_SW_TRIGGER when a conversion is initiated by writing to SC1A register. Use ADC16_HW_TRIGGER when a conversion is initiated by the assertion of the ADHWT input after a pulse of the ADHWTSn input.		✓
ADC16_SET_DIVIDER	ADC16_CLOCK_DIVIDER_xxx (xxx=1/2/4/8)	Select the divide ratio used by the ADC to generate the internal clock ADCK.		✓
ADC16_SET_DMA	ADC16_ENABLE/ADC16_DISABLE	Enable/disable the ADC DMA request. When DMA is enabled assert the DMA request on an ADC conversion complete event.		✓
ADC16_SET_HARDWARE_AVERAGE	ADC16_ENABLE/ADC16_DISABLE	Enable/disable the hardware average function of the ADC. The number of samples is set by the ADC16_SET_HARDWARE_AVERAGE_SAMPLES ioctl command.		✓
ADC16_SET_HARDWARE_AVERAGE_SAMPLES	ADC16_xxx (xxx=4_SAMPLES/8_SAMPLES/16_SAMPLES/32_SAMPLES)	Select how many ADC conversions will be averaged to create the ADC average result.		✓
ADC16_SET_HIGH_SPEED	ADC16_ENABLE/ADC16_DISABLE	Enable/disable the ADC for very high-speed operation. The conversion sequence is altered with 2 ADCK cycles added to the conversion time to allow higher speed conversion clocks.		✓
ADC16_SET_INPUT_CHANNEL	ADC16_xxx (xxx=AD0-AD23/VREFH/VREFL/DEACTIVATE/BANDGAP/TEMP_SENSOR)	Select one of the ADC input channels. Note: Some of the input channel options might not be available for all devices or packages.		✓
ADC16_SET_INT	ADC16_ENABLE/ADC16_DISABLE	Enable/disable the conversion complete interrupt. An interrupt is asserted when COCO becomes set while the AIEN is high.		✓
ADC16_SET_LONG_SAMPLE_TIME	ADC16_ENABLE/ADC16_DISABLE	Select between long and short sample time. When long sample time is selected, the sample time might be selected by the ADC16_SELECT_LONG_SAMPLE_TIME ioctl command.		✓

Table 5-5. ADC16 Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC16_SET_LOW_POWER_CFG	ADC16_xxx (xxx=HIGH_SPEED/LOW_POWER)	Select between the high sample rate or the power consumption-optimized sample rate.		✓
ADC16_SET_RESOLUTION	ADC16_MODE_xxx (xxx=8BIT/10BIT/12BIT/16BIT)	Set the converter's resolution.		✓
ADC16_SET_VOLTAGE_REFERENCE	ADC16_SOURCE_xxx (xxx=VREF/ALT/BANDGAP)	Select the voltage reference source used for conversions.		✓
ADC16_TEST_CALIBRATION_FAILED_FLAG	NULL	Return a non-zero value when the calibration failed and zero when passed. The calibration sequence fails if the HW trigger is enabled, any ADC register is written, or any stop mode is entered before the calibration sequence completes.		✓
ADC16_TEST_CALIBRATION_START	NULL	Return a non-zero value when the calibration sequence is in progress and zero when is completed.		✓
ADC16_TEST_CONVERSION_ACTIVE	NULL	Return a non-zero value when a ADC conversion or hardware averaging is in progress and zero when a conversion is completed or aborted.		✓
ADC16_TEST_CONVERSION_COMPLETE	NULL	Return a non-zero value when the conversion complete (COCO) flag is set. The COCO flag is cleared when the ADC Status and Control register 1 (SC1A) is written or when the respective ADC Result register (Rn) is read.		✓
ADC16_WRITE_CFG1_REG	UWord16	Write the parameter value to the Configuration register 1.		✓
ADC16_WRITE_CFG2_REG	UWord16	Write the parameter value to the Configuration register 2.		✓
ADC16_WRITE_CLP0_REG	UWord16	Write the parameter value to the ADC Plus-Side General Calibration Value 0 register.		✓
ADC16_WRITE_CLP1_REG	UWord16	Write the parameter value to the ADC Plus-Side General Calibration Value 1 register.		✓

Table 5-5. ADC16 Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC16_WRITE_CLP2_REG	UWord16	Write the parameter value to the ADC Plus-Side General Calibration Value 2 register.		✓
ADC16_WRITE_CLP3_REG	UWord16	Write the parameter value to the ADC Plus-Side General Calibration Value 3 register.		✓
ADC16_WRITE_CLP4_REG	UWord16	Write the parameter value to the ADC Plus-Side General Calibration Value 4 register.		✓
ADC16_WRITE_CLPD_REG	UWord16	Write the parameter value to the Plus-Side General Calibration Value register.		✓
ADC16_WRITE_CLPS_REG	UWord16	Write the parameter value to the Plus-Side General Calibration Value register.		✓
ADC16_WRITE_CV1_REG	UWord16	Write the parameter value to the Compare Value 1 register. This register is formatted in the same way as the Result Rn register in different modes of operation for both bit position definition and value format using unsigned or sign-extended 2's complement.		✓
ADC16_WRITE_CV2_REG	UWord16	Write the parameter value to the Compare Value 2 register. This register is used only when the compare function is set to one of RANGE modes. The relation of CV1 and CV2 register values determine whether inside-of-range or outside-of-range condition is evaluated.		✓
ADC16_WRITE_OFS_REG	UWord16	Write the parameter value to the Offset register.		✓
ADC16_WRITE_PLUS_SIDE_GAIN_REG	UWord16	Write the parameter value to the Plus-Side Gain register.		✓
ADC16_WRITE_SC1_REG	UWord16	Write the parameter value to the Status and Control register 1. This operation clears the conversion complete flag.		✓
ADC16_WRITE_SC2_REG	UWord16	Write the parameter value to the Status and Control register 2.		✓

Table 5-5. ADC16 Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ADC16_WRITE_SC3_REG	UWord16	Write the parameter value to the Status and Control register 3. Note: an inappropriate write to the register can clear Write-1-to-Clear (CALF) flag.		✓

5.1.3 Crossbar AND/OR/INVERT (AOI) Driver

The AND/OR/INVERT module (known simply as the AOI module) supports the generation of a configurable number of EVENT signals. Each output EVENTn is a configurable and/or/invert function of four associated AOI inputs: An, Bn, Cn, and Dn.

The Table 5-6 shows module identifiers for AOI Driver.

Table 5-6. Identifiers for AOI Driver

Module identifier	56F82xxx	56F84xxx
AOI	✓	✓

The Table 5-7 shows all commands dedicated for AOI Driver.

Table 5-7. AOI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
AOI_INIT	NULL	Initialize AOI peripheral registers using the appconfig.h _INIT values.	✓	✓
AOI_READ_BFCRT010	NULL	Return UWord16 value of AOI Boolean Function Term register.	✓	✓
AOI_READ_BFCRT011	NULL	Return UWord16 value of AOI Boolean Function Term register.	✓	✓
AOI_READ_BFCRT012	NULL	Return UWord16 value of AOI Boolean Function Term register.	✓	✓
AOI_READ_BFCRT013	NULL	Return UWord16 value of AOI Boolean Function Term register.	✓	✓
AOI_READ_BFCRT230	NULL	Return UWord16 value of AOI Boolean Function Term register.	✓	✓
AOI_READ_BFCRT231	NULL	Return UWord16 value of AOI Boolean Function Term register.	✓	✓
AOI_READ_BFCRT232	NULL	Return UWord16 value of AOI Boolean Function Term register.	✓	✓
AOI_READ_BFCRT233	NULL	Return UWord16 value of AOI Boolean Function Term register.	✓	✓
AOI_SET_EVENT0_TERM_0	combination of AOI_INPUT_n_xxx (n = A/B/C/D; xxx = LOG0/INVERT/NOTINVER/LOG1)	Set all inputs at once of the Term 0 for EVENT0.	✓	✓

Table 5-7. AOI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
AOI_SET_EVENT0_TERM_0_INPUT_A	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_A of the Term 0 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_0_INPUT_B	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_B of the Term 0 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_0_INPUT_C	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_C of the Term 0 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_0_INPUT_D	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_D of the Term 0 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_1	combination of AOI_INPUT_n_xxx (n = A/B/C/D; xxx = LOG0/INVERT/NOTINVER/LOG1)	Set all inputs at once of the Term 1 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_1_INPUT_A	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_A of the Term 1 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_1_INPUT_B	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_B of the Term 1 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_1_INPUT_C	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_C of the Term 1 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_1_INPUT_D	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_D of the Term 1 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_2	combination of AOI_INPUT_n_xxx (n = A/B/C/D; xxx = LOG0/INVERT/NOTINVER/LOG1)	Set all inputs at once of the Term 2 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_2_INPUT_A	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_A of the Term 2 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_2_INPUT_B	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_B of the Term 2 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_2_INPUT_C	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_C of the Term 2 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_2_INPUT_D	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_D of the Term 2 for EVENT0.	✓	✓

Table 5-7. AOI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
AOI_SET_EVENT0_TERM_3	combination of AOI_INPUT_n_xxx (n = A/B /C/D; xxx = LOG0/INVERT/NOTIN-VER/LOG1)	Set all inputs at once of the Term 3 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_3_INPUT_A	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_A of the Term 3 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_3_INPUT_B	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_B of the Term 3 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_3_INPUT_C	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_C of the Term 3 for EVENT0.	✓	✓
AOI_SET_EVENT0_TERM_3_INPUT_D	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_D of the Term 3 for EVENT0.	✓	✓
AOI_SET_EVENT1_TERM_0	combination of AOI_INPUT_n_xxx (n = A/B /C/D; xxx = LOG0/INVERT/NOTIN-VER/LOG1)	Set all inputs at once of the Term 0 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_0_INPUT_A	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_A of the Term 0 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_0_INPUT_B	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_B of the Term 0 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_0_INPUT_C	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_C of the Term 0 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_0_INPUT_D	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_D of the Term 0 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_1	combination of AOI_INPUT_n_xxx (n = A/B /C/D; xxx = LOG0/INVERT/NOTIN-VER/LOG1)	Set all inputs at once of the Term 1 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_1_INPUT_A	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_A of the Term 1 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_1_INPUT_B	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_B of the Term 1 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_1_INPUT_C	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_C of the Term 1 for EVENT1.	✓	✓

Table 5-7. AOI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
AOI_SET_EVENT1_TERM_1_INPUT_D	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_D of the Term 1 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_2	combination of AOI_INPUT_n_xxx (n = A/B/C/D; xxx = LOG0/INVERT/NOTINVER/LOG1)	Set all inputs at once of the Term 2 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_2_INPUT_A	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_A of the Term 2 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_2_INPUT_B	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_B of the Term 2 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_2_INPUT_C	AOI_LOG0/AOI_INVERT/AOI_NOTINVERT/AOI_LOG1	Set INPUT_C of the Term 2 for EVENT1.	✓	✓
AOI_SET_EVENT1_TERM_3	combination of AOI_INPUT_n_xxx (n = A/B/C/D; xxx = LOG0/INVERT/NOTINVER/LOG1)	Set all inputs at once of the Term 3 for EVENT1.	✓	✓
AOI_SET_EVENT2_TERM_0	combination of AOI_INPUT_n_xxx (n = A/B/C/D; xxx = LOG0/INVERT/NOTINVER/LOG1)	Set all inputs at once of the Term 0 for EVENT2.	✓	✓
AOI_SET_EVENT2_TERM_1	combination of AOI_INPUT_n_xxx (n = A/B/C/D; xxx = LOG0/INVERT/NOTINVER/LOG1)	Set all inputs at once of the Term 1 for EVENT2.	✓	✓
AOI_SET_EVENT2_TERM_2	combination of AOI_INPUT_n_xxx (n = A/B/C/D; xxx = LOG0/INVERT/NOTINVER/LOG1)	Set all inputs at once of the Term 2 for EVENT2.	✓	✓
AOI_SET_EVENT2_TERM_3	combination of AOI_INPUT_n_xxx (n = A/B/C/D; xxx = LOG0/INVERT/NOTINVER/LOG1)	Set all inputs at once of the Term 3 for EVENT2.	✓	✓

Table 5-7. AOI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
AOI_SET_EVENT3_TERM_0	combination of AOI_INPUT_n_xxx (n = A/B /C/D; xxx = LOG0/INVERT/NOTIN-VER/LOG1)	Set all inputs at once of the Term 0 for EVENT3.	✓	✓
AOI_SET_EVENT3_TERM_1	combination of AOI_INPUT_n_xxx (n = A/B /C/D; xxx = LOG0/INVERT/NOTIN-VER/LOG1)	Set all inputs at once of the Term 1 for EVENT3.	✓	✓
AOI_SET_EVENT3_TERM_2	combination of AOI_INPUT_n_xxx (n = A/B /C/D; xxx = LOG0/INVERT/NOTIN-VER/LOG1)	Set all inputs at once of the Term 2 for EVENT3.	✓	✓
AOI_SET_EVENT3_TERM_3	combination of AOI_INPUT_n_xxx (n = A/B /C/D; xxx = LOG0/INVERT/NOTIN-VER/LOG1)	Set all inputs at once of the Term 3 for EVENT3.	✓	✓
AOI_WRITE_BFCRT010	UWord16	Write in to AOI Boolean Function Term register.	✓	✓
AOI_WRITE_BFCRT011	UWord16	Write in to AOI Boolean Function Term register.	✓	✓
AOI_WRITE_BFCRT012	UWord16	Write in to AOI Boolean Function Term register.	✓	✓
AOI_WRITE_BFCRT013	UWord16	Write in to AOI Boolean Function Term register.	✓	✓
AOI_WRITE_BFCRT230	UWord16	Write in to AOI Boolean Function Term register.	✓	✓
AOI_WRITE_BFCRT231	UWord16	Write in to AOI Boolean Function Term register.	✓	✓
AOI_WRITE_BFCRT232	UWord16	Write in to AOI Boolean Function Term register.	✓	✓
AOI_WRITE_BFCRT233	UWord16	Write in to AOI Boolean Function Term register.	✓	✓

5.1.4 Computer Operating Properly (COP) Driver

The computer operating properly (COP) module is used to help software recover from runaway code. The COP is a free-running down counter that, once enabled, is designed to generate a reset upon reaching zero. Software must periodically service the COP in order to reload the counter and prevent a reset.

The Table 5-8 shows module identifiers for COP Driver.

Table 5-8. Identifiers for COP Driver

Module identifier	56F82xxx	56F84xxx
COP	✓	✓

The Table 5-9 shows all commands dedicated for COP Driver.

Table 5-9. COP Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
COP_CLEAR_COUNTER	NULL	Clear COP counter (both steps are performed).	✓	✓
COP_CLEAR_COUNTER_PART1	NULL	Clear COP counter (1st step of the sequence).	✓	✓
COP_CLEAR_COUNTER_PART2	NULL	Clear COP counter (2nd step of the sequence).	✓	✓
COP_DEVICE	COP_ENABLE/COP_DISABLE	Enable/disable COP watchdog counter.	✓	✓
COP_INIT	NULL	Initialize COP peripheral registers using the appconfig.h _INIT values.	✓	✓
COP_LOR_WATCHDOG	COP_ENABLE/COP_DISABLE	Enable/disable Loss-of-reference clock watchdog.	✓	✓
COP_READ_COUNTER	NULL	Read current value of COP counter.	✓	✓
COP_RUN_IN_STOP	COP_ENABLE/COP_DISABLE	Control the state of COP in WAIT mode.	✓	✓
COP_RUN_IN_WAIT	COP_ENABLE/COP_DISABLE	Control the state of COP in STOP mode.	✓	✓
COP_SET_CLOCK_PRESCALER	COP_xxx (xxx=DIV1024/DIV256/DIV16/DIV1)	Select COP clock source prescaler.	✓	✓

Table 5-9. COP Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
COP_SET_CLOCK_SOURCE	COP_xxx (xxx=1KHZ/IPBUS/COSC/ROSC)	Select COP clock source.	✓	✓
COP_SET_INT_VAL	UWord16	Set COP interrupt value; When the count value is equal to the COP interrupt value an interrupt is generated.	✓	✓
COP_SET_TIMEOUT	UWord16	Set COP Timeout Value.	✓	✓
COP_SET_WINDOW_VAL	UWord16	Set upper bound of the CNTR value that must be crossed prior to the CNTR being serviced. If CNTR is above this value when a service occurs, then a COP window reset is generated. If the CNTR value is less than or equal to this value at the time of the service, then the service is allowed to occur normally.	✓	
COP_WRITE_PROTECT	NULL	Write-protect COP settings (until Reset).	✓	✓

5.1.5 Cyclic Redundancy Check (CRC) Driver

The Cyclic Redundancy Check (CRC) generator module uses the 16-bit CRC-CCITT polynomial, x16 + x12 + x5 + 1, to generate a CRC code for error detection. The 16-bit code is calculated for 8 bits of data at a time and provides a simple check for all accessible memory locations, whether they be in a flash memory or RAM.

The Table 5-10 shows module identifiers for CRC Driver.

Table 5-10. Identifiers for CRC Driver

Module identifier	56F82xxx	56F84xxx
CRC	✓	✓

The Table 5-11 shows all commands dedicated for CRC Driver.

Table 5-11. CRC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
CRC_READ_16BIT_CHECKSUM	NULL	Read and return the value low Word of the CRC Data register.		✓
CRC_READ_32BIT_CHECKSUM	NULL	Read and return the value of the whole CRC Data register.		✓
CRC_READ_CRC_HIGH_REG	NULL	Read and return the value of CRC High Byte register. This register represents high byte of the CRC Generator result.	✓	
CRC_READ_CRC_LOW_REG	NULL	Read and return the value of CRC Low byte register. This register represents low byte of the CRC Generator result.	✓	
CRC_READ_CRC_REG	NULL	Read and return value of CRC Data register.		✓
CRC_READ_CRC_RESULT	NULL	Read and return the value of CRC result bytes.	✓	
CRC_READ_CRC_TRANSPOSE	NULL	Read and return value of the CRC Transpose register. This register is using to convert data from MSb to LSb.	✓	
CRC_READ_CTRL_REG	NULL	Read and return value of CRC Control register.		✓

Table 5-11. CRC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
CRC_READ_GPOLY_REG	NULL	Read and return value of CRC Polynomial register.		✓
CRC_SET_COMPLEMENT_READ_OF_DATA_REG	CRC_ENABLE/CRC_DISABLE	Enable/disable on-the-fly complementing the read data. Some CRC protocols require the final checksum to be XORed with 0xFFFFFFFF or 0xFFFF.		✓
CRC_SET_PROTOCOL_WIDTH	CRC_16_BIT/CRC_32_BIT	Set the width of CRC protocol.		✓
CRC_SET_TRANSPOSE_TYPE_FOR_READ	CRC_xxx (xxx=NO_TRANSPOSITION/BITS_TRANSPOSED/BITS_AND_BYTES_TRANSPOSED/BYTES_TRANSPOSED)	Set the transpose configuration of the value read from the CRC Data register.		✓
CRC_SET_TRANSPOSE_TYPE_FOR_WRITES	CRC_xxx (xxx=NO_TRANSPOSITION/BITS_TRANSPOSED/BITS_AND_BYTES_TRANSPOSED/BYTES_TRANSPOSED)	Set the transpose configuration of the data written into the CRC data register.		✓
CRC_SET_WRITE_AS_SEED	CRC_ENABLE/CRC_DISABLE	When enabled, any value written to the CRC data register is considered to be a seed value. When deasserted, a value written is taken as data for CRC computation.		✓
CRC_WRITE_16BIT_CRC_VALUE	UWord32 value 0-65535	Write seed or data value used for CRC checksum generation.		✓
CRC_WRITE_32BIT_CRC_VALUE	UWord32 value 0-65535	Write seed or data value used for CRC checksum generation.		✓
CRC_WRITE_8BIT_CRC_VALUE	UWord32 value 0-255	Write seed or data value used for CRC checksum generation.		✓
CRC_WRITE_CRC_DATA	UWord16 value 0-255	Write the parameter value into the CRC Low byte register. This register is using for finish the CRC generator initialization and for writing the data to generate CRC error check code.	✓	
CRC_WRITE_CRC_HIGH_REG	UWord16 value 0-255	Write the parameter value into the CRC High byte register. To complete the CRC generator initialization the module expects writing the low part of the initialization byte to the CRC Low byte register.	✓	

Table 5-11. CRC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
CRC_WRITE_CRC_LOW_REG	UWord16 value 0-255	Write the parameter value into the CRC Low byte register. This register is using for the CRC generator initialization and for writing the data to generate CRC error check code.	✓	
CRC_WRITE_CRC_REG	UWord32	Write the CRC Data register.		✓
CRC_WRITE_CRC_TRANSPOSE	UWord16	Write the CRC Transpose register. This register is used to convert data from MSb to LSb.	✓	
CRC_WRITE_CRC_TRANSPOSED_DATA	UWord16 value 0-255	Write the parameter value (data) in to transpose register, transposed data are written into CRC low byte.	✓	
CRC_WRITE_CTRL_REG	UWord32	Write the CRC Control register.		✓
CRC_WRITE_GPOLY_REG	UWord32	Write the CRC Polynomial register.		✓
CRC_WRITE_HIGH_POLYNOMINAL	UWord16	Write the parameter value into higher Word of the CRC Polynominal register.		✓
CRC_WRITE_INIT_VALUE	UWord16	Initialize the CRC function.	✓	
CRC_WRITE_LOW_POLYNOMINAL	UWord16	Write the parameter value into lower Word of the CRC Polynominal register.		✓

5.1.6 12-bit Digital-to-Analog Converter (DAC) Driver

The 12-bit digital-to-analog converter (DAC) provides a voltage reference to on-chip modules or an output to a package pin. It can also be used as a waveform generator to generate square, triangle, and sawtooth waveforms. The DAC can be put in powerdown mode if needed.

The Table 5-12 shows module identifiers for DAC Driver.

Table 5-12. Identifiers for DAC Driver

Module identifier	56F82xxx	56F84xxx
DAC_A	✓	
DAC_B	✓	
DAC		✓

The Table 5-13 shows all commands dedicated for DAC Driver.

Table 5-13. DAC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
DAC_DISABLE_FILTER	NULL	Disable the glitch-suppression filter. See more details about the filter at DAC_ENABLE_FILTER.	✓	✓
DAC_DMA_ENABLE	DAC_ENABLE/DAC_DISABLE	Enable/disable the DMA to feed the DAC output.	✓	✓
DAC_ENABLE_FILTER	NULL	Enable the glitch-suppression filter on the DAC output. The glitch suppression filter introduces a latency between the DATA Register update (both manual or automatic) and the actual DAC output update.	✓	✓
DAC_INIT	NULL	Initialize DAC peripheral registers using the appconfig.h _INIT values.	✓	✓
DAC_MODULE	DAC_ENABLE/DAC_DISABLE	Enable/disable the DAC module. Before the DAC module is used; the DAC device should be configured (in disabled state) and then enabled.	✓	✓
DAC_READ_CONTROL_REG	NULL	Read and return the value of the DAC Control Register.	✓	✓
DAC_READ_DATA	NULL	Read and return a value of the DAC Data Register.	✓	✓

Table 5-13. DAC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
DAC_READ_FIFO_EMPTY	NULL	Read and return the empty status of FIFO.	✓	✓
DAC_READ_FIFO_FULL	NULL	Read and return the full status of FIFO.	✓	✓
DAC_READ_MAXVAL	NULL	Read and return a value of the DAC Maximum Value Register.	✓	✓
DAC_READ_MINVAL	NULL	Read and return a value of the DAC Minimum Value Register.	✓	✓
DAC_READ_STEP	NULL	Read and return a value of the DAC Step Register.	✓	✓
DAC_SET_AUTO_MODE	DAC_AUTO_xxx (xxx=OFF/SAWTOOTH1/SAWTOOTH2/TRIANGLE)	Set generation of a shaped analog signal on the DAC output.	✓	✓
DAC_SET_DATA_FORMAT	DAC_RIGHT_ALIGNED_FMT/DAC_LEFT_ALIGNED_FMT	Configure the data alignment for the DATA, STEP, MINVAL, and MAXVAL Registers. The alignment defines what bits of the registers contain the 12-bit DAC value.	✓	✓
DAC_SET_FILTER	UWord16 value 0-31	Set the number of IP Bus clock cycles for which the DAC output is held unchanged after new data is presented to the analog DAC's inputs. The number of clock cycles for which DAC output is held unchanged is equal to the value of FILT_CNT.	✓	✓
DAC_SET_SPEED	DAC_LOW_SPEED/DAC_HIGH_SPEED	Select between speed and power while operating in normal mode. Setting this input low selects high speed mode, in which the settling time of the DAC is 1 ?s (faster response) but at the expense of higher power consumption.	✓	✓
DAC_SET_SYNC_SOURCE	DAC_IPBUS_SOURCE/DAC_SYNCIN_SOURCE	Select the DAC trigger signal to be used to trigger an update of the buffered data to the analog DAC output. Restriction: Do not set SYNC_EN low when DMA_EN is set high.	✓	✓

Table 5-13. DAC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
DAC_SET_WATER_MARK_LEVEL	DAC_LEVEL_x (x=0/2/4/6)	Select DAC water mark level. When the level of FIFO is less than or equal to this field, a DMA request should be sent. The FIFO used for DMA support generates a watermark signal depending on the value of WTMK_LVL, which is used for asserting a DMA request.	✓	✓
DAC_WRITE_CONTROL_REG	UWord16	Write the parameter value into the DAC Control Register.	✓	✓
DAC_WRITE_DATA	UWord16	Write the parameter value into the DAC DATA Register. This causes the DAC output to be changed after the next update-trigger signal which is either SYNC_IN or IP Bus clock.	✓	✓
DAC_WRITE_MAXVAL	UWord16	Write the parameter value into the DAC Maximum Value Register. This value is used anytime the DAC is switched to an automatic mode.	✓	✓
DAC_WRITE_MINVAL	UWord16	Write the parameter value into the DAC Minimum Value Register. This value is used anytime the DAC is switched to an automatic mode.	✓	✓
DAC_WRITE_STEP	UWord16	Write the parameter value into the DAC STEP Register. This value is used anytime the DAC is switched to an automatic mode.	✓	✓

5.1.7 DMA Controller (DMA) Driver

The DMA controller module enables fast transfers of data, providing an efficient way to move blocks of data with minimal processor interaction. The DMA module, shown in the following figure, has four channels that allow byte, word, or longword data transfers. Each channel has a dedicated source address register (SARn), destination address register (DARn), status register (DSRn), byte count register (BCRn), and control register (DCRn). Collectively, the combined program-visible registers associated with each channel define a transfer control descriptor (TCD). All transfers are dual address, moving data from a source memory location to a destination memory location with the module operating as a 32-bit bus master connected to the system bus. The programming model is accessed through a 32-bit connection with the slave peripheral bus. DMA data transfers may be explicitly initiated by software or by peripheral hardware requests.

The Table 5-14 and Table 5-16 show module identifiers for DMA Driver.

Table 5-14. Identifiers for DMA Driver

Module identifier	56F82xxx	56F84xxx
DMA	✓	✓

The Table 5-15 shows commands dedicated for DMA Driver.

Table 5-15. DMA Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
DMA_CH0_CLEAR_STATE_MACHINE_CONTROL	NULL	Clear the state machine for DMA channel 0.	✓	✓
DMA_CH0_SELECT_SOURCE	DMA_REQUEST_xxx (xxx=0-15)	Select DMA request which will be routed to the DMA channel 0.	✓	✓
DMA_CH1_CLEAR_STATE_MACHINE_CONTROL	NULL	Clear the state machine for DMA channel 1.	✓	✓
DMA_CH1_SELECT_SOURCE	DMA_REQUEST_xxx (xxx=0-15)	Select DMA request which will be routed to the DMA channel 1.	✓	✓
DMA_CH2_CLEAR_STATE_MACHINE_CONTROL	NULL	Clear the state machine for DMA channel 2.	✓	✓
DMA_CH2_SELECT_SOURCE	DMA_REQUEST_xxx (xxx=0-15)	Select DMA request which will be routed to the DMA channel 2.	✓	✓
DMA_CH3_CLEAR_STATE_MACHINE_CONTROL	NULL	Clear the state machine for DMA channel 3.	✓	✓

Table 5-15. DMA Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
DMA_CH3_SELECT_SOURCE	DMA_REQUEST_xxx (xxx=0-15)	Select DMA request which will be routed to the DMA channel 3.	✓	✓
DMA_INIT	NULL	Initialization of the DMA peripheral registers using appconfig.h _INIT values.	✓	✓

Table 5-16. Identifiers for DMA Driver

Module identifier	56F82xxx	56F84xxx
DMA_0	✓	✓
DMA_1	✓	✓
DMA_2	✓	✓
DMA_3	✓	✓

The Table 5-17 incorporates commands where DMA_x should be used as the device (unlike the previous table where DMA is used as the module).

Table 5-17. DAC_x Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
DMA_CLEAR_TRANSACTION_DONE	NULL	Clear DMA transaction status bit. Use in an interrupt service routine to clear the DMA interrupt flag and error bits.	✓	✓
DMA_DISABLE_REQUEST	DMA_ENABLE/DMA_DISABLE	If enabled, the DMA hardware automatically clears the corresponding DCRn[ERQ] bit when the byte count register reaches zero.	✓	✓
DMA_GET_DESTINATION_ADDRESS	NULL	Read and return the destination address used by the DMA channel.	✓	✓
DMA_GET_LINK_CHANNEL_1	NULL	Get the DMA channel assigned as link channel 1. The link channel number cannot be the same as the currently executing channel.	✓	✓

Cmd	pParam	Description	56F82xxx	56F84xxx
DMA_GET_LINK_CHANNEL_2	NULL	Get the DMA channel assigned as link channel 2. The link channel number cannot be the same as the currently executing channel.	✓	✓
DMA_GET_SOURCE_ADDRESS	NULL	Read and return the source address used by the DMA channel.	✓	✓
DMA_READ_BUS_ERROR_DESTINATION	NULL	Get the bus error on destination [BED] flag; cleared at hardware reset or by writing a 1 to the [DONE] bit.	✓	✓
DMA_READ_BUS_ERROR_SOURCE	NULL	Get the bus error on source [BES] flag; cleared at hardware reset or by writing a 1 to the [DONE] bit.	✓	✓
DMA_READ_BUSY	NULL	Get the busy [BSY] bit; the bit is cleared when the DMA completes the last transaction and it is set the first time that the channel is enabled after a transfer is initiated.	✓	✓
DMA_READ_BYTES_TO_BE_TRANSFERRED	NULL	Return number of bytes yet to be transferred for a given block.	✓	✓
DMA_READ_CONFIG_ERROR	NULL	Get the configuration error [CE] flag; A configuration error occurs when any of the following conditions occurs: BCR, SAR, or DAR does not match the requested transfer size; SSIZE or DSIZE is set to an unsupported value; BCR equals 0 when the DMA receives a start condition.	✓	✓
DMA_READ_DCR	NULL	Read and return channel n DMA_DCR register.	✓	✓
DMA_READ_DSR_BCR	NULL	Read and return channel n DMA_DSR_BCR register.	✓	✓
DMA_READ_REQUEST	NULL	Get the request pending [REQ] bit; the DMA channel has a transfer remaining, Cleared when the channel is selected.	✓	✓
DMA_READ_TRANSACTION_DONE	NULL	Get the DMA transfer completed [DONE] flag.	✓	✓
DMA_SET_AUTO_ALIGN	DMA_ENABLE/DMA_DISABLE	Set optimized transfers based on the address and size.	✓	✓

Cmd	pParam	Description	56F82xxx	56F84xxx
DMA_SET_DESTINATION_ADDRESS	UWord32 destination address	Set the destination address used by the DMA channel to write data.	✓	✓
DMA_SET_DESTINATION_ADDRESS_MODULO	DMA_xxx (xxx=DISABLE/16B/32B/64B/128B/256B/512B/1KB/2KB/4KB/8KB/16KB/32KB/64KB/128KB/256KB)	Set the size of the destination data circular buffer used by the DMA channel.	✓	✓
DMA_SET_DESTINATION_INCREMENT	DMA_ENABLE/DMA_DISABLE	Set destination address increment after each successful transfer.	✓	✓
DMA_SET_DESTINATION_SIZE	DMA_xxx (xxx=BYTE/WORD/LONGWORD)	Set the data size of the destination bus cycle for the DMA channel.	✓	✓
DMA_SET_INTERRUPT_COMPLETED	DMA_ENABLE/DMA_DISABLE	Enable/disable interrupt to be generated when completing a transfer or by an error condition.	✓	✓
DMA_SET_LINK_CHANNEL_1	DMA_CH_xxx (xxx=0-3)	Set the DMA channel assigned as link channel 1.	✓	✓
DMA_SET_LINK_CHANNEL_2	DMA_CH_xxx (xxx=0-3)	Set the DMA channel assigned as link channel 2.	✓	✓
DMA_SET_LINK_CHANNEL_MODE	DMA_xxx (xxx=NO_LINKING/LCH1_THEN_LCH2/LCH1_AFTER_CS/LCH1_WHEN_BCR_0)	Set the DMA channels to have their transfers linked. The current DMA channel triggers a DMA request to the linked channels (LCH1 or LCH2) depending on the condition described by the parameter.	✓	✓
DMA_SET_PERIPHERAL_REQUEST	DMA_ENABLE/DMA_DISABLE	Enable peripheral request to initiate the DMA transfer.	✓	✓
DMA_SET_SOURCE_ADDRESS	UWord32 source address	Set the source address used by the DMA channel to read data.	✓	✓
DMA_SET_SOURCE_ADDRESS_MODULO	DMA_xxx (xxx=DISABLE/16B/32B/64B/128B/256B/512B/1KB/2KB/4KB/8KB/16KB/32KB/64KB/128KB/256KB)	Set the size of the source data circular buffer used by the DMA channel.	✓	✓
DMA_SET_SOURCE_INCREMENT	DMA_ENABLE/DMA_DISABLE	Set source address increment after each successful transfer.	✓	✓
DMA_SET_SOURCE_SIZE	DMA_xxx (xxx=BYTE/WORD/LONGWORD)	Set the data size of the source bus cycle for the DMA channel.	✓	✓

Cmd	pParam	Description	56F82xxx	56F84xxx
DMA_SET_START_TRANSFER	DMA_ENABLE/DMA_DISABLE	DMA begins the transfer in accordance to the values in the TCDn.	✓	✓
DMA_SET_TRANSFER_MODE	DMA_SINGLE/DMA_CONTINUOUS	Select single read/write transfers per request or continuous read/write transfers until the BCR decrements to zero.	✓	✓
DMA_WRITE_DCR	UWord32	Write the parameter value into channel n DMA_DCR register.	✓	✓
DMA_WRITE_DSR_BCR	UWord32	Write the parameter value into the channel n DMA_DSR_BCR register.	✓	✓

5.1.8 Enhanced Flexible Pulse Width Modulator (EFPWM) Driver

The enhanced flexible pulse width modulator (EFPWM) module contains EFPWM submodules, each of which is set up to control a single half-bridge power stage. Fault channel support is provided. PWM module can generate various switching patterns including highly sophisticated waveforms. It can be used to control all known motor types and is ideal for controlling different Switched Mode Power Supplies (SMPS) topologies.

The Table 5-18 shows module identifiers for EFPWM Driver.

Table 5-18. Identifiers for EFPWM Driver

Module identifier	56F82xxx	56F84xxx
EFPWMA	✓	✓
EFPWMA_SUB0	✓	✓
EFPWMA_SUB1	✓	✓
EFPWMA_SUB2	✓	✓
EFPWMA_SUB3	✓	✓
EFPWMB		✓
EFPWMB_SUB0	✓	
EFPWMB_SUB1	✓	
EFPWMB_SUB2	✓	
EFPWMB_SUB3	✓	

The Table 5-19 shows all commands for EFPWM Driver.

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWM_CENTER_ALIGN_UPDATE_VALUE_REGS_COMPL_012	pwm_sComplementaryValues*	Set PWM Submodule 0, 1, and 2 outputs in complementary mode and set LDOK bit afterwards.	✓	✓
EFPWM_CENTER_ALIGN_UPDATE_VALUE_REGS_COMPL_013	pwm_sComplementaryValues*	Set PWM Submodule 0, 1, and 3 outputs in complementary mode and set LDOK bit afterwards.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWM_CENTER_ALIGN_UPDATE_VALUE_REGS_COMPL_023	pwm_sComplementaryValues*	Set PWM Submodule 0, 2, and 3 outputs in complementary mode and set LDOK bit afterwards.	✓	✓
EFPWM_CLEAR_FAULT_FLAGS	EFPWM_FAULT_X(0|1|2|3)	Clear selected fault flags.	✓	✓
EFPWM_CLEAR_FAULT_TEST	NULL	Clear simulated fault condition.	✓	✓
EFPWM_CLEAR_FAULT0_FLAGS	EFPWM_FAULT_X(0|1|2|3)	Clear selected fault flags.	✓	✓
EFPWM_CLEAR_FAULT0_TEST	NULL	Clear simulated fault condition.	✓	✓
EFPWM_CLEAR_FAULT1_FLAGS	EFPWM_FAULT_X(0|1|2|3)	Clear selected fault flags.	✓	✓
EFPWM_CLEAR_FAULT1_TEST	NULL	Clear simulated fault condition.	✓	✓
EFPWM_CLEAR_LOAD_OK	EFPWM_SUBMODULE_0|EFPWM_SUBMODULE_1|EFPWM_SUBMODULE_2|EFPWM_SUBMODULE_3	Clear selected LDOK request.	✓	✓
EFPWM_EDGE_ALIGN_UPDATE_VALUE_REGS_INDEP_012	pwm_sIndependentValues*	Set PWM Submodule 0, 1, and 2 outputs in independent mode and set LDOK bit afterwards.	✓	✓
EFPWM_EDGE_ALIGN_UPDATE_VALUE_REGS_INDEP_013	pwm_sIndependentValues*	Set PWM Submodule 0, 1, and 3 outputs in independent mode and set LDOK bit afterwards.	✓	✓
EFPWM_EDGE_ALIGN_UPDATE_VALUE_REGS_INDEP_023	pwm_sIndependentValues*	Set PWM Submodule 0, 1, and 3 outputs in independent mode and set LDOK bit afterwards.	✓	✓
EFPWM_FAULT_FILTER_COUNTER	EFPWM_SAMPLES_X (3/4/5/6/7/8/9/10)	Set number of samples to the input filter accepting an input transition.	✓	✓
EFPWM_FAULT_FILTER_PERIOD	UWord16	Value 0 to 255	✓	✓
EFPWM_FAULT_GLITCH_STRETCH	EFPWM_ENABLE/EFPWM_DISABLE	Enable/disable Fault glitch stretching.	✓	✓
EFPWM_FAULT_INT_DISABLE	EFPWM_FAULT_X(0|1|2|3)	Disable fault interrupt.	✓	✓
EFPWM_FAULT_INT_ENABLE	EFPWM_FAULT_X(0|1|2|3)	Enable fault interrupt.	✓	✓
EFPWM_FAULT0_FILTER_COUNTER	EFPWM_SAMPLES_X (3/4/5/6/7/8/9/10)	Set number of samples to the input filter accepting an input transition.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWM_FAULT0_FILTER_PERIOD	UWord16	Value 0 to 255.	✓	✓
EFPWM_FAULT0_GLITCH_STRETCH	EFPWM_ENABLE/EFPWM_DISABLE	Enable/disable Fault glitch stretching.	✓	✓
EFPWM_FAULT0_INT_DISABLE	EFPWM_FAULT_X(0|1|2|3)	Disable fault interrupt.	✓	✓
EFPWM_FAULT0_INT_ENABLE	EFPWM_FAULT_X(0|1|2|3)	Enable fault interrupt.	✓	✓
EFPWM_FAULT0_TEST	EFPWM_ENABLE/EFPWM_DISABLE	Activates simulated fault condition for fault 0. Simulated fault to be sent into all of the fault filters.	✓	✓
EFPWM_FAULT1_FILTER_COUNTER	EFPWM_SAMPLES_X (3/4/5/6/7/8/9/10)	Set number of samples to the input filter accepting an input transition.	✓	✓
EFPWM_FAULT1_FILTER_PERIOD	UWord16	Value 0 to 255.	✓	✓
EFPWM_FAULT1_GLITCH_STRETCH	EFPWM_ENABLE/EFPWM_DISABLE	Enable/disable Fault glitch stretching.	✓	✓
EFPWM_FAULT1_INT_DISABLE	EFPWM_FAULT_X(0|1|2|3)	Disable fault interrupt.	✓	✓
EFPWM_FAULT1_INT_ENABLE	EFPWM_FAULT_X(0|1|2|3)	Enable fault interrupt.	✓	✓
EFPWM_FAULT1_TEST	EFPWM_ENABLE/EFPWM_DISABLE	Activates simulated fault condition for fault 1. Simulated fault to be sent into all of the fault filters.	✓	✓
EFPWM_INIT	NULL	Initialization of the peripheral registers using appconfig.h _INIT values	✓	✓
EFPWM_MONITOR_PLL	EFPWM_ENABLE(_PERMANENT)/EFPWM_DISABLE(_PERMANENT)	Enable/disable PLL monitor.	✓	✓
EFPWM_READ_DEADTIME_SOURCE_REG	NULL	Return value of the Deadtime Source Select Register.	✓	✓
EFPWM_READ_FAULT_CONTROL_REG	NULL	Return value of the Fault Register.	✓	✓
EFPWM_READ_FAULT_STATUS_REG	NULL	Return value of the Fault Status Register.	✓	✓
EFPWM_READ_FAULT0_CONTROL_REG	NULL	Return value of the Fault Register.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWM_READ_FAULT0_STATUS_REG	NULL	Return value of the Fault Status Register.	✓	✓
EFPWM_READ_FAULT1_CONTROL_REG	NULL	Return value of the Fault Register.	✓	✓
EFPWM_READ_FAULT1_STATUS_REG	NULL	Return value of the Fault Status Register.	✓	✓
EFPWM_READ_MASK_REG	NULL	Return value of the Mask Register.	✓	✓
EFPWM_READ_MASTER_CONTROL_REG	NULL	Return value of the Master Control Register.	✓	✓
EFPWM_READ_OUTPUT_ENABLE_REG	NULL	Return value of the Output Enable Register.	✓	✓
EFPWM_READ_SW_CONTROL_OUT_REG	NULL	Return value of the Software Controlled Output Register.	✓	✓
EFPWM_SET_ACTIVE_HIGH_FAULTS	EFPWM_FAULT_X(0|1|2|3)	Set active fault level to high at selected fault inputs.	✓	✓
EFPWM_SET_ACTIVE_HIGH_FAULTS0	EFPWM_FAULT_X(0|1|2|3)	Set active fault level to high at selected fault inputs.	✓	✓
EFPWM_SET_ACTIVE_HIGH_FAULTS1	EFPWM_FAULT_X(0|1|2|3)	Set active fault level to high at selected fault inputs.	✓	✓
EFPWM_SET_ACTIVE_LOW_FAULTS	EFPWM_FAULT_X(0|1|2|3)	Set active fault level to low at selected fault inputs.	✓	✓
EFPWM_SET_ACTIVE_LOW_FAULTS0	EFPWM_FAULT_X(0|1|2|3)	Set active fault level to low at selected fault inputs.	✓	✓
EFPWM_SET_ACTIVE_LOW_FAULTS1	EFPWM_FAULT_X(0|1|2|3)	Set active fault level to low at selected fault inputs.	✓	✓
EFPWM_SET_AUTOMATIC_FAULT_CLEAR	EFPWM_FAULT_X(0|1|2|3)	Set automatic fault clearing.	✓	✓
EFPWM_SET_AUTOMATIC_FAULT0_CLEAR	EFPWM_FAULT_X(0|1|2|3)	Set automatic fault clearing.	✓	✓
EFPWM_SET_AUTOMATIC_FAULT1_CLEAR	EFPWM_FAULT_X(0|1|2|3)	Set automatic fault clearing.	✓	✓
EFPWM_SET_CURRENT_POLARITY_TO_PWM23	EFPWM_SUBMODULE_0|EFPWM_SUBMODULE_1|EFPWM_SUBMODULE_2|EFPWM_SUBMODULE_3	Set PWM23 output as PWM source in complementary mode.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWM_SET_CURRENT_POLARITY_TO_PWM45	EFPWM_SUBMODULE_0|EFPWM_SUBMODULE_1|EFPWM_SUBMODULE_2|EFPWM_SUBMODULE_3	Set PWM45 output as PWM source in complementary mode.	✓	✓
EFPWM_SET_FAULT_FULL_CYCLE	EFPWM_FAULT_X(0|1|2|3)	Set re-enabling PWM outputs at start of a full cycle.	✓	✓
EFPWM_SET_FAULT_HALF_FULL_CYCLE	EFPWM_FAULT_X(0|1|2|3)	Set re-enabling PWM outputs at start of a half or full cycle.	✓	✓
EFPWM_SET_FAULT_NORMAL_MODE	EFPWM_FAULT_X(0|1|2|3)	Set fault normal mode.	✓	✓
EFPWM_SET_FAULT_SAFETY_MODE	EFPWM_FAULT_X(0|1|2|3)	Set fault safety mode.	✓	✓
EFPWM_SET_FAULT0_FULL_CYCLE	EFPWM_FAULT_X(0|1|2|3)	Set re-enabling PWM outputs at start of a full cycle.	✓	✓
EFPWM_SET_FAULT0_HALF_FULL_CYCLE	EFPWM_FAULT_X(0|1|2|3)	Set re-enabling PWM outputs at start of a half or full cycle.	✓	✓
EFPWM_SET_FAULT0_NORMAL_MODE	EFPWM_FAULT_X(0|1|2|3)	Set fault normal mode.	✓	✓
EFPWM_SET_FAULT0_SAFETY_MODE	EFPWM_FAULT_X(0|1|2|3)	Set fault safety mode.	✓	✓
EFPWM_SET_FAULT1_FULL_CYCLE	EFPWM_FAULT_X(0|1|2|3)	Set re-enabling PWM outputs at start of a full cycle.	✓	✓
EFPWM_SET_FAULT1_HALF_FULL_CYCLE	EFPWM_FAULT_X(0|1|2|3)	Set re-enabling PWM outputs at start of a half or full cycle.	✓	✓
EFPWM_SET_FAULT1_NORMAL_MODE	EFPWM_FAULT_X(0|1|2|3)	Set fault normal mode.	✓	✓
EFPWM_SET_FAULT1_SAFETY_MODE	EFPWM_FAULT_X(0|1|2|3)	Set fault safety mode.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWM_SET_FORCE_OUT	EFPWM_SUB3_PWM23_SOURCE_xxx(PWM/ INV_PWM/ SWOUT/ EXT)|EFPWM_SUB3_PWM45_SOURCE_xxx(PWM/ INV_PWM/ SWOUT/ EXT)|EFPWM_SUB2_PWM23_SOURCE_xxx(PWM/ INV_PWM/ SWOUT/ EXT)|EFPWM_SUB2_PWM45_SOURCE_xxx(PWM/ INV_PWM/ SWOUT/ EXT)|EFPWM_SUB1_PWM23_SOURCE_xxx(PWM/ INV_PWM/ SWOUT/ EXT)|EFPWM_SUB1_PWM45_SOURCE_xxx(PWM/ INV_PWM/ SWOUT/ EXT)|EFPWM_SUB0_PWM23_SOURCE_xxx(PWM/ INV_PWM/ SWOUT/ EXT)|EFPWM_SUB0_PWM45_SOURCE_xxx(PWM/ INV_PWM/ SWOUT/ EXT)	Set Force Out mode.	✓	✓
EFPWM_SET_FORCE_OUT_SW_SOURCE_TO_HIGH	EFPWM_SUB0_PWMXX (23|45)|EFPWM_SUB1_PWMXX (23|45)| EFPWM_SUB2_PWMXX (23|45)|EFPWM_SUB3_PWMXX (23|45)	Set Force Out software level to high.	✓	✓
EFPWM_SET_FORCE_OUT_SW_SOURCE_TO_LOW	EFPWM_SUB0_PWMXX (23|45)| EFPWM_SUB1_PWMXX (23|45)|EFPWM_SUB2_PWMXX (23|45)|EFPWM_SUB3_PWMXX (23|45)	Set Force Out software level to high.	✓	✓
EFPWM_SET_LOAD_OK	EFPWM_SUBMODULE_0|EFPWM_SUBMODULE_1|EFPWM_SUBMODULE_2|EFPWM_SUBMODULE_3	Set selected LDOK request.	✓	✓
EFPWM_SET_MANUAL_FAULT_CLEAR	EFPWM_FAULT_X(0|1|2|3)	Set manual fault clearing.	✓	✓
EFPWM_SET_MANUAL_FAULT0_CLEAR	EFPWM_FAULT_X(0|1|2|3)	Set manual fault clearing.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWM_SET_MANUAL_FAULT1_CLEAR	EFPWM_FAULT_X(0|1|2|3)	Set manual fault clearing.	✓	✓
EFPWM_SET_MASK_DISABLE	EFPWM_SUB0_PWM_X (A|B|X)|EFPWM_SUB1_PWM_X (A|B|X)|EFPWM_SUB2_PWM_X (A|B|X)|EFPWM_SUB3_PWM_X (A|B|X)	Set normal PWM outputs.	✓	✓
EFPWM_SET_MASK_ENABLE	EFPWM_SUB0_PWM_X (A|B|X)|EFPWM_SUB1_PWM_X (A|B|X)|EFPWM_SUB2_PWM_X (A|B|X)|EFPWM_SUB3_PWM_X (A|B|X)	Masks selected PWM outputs.	✓	✓
EFPWM_SET_OUTPUTS	EFPWM_SUB0_PWM_X_ENABLE (A|B|X)|EFPWM_SUB0_PWM_X_DISABLE (A|B|X)|EFPWM_SUB1_PWM_X_ENABLE (A|B|X)|EFPWM_SUB1_PWM_X_DISABLE (A|B|X)|EFPWM_SUB2_PWM_X_ENABLE (A|B|X)|EFPWM_SUB2_PWM_X_DISABLE (A|B|X)|EFPWM_SUB3_PWM_X_ENABLE (A|B|X)|EFPWM_SUB3_PWM_X_ENABLE (A|B|X)|	Enable/disable selected PWM outputs at selected submodules.	✓	✓
EFPWM_SET_OUTPUTS_DISABLE	EFPWM_SUB0_PWM_X (A|B|X)|EFPWM_SUB1_PWM_X (A|B|X)|EFPWM_SUB2_PWM_X (A|B|X)|EFPWM_SUB3_PWM_X (A|B|X)	Disable selected PWM outputs at selected submodules.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWM_SET_OUTPUTS_ENABLE	EFPWM_SUB0_PWM_X (A|B|X)|EFPWM_SUB1_PWM_X (A|B|X)|EFPWM_SUB2_PWM_X (A|B|X)|EFPWM_SUB3_PWM_X (A|B|X)	Enable selected PWM outputs at selected submodules.	✓	✓
EFPWM_SET_PWM_CLOCK_DISABLE	EFPWM_SUBMODULE_0|EFPWM_SUBMODULE_1|EFPWM_SUBMODULE_2|EFPWM_SUBMODULE_3	Set PWM generator clock disable.	✓	✓
EFPWM_SET_PWM_CLOCK_ENABLE	EFPWM_SUBMODULE_0|EFPWM_SUBMODULE_1|EFPWM_SUBMODULE_2|EFPWM_SUBMODULE_3	Set PWM generator clock enable.	✓	✓
EFPWM_SET_SUB0_FORCE_OUT_PWM23	EFPWM_SOURCE_XXX (PWM/INV_PWM/SWOUT/EXT)	Set force out source.	✓	✓
EFPWM_SET_SUB0_FORCE_OUT_PWM45	EFPWM_SOURCE_XXX (PWM/INV_PWM/SWOUT/EXT)	Set force out source.	✓	✓
EFPWM_SET_SUB1_FORCE_OUT_PWM23	EFPWM_SOURCE_XXX (PWM/INV_PWM/SWOUT/EXT)	Set force out source.	✓	✓
EFPWM_SET_SUB1_FORCE_OUT_PWM45	EFPWM_SOURCE_XXX (PWM/INV_PWM/SWOUT/EXT)	Set force out source.	✓	✓
EFPWM_SET_SUB2_FORCE_OUT_PWM23	EFPWM_SOURCE_XXX (PWM/INV_PWM/SWOUT/EXT)	Set force out source.	✓	✓
EFPWM_SET_SUB2_FORCE_OUT_PWM45	EFPWM_SOURCE_XXX (PWM/INV_PWM/SWOUT/EXT)	Set force out source.	✓	✓
EFPWM_SET_SUB3_FORCE_OUT_PWM23	EFPWM_SOURCE_XXX (PWM/INV_PWM/SWOUT/EXT)	Set force out source.	✓	✓
EFPWM_SET_SUB3_FORCE_OUT_PWM45	EFPWM_SOURCE_XXX (PWM/INV_PWM/SWOUT/EXT)	Set force out source.	✓	✓
EFPWM_TEST_FAULT_FLAGS	EFPWM_FAULT_X(0|1|2|3)	Return state of selected fault flags.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWM_TEST_FAULT_PINS	EFPWM_FAULT_X(0|1|2|3)	Return state of filtered fault pins.	✓	✓
EFPWM_TEST_FAULT0_FLAGS	EFPWM_FAULT_X(0|1|2|3)	Return state of selected fault flags.	✓	✓
EFPWM_TEST_FAULT0_PINS	EFPWM_FAULT_X(0|1|2|3)	Return state of filtered fault pins.	✓	✓
EFPWM_TEST_FAULT1_FLAGS	EFPWM_FAULT_X(0|1|2|3)	Return state of selected fault flags.	✓	✓
EFPWM_TEST_FAULT1_PINS	EFPWM_FAULT_X(0|1|2|3)	Return state of filtered fault pins.	✓	✓
EFPWM_UPDATE_MASK_BITS_IMMEDIATELY	EFPWM_SUB0_PWM_X (A|B|X)|EFPWM_SUB1_PWM_X (A|B|X)|EFPWM_SUB2_PWM_X (A|B|X)|EFPWM_SUB3_PWM_X (A|B|X)	Masks selected PWM outputs.	✓	✓
EFPWM_WRITE_DEADTIME_SOURCE_REG	UWord16	Writes prepared data in to the Dead-time Source Select Register.	✓	✓
EFPWM_WRITE_FAULT_CONTROL_REG	UWord16	Writes prepared data in to the Fault Register.	✓	✓
EFPWM_WRITE_FAULT_STATUS_REG	UWord16	Writes prepared data in to the Fault Status Register.	✓	✓
EFPWM_WRITE_FAULT0_CONTROL_REG	UWord16	Writes prepared data in to the Fault Register.	✓	✓
EFPWM_WRITE_FAULT0_STATUS_REG	UWord16	Writes prepared data in to the Fault Status Register.	✓	✓
EFPWM_WRITE_FAULT1_CONTROL_REG	UWord16	Writes prepared data in to the Fault Register.	✓	✓
EFPWM_WRITE_FAULT1_STATUS_REG	UWord16	Writes prepared data in to the Fault Status Register.	✓	✓
EFPWM_WRITE_MASK_REG	UWord16	Writes prepared data in to the Mask Register.	✓	✓
EFPWM_WRITE_MASTER_CONTROL_REG	UWord16	Writes prepared data to the Master Control Register.	✓	✓
EFPWM_WRITE_OUTPUT_ENABLE_REG	UWord16	Writes prepared data in to the Output Enable Register.	✓	✓
EFPWM_WRITE_SW_CONTROL_OUT_REG	UWord16	Writes prepared data in to the Soft-ware Controlled Output Register.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWMS_ACTIVE_CAPTURE_A	NULL	Actives capture A operation.	✓	✓
EFPWMS_ACTIVE_CAPTURE_B	NULL	Actives capture B operation.	✓	✓
EFPWMS_ACTIVE_CAPTURE_X	NULL	Actives capture B operation.	✓	✓
EFPWMS_ACTIVE_FORCE_INIT	NULL	Active force initialization.	✓	✓
EFPWMS_CAPTURE_A_DISABLE	NULL	Disable capture A operation.	✓	✓
EFPWMS_CAPTURE_B_DISABLE	NULL	Disable capture B operation.	✓	✓
EFPWMS_CAPTURE_X_DISABLE	NULL	Disable capture B operation.	✓	✓
EFPWMS_CENTER_ALIGN_UPDATE_CHANNEL_23	Word16 in Signed Fractional representation	Range 0 to 1, Set Value2 and Value3 registers.	✓	✓
EFPWMS_CENTER_ALIGN_UPDATE_CHANNEL_23_FRAC	Word16 in Signed Fractional representation	Range 0 to 1, Modulo register can be maximally 1024, Set Value2, Fractional2, Value3 and Fractional3 registers.	✓	✓
EFPWMS_CENTER_ALIGN_UPDATE_CHANNEL_45	Word16 in Signed Fractional representation	Range 0 to 1, Set Value4 and Value5 registers.	✓	✓
EFPWMS_CENTER_ALIGN_UPDATE_CHANNEL_45_FRAC	Word16 in Signed Fractional representation	Range 0 to 1, Modulo register can be maximally 1024, Set Value2, Fractional2, Value3 and Fractional3 registers.	✓	✓
EFPWMS_CENTER_ALIGN_WRITE_CHANNEL_23	UWord16	Range 0 to 32767, Set Value2 and Value3 registers to generate center align output signal.	✓	✓
EFPWMS_CENTER_ALIGN_WRITE_CHANNEL_45	UWord16	Range 0 to 32767, Set Value4 and Value5 registers to generate center align output signal.	✓	✓
EFPWMS_CLEAR_SUBMODULE_FLAGS	EFPWM_xxx (RELOAD_ERROR|RELOAD|COMPARE_VAL0|COMPARE_VAL1|COMPARE_VAL2|COMPARE_VAL3|COMPARE_VAL4|COMPARE_VAL5|CAPTURE_A1|CAPTURE_A0|CAPTURE_B1|CAPTURE_B0|CAPTURE_X1|CAPTURE_X0)	Clear selected interrupt flags. note: All parameters are not supported in all PWM submodules, see documentation	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWMS_DEBUG_OPERATION	EFPWM_STOP/EFPWM_RUN	Set PWM operation during chip debugging.	✓	✓
EFPWMS_DMA_CAPTURE_DISABLE	EFPWM_DMA_FIFO_X0|EFPWM_DMA_FIFO_B0|EFPWM_DMA_FIFO_A0|EFPWM_DMA_FIFO_X1|EFPWM_DMA_FIFO_B1|EFPWM_DMA_FIFO_A1	Disable DMA read requests for the Capture (A0/A1/B0/B1/X0/X1) FIFO data in the DMA Enable Register	✓	✓
EFPWMS_DMA_CAPTURE_ENABLE	EFPWM_DMA_FIFO_X0|EFPWM_DMA_FIFO_B0|EFPWM_DMA_FIFO_A0|EFPWM_DMA_FIFO_X1|EFPWM_DMA_FIFO_B1|EFPWM_DMA_FIFO_A1	Enable DMA read requests for the Capture (A0/A1/B0/B1/X0/X1) FIFO data in the DMA Enable Register.	✓	✓
EFPWMS_DMA_FIFO_WATERMARK_CONTROL	EFPWM_DMA_WRITE_FIFO_WATERMARK_AND/EFPWM_DMA_WRITE_FIFO_WATERMARK_OR	Select whether FIFO watermarks are OR'ed or AND'ed together. Modify the DMA Enable Register.	✓	✓
EFPWMS_DMA_SET_CLOCK_SOURCE	EFPWM_DMA_REQUEST_DISABLE/EFPWM_DMA_REQUEST_FIFO_WATERMARK/EFPWM_DMA_REQUEST_LOCAL_SYNC/EFPWM_DMA_REQUEST_LOCAL_RELOAD	Enable Source for Capture DMA according to command parameter. Modify the DMA Enable Register.	✓	✓
EFPWMS_DMA_VALUE_REGISTERS	EFPWM_DMA_WRITE_REQUEST_ENABLE/EFPWM_DMA_WRITE_REQUEST_DISABLE	Enable/disable DMA write requests for the VALx and FRACVALx registers. Modify the DMA Enable Register.	✓	✓
EFPWMS_EDGE_ALIGN_UPDATE_CHANNEL_23	Word16 in Signed Fractional representation	Range 0 to 1, Set Value2 and Value3 registers.	✓	✓
EFPWMS_EDGE_ALIGN_UPDATE_CHANNEL_23_FRAC	Word16 in Signed Fractional representation	Range 0 to 1, Modulo register can be maximally 1024, Set Value2, Fractional2, Value3 and Fractional3 registers.	✓	✓
EFPWMS_EDGE_ALIGN_UPDATE_CHANNEL_45	Word16 in Signed Fractional representation	Range 0 to 1, Set Value2 and Value3 registers.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWMS_EDGE_ALIGN_UPDATE_CHANNEL_45_FRAC	Word16 in Signed Fractional representation	Range 0 to 1, Modulo register can be maximally 1024, Set Value4, Fractional4, Value5 and Fractional5 registers.	✓	✓
EFPWMS_EDGE_ALIGN_WRITE_CHANNEL_23	UWord16	Range 0 to 32767, Set Value2 and Value3 registers to generate edge align output signal.	✓	✓
EFPWMS_EDGE_ALIGN_WRITE_CHANNEL_45	UWord16	Range 0 to 32767, Set Value4 and Value5 registers to generate edge align output signal.	✓	✓
EFPWMS_FULL_CYCLE_RELOAD	EFPWM_ENABLE/EFPWM_DISABLE	Enable/disable full cycle reload.	✓	✓
EFPWMS_HALF_CYCLE_RELOAD	EFPWM_ENABLE/EFPWM_DISABLE	Enable/disable middle cycle reload.	✓	✓
EFPWMS_INT_DISABLE	EFPWM_xxx (RELOAD_ERROR|RELOAD|COMPARE_VAL0|COMPARE_VAL1|COMPARE_VAL2|COMPARE_VAL3|COMPARE_VAL4|COMPARE_VAL5|CAPTURE_A1|CAPTURE_A0|CAPTURE_B1|CAPTURE_B0|CAPTURE_X1|CAPTURE_X0)	Enable selected interrupts. note: All parameters are not supported in all PWM submodules, see documentation	✓	✓
EFPWMS_INT_ENABLE	EFPWM_xxx (RELOAD_ERROR|RELOAD|COMPARE_VAL0|COMPARE_VAL1|COMPARE_VAL2|COMPARE_VAL3|COMPARE_VAL4|COMPARE_VAL5|CAPTURE_A1|CAPTURE_A0|CAPTURE_B1|CAPTURE_B0|CAPTURE_X1|CAPTURE_X0)	Enable selected interrupts. note: All parameters are not supported in all PWM submodules, see documentation	✓	✓
EFPWMS_OUTPUT_TRIGGER_DISABLE	EFPWM_TRIG0_VALx(0|2|4)|EFPWM_TRIG1_VALx(1|3|5)	Disconnect selected output triggers from OUT_TRIG0 and OUT_TRIG1 signals.	✓	✓
EFPWMS_OUTPUT_TRIGGER_ENABLE	EFPWM_TRIG0_VALx(0|2|4)|EFPWM_TRIG1_VALx(1|3|5)	Connect selected output triggers in to OUT_TRIG0 and OUT_TRIG1 signals.	✓	✓
EFPWMS_PWMA_FAULT_DISABLE	EFPWM_FAULT_X(0|1|2|3)	Disable selected faults at PWM A pin.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWMS_PWMA_FAULT_ENABLE	EFPWM_FAULT_X(0|1|2|3)	Enable selected faults at PWM A pin.	✓	✓
EFPWMS_PWMA_FAULT0_DISABLE	EFPWM_FAULT_X(0|1|2|3)	Disable selected faults at PWM A pin.	✓	✓
EFPWMS_PWMA_FAULT0_ENABLE	EFPWM_FAULT_X(0|1|2|3)	Enable selected faults at PWM A pin.	✓	✓
EFPWMS_PWMA_FAULT1_DISABLE	EFPWM_FAULT_X(0|1|2|3)	Disable selected faults at PWM A pin.	✓	✓
EFPWMS_PWMA_FAULT1_ENABLE	EFPWM_FAULT_X(0|1|2|3)	Enable selected faults at PWM A pin.	✓	✓
EFPWMS_PWMB_FAULT_DISABLE	EFPWM_FAULT_X(0|1|2|3)	Disable selected faults at PWM B pin.	✓	✓
EFPWMS_PWMB_FAULT_ENABLE	EFPWM_FAULT_X(0|1|2|3)	Enable selected faults at PWM B pin.	✓	✓
EFPWMS_PWMB_FAULT0_DISABLE	EFPWM_FAULT_X(0|1|2|3)	Disable selected faults at PWM B pin.	✓	✓
EFPWMS_PWMB_FAULT0_ENABLE	EFPWM_FAULT_X(0|1|2|3)	Enable selected faults at PWM B pin.	✓	✓
EFPWMS_PWMB_FAULT1_DISABLE	EFPWM_FAULT_X(0|1|2|3)	Disable selected faults at PWM B pin.	✓	✓
EFPWMS_PWMB_FAULT1_ENABLE	EFPWM_FAULT_X(0|1|2|3)	Enable selected faults at PWM B pin.	✓	✓
EFPWMS_PWMX_FAULT_DISABLE	EFPWM_FAULT_X(0|1|2|3)	Disable selected faults at PWM X pin.	✓	✓
EFPWMS_PWMX_FAULT_ENABLE	EFPWM_FAULT_X(0|1|2|3)	Enable selected faults at PWM X pin.	✓	✓
EFPWMS_PWMX_FAULT0_DISABLE	EFPWM_FAULT_X(0|1|2|3)	Disable selected faults at PWM X pin.	✓	✓
EFPWMS_PWMX_FAULT0_ENABLE	EFPWM_FAULT_X(0|1|2|3)	Enable selected faults at PWM X pin.	✓	✓
EFPWMS_PWMX_FAULT1_DISABLE	EFPWM_FAULT_X(0|1|2|3)	Disable selected faults at PWM X pin.	✓	✓
EFPWMS_PWMX_FAULT1_ENABLE	EFPWM_FAULT_X(0|1|2|3)	Enable selected faults at PWM X pin.	✓	✓
EFPWMS_READ_CAPTURE_A0_FIFO_COUNT	NULL	Return value of FIFO counter.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWMS_READ_CAPTURE_A1_FIFO_COUNT	NULL	Return value of FIFO counter.	✓	✓
EFPWMS_READ_CAPTURE_B0_FIFO_COUNT	NULL	Return value of FIFO counter.	✓	✓
EFPWMS_READ_CAPTURE_B1_FIFO_COUNT	NULL	Return value of FIFO counter.	✓	✓
EFPWMS_READ_CAPTURE_CYCLE_VAL0	NULL	Return Capture Value 0.	✓	✓
EFPWMS_READ_CAPTURE_CYCLE_VAL1	NULL	Return Capture Value 1.	✓	✓
EFPWMS_READ_CAPTURE_CYCLE_VAL2	NULL	Return Capture Value 2.	✓	✓
EFPWMS_READ_CAPTURE_CYCLE_VAL3	NULL	Return Capture Value 3.	✓	✓
EFPWMS_READ_CAPTURE_CYCLE_VAL4	NULL	Return Capture Value 4.	✓	✓
EFPWMS_READ_CAPTURE_CYCLE_VAL5	NULL	Return Capture Value 5.	✓	✓
EFPWMS_READ_CAPTURE_VAL0	NULL	Return Capture Value 0.	✓	✓
EFPWMS_READ_CAPTURE_VAL1	NULL	Return Capture Value 1.	✓	✓
EFPWMS_READ_CAPTURE_VAL2	NULL	Return Capture Value 2.	✓	✓
EFPWMS_READ_CAPTURE_VAL3	NULL	Return Capture Value 3.	✓	✓
EFPWMS_READ_CAPTURE_VAL4	NULL	Return Capture Value 4.	✓	✓
EFPWMS_READ_CAPTURE_VAL5	NULL	Return Capture Value 5.	✓	✓
EFPWMS_READ_CAPTURE_X0_FIFO_COUNT	NULL	Return value of FIFO counter.	✓	✓
EFPWMS_READ_CAPTURE_X1_FIFO_COUNT	NULL	Return value of FIFO counter.	✓	✓
EFPWMS_READ_COUNTER_REG	NULL	Return value from the Counter Register.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWMS_READ_EDGE_COUNTER_A	NULL	Return Edge counter value.	✓	✓
EFPWMS_READ_EDGE_COUNTER_B	NULL	Return Edge counter value	✓	✓
EFPWMS_READ_EDGE_COUNTER_X	NULL	Return Edge counter value.	✓	✓
EFPWMS_READ_INIT_REG	NULL	Return Word16 from the Init Register.	✓	✓
EFPWMS_READ_VALUE_REG_0	NULL	Return Word16 from Value Register 0.	✓	✓
EFPWMS_READ_VALUE_REG_1	NULL	Return Word16 from Value Register 1.	✓	✓
EFPWMS_READ_VALUE_REG_2	NULL	Return Word16 from Value Register 2.	✓	✓
EFPWMS_READ_VALUE_REG_3	NULL	Return Word16 from Value Register 3.	✓	✓
EFPWMS_READ_VALUE_REG_4	NULL	Return Word16 from Value Register 4.	✓	✓
EFPWMS_READ_VALUE_REG_5	NULL	Return Word16 from Value Register 5.	✓	✓
EFPWMS_SET_CAPTURE_A_0	EFPWM_CAPTURE_0_XXX (DISABLE/FALLING_EDGE/RISING_EDGE/ANY_EDGE)	Set input capture A 0 edge sensitivity.	✓	✓
EFPWMS_SET_CAPTURE_A_1	EFPWM_CAPTURE_1_XXX (DISABLE/FALLING_EDGE/RISING_EDGE/ANY_EDGE)	Set input capture A 1 edge sensitivity.	✓	✓
EFPWMS_SET_CAPTURE_A_FIFO_WATERMARK	UWord16	Value 0 to 3 (in 824x5x value 0 to 1).	✓	✓
EFPWMS_SET_CAPTURE_A_INPUT	EFPWM_RAW_INPUT/EFPWM_EDGE_COUNTER	Set input capture A source.	✓	✓
EFPWMS_SET_CAPTURE_A_MODE	EFPWM_FREE_RUNNING/ EFPWM_ONE_SHOT	Set capture mode.	✓	✓
EFPWMS_SET_CAPTURE_B_0	EFPWM_CAPTURE_0_XXX (DISABLE/FALLING_EDGE/RISING_EDGE/ANY_EDGE)	Set input capture B 0 edge sensitivity.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWMS_SET_CAPTURE_B_1	EFPWM_CAPTURE_1_XXX (DISABLE/FALLING_EDGE/RISING_EDGE/ANY_EDGE)	Set input capture B 1 edge sensitivity.	✓	✓
EFPWMS_SET_CAPTURE_B_FIFO_WATERMARK	UWord16	Value 0 to 3 (in 824x5x value 0 to 1).	✓	✓
EFPWMS_SET_CAPTURE_B_INPUT	EFPWM_RAW_INPUT/EFPWM_EDGE_COUNTER	Set input capture B source.	✓	✓
EFPWMS_SET_CAPTURE_B_MODE	EFPWM_FREE_RUNNING/EFPWM_ONE_SHOT	Set capture mode.	✓	✓
EFPWMS_SET_CAPTURE_X_0	EFPWM_CAPTURE_0_XXX (DISABLE/FALLING_EDGE/RISING_EDGE/ANY_EDGE)	Set input capture X 0 edge sensitivity.	✓	✓
EFPWMS_SET_CAPTURE_X_1	EFPWM_CAPTURE_1_XXX (DISABLE/FALLING_EDGE/RISING_EDGE/ANY_EDGE)	Set input capture X 1 edge sensitivity.	✓	✓
EFPWMS_SET_CAPTURE_X_FIFO_WATERMARK	UWord16	Value 0 to 3 (in 824x5x value 0 to 1).	✓	✓
EFPWMS_SET_CAPTURE_X_INPUT	EFPWM_RAW_INPUT/EFPWM_EDGE_COUNTER	Set input capture X source.	✓	✓
EFPWMS_SET_CAPTURE_X_MODE	EFPWM_FREE_RUNNING/EFPWM_ONE_SHOT	Set capture mode.	✓	✓
EFPWMS_SET_CENTER_ALIGN_MODULO_INIT_REG	UWord16	Range 0 to 2^16-2, writes modulo value in to Var1 register and Init register to prepare generating Center Align output signal.	✓	✓
EFPWMS_SET_CLOCK_SOURCE	EFPWM_XXX_CLOCK (IPBUS/EXT/SUB0)	Set reload PWM clock source.	✓	✓
EFPWMS_SET_COMPARE_A	UWord16	Set Edge Compare A value, value 0 to 255.	✓	✓
EFPWMS_SET_COMPARE_B	UWord16	Edge Compare B value, value 0 to 255	✓	✓
EFPWMS_SET_COMPARE_X	UWord16	Edge Compare X value, value 0 to 255.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWMS_SET_COMPLEMENTARY_MODE	NULL	Set pair operation to complementary.	✓	✓
EFPWMS_SET_DEADTIME_0	UWord16	Deadtime 0 logic; value 0 to 2048. Modify Deadtime Count Register 0.	✓	✓
EFPWMS_SET_DEADTIME_1	UWord16	Deadtime 1 logic; value 0 to 2048. Modify Deadtime Count Register 1.	✓	✓
EFPWMS_SET_DOUBLE_SWITCHING	EFPWM_ENABLE/EFPWM_DISABLE	Enable/disable double switching mode.	✓	✓
EFPWMS_SET_EDGE_ALIGN_MODULO_INIT_REG	UWord16	Range 0 to 32767, writes modulo value in to Var1 register and Init register to prepare generating Edge Align output signal.	✓	✓
EFPWMS_SET_EDGE_COUNTER_A	EFPWM_ENABLE/EFPWM_DISABLE	Enable/disable edge counter A.	✓	✓
EFPWMS_SET_EDGE_COUNTER_B	EFPWM_ENABLE/EFPWM_DISABLE	Enable/disable edge counter B.	✓	✓
EFPWMS_SET_EDGE_COUNTER_X	EFPWM_ENABLE/EFPWM_DISABLE	Enable/disable edge counter X.	✓	✓
EFPWMS_SET_FORCE_INIT	EFPWM_ENABLE/EFPWM_DISABLE	Enable/disable force initialization.	✓	✓
EFPWMS_SET_FORCE_INIT_PWMOUT_TO_HIGH	EFPWM_CHANNEL_45|EFPWM_CHANNEL_23|EFPWM_CHANNEL_X	Determine the initial value and the value to which it is forced when FORCE_INIT;Control 2 Register.	✓	✓
EFPWMS_SET_FORCE_INIT_PWMOUT_TO_LOW	EFPWM_CHANNEL_45|EFPWM_CHANNEL_23|EFPWM_CHANNEL_X	Determine the initial value and the value to which it is forced when FORCE_INIT;Control 2 Register.	✓	✓
EFPWMS_SET_FORCE_INIT_SOURCE	EFPWM_FORCE_XXX (LOCAL_FORCE/MASTER_FORCE/LOCAL_RELOAD/MASTER_RELOAD/LOCAL_SYNC/MASTER_SYNC/EXT_SYNC)	Select force initialization source.	✓	✓
EFPWMS_SET_FRACTIONAL_DELAY_DISABLE	EFPWM_FRAC_DELAY_X (1|23|45|POWERUP)	Disable selected fractional delay block.	✓	✓
EFPWMS_SET_FRACTIONAL_DELAY_ENABLE	EFPWM_FRAC_DELAY_X (1|23|45|POWERUP)	Enable selected fractional delay block.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWMS_SET_INDEPENDENT_MODE	NULL	Set pair operation to independent.	✓	✓
EFPWMS_SET_LOAD_MODE	EFPWM_LOAD_xx (IMMEDIATE/END_CYCLE)	Select load mode.	✓	✓
EFPWMS_SET_PAIR_OPERATION	EFPWM_XXX (COMPLEMENTARY/INDEPENDENT)	Set pair operation.	✓	✓
EFPWMS_SET_PRESCALER	EFPWM_PRESCALER_DIV_X (1/2/4/8/16/32/64/128)	Set reload PWM submodule prescaler.	✓	✓
EFPWMS_SET_PWM_FAULT_STATEOUT_A	EFPWM_XXX (LOG_0/LOG_1/TRISTATED)	Set level of output pin PWMA during fault state.	✓	✓
EFPWMS_SET_PWM_FAULT_STATEOUT_B	EFPWM_XXX (LOG_0/LOG_1/TRISTATED)	Set level of output pin PWMB during fault state.	✓	✓
EFPWMS_SET_PWM_FAULT_STATEOUT_X	EFPWM_XXX (LOG_0/LOG_1/TRISTATED)	Set level of output pin PWMX during fault state.	✓	✓
EFPWMS_SET_PWM_POLARITY_HIGH_ACTIVE	EFPWM_OUTPUT_X (A|B|X)	Set output polarity to non inverted, where high is active state.	✓	✓
EFPWMS_SET_PWM_POLARITY_LOW_ACTIVE	EFPWM_OUTPUT_X (A|B|X)	Set output polarity to inverted, where low is active state	✓	✓
EFPWMS_SET_RELOAD_FREQUENCY	EFPWM_RELOAD_OPPORTUNITY_X(1 to 16)	Set reload period.	✓	✓
EFPWMS_SET_RELOAD_SOURCE	EFPWM_RELOAD_XXX (LOCAL/MASTER)	Select PWM reload source.	✓	✓
EFPWMS_SET_SYNC_SOURCE	EFPWM_XXX (LOCAL_SYNC/MASTER_RELOAD/MASTER_SYNC/EXT_SYNC)	Set reload PWM sync source.	✓	✓
EFPWMS_SPLIT_DBLPWM	EFPWM_ENABLE/EFPWM_DISABLE	Enable/disable splitting one pulse on PWMA and one on PWMB.	✓	
EFPWMS_TEST_DEADTIME_SAMPLE_BITS	EFPWM_DEADTIME_0_BIT|EFPWM_DEADTIME_1_BIT	Return sampled PWMX inputs at dealdtime 0/1.	✓	✓
EFPWMS_TEST_PWM_INPUTS	EFPWM_INPUT_X (A|B|X)	Return actual state of selected PWM pins.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWMS_TEST_SUBMODULE_FLAGS	EFPWM_xxx (REGISTER_UPDATE|RELOAD_ERROR|RELOAD|COMPARE_VAL0|COMPARE_VAL1|COMPARE_VAL2|COMPARE_VAL3|COMPARE_VAL4|COMPARE_VAL5|CAPTURE_A1|CAPTURE_A0|CAPTURE_B1|CAPTURE_B0|CAPTURE_X1|CAPTURE_X0)	Return state of selected interrupt flags. note: All parameters are not supported in all PWM submodules, see documentation	✓	✓
EFPWMS_WAIT_OPERATION	EFPWM_STOP/EFPWM_RUN	Set PWM operation during the wait mode.	✓	✓
EFPWMS_WRITE_FAULT_MAPPING_REG	UWord16	Write directly in to the fault Disable Mapping Register.	✓	✓
EFPWMS_WRITE_FAULT0_MAPPING_REG	UWord16	Write directly in to the fault Disable Mapping Register.	✓	✓
EFPWMS_WRITE_FAULT1_MAPPING_REG	UWord16	Write directly in to the fault Disable Mapping Register.	✓	✓
EFPWMS_WRITE_FRAC_VALUE_REG_1	Word16	Write fractional Value to Fractional Value Register 1.	✓	✓
EFPWMS_WRITE_FRAC_VALUE_REG_2	Word16	Write fractional Value to Fractional Value Register 2.	✓	✓
EFPWMS_WRITE_FRAC_VALUE_REG_3	Word16	Write fractional Value to Fractional Value Register 3.	✓	✓
EFPWMS_WRITE_FRAC_VALUE_REG_4	Word16	Write fractional Value to Fractional Value Register 4.	✓	✓
EFPWMS_WRITE_FRAC_VALUE_REG_5	Word16	Write fractional Value to Fractional Value Register 5.	✓	✓
EFPWMS_WRITE_INIT_REG	Word16	Write value to the Init Register.	✓	✓
EFPWMS_WRITE_OUTPUT_CONTROL_REG	UWord16	Writes in to Output Control Register	✓	✓
EFPWMS_WRITE_VALUE_REG_0	Word16	Write Value to Value Register 0.	✓	✓
EFPWMS_WRITE_VALUE_REG_1	Word16	Write Value to Value Register 1.	✓	✓
EFPWMS_WRITE_VALUE_REG_2	Word16	Write Value to Value Register 2.	✓	✓

Table 5-19. EFPWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EFPWMS_WRITE_VALUE_REG_3	Word16	Write Value to Value Register 3.	✓	✓
EFPWMS_WRITE_VALUE_REG_4	Word16	Write Value to Value Register 4.	✓	✓
EFPWMS_WRITE_VALUE_REG_5	Word16	Write Value to Value Register 5.	✓	✓

5.1.9 Enhanced Quadrature Encoder/Decoder (ENC)

The enhanced quadrature encoder/decoder module provides interfacing capability to position/speed sensors used in industrial motor control applications. It has four input signals: PHASEA, PHASEB, INDEX, and HOME. This module is used to decode shaft position, revolution count and speed.

The Table 5-20 shows module identifiers for ENC Driver.

Table 5-20. Identifiers for ENC Driver

Module identifier	56F82xxx	56F84xxx
ENC		✓

The Table 5-21 shows all commands for ENC Driver.

Table 5-21. ENC Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ENC_CALCULATE_SCALE_COEF	pointer to decoder_sEncScale type	Calculate the scaling coefficients needed for correct functionality of the ENC_GET_SCALED_POSITION and the ENC_GET_SCALED_POSITION_DIFFERENCE commands. This command must be executed before using the scaling position commands. The EncPulses and RevolutionScale members of the decoder_sEncScale structure should be set prior to calling this command. EncPulses represents the nominal number of Encoder pulses per revolution and RevolutionScale represents the number of revolutions to be reflected by the 16 bit register full range: RevolutionScale = n represents a range +/- 2^(n)*PI.		✓
ENC_DIRECTION_COUNTING_ENABLE	ENC_REVERSE/ENC_NORMAL	Reverse the interpretation of the quadrature signal. It changes the direction of count.		✓
ENC_GET_COUNT_DIRECTION_FLAG	NULL	Get the direction flag of the last count (return 0/1 for the down/up direction).		✓

Table 5-21. ENC Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ENC_GET_FILTERED_ENCSIGNALS	NULL	Read and return the filtered version of HOME (Bit0), INDEX (Bit1), PHASEB (Bit2) and PHASEA (Bit3) encoder signals from the Input Monitor Register (IMR) as UWord16 or as decoder_sEncSignals structure members.		✓
ENC_GET_RAW_ENCSIGNALS	NULL	Read and return the raw version of HOME (Bit0), INDEX (Bit1), PHASEB (Bit2) and PHASEA (Bit3) encoder signals from the Input Monitor Register (IMR) as UWord16 or as decoder_sEncSignals structure members.		✓
ENC_GET_SCALED_POSITION	pointer to decoder_sEncScale type	Calculate and return absolute position as Word32, where the MSB part represents the number of revolutions (equals to the content of the Revolution Register) while the LSB part represents the portion of the current revolution, scaled into the range of a 16bit unsigned data. The DEC_CALCULATE_SCALE_COEF command must be executed prior to this command.		✓
ENC_GET_SCALED_POSITION_DIFFERENCE	pointer to decoder_sEncScale type	Calculate and return a relative position difference as Word16. The DEC_CALCULATE_SCALE_COEF command must be executed prior to this command. This command reads the content of the Position Difference Counter Register (POSD).		✓
ENC_GET_TEST_COUNT	NULL	Get the number of quadrature advances to generate during self-test operation.		✓
ENC_GET_TEST_PERIOD	NULL	Get the number of quadrature advances to generate during self-test operation.		✓
ENC_HOME_EDGE	ENC_NEGATIVE/ENC_POSITIVE	Set the rising or falling edge of the HOME signal to trigger the initialization of the Upper and the Lower Position Counter Registers (UPOS, LPOS).		✓

Table 5-21. ENC Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ENC_HOME_TRIGGERED_INIT	ENC_ENABLE/ENC_DISABLE	Enable/disable the initialization of the Upper and Lower Position Counter Registers (UPOS, LPOS) with the HOME signal.		✓
ENC_INDEX_EDGE	ENC_NEGATIVE/ENC_POSITIVE	Set the rising or falling edge of the INDEX pulse to trigger the initialization of the Upper and Lower Position Counter Registers (UPOS, LPOS).		✓
ENC_INDEX_TRIGGERED_INIT	ENC_ENABLE/ENC_DISABLE	Enable/disable the initialization of the Upper and the Lower Position Counter Registers (UPOS, LPOS) using the INDEX pulse.		✓
ENC_INIT	NULL	Initialize the ENC peripheral registers using the appconfig.h _INIT values.		✓
ENC_INT_DISABLE	combination of ENC_xxx (xxx=HOME|INDEX|WDTIMEOUT|COMPARE)	Disable the selected interrupt.		✓
ENC_INT_ENABLE	combination of ENC_xxx (xxx=HOME|INDEX|WDTIMEOUT|COMPARE)	Enable the selected interrupt.		✓
ENC_INT_REQUEST_CLEAR	combination of ENC_xxx (xxx=HOME|INDEX|WDTIMEOUT|COMPARE)	Clear the selected interrupt flag.		✓
ENC_INT_ROLL_DISABLE	combination of ENC_ROLL_xxx (xxx=OVER|UNDER)	Disable the selected interrupt.		✓
ENC_INT_ROLL_ENABLE	combination of ENC_ROLL_xxx (xxx=OVER|UNDER)	Enable the selected interrupt.		✓
ENC_INT_ROLL_REQUEST_CLEAR	combination of ENC_ROLL_xxx (xxx=OVER|UNDER)	Clear the selected interrupt request flag. The roll-over interrupt request is set when the position counter (POS) rolls over from the MOD value to the INIT value or from 0xffffffff to 0x00000000. The roll-under interrupt request is set when the position counter (POS) rolls under from the INIT value to the MOD value or from 0x00000000 to 0xffffffff.		✓
ENC_READ_CONTROL_REG	NULL	Read and return the value of the Control register (CTRL) as UWord16.		✓

Table 5-21. ENC Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ENC_READ_CTRL2_REG	NULL	Read and return the value of the Control 2 register as UWord16.		✓
ENC_READ_HOLD_DATA_REGS	pointer to decoder_sState type	Read consistent snapshot of values of the Upper and Lower Position Counter Registers (UPOS, LPOS), the Position Difference Counter Register (POSD) and the Revolution Counter Register (REV). The values are filled to structure passed to a parameter.		✓
ENC_READ_MONITOR_REG	NULL	Read and return the content of the Input Monitor Register (IMR) as UWord16.		✓
ENC_READ_POSITION	pointer to the decoder_uReg32bit type or to UWord32	Read the content of the Upper and the Lower Position Counter registers (UPOS, LPOS).		✓
ENC_READ_POSITION_DIFFERENCE	NULL	Read and return the value of the Position Difference Counter register (POSD) as UWord16.		✓
ENC_READ_REVOLUTION	NULL	Read and return the value of the Revolution Counter register (REV) as UWord16.		✓
ENC_REVOLUTION_COUNTER_MOD_ENABLE	ENC_REV_INDEX/ENC_REV_MODULUS	Select the revolution counter (REV) source. By default REV is controlled based on the count direction and the INDEX pulse. REV can be controlled using the roll-over/under detection during modulo counting.		✓
ENC_SET_DECODER_SIGNAL_POLARITY	ENC_POSITIVE/ENC_NEGATIVE	Set the polarity of the quadrature decoder signal.		✓

Table 5-21. ENC Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ENC_SET_MODULO_COUNTING	ENC_ENABLE/ENC_DISABLE	Enable/disable the position counters (UPOS and LPOS) to count in a modulo fashion using MOD and INIT as the upper and lower bounds of the counting range. During modulo counting when a count up is indicated and the position counter is equal to MOD, then the postion counter will be reloaded with the value of INIT. When a count down is indicated and the position counter is equal to INIT, then the position counter will be reloaded with the value of MOD. When clear, then the values of MOD and INIT are ignored and the position counter wraps around the 0 value.		✓
ENC_SET_POSMATCH_OUTPUT	ENC_POS_COMP_MATCH/ ENC_REGS_READ	Select the behavior of the POSMATCH output signal. The POSMATCH output can be used to trigger a timer channel to record the time stamp. Use ENC_POS_COMP_MATCH - to record the time stamp when a match occurs between the position counters (POS) and the compare value (COMP). Use ENC_REGS_READ - to record the time stamp when the UPOS, LPOS, REV, or POSD registers are read.		✓
ENC_SET_TEST_COUNT	UWord16 value 0-255	Set the number of quadrature advances to generate during self-test operation.		✓
ENC_SET_TEST_COUNTER	ENC_ENABLE/ENC_DISABLE	Enable/disable the test counter to generate the quadrature signal used for self-test.		✓
ENC_SET_TEST_MODE	ENC_ENABLE/ENC_DISABLE	Enable/disable the connection of self-test signals to the inputs of the quadrature decoder module.		✓
ENC_SET_TEST_PERIOD	Uword16 value 0-31	Set the period of quadrature phase in IPBus clock cycles for the self-test operation.		✓
ENC_SET_TRG_CLEAR_POSITION_REGISTERS	ENC_ENABLE/ENC_DISABLE	Enable/disable the rising edge of TRIGGER input to clear POSD, REV, UPOS and LPOS registers.		✓

Table 5-21. ENC Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ENC_SET_TRG_UPDATE_HOLD_REGISTERS	ENC_ENABLE/ENC_DISABLE	Enable/disable the rising edge of the TRIGGER input to cause an update of the POSDH, REVH, UPOSH, and LPOSH registers. Note: Updating the POSDH register will also cause the POSD register to be cleared.		✓
ENC_SINGLE_PHASE_COUNT	ENC_ENABLE/ENC_DISABLE	Enable/disable the Quadrature Decoder logic. When the Quadrature Decoder logic is bypassed, the PHASEA signal is used as a single phase pulse stream and PHASEB is ignored.		✓
ENC_SOFTWARE_TRIGGERED_INIT	NULL	Initialize the Upper and the Lower Position Counter Registers (UPOS, LPOS) by the values stored in the Upper and the Lower Initialization Registers.		✓
ENC_WATCHDOG	ENC_ENABLE/ENC_DISABLE	Enable/disable the watchdog timer to monitor PHASEA and PHASEB inputs changes.		✓
ENC_WRITE_CTRL2_REG	UWord16	Write to the Control 2 register the parameter value. Note: an inappropriate write to register may cause accidental clear of Write-1-to-Clear flags (ROIRQ/RUIRQ).		✓
ENC_WRITE_FILTER	UWord16 value 0-255	Set the filter interval periods in number of IP Bus clock periods.		✓
ENC_WRITE_FILTER_COUNT_SAMPLES_COUNT	UWord16 value 0-7	Set the number of consecutive samples that must agree prior to the input filter accepting an input transition. A value of 0x0 represents 3 samples. A value of 0x7 represents 10 samples. This value affects the input signal latency.		✓
ENC_WRITE_INIT_STATE	Word32	Writes the parameter value to the Lower and the Upper Initialization Registers (UINIT, LINIT). This value represents the initialization number of encoder pulses.		✓
ENC_WRITE_LOWER_MODULUS_REG	UWord16	Write the parameter value to the Lower Modulus register.		✓

Table 5-21. ENC Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
ENC_WRITE_LOWER_POSITION_COMPARE_REG	UWord16	Write the parameter value to the Lower Position Compare register.		✓
ENC_WRITE_POSITION	Word32	Write the parameter value to the Lower and the Upper Position Counter Registers (UPOS, LPOS). This value represents the required number of encoder pulses. This command writes the value to the Upper and the Lower Initialization Register followed by initialization of the position registers with the software trigger command.		✓
ENC_WRITE_REVOLUTION	Word16	Write the parameter value to the Revolution Counter register (REV). This value represents the required number of revolutions.		✓
ENC_WRITE_UPPER_MODULUS_REG	UWord16	Write the parameter value to the Upper Modulus register.		✓
ENC_WRITE_UPPER_POSITION_COMPARE_REG	UWord16	Write the parameter value to the Upper Position Compare register.		✓
ENC_WRITE_WATCHDOG_TIMEOUT	UWord16	Set the number of clock cycles (plus one added by hardware) that the watchdog timer counts before timing out and optionally generating an interrupt.		✓

5.1.10 External Watchdog Monitor (EWM) Driver

For safety, a redundant watchdog system, External Watchdog Monitor (EWM), is designed to monitor external circuits and the MCU software flow. This provides a back-up mechanism to the internal watchdog that resets the MCU's CPU and peripherals. The EWM differs from the internal watchdog in that it does not reset the MCU's CPU and peripherals. The EWM, if allowed to time-out, provides an independent EWM_out pin that when asserted resets or places an external circuit into a safe mode. The CPU resets the EWM counter that is logically ANDed with an external digital input pin. This pin allows an external circuit to influence the reset_out signal.

The Table 5-22 shows module identifiers for EWM Driver.

Table 5-22. Identifiers for EWM Driver

Module identifier	56F82xxx	56F84xxx
EWM	✓	✓

The Table 5-23 shows all commands for EWM Driver.

Table 5-23. EWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EWM_CLEAR_COUNTER	NULL	Clear/service the EWM counter (both steps are performed).	✓	✓
EWM_DEVICE_CONFIG	combination of EWM_xxx (xxx=INPUT_ENABLED|EWM_INT_ENABLED|EWM_ASERTION_ONE|EWM_DEVICE_ENABLE)	Configure the EWM device. The command may be used only once, for the next time the reset is needed, because the register can be written to only once after the CPU reset. Modifying these bits more than once, generates a bus transfer error.	✓	✓
EWM_INIT	NULL	Initialize the EWM (External watchdog monitor) peripheral registers using the appconfig.h _INIT values.	✓	✓
EWM_READ_COMPAREH_REG	NULL	Read and return the value of the Compare High Register.	✓	✓
EWM_READ_COMPAREL_REG	NULL	Read and return the value of the Compare Low Register.	✓	✓
EWM_SELECT_CLK	EWM_xxx (xxx=ROSC_8M/XTAL_OSC/EWM_BUS_CLK/EWM_ROSC_32K)	Select the low power clock sources for running the EWM counter. Register can be written only once after the CPU reset. Modifying these bits more than once, generates a bus transfer error.	✓	✓

Table 5-23. EWM Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
EWM_SET_PRESCALER	UWORD16 value 0-255	Set the EWM the prescaler value. Call this command before enabling the EWM. The register can be written to only once after the CPU reset. Modifying these bits more than once, generates a bus transfer error.	✓	✓
EWM_WRITE_COMPAREH_REG	UWord16 value 0-255	Set the maximum time to service the EWM counter. The expiration happens only if EWM counter is greater than CMPH. This register can be written only once after the CPU reset.	✓	✓
EWM_WRITE_COMPAREL_REG	UWord16 value 0-255	Set the minimum time to service the EWM counter. This register can be written only once after the CPU reset.	✓	✓
EWM_WRITE_SERVICE_REG	UWord16 value 0-255	Write the Service register. The EWM service mechanism requires the CPU to write two values to the SERV register: a first data byte of 0xB4, followed by a second data byte of 0x2C.	✓	✓

5.1.11 FlexCAN (FCAN) Driver

This driver has only 56F84xxx devices. The FlexCAN module is a communication controller implementing the CAN protocol according to the CAN 2.0B protocol specification. A general block diagram is shown in the following figure, which describes the main sub-blocks implemented in the FlexCAN module, including one associated memory for storing Message Buffers, Rx Global Mask Registers, Rx Individual Mask Registers, Rx FIFO and Rx FIFO ID Filters. The functions of the sub-modules are described in subsequent sections.

The Table 5-24 shows module identifiers for FCAN Driver.

Table 5-24. Identifiers for FCAN Driver

Module identifier	56F82xxx	56F84xxx
FCAN		✓

The Table 5-25 shows commands dedicated for FCAN Driver.

Table 5-25. FCAN Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
FCAN_INIT	NULL	Initialize FlexCAN peripheral registers using the appconfig.h _INIT values.		✓
FCAN_MODULE	FCAN_ENABLE/FCAN_DISABLE	Enable or disable the FlexCAN module.		✓
FCAN_DOZE_MODE	FCAN_ENABLE/FCAN_DISABLE	Enable/disable Low-power Doze (Stop) Mode.		✓
FCAN_STOP_MODE	FCAN_ENABLE/FCAN_DISABLE	Backward compatibility alias for FCAN_DOZE_MODE.		✓
FCAN_DEBUG_MODE	FCAN_ENABLE/FCAN_DISABLE	Enter/Leave Freeze (Debug/halt) mode.		✓
FCAN_SOFT_RESET	NULL	Trigger the soft-reset of the FlexCAN module. Do not use in when FlexCAN is in low power mode.		✓
FCAN_SELF_WAKEUP_MODE	FCAN_ENABLE/FCAN_DISABLE	Enable or disable Self-Wakeup mode when bus activity is detected.		✓
FCAN_TEST_READY	NULL	Test if FlexCAN module is ready (MCR.NOTRDY bit cleared).		✓
FCAN_TEST_DEBUG	NULL	Test if FlexCAN is in the Freeze mode (MCR.FREEZ_ACK bit).		✓

Table 5-25. FCAN Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
FCAN_TEST_STOP	NULL	Test if FlexCAN module is in the Low-power mode (MCR.LPMACK bit).		✓
FCAN_INT_ENABLE	FCAN_xxx_INT (xxx=BUSOFF|ERROR|WAKEUP|TX_WARNING|RX_WARNING)	Enable selected interrupts. Note that the RX and TX Warning interrupts first need to be enabled by the FCAN_WARNING_INTERRUPT command.		✓
FCAN_INT_DISABLE	FCAN_xxx_INT (xxx=BUSOFF|ERROR|WAKEUP|TX_WARNING|RX_WARNING)	Disable selected interrupts.		✓
FCAN_WARNING_INTERRUPT	FCAN_ENABLE/FCAN_DISABLE	Enable or disable occurrence of warning interrupts; when enabled, the RX and/or TX warning interrupts still need to be enabled by the FCAN_INT_ENABLE command.		✓
FCAN_LOOPBACK_MODE	FCAN_ENABLE/FCAN_DISABLE	Enable or disable test loopback mode.		✓
FCAN_TIMER_SYNC_MODE	FCAN_ENABLE/FCAN_DISABLE	Enable or disable Timer Sync mode. In this mode the free-running timer is reset each time a message is received in Message Buffer 0.		✓
FCAN_LISTEN_ONLY_MODE	FCAN_ENABLE/FCAN_DISABLE	Enable or disable Listen Only mode. No acknowledge signal is generated. Only messages acknowledged by other CAN nodes are received.		✓
FCAN_SET_TX_FIRST_SCHEME	FCAN_HIGHEST_PRIORITY/FCAN_LOWEST_MB_NUMBER	Set ordering mechanism for Message Buffer transmission. Either a buffer with highest assigned priority or a buffer with the lowest number is transmitted first.		✓
FCAN_INDIVIDUAL_RX_MASKING	FCAN_ENABLE/FCAN_DISABLE	Enable or disable Individual RX mask registers.		✓
FCAN_SET_CLOCK_SOURCE	FCAN_OSCILATOR_CLOCK/FCAN_PERIPHERAL_CLOCK	Set Clock Source for CAN engine.		✓
FCAN_SUPERVISOR_MODE	FCAN_ENABLE/FCAN_DISABLE	Enable or disable Supervisor Mode. In Supervisor mode certain registers are only accessible when CPU operates in privileged mode.		✓

Table 5-25. FCAN Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
FCAN_WAKEUP_SOURCE	FCAN_UNFILTERED_RX / FCAN_FILTERED_RX	Select Wake Up Source.		✓
FCAN_SELF_RECEPTION	FCAN_ENABLE/FCAN_DISABLE	Enable or disable reception of self-transmitted frames.		✓
FCAN_LOCAL_PRIORITY	FCAN_ENABLE/FCAN_DISABLE	Enable or disable TX priority to be set in individual MBs by using FCANMB_SET_TX_PRIORITY command. Note that this requires the FCAN_HIGHEST_PRIORITY mode to be set by the FCAN_SET_TX_FIRST_SCHEME command.		✓
FCAN_TX_ABORT_OPERATION	FCAN_ENABLE/FCAN_DISABLE	Enable or disable TX Abort operation.		✓
FCAN_SET_SAMPLING	FCAN_1SAMP_PER_BIT / FCAN_3SAMPS_PER_BIT	Set number of hardware samples per bit.		✓
FCAN_SET_PRESCALER	UWord (0-255)	Set PRES_DIV prescaler divisor.		✓
FCAN_SET_RJW	FCAN_RJW_x (x=1-4)	Set RJW bit time parameter.		✓
FCAN_SET_PROP_SEG	FCAN_PROPSEG_n (n=1...8) or UWord16 (value 0-7)	Set PROP_SEG bit time parameter.		✓
FCAN_SET_PHASE_SEG1	FCAN_PSEG_n (n=1...8) or UWord16 (value 0-7)	Set PHASE_SEG1 bit time parameter.		✓
FCAN_SET_PHASE_SEG2	FCAN_PSEG_n (n=1...8) or UWord16 (value 0-7)	Set PHASE_SEG2 bit time parameter.		✓
FCAN_UNLOCK_ALL_MB	NULL	Unlocks all message boxes by reading the free running timer register.		✓
FCAN_GET_MAXMB	NULL	Get maximum number of MB used.		✓
FCAN_SET_MAXMB	UWord16 (number 0-15)	Set maximum number of MB used.		✓
FCAN_READ_ERR_AND_STATUS	NULL	Read value of error and status register (error bits are self-cleared by reading).		✓
FCAN_CLEAR_INT	FCAN_ESR1_xxx (BOFFINT|ERRINT|WAKINT|TWRNINT|RWRNINT)	Clear selected interrupt flags.		✓
FCAN_CLEAR_BOFF_INT	NULL	Clear BusOff interrupt flag.		✓

Table 5-25. FCAN Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
FCAN_CLEAR_ERR_INT	NULL	Clear Error interrupt flag.		✓
FCAN_CLEAR_WAKE_INT	NULL	Clear WakeUp interrupt flag.		✓
FCAN_CLEAR_RX_WARNING_INT	NULL	Clear Rx Warning Interrupt flag.		✓
FCAN_CLEAR_TX_WARNING_INT	NULL	Clear Tx Warning Interrupt flag.		✓
FCAN_MBINT_ENABLE	UWord16 with MB bits or combination of FCAN_MBINT_x (x=0...MAXMB)	Enable selected MB interrupts.		✓
FCAN_MBINT_DISABLE	UWord16 with MB bits or combination of FCAN_MBINT_x (x=0...MAXMB)	Disable selected MB interrupts.		✓
FCAN_READ_MBINT_FLAGS	NULL	Get all MB interrupt flags.		✓
FCAN_CLEAR_MBINT_FLAGS	UWord16 with MB bits or combination of FCAN_MBINT_x (x=0...MAXMB)	Clear selected MB interrupts.		✓
FCAN_SET_RXMGMASK	UWord32 mask value; optionally combined with FCAN_ID_EXT or FCAN_ID_RTR flags	Set Global RX mask which affects the MB0-MB13. Logic ones in the mask determines bits which are compared in ID filtering process. Logic zeros identify don't care bits.		✓
FCAN_SET_RXMGMASK_V	UWord32 mask value; optionally combined with FCAN_ID_EXT or FCAN_ID_RTR flags	Set Global RX mask, implemented as a function call. Use when passing a variable as a parameter.		✓
FCAN_SET_RXMGMASK_RAW	UWord32 mask value in raw register format	Set Global RX mask register directly.		✓
FCAN_SET_RX14MASK	UWord32 mask value; optionally combined with FCAN_ID_EXT or FCAN_ID_RTR flags	Set MB14 RX mask. Logic ones in the mask determines bits which are compared in ID filtering process. Logic zeros identify don't care bits.		✓
FCAN_SET_RX14MASK_V	UWord32 mask value; optionally combined with FCAN_ID_EXT or FCAN_ID_RTR flags	Set MB14 RX mask, implemented as a function call. Use when passing a variable as a parameter.		✓
FCAN_SET_RX14MASK_RAW	UWord32 mask value in raw register format	Set MB14 RX mask register directly.		✓

Table 5-25. FCAN Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
FCAN_SET_RX15MASK	UWord32 mask value; optionally combined with FCAN_ID_EXT or FCAN_ID_RTR flags	Set MB15 RX mask. Logic ones in the mask determines bits which are compared in ID filtering process. Logic zeros identify don't care bits.		✓
FCAN_SET_RX15MASK_V	UWord32 mask value; optionally combined with FCAN_ID_EXT or FCAN_ID_RTR flags	Set MB15 RX mask, implemented as a function call. Use when passing a variable as a parameter.		✓
FCAN_SET_RX15MASK_RAW	UWord32 mask value in raw register format	Set MB15 RX mask register directly.		✓
FCAN_GET_RX_ERR_COUNT	NULL	Read RX error counter.		✓
FCAN_GET_TX_ERR_COUNT	NULL	Read TX error counter.		✓
FCAN_GET_MB_MODULE	UWord16 with MB index	Get pointer to specified MB module. Use the return value with any FCANMB_ commands.		✓
FCAN_RXFIFO_OPERATION	FCAN_ENABLE/FCAN_DISABLE	Enable or disable the Receiver FIFO. Beware, this option breaks a compatibility with older FlexCAN modules. The FIFO mode is not supported by the 56F800EX_Quick_Start.		✓
FCAN_ID_ACCEPTANCE_MODE	FCAN_ONE_FULL_ID/ FCAN_TWO_FULL_STD_IDS/FCAN_FOUR_PARTIAL_IDS/FCAN_ALL_FRAMES_REJECTED	Set FIFO ID filter Acceptance Mode. Note that FIFO mode is not supported by this version of the FCAN driver.		✓
FCAN_RXFIFO_INT_ENABLE	FCAN_RXFIFO_OVERFLOW_INT|FCAN_RXFIFO_WARNING_INT|FCAN_FRAMES_IN_RXFIFO_INT	Enable interrupts when operating in FIFO mode. Note that FIFO mode is not supported by this version of the FCAN driver.		✓
FCAN_RXFIFO_INT_DISABLE	FCAN_RXFIFO_OVERFLOW_INT|FCAN_RXFIFO_WARNING_INT|FCAN_FRAMES_IN_RXFIFO_INT	Disable interrupts when operating in FIFO mode. Note that FIFO mode is not supported by this version of the FCAN driver.		✓
FCAN_READ_RXFIFO_FLAGS	FCAN_RXFIFO_OVERFLOW_INT|FCAN_RXFIFO_WARNING_INT|FCAN_FRAMES_IN_RXFIFO_INT	Read and test specified FIFO interrupts when operating in FIFO mode. Note that FIFO mode is not supported by this version of the FCAN driver.		✓

Table 5-25. FCAN Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
FCAN_CLEAR_RXFIFO_FLAGS	FCAN_RXFIFO_OVERFLOW_INT|FCAN_RXFIFO_WARNING_INT|FCAN_FRAMES_IN_RXFIFO_INT	Clear FIFO interrupts when operating in FIFO mode. Note that FIFO mode is not supported by this version of the FCAN driver.		✓

This table shows the MB-specific commands. Use the FCAN_MBx constants or the value returned from FCAN_GET_MB_MODULE as the module identifier.

The Table 5-26 shows all MB-specific commands dedicated for FCAN driver.

Table 5-26. FCAN driver - MB-specific commands

Cmd	pParam	Description	56F82xxx	56F84xxx
FCANMB_GET_ID	NULL	Parse the ID from the appropriate bits in given MB. The returned value is numerical ID, with FCAN_ID_EXT bit set for extended frames.		✓
FCANMB_SET_ID	UWord32 ID value	Optionally combined with FCAN_ID_EXT or FCAN_ID_RTR flags,		✓
FCANMB_SET_ID_V	UWord32 ID value	Optionally combined with FCAN_ID_EXT or FCAN_ID_RTR flags,		✓
FCANMB_SET_RTR	FCAN_ON/FCAN_OFF	Set or clear RTR bit in given MB. Use before a frame is transmitted.		✓
FCANMB_SET_LEN	UWord16 frame length (value 0-8)	Set data length field of the MB. Use before a frame is transmitted.		✓
FCANMB_SET_ID_RAW	UWord32 ID value in raw register format	Set 32bit raw value into the ID register of the MB.		✓
FCANMB_GET_LEN	NULL	Get data length field of the MB. Use after a frame is received.		✓
FCANMB_GET_ID_RAW	NULL	Get raw 32bit ID register value. Use FCANMB_GET_ID command when a numerical value is required instead of a raw register value.		✓
FCANMB_GET_TIMESTAMP	NULL	Get MB Time Stamp value. The time stamp is a value of the Free Running Timer captured at the moment of frame reception or transmission.		✓

Table 5-26. FCAN driver - MB-specific commands

Cmd	pParam	Description	56F82xxx	56F84xxx
FCANMB_SET_TX_PRIORITY	UWord16 (value 0-7)	Set MB transmission priority. Only applicable when local priority is enabled with FCAN_LOCAL_PRIORITY command.		✓
FCANMB_SET_CODE	FCAN_MB_CODE_xxx (xxx=RXVOID/RXEMPTY/RXFULL/TXABORT/TXVOID/TXONCE/TXRTR/TXRALWAYS)	Set code field of the MB. This command controls the reception or transmission of the MB.		✓
FCANMB_GET_CODE	NULL	Get code field of the MB to determine its operation status. Compare the value with one of FCAN_MB_CODE_xxx constants.		✓
FCANMB_REORDER_BYTES	NULL	Swap bytes in both 32bit data words of the MB. This switches data from CPU-ordered to bus-ordered format and vice versa.		✓
FCANMB_REORDER_WORDS	NULL	Swap 16bit words in both 32bit data words of the MB. This switches data between legacy DSC 16bit FlexCAN implementation and the new 32bit implementation.		✓
FCANMB_GET_DATAPTR	NULL	This command is not implemented intentionally. The behavior would not be backward compatible with the same command implemented in 16bit FlexCAN module driver. To get access to frame data, use the FCANMB_GET_DATAPTR32 command and be aware of different data byte endianness format.		✓
FCANMB_GET_DATAPTR32	NULL	Get a pointer to data buffer of the MB as a pointer to UWord32 word. Note that the endianness of the data register is different than the one of the CAN bus. Use the FCANMB_REORDER_BYTES command to switch between different data formats.		✓

5.1.12 Flash Memory Module (FTFA) Driver

The driver has only 56F82xxx devices. The flash memory module includes the following accessible memory regions:

- Program flash memory for vector space and code store

Flash memory is ideal for single-supply applications, permitting in-the-field erase and reprogramming operations without the need for any external high voltage power sources. The flash memory module includes a memory controller that executes commands to modify flash memory contents. An erased bit reads '1' and a programmed bit reads '0'. The programming operation is unidirectional; it can only move bits from the '1' state (erased) to the '0' state (programmed). Only the erase operation restores bits from '0' to '1'; bits cannot be programmed from a '0' to a '1'.

CAUTION

A flash memory location must be in the erased state before being programmed. Cumulative programming of bits (back-to-back program operations without an intervening erase) within a flash memory location is not allowed. Re-programming of existing 0s to 0 is not allowed as this overstresses the device. The standard shipping condition for flash memory is erased with security disabled. Data loss over time may occur due to degradation of the erased ('1') states and/or programmed ('0') states. Therefore, it is recommended that each flash block or sector be re-erased immediately prior to factory programming to ensure that the full data retention capability is achieved.

The Table 5-27 shows module identifiers for FTFA Driver.

Table 5-27. Identifiers for FTFA Driver

Module identifier	56F82xxx	56F84xxx
FTFL	✓	

The Table 5-28 shows all commands dedicated for FTFA Driver.

Table 5-28. FTFA Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
FTFL_INIT	NULL	Initialize the FTFL peripheral registers using the appconfig.h _INIT values.	✓	

5.1.13 Flash Memory Module (FTFL) Driver

The driver has only 56F84xxx devices. The flash memory module includes the following accessible memory regions:

- Program flash memory for vector space and code store
- FlexNVM for data store and additional code store
- FlexRAM for high-endurance data store or traditional RAM

Flash memory is ideal for single-supply applications, permitting in-the-field erase and reprogramming operations without the need for any external high voltage power sources. The flash memory module includes a memory controller that executes commands to modify flash memory contents. An erased bit reads '1' and a programmed bit reads '0'. The programming operation is unidirectional; it can only move bits from the '1' state (erased) to the '0' state (programmed). Only the erase operation restores bits from '0' to '1'; bits cannot be programmed from a '0' to a '1'.

CAUTION

A flash memory location must be in the erased state before being programmed. Cumulative programming of bits (back-to-back program operations without an intervening erase) within a flash memory location is not allowed. Re-programming of existing 0s to 0 is not allowed as this overstresses the device. The standard shipping condition for flash memory is erased with security disabled. Data loss over time may occur due to degradation of the erased ('1') states and/or programmed ('0') states. Therefore, it is recommended that each flash block or sector be re-erased immediately prior to factory programming to ensure that the full data retention capability is achieved.

The Table 5-29 shows module identifiers for FTFL Driver.

Table 5-29. Identifiers for FTFL Driver

Module identifier	56F82xxx	56F84xxx
FTFL		✓

The Table 5-30 shows all commands dedicated for FTFL Driver.

Table 5-30. FTFL Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
FTFL_INIT	NULL	Initialize the FTFL peripheral registers using the appconfig.h _INIT values.		✓

5.1.14 Flash Memory Controller (FMC) Driver

The Flash Memory Controller (FMC) is a memory acceleration unit that provides:

- an interface between the device and the dual-bank nonvolatile memory. Bank 0 consists of program flash memory, and bank 1 consists of FlexNVM.
- buffers that can accelerate flash memory transfers.

The Flash Memory Controller manages the interface between the device and the dual-bank flash memory. The FMC receives status information detailing the configuration of the memory and uses this information to ensure a proper interface.

In addition, for bank 0, the FMC provides three separate mechanisms for accelerating the interface between the device and the flash memory. A 64-bit speculation buffer can prefetch the next 64-bit flash memory location, and both a 4-way, 8-set cache and a single-entry 64-bit buffer can store previously accessed flash memory data for quick access times.

The Table 5-31 shows module identifiers for FMC Driver.

Table 5-31. Identifiers for FMC Driver

Module identifier	56F82xxx	56F84xxx
FMC	✓	✓

The Table 5-32 shows all commands dedicated for FMC Driver.

Table 5-32. FMC Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
FMC_INIT	NULL	Initialize the FMC peripheral registers using the appconfig.h _INIT values.	✓	✓

5.1.15 General-Purpose Input/Output (GPIO) Driver

The general-purpose input/output (GPIO) module allows direct read or write access to pin values or the ability to assign a pin to be used as an external interrupt. GPIO pins are multiplexed with other peripherals on the package. The device's data sheet specifies the assigned GPIO ports and the multiplexed pin package. GPIOs are placed on the device in groups of one to sixteen bits, called ports and designated as A, B, C, and so on. Refer to the device's data sheet for the specific definition of each of the GPIO ports on the chip.

The Table 5-33 shows module identifiers for GPIO Driver.

Table 5-33. Identifiers for GPIO Driver

Module identifier	56F82xxx	56F84xxx
GPIO_A	✓	✓
GPIO_B	✓	✓
GPIO_C	✓	✓
GPIO_D	✓	✓
GPIO_E	✓	✓
GPIO_F	✓	✓
GPIO_G		✓

The Table 5-34 shows all commands dedicated for GPIO Driver.

Table 5-34. GPIO Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
GPIO_CLEAR_INT_PENDING	combination of BIT_x (x=0|1|...|15)	Clear the selected interrupt request flags generated by the GPIO by writing ones to the Interrupt Edge Sensitive Register.	✓	✓
GPIO_CLEAR_PIN	combination of BIT_x (x=0|1|...|15)	Clear the selected GPIO pins by modifying the content of the Data Register.	✓	✓
GPIO_CLEAR_SW_INT_PENDING	combination of BIT_x (x=0|1|...|15)	Disable a software generated interrupt request by modifying the content of the Interrupt Assert Register.	✓	✓
GPIO_CLEAR_SW_INT_PENDING	combination of BIT_x (x=0|1|...|15)	Disable a software generated interrupt request by modifying the content of the Interrupt Assert Register.	✓	✓

Table 5-34. GPIO Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
GPIO_GET_INT_PENDING_FLAG	combination of BIT_x (x=0|1|...|15)	Read and return the selected interrupt pending flag(s) from the Interrupt Pending Register.	✓	✓
GPIO_INIT	NULL	Initialize the selected GPIO port registers using appconfig.h _INIT values.	✓	✓
GPIO_INIT_ALL	NULL	Initialize all available GPIO ports registers using appconfig.h _INIT values.	✓	✓
GPIO_INT_DETECTION_ACTIVE_HIGH	combination of BIT_x (x=0|1|...|15)	Set the selected GPIO pins to be active high by modifying the content of the Interrupt Polarity Register.	✓	✓
GPIO_INT_DETECTION_ACTIVE_LOW	combination of BIT_x (x=0|1|...|15)	Set the selected GPIO pins to be active low by modifying the content of the Interrupt Polarity Register.	✓	✓
GPIO_INT_DISABLE	combination of BIT_x (x=0|1|...|15)	Disable an interrupt request generated by a GPIO pin by modifying the content of the Interrupt Enable Register.	✓	✓
GPIO_INT_ENABLE	combination of BIT_x (x=0|1|...|15)	Enable an interrupt request generated by a GPIO pin by modifying the content of the Interrupt Enable Register.	✓	✓
GPIO_PULLUP_DISABLE	combination of BIT_x (x=0|1|...|15)	Disable pull-up on the selected pins by modifying the content of the Pull-Up Enable Register.	✓	✓
GPIO_PULLUP_ENABLE	combination of BIT_x (x=0|1|...|15)	Enable pull-up on the selected pins by modifying the content of the Pull-Up Enable Register.	✓	✓
GPIO_READ_DATA	NULL	Read and return the whole GPIO port by reading the GPIO Data Register.	✓	✓
GPIO_READ_INT_PENDING_REG	NULL	Read and return the whole content of the Interrupt Pending Register.	✓	✓
GPIO_READ_RAW_DATA	NULL	Read and return the logic value of each GPIO pin from the GPIO Raw Data Register; even when pins are not in GPIO mode. This command reads the.	✓	✓

Table 5-34. GPIO Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
GPIO_SET_HIGH_DRIVE_STRENGTH	combination of BIT_x (x=0|1|...|15)	Set the high strength (8mA) of the selected GPIO pin output driver by modifying the content of the Drive Strength Control Register (DRIVE->).	✓	✓
GPIO_SET_LOW_DRIVE_STRENGTH	combination of BIT_x (x=0|1|...|15)	Set the low strength (4mA) of the selected GPIO pin output driver by modifying the content of the Drive Strength Control Register (DRIVE->).	✓	✓
GPIO_SET_LOW_PASS_FILTER_DISABLE	combination of BIT_x (x=0|1|...|15)	Disable the low pass input filter of the selected GPIO pin by modifying the content of the Input Filter Control Register.	✓	✓
GPIO_SET_LOW_PASS_FILTER_ENABLE	combination of BIT_x (x=0|1|...|15)	Enable the low pass input filter of the selected GPIO pin by modifying the content of the Input Filter Control Register.	✓	✓
GPIO_SET_PIN	combination of BIT_x (x=0|1|...|15)	Set the selected GPIO pins by modifying the content of the Data Register.	✓	✓
GPIO_SET_PULL_DOWN	combination of BIT_x (x=0|1|...|15)	Enable pull-down on the selected pins by modifying the content of the Pull Resistor Enable Register.	✓	✓
GPIO_SET_PULL_UP	combination of BIT_x (x=0|1|...|15)	Enable pull-up on the selected pins by modifying the content of the Pull Resistor Enable Register.	✓	✓
GPIO_SET_SLEW_RATE_DISABLE	combination of BIT_x (x=0|1|...|15)	Disable the slew rate mode of the selected GPIO pin output driver by modifying the content of the Slew Rate Control Register.	✓	✓
GPIO_SET_SLEW_RATE_ENABLE	combination of BIT_x (x=0|1|...|15)	Enable the slew rate mode of the selected GPIO pin output driver by modifying the content of the Slew Rate Control Register.	✓	✓
GPIO_SETAS_GPIO	combination of BIT_x (x=0|1|...|15)	Set the selected GPIO pins of the GPIO port as GPIO pins by modifying content of the Peripheral Enable Register.	✓	✓
GPIO_SETAS_INPUT	combination of BIT_x (x=0|1|...|15)	Set the selected GPIO pins as an input pins by modifying the content of the Data Direction Register.	✓	✓

Table 5-34. GPIO Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
GPIO_SETAS_OPENDRAIN	combination of BIT_x (x=0|1|...|15)	Set the output driver of the selected GPIO pins to open drain mode by modifying the content of the Push-Pull Mode Register.	✓	✓
GPIO_SETAS_OPENDRAIN	combination of BIT_x (x=0|1|...|15)	Set the output driver of the selected GPIO pins to open drain mode by modifying the content of the Push-Pull Mode Register.	✓	✓
GPIO_SETAS_OUTPUT	combination of BIT_x (x=0|1|...|15)	Set the selected GPIO pins as an output pins by modifying the content of the Data Direction Register.	✓	✓
GPIO_SETAS_PERIPHERAL	combination of BIT_x (x=0|1|...|15)	Assign the selected GPIO pins of the GPIO to a peripheral by modifying the content of the Peripheral Enable Register.	✓	✓
GPIO_SETAS_PUSHPULL	combination of BIT_x (x=0|1|...|15)	Set the output driver of the selected GPIO pins to push-pull mode by modifying the content of the Push-Pull Mode Register.	✓	✓
GPIO_SETAS_PUSHPULL	combination of BIT_x (x=0|1|...|15)	Set the output driver of the selected GPIO pins to push-pull mode by modifying the content of the Push-Pull Mode Register.	✓	✓
GPIO_SW_INT_ASSERT	combination of BIT_x (x=0|1|...|15)	Enable a software generated interrupt request by modifying the content of the Interrupt Assert Register.	✓	✓
GPIO_SW_INT_ASSERT	combination of BIT_x (x=0|1|...|15)	Enable a software generated interrupt request by modifying the content of the Interrupt Assert Register.	✓	✓
GPIO_TEST_INT_PENDING	combination of BIT_x (x=0|1|...|15)	Test the selected interrupt pending flag(s) from the Interrupt Pending Register.	✓	✓
GPIO_TOGGLE_PIN	combination of BIT_x (x=0|1|...|15)	Toggle the selected GPIO pins by modifying the content of the Data Register.	✓	✓
GPIO_WRITE_DATA	UWord16	Write to the whole port by writing to the GPIO Data Register.	✓	✓

5.1.16 High Speed Comparator (HSCMP) Driver

The high speed comparator (HSCMP) module provides a circuit for comparing two analog input voltages. The comparator circuit is designed to operate across the full range of the supply voltage, known as rail-to-rail operation.

The Analog MUX (ANMUX) provides a circuit for selecting an analog input signal from eight channels. One signal is provided by the 6-bit digital-to-analog converter (DAC). The mux circuit is designed to operate across the full range of the supply voltage.

The Table 5-35 shows module identifiers for HSCMP Driver.

Table 5-35. Identifiers for HSCMP Driver

Module identifier	56F82xxx	56F84xxx
HSCMP_A	✓	✓
HSCMP_B	✓	✓
HSCMP_C	✓	✓
HSCMP_D	✓	✓

The Table 5-36 shows all commands dedicated for HSCMP Driver

.

Table 5-36. HSCMP Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
HSCMP_CLEAR_INT_FLAGS	HSCMP_FLAG_RISING_EDGE/HSCMP_FLAG_FALLING_EDGE	Clear the selected comparator interrupt flag.	✓	✓
HSCMP_DAC	HSCMP_ENABLE/HSCMP_DISABLE	Enable/disable the 6-bit DAC comparator reference.	✓	✓
HSCMP_DAC_OUT_VOLTAGE_SELECT	UWord16 value 0-63	Set the "VOSEL" DAC output voltage DACO = V_in /64 * (VOSEL + 1).	✓	✓
HSCMP_HARD_BLOCK_HYSTERESIS	HSCMP_HYST_LEVEL_x (x=0/1/2/3)	Set the programmable hysteresis level.	✓	✓
HSCMP_INIT	NULL	Initialize the HSCMP peripheral registers using the appconfig.h _INIT values.	✓	✓
HSCMP_INT_FALLING_EDGE	HSCMP_ENABLE/HSCMP_DISABLE	Enable/disable the falling edge interrupt.	✓	✓

Table 5-36. HSCMP Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
HSCMP_INT_RISING_EDGE	HSCMP_ENABLE/HSCMP_DISABLE	Enable/disable the rising edge interrupt.	✓	✓
HSCMP_MINUS_INPUT	HSCMP_INx (x=0-7)	Select the negative input of the comparator.	✓	✓
HSCMP_MODULE	HSCMP_ENABLE/HSCMP_DISABLE	Enable/disable the HSCMP module.	✓	✓
HSCMP_PASS_THROUGH_MODE	HSCMP_ENABLE/HSCMP_DISABLE	Enable/disable the MUX pass through mode.	✓	✓
HSCMP_PLUS_INPUT	HSCMP_INx (x=0-7)	Select the positive input of the comparator.	✓	✓
HSCMP_READ_FILT_COUNTER	NULL	Read and return the value of the filter counter.	✓	✓
HSCMP_READ_FILT_REG	NULL	Read and return the value of the Output Filter register as UWord16.	✓	✓
HSCMP_REFERENCE_SELECT	HSCMP_VIN1IN / HSCMP_VIN2IN	Select the supply voltage for the comparator reference source.	✓	✓
HSCMP_SET_HIGH_SPEED	HSCMP_ENABLE/HSCMP_DISABLE	If enabled, the comparator is put to the high speed comparison mode. If disabled, the comparator is put to power saving mode.	✓	✓
HSCMP_SET_INVERT	HSCMP_ENABLE/HSCMP_DISABLE	Enable/disable the logic-level inverter at the high speed comparator output.	✓	✓
HSCMP_SET_OUTPUT_ACTIVE	HSCMP_ENABLE/HSCMP_DISABLE	Enable/disable the comparator ouput pin.	✓	✓
HSCMP_SET_OUTPUT_PIN	HSCMP_COUT/HSCMP_COUTA	The parameter HSCMP_COUT sets CMPO to filtered comparator output (COUT). The HSCMP_COUTA selects unfiltered comparator output (COUTA).	✓	✓
HSCMP_SET_SAMPLE	HSCMP_ENABLE/HSCMP_DISABLE	Enable/disable the sample mode at the high speed comparator module.	✓	✓
HSCMP_SET_WINDOWING	HSCMP_ENABLE/HSCMP_DISABLE	Enable/disable the windowing mode at the high speed comparator output.	✓	✓
HSCMP_TEST_INT_FLAGS	HSCMP_FLAG_RISING_EDGE/HSCMP_FLAG_FALLING_EDGE	Test and returns the value of the selected comparator interrupt flag.	✓	✓

Table 5-36. HSCMP Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
HSCMP_TEST_OUTPUT	NULL	Return zero/nonzero current comparator output state.	✓	✓
HSCMP_WRITE_FILT_COUNTER	HSCMP_FILTER_COUNTER_x (x=0-7)	Set the filter counter.	✓	✓
HSCMP_WRITE_FILT_REG	UWord16	Write directly to the Filter Period Register. The comparator output signal can be filtered by applying a digital counting filter. The FPR register contains the filter sample period value so this command may be used to reconfigure the filter in run-time.	✓	✓

5.1.17 Inter-Integrated Circuit (IIC) Driver

The inter-integrated circuit (I^2C, I2C, or IIC) module provides a method of communication between a number of devices. The interface is designed to operate up to 100 kbit/s with maximum bus loading and timing. The I2C device is capable of operating at higher baud rates, up to a maximum of clock/20, with reduced bus loading.

The Table 5-37 shows module identifiers for I2C Driver.

Table 5-37. Identifiers for I2C Driver

Module identifier	56F82xxx	56F84xxx
IIC | I2C	✓	
IIC_0		✓
IIC_1		✓

The Table 5-38 shows all commands dedicated for IICDriver.

Table 5-38. IIC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
IIC_CLEAR_ARBITRATION_LOST	NULL	Clear arbitration lost flag.	✓	✓
IIC_CLEAR_HIGH_TIMEOUT_FLAG2	NULL	Clear the High Timeout flag 2 by writing 1 to it.	✓	✓
IIC_CLEAR_I_BUS_INT	NULL	Clear the I-Bus interrupt flag.	✓	✓
IIC_CLEAR_LOW_TIMEOUT_FLAG	NULL	Clear low timeout flags.	✓	✓
IIC_CLEAR_STOP_START_FLAGS	combination of IIC_xxx_FLAG (xxx=STOP|START)	Clear the start/stop detection flags.	✓	✓
IIC_CLEAR_TIMEOUT_FLAGS	combination of IIC_xxx (xxx=LOW_TIMEOUT|HIGH_TIMEOUT2)	Clear selected timeout flags by writing 1 to them.	✓	✓
IIC_GET_10BIT_ADDRESS	NULL	Read and return the 10-bit slave address.	✓	✓
IIC_GET_ADDRESS	NULL	Read and return the IIC Address (0-127) which is currently active for the slave operation.	✓	✓

Table 5-38. IIC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
IIC_GET_ADDRESSED_AS_SLAVE	NULL	Get the addressed as-a-slave flag.	✓	✓
IIC_GET_ARBITRATION_LOST	NULL	Get arbitration lost status.	✓	✓
IIC_GET_BUS_BUSY	NULL	Get the bus busy status.	✓	✓
IIC_GET_I_BUS_INT	NULL	Get the I-Bus interrupt flag.	✓	✓
IIC_GET_MASTER_MODE	NULL	Return non-zero if IIC Master mode is set.	✓	✓
IIC_GET_RANGE_SLAVE_ADDRESS	NULL	Get the slave address range.	✓	✓
IIC_GET_RX_ACK	NULL	Get the received acknowledge flag.	✓	✓
IIC_GET_SLAVE_TRANSMIT	NULL	Get slave read/write status.	✓	✓
IIC_GET_SMBUS_ADDRESS	NULL	Read and return the IIC SMBus slave address of the node in the range 0..127 as UWord16.	✓	✓
IIC_GET_TRANSFER_COMPLETE	NULL	Get the data transferring status.	✓	✓
IIC_GET_TX_MODE	NULL	Return non-zero if transmit mode is set.	✓	✓
IIC_I_BUS	IIC_ENABLE/IIC_DISABLE	Enable/Disable the IIC module as a whole.	✓	✓
IIC_I_BUS_INT	IIC_ENABLE/IIC_DISABLE	Enable/Disable the IIC Interrupt. The core receives the interrupt provided if it is enabled in the INTC Interrupt Controller module and also when interrupts are enabled globally in the core Status Register (SR).	✓	✓
IIC_INIT	NULL	Initialize the IIC peripheral registers using the appconfig.h _INIT values.	✓	✓

Table 5-38. IIC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
IIC_MASTER_SLAVE_MODE	IIC_MASTER/IIC_SLAVE	Select the mode the IIC module operates in. When used as a master mode in a single-master application, this command may be used once after the IIC initialization to set the Master mode. In a multi-master application, the IIC is typically set to Slave (listen) mode by default and is momentarily switched to the Master mode when needed.	✓	✓
IIC_READ_ADDRESS2_REG	NULL	Read and return the IIC-Bus Address Register 2 as UWord16.	✓	✓
IIC_READ_CONTROL_REG	NULL	Read and return the IIC-Bus Control Register as UWord16.	✓	✓
IIC_READ_CONTROL2_REG	NULL	Read and return the IIC-Bus Control Register 2 as UWord16.	✓	✓
IIC_READ_DATA	NULL	Read and return the fetched byte received from the IIC bus by directly reading the IIC Data I/O Register. Typically, reading of the byte is done in the IIC interrupt service routine.	✓	✓
IIC_READ_FREQ_DIV_REG	NULL	Read and return the IIC-Bus Frequency Divider Register as UWord16.	✓	✓
IIC_READ_GLITCH_FILTER_REG	NULL	Read and return the IIC-bus Programmable Input Glitch Filter Register as UWord16.	✓	✓
IIC_READ_RANGE_ADDRESS_REG	NULL	Read and return the IIC-Bus Range Address Register as UWord16.	✓	✓
IIC_READ_SCL_LOW_TIMEOUT	NULL	Read and return the SCL low timeout value.	✓	✓
IIC_READ_SCL_LOW_TIMEOUT_HIGH_REG	NULL	Read and return the IIC-Bus SCL Low Timeout MSByte Register as UWord16.	✓	✓
IIC_READ_SCL_LOW_TIMEOUT_LOW_REG	NULL	Read and return the IIC-Bus SCL Low Timeout LSByte Register as UWord16.	✓	✓
IIC_READ_SMBUS_REG	NULL	Read and return the IIC-Bus SMBus Control and Status as UWord16.	✓	✓

Table 5-38. IIC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
IIC_READ_STATUS_REG	NULL	Read and return the IIC Bus Status Register as UWord16.	✓	✓
IIC_REPEAT_START	NULL	Generate a repeated START condition on the bus, provided the node is active bus Master (otherwise the Arbitration Lost status flag is set).	✓	✓
IIC_SET_10BIT_ADDRESS	UWord16 value 0-1023	Write to the 10-bit slave address to the IIC Bus Address Register and the upper three bits to the Control Register 2 (0-1023).	✓	✓
IIC_SET_ADDRESS	UWord16 value 0-127	Set the IIC node (slave) address. The IIC address is used in the slave mode only to detect it is being addressed in an IIC transaction. Typically, it is not necessary to change the slave address once it is set e.g. by the IIC_INIT call.	✓	✓
IIC_SET_ADDRESS_EXTENSION	UWord16 value of the 10bit address >> 8	Set the upper three bits of the slave address in the 10-bit address scheme.	✓	✓
IIC_SET_ADDRESS_EXTENSION_MODE	IIC_nBIT (n=7/10)	Set the number of bits used for the slave address.	✓	✓
IIC_SET_DMA_TRANSFER	IIC_ENABLE/IIC_DISABLE	Enable/disable the DMA function, see documentation how FAST_ACK mode affects the DMA receive and transmit functions.	✓	✓
IIC_SET_FAST_ACK_NACK	IIC_ENABLE/IIC_DISABLE	Enable/disable the fast set up ACK/NACK response.	✓	✓
IIC_SET_GENERAL_CALL_ADDRESS	IIC_ENABLE/IIC_DISABLE	Enable/disable the general call address.	✓	✓
IIC_SET_GLITCH_FILTER	UWord16 value 0 (=disable) or 1-7 (=enable)	Enable/disable the glitch filter. The value 1-7 represents the number of filter glitches up to width of n bus clock cycles.	✓	✓
IIC_SET_HIGH_DRIVE_PADS	IIC_ENABLE/IIC_DISABLE	Enable/disable the high drive capability of the I2C pads.	✓	✓
IIC_SET_HIGH_TIMEOUT2_INTERRUPT	IIC_ENABLE/IIC_DISABLE	Enable/disable the high timeout 2 interrupt.	✓	✓

Table 5-38. IIC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
IIC_SET_HOLD_OFF_TO_STOP	IIC_ENABLE/IIC_DISABLE	Enable/disable waiting to finish currently transferred data, then enter to the stop mode.	✓	✓
IIC_SET_PRESCALER	UWord16	Write directly into the IIC Bus Frequency Divider Register register, which controls several prescalers and delays applied to the IIC bit-sampling and bit-transmission process.	✓	✓
IIC_SET_RANGE_MODE	IIC_ENABLE/IIC_DISABLE	Enable/disable the slave address matching between the values of the A1 and RA registers.	✓	✓
IIC_SET_RANGE_SLAVE_ADDRESS	UWord16 value 0-127	Set the slave address range to by used by the IIC module, any nonzero write enables this register.	✓	✓
IIC_SET_SECOND_IIC_ADDRESS	IIC_ENABLE/IIC_DISABLE	Enable/disable the SMBus device default address.	✓	✓
IIC_SET_SLAVE_BAUD_RATE_CTRL	IIC_MASTER_INDEPENDENT/IIC_MASTER_FOLLOW	Enable/disable the slave baud rate (0 - slave follows master baud rate).	✓	✓
IIC_SET_SMBUS_ADDRESS	UWord16 value 0-127	Write the value into the Secondary IIC Bus Address Register.	✓	✓
IIC_SET_SMBUS_RESPONSE_ADDRESS	IIC_ENABLE/IIC_DISABLE	Enable/disable the SMBUS alert response address.	✓	✓
IIC_SET_STOP_START_INT	IIC_ENABLE/IIC_DISABLE	Enable/disable the interrupt for the IIC bus stop or the start detection.	✓	✓
IIC_SET_TIME_OUT_CLOCK	IIC_DIV64/IIC_DIV1	Select the clock sources of the timeout counter.	✓	✓
IIC_SET_WAKEUP_IN_STOP	IIC_ENABLE/IIC_DISABLE	Enable/disable the wake up function in stop mode.	✓	✓
IIC_TEST_STATUS_REG	combination of IIC_xxx (xxx=TRANSFER_COMPLETE|ADDRESSED_AS_SLAVE|BUS_BUSY|ARBITRATION_LOST|SLAVE_TRANSMIT|IBUS_INT|RX_ACK)	Test IIC Bus Status Register for selected bits.	✓	✓
IIC_TEST_STOP_START_FLAGS	combination of IIC_xxx_FLAG (xxx=STOP|START)	Test the state of the start/stop detection flags.	✓	✓

Table 5-38. IIC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
IIC_TEST_TIMEOUT_FLAGS	combination of IIC_xxx (xxx=LOW_TIMEOUT|HIGH_TIME-OUT|HIGH_TIMEOUT2)	Test and return the state of the selected timeout flags.	✓	✓
IIC_TX_ACK	IIC_NO_ACK/IIC_ACK	Enable/Disable transmitting of the acknowledge signal after a data byte is received (matching address byte is always acknowledged). By disabling an acknowledge signal a receiver informs the transmitting node that it wants to finish the transaction.	✓	✓
IIC_TX_RX_MODE	IIC_TRANSMIT/IIC_RECEIVE	Select the direction of data transfers. The Receive/Transmit mode selection should not be confused with the Master/Slave selection.	✓	✓
IIC_WRITE_ADDRESS2_REG	UWord16 value 2-255	Write to the IIC-Bus Address Register 2.	✓	✓
IIC_WRITE_CONTROL_REG	UWord16	Write the value to IIC-Bus Control Register 1.	✓	✓
IIC_WRITE_CONTROL2_REG	UWord16 value 0-255	Write to the IIC-Bus Control Register 2.	✓	✓
IIC_WRITE_DATA	UWord16 value 0-255	Write the value to the IIC Bus Data I/O Register. Typically, writing the data register is done in the IIC interrupt service routine.	✓	✓
IIC_WRITE_FREQ_DIV_REG	UWord16 value 0-255	Write to the IIC-Bus Frequency Divider Register.	✓	✓
IIC_WRITE_GLITCH_FILTER_REG	UWord16	Write to the IIC-bus Programmable Input Glitch Filter register.	✓	✓
IIC_WRITE_RANGE_ADDRESS_REG	UWord16	Write to the IIC-Bus Range Address Register.	✓	✓
IIC_WRITE_SCL_LOW_TIMEOUT	UWord16	Set the SCL low timeout . This command writes directly into the SSLT bit-fields in the IIC_SLTH register and in the IIC_SLTL register.	✓	✓
IIC_WRITE_SCL_LOW_TIMEOUT_HIGH_REG	UWord16 value 0-255	Write to the IIC-Bus SCL Low Timeout MSByte of Register.	✓	✓
IIC_WRITE_SCL_LOW_TIMEOUT_LOW_REG	UWord16 value 0-255	Write to the IIC-Bus SCL Low Timeout LSByte of Register.	✓	✓

Table 5-38. IIC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
IIC_WRITE_SMBUS_REG	UWord16 value 0-255	Write to the IIC-Bus SMBus Control and Status register. Note: an inappropriate write to register can clear Write-1-to-Clear (SLTF/SHTF2) flags.	✓	✓

5.1.18 Interrupt Controller (INTC) Driver

The Interrupt Controller (INTC) module arbitrates among the various interrupt requests (IRQs). The module supports unique interrupt vectors and programmable interrupt priority. It signals to the DSC core when an interrupt of sufficient priority exists and to what address to jump to service this interrupt.

The INTC module design has these distinctive features:

- Programmable priority levels for each IRQ
- Two programmable fast interrupts
- Notification to System Integration Module (SIM) to restart clocks when exiting wait and stop modes
- Driving of initial address on the address bus after reset

The Table 5-39 shows module identifiers for INTC Driver.

Table 5-39. Identifiers for INTC Driver

Module identifier	56F82xxx	56F84xxx
INTC	✓	✓

The Table 5-40 shows all commands dedicated for INTC Driver.

Table 5-40. INTC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
INTC_GET_INT_LEVEL	NULL	Read and return the current level of the interrupt which is currently being sent to the processor core.	✓	✓
INTC_GET_INT_NUMBER	NULL	Read and return the number of the currently processed interrupt which is the value of VAB field of the INTC Control Register.	✓	✓
INTC_GET_INT_STATE	NULL	Read and return the nonzero value if the interrupt which is currently being sent to the processor core.	✓	✓
INTC_GET_IPL_n_RAW	n = given interrupt; use NULL as parameter	Return two-bit IPL value for given interrupt.	✓	✓
INTC_GET_PENDING_FLAG	UWord16 value of the selected interrupt.	Read and return the bit in the INTC Pending Register for requested interrupt.	✓	✓
INTC_INIT	NULL	Initialize the INTC peripheral registers using the appconfig.h _INIT values.	✓	✓

Table 5-40. INTC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
INTC_INIT	NULL	Initialize the INTC peripheral registers using the appconfig.h _INIT values.	✓	✓
INTC_INTERRUPTS	INTC_ENABLE/INTC_DISABLE	Enable/disable the interrupt processing by the INTC module.	✓	✓
INTC_READ_CONTROL_REG	NULL	Read and return the immediate value of the INTC Control Register.	✓	✓
INTC_READ_IRQPINS	combination of INTC_IRQxxx (xxx=A|B)	Read and return the immediate state of the selected external interrupt pins as UWord16.	✓	✓
INTC_SELECT_EDGE_MODE	combination of INTC_IRQxxx (xxx=A|B)	Set the selected interrupts to be an falling-edge-sensitive.	✓	✓
INTC_SELECT_LEVEL_MODE	combination of INTC_IRQxxx (xxx=A|B)	Set the selected interrupts to be an low-level-sensitive.	✓	✓
INTC_SET_FASTINT0	NULL	Register the specified interrupt as the fast interrupt 0.	✓	✓
INTC_SET_FASTINT0_VEC	ISR address	Set the fast interrupt 0 ISR handler address.	✓	✓
INTC_SET_FASTINT1	NULL	Register the specified interrupt as the fast interrupt 1.	✓	✓
INTC_SET_FASTINT1_VEC	ISR address	Set the fast interrupt 1 ISR handler address.	✓	✓
INTC_SET_IPL_n	n = given interrupt; parameter is one of INTC_DISABLED or INTC_LEVELx (x=0/1/2/3)	Set the interrupt priority level for given interrupt. The command writes the IPL bits in the Interrupt Priority Register for the interrupt number n.	✓	✓
INTC_SET_IPL_n_RAW	n = given interrupt; parameter is a two-bit IPL value in the IPR register.	Set one of priority levels: Disabled, Level 0, 1, and 2. Note that for some system interrupts the Level 0 is not allowed and the two bit value assigns priority levels.	✓	✓

5.1.19 Miscellaneous Control Module (MCM) Driver

The Miscellaneous Control Module (MCM) provides a myriad of miscellaneous control functions.

The MCM provides the following features :

- Program-visible information about the configuration and revision of the core and select system peripherals
- Registers for capturing information on platform bus errors, if enabled
- Control and configuration of memory resource protection (MRP)

Restriction:

The MCM is a supervisor-only space. All MCM registers must be accessed by supervisor code. In addition, each MCM register must be written in an access size equal to the register's width. For example, a 32-bit register must be written using a 32-bit access.

The Table 5-41 shows module identifiers for MCM Driver.

Table 5-41. Identifiers for MCM Driver

Module identifier	56F82xxx	56F84xxx
MCM	✓	✓

The Table 5-42 shows all commands dedicated for MCM Driver.

Table 5-42. MCM Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
MCM_INIT	NULL	Initialize the MCM peripheral registers using the appconfig.h _INIT values.	✓	✓

5.1.20 Modular/Scalable Controller Area Network (MSCAN) Driver

The module is a communication controller implementing the CAN 2.0A/B protocol as defined in the Bosch specification dated September 1991. For users to fully understand the MSCAN specification, it is recommended that the Bosch specification be read first to familiarize the reader with the terms and concepts contained within this document.

Though not exclusively intended for automotive applications, CAN protocol is designed to meet the specific requirements of a vehicle serial data bus: real-time processing, reliable operation in the EMI environment of a vehicle, cost-effectiveness, and required bandwidth.

MSCAN uses an advanced buffer arrangement resulting in predictable real-time behavior and simplified application software.

The Table 5-43 and Table 5-45 show module identifiers for MSCAN Driver.

Table 5-43. Identifiers for MSCAN Driver

Module identifier	56F82xxx	56F84xxx
MSCAN	✓	

The Table 5-44 shows all commands dedicated for MSCAN Driver.

Table 5-44. MSCAN Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
MSCAN_ABORT_TRANSMIT	combination of MSCAN_TXBUFFERxxx (xxx=0|1|2)	Cancel (abort) the transmission of the selected buffers. The cancellation is successful if the message is not already in transmission, or if the transmission is not successful (lost arbitration or error). When a message is aborted, the associated buffer is marked as empty and is reported in the abort acknowledge register.	✓	
MSCAN_AUTO_WAKEUP	MSCAN_ENABLE/MSCAN_DISABLE	Enable/disable the automatic wakeup.	✓	
MSCAN_CLEAR_EINT_FLAGS	combination of MSCAN_xxx_INT (xxx=STATCHNG|OVERRUN)	Clear the selected error (status change or receiver overrun) interrupt flags.	✓	
MSCAN_CLEAR_ERINT_FLAGS	combination of MSCAN_xxx_INT (xxx=WAKEUP|STATCHNG|OVERRUN|RXFULL)	Clear the selected wake-up|status change|receiver overrun|receiver full interrupt flags.	✓	

Table 5-44. MSCAN Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
MSCAN_CLEAR_RINT_FLAG	NULL	Clear the receiver buffer full interrupt flag. Typically, this command is used in the receiver interrupt service routine to clear and acknowledge the interrupt.	✓	
MSCAN_CLEAR_RXFRM	NULL	Clear the frame-received flag.	✓	
MSCAN_CLEAR_WINT_FLAG	NULL	Clear the wakeup interrupt flag. Typically, this command is used in the CAN wake-up interrupt service routine to clear and acknowledge the interrupt.	✓	
MSCAN_DEVICE	MSCAN_ENABLE/MSCAN_DISABLE	Enable/disable the MSCAN peripheral.	✓	
MSCAN_ERINT_DISABLE	combination of MSCAN_xxx_INT (xxx=WAKEUP|STATCHNG|OVERRUN|RXFULL)	Disable the selected MSCAN interrupts.	✓	
MSCAN_ERINT_ENABLE	combination of MSCAN_xxx_INT (xxx=WAKEUP|STATCHNG|OVERRUN|RXFULL)	Enable the selected MSCAN interrupts.	✓	
MSCAN_GET_ENABLED_TINT	NULL	Return the mask of all Transmit Buffer Empty interrupts which are currently enabled. The result value can then be used to determine which transmit buffer needs servicing.	✓	
MSCAN_GET_RX_ERR_COUNT	NULL	Return the 8-bit value of the MSCAN Receive Error Counter (CANRXERR).	✓	
MSCAN_GET_SLEEP_MODE	NULL	Return a non-zero value as UWord16; if the MSCAN is in the sleep mode. This command returns zero when the MSCAN module is active (not-sleeping).	✓	
MSCAN_GET_TX_ERR_COUNT	NULL	Return the 8-bit value of the MSCAN Transmit Error Counter Register (CANTXERR).	✓	
MSCAN_GET_WINNING_ACC_FILTER	NULL	Return an index of the acceptance filter as UWord16 value 0-7; which was hit during reception of a message currently available in the receive buffer.	✓	

Table 5-44. MSCAN Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
MSCAN_INIT	NULL	Initialize the MSCAN peripheral registers using the appconfig.h _INIT values.	✓	
MSCAN_LISTEN_ONLY_MODE	MSCAN_ENABLE/MSCAN_DISABLE	Enable/disable the listen only mode in which the module does not drive the ACK signal.	✓	
MSCAN_LOOPBACK_MODE	MSCAN_ENABLE/MSCAN_DISABLE	Enable/disable the test loopback mode.	✓	
MSCAN_MANUAL_BOFF_RECOVERY	MSCAN_ENABLE/MSCAN_DISABLE	Enable/disable the manual bus-off recovery mode.	✓	
MSCAN_READ_ABORT_ACK	NULL	Read and return the transmission abort acknowledge flags for those buffers which were not transmitted due to a call of the MSCAN_ABORT_TRANSMIT ioctl command. The returned value may be tested for occurrence of MSCAN_TXBUFFERx flags.	✓	
MSCAN_READ_EINT_FLAGS	NULL	Return the Error interrupt flags. This command is typically used in the MSCAN error interrupt service routine to retrieve the error interrupt events to be handled. The MSCAN_CLEAR_EINT_FLAGS command can then be used to clear such events by using the MSCAN_READ_EINT_FLAGS return value as a parameter.	✓	

Table 5-44. MSCAN Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
MSCAN_READ_ERINT_FLAGS	NULL	Return a value of the Error and Receive interrupt flags. This command can be used to poll the state of the error and receiver interrupts. The value returned by this command may be used as a parameter to the MSCAN_CLEAR_ERINT_FLAGS ioctl command to acknowledge and clear the polled interrupt sources. This command may also be used for read-clear sequence within the interrupt service routine, if this routine is used to handle both the error and receive interrupts. Note that this command is not suitable for read-clear sequence within the interrupt service routine when two different service routines exist for the error and receive interrupts. If this is the case, use the MSCAN_READ_EINT_FLAGS and MSCAN_CLEAR_EINT_FLAGS commands for the error interrupt and the MSCAN_CLEAR_RINT_FLAGS command for the receiver interrupt.	✓	
MSCAN_READ_TINT_FLAGS	NULL	Get the transmitter interrupt status (all TXEn bits).	✓	
MSCAN_RECOVER_BUSOFF_STATE	NULL	Request a recovery from the bus-off state. This command needs to be used to recover from the bus-off state if manual bus-off recovery mode was configured for the MSCAN module and the bus-off state is detected using the MSCAN_TEST_BUSOFF_HOLD command.	✓	
MSCAN_SELECT_NEXT_TXBUFF	NULL	Find an empty TX buffer, select it into address space and return its bit; returns 0 when no buffer is available.	✓	

Table 5-44. MSCAN Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
MSCAN_SELECT_TXBUFF	combination of MSCAN_TXBUFFERxxx (xxx=0|1|2) or MSCAN_ANY_TXBUFFER	Look for an empty transmit buffer(s) from the ones specified by a parameter value. If at least one empty buffer is found, it is selected (mapped) to the MSCAN peripheral space and made available for the CPU access. A flag identifying such a "winning" buffer is then returned to the caller. The zero value is returned when no of the specified transmit buffers is empty. In this case the buffer mapping is not changed.	✓	
MSCAN_SET_ACC_IDR_16_0	UWord16 portion of the ID acceptance value	Set 16bit acceptance ID 0. The value includes the RTR/SRR and IDE bits.	✓	
MSCAN_SET_ACC_IDR_16_1	UWord16 portion of the ID acceptance value	Set 16bit acceptance ID 1. The value includes the RTR/SRR and IDE bits.	✓	
MSCAN_SET_ACC_IDR_16_2	UWord16 portion of the ID acceptance value	Set 16bit acceptance ID 2. The value includes the RTR/SRR and IDE bits.	✓	
MSCAN_SET_ACC_IDR_16_3	UWord16 portion of the ID acceptance value	Set 16bit acceptance ID 3. The value includes the RTR/SRR and IDE bits.	✓	
MSCAN_SET_ACC_IDR_32_0	UWord32 ID acceptance value	Set 32bit acceptance ID 0. The value includes the RTR(ex), RTR/SRR and IDE bits.	✓	
MSCAN_SET_ACC_IDR_32_1	UWord32 ID acceptance value	Set 32bit acceptance ID 1. The value includes the RTR(ex), RTR/SRR and IDE bits.	✓	
MSCAN_SET_ACC_IDR_8_0	UWord16 portion of the ID acceptance value (lower byte only).	Set 8bit acceptance ID 0.	✓	
MSCAN_SET_ACC_IDR_8_1	UWord16 portion of the ID acceptance value (lower byte only).	Set 8bit acceptance ID 1.	✓	
MSCAN_SET_ACC_IDR_8_2	UWord16 portion of the ID acceptance value (lower byte only).	Set 8bit acceptance ID 2.	✓	
MSCAN_SET_ACC_IDR_8_3	UWord16 portion of the ID acceptance value (lower byte only).	Set 8bit acceptance ID 3.	✓	

Table 5-44. MSCAN Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
MSCAN_SET_ACC_IDR_8_4	UWord16 portion of the ID acceptance value (lower byte only).	Set 8bit acceptance ID 4.	✓	
MSCAN_SET_ACC_IDR_8_5	UWord16 portion of the ID acceptance value (lower byte only).	Set 8bit acceptance ID 5.	✓	
MSCAN_SET_ACC_IDR_8_6	UWord16 portion of the ID acceptance value (lower byte only).	Set 8bit acceptance ID 6.	✓	
MSCAN_SET_ACC_IDR_8_7	UWord16 portion of the ID acceptance value (lower byte only).	Set 8bit acceptance ID 7.	✓	
MSCAN_SET_ACC_MASKR_16_0	UWord16 portion of the mask value including the RTR/SRR and IDE bits	Set 16bit acceptance mask 0 for the case when using 16-bit mask (MSCAN_SET_ACC_MODE used with the MSCAN_ACC_MODE_4X16 parameter). The 0 bits in the mask determine which bits are matched with the acceptance value. The bits set to 1 in the mask are the "don't care" bits. The mask and ID values for the 4x16 mask mode affect all Standard-ID bits and/or Extended-ID bits 28:15.	✓	
MSCAN_SET_ACC_MASKR_16_1	UWord16 portion of the mask value including the RTR/SRR and IDE bits	Set 16bit acceptance mask 1 for the case when using 16-bit mask.	✓	
MSCAN_SET_ACC_MASKR_16_2	UWord16 portion of the mask value including the RTR/SRR and IDE bits	Set 16bit acceptance mask 2 for the case when using 16-bit mask.	✓	
MSCAN_SET_ACC_MASKR_16_3	UWord16 portion of the mask value including the RTR/SRR and IDE bits	Set 16bit acceptance mask 3 for the case when using 16-bit mask.	✓	
MSCAN_SET_ACC_MASKR_32_0	UWord32 mask value, including the RTR_EX, RTR/SRR and IDE bits	Set 32bit acceptance mask 0 for the case when using 32-bit mask (MSCAN_SET_ACC_MODE used with the MSCAN_ACC_MODE_4X16 parameter). The 0 bits in the mask determine which bits are matched with the acceptance value. The bits set to 1 in the mask are the "don't care" bits. The mask and ID values for the 2x32 mask mode affect all Standard-ID bits and all Extended-ID bits.	✓	

Table 5-44. MSCAN Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
MSCAN_SET_ACC_MASKR_32_1	UWord32 mask value, including the RTR_EX, RTR/SRR and IDE bits	Set 32bit acceptance mask 1 for the case when using 32-bit mask.	✓	
MSCAN_SET_ACC_MASKR_8_0	UWord16 portion of the mask value (only lower byte)	Set 8bit acceptance mask 0 for the case when using 8-bit mask (MSCAN_SET_ACC_MODE used with the MSCAN_ACC_MODE_8X8 parameter). The 0 bits in the mask determine which bits are matched with the acceptance value. The bits set to 1 in the mask are the "don't care" bits. The mask and ID values for 8x8 mask mode affect the Standard-ID bits 10:3 and/or Extended-ID bits 28:21.	✓	
MSCAN_SET_ACC_MASKR_8_1	UWord16 portion of the mask value (only lower byte)	Set 8bit acceptance mask 1 for the case when using 8-bit mask.	✓	
MSCAN_SET_ACC_MASKR_8_2	UWord16 portion of the mask value (only lower byte)	Set 8bit acceptance mask 2 for the case when using 8-bit mask.	✓	
MSCAN_SET_ACC_MASKR_8_3	UWord16 portion of the mask value (only lower byte)	Set 8bit acceptance mask 3 for the case when using 8-bit mask.	✓	
MSCAN_SET_ACC_MASKR_8_4	UWord16 portion of the mask value (only lower byte)	Set 8bit acceptance mask 4 for the case when using 8-bit mask.	✓	
MSCAN_SET_ACC_MASKR_8_5	UWord16 portion of the mask value (only lower byte)	Set 8bit acceptance mask 5 for the case when using 8-bit mask.	✓	
MSCAN_SET_ACC_MASKR_8_6	UWord16 portion of the mask value (only lower byte)	Set 8bit acceptance mask 6 for the case when using 8-bit mask.	✓	
MSCAN_SET_ACC_MASKR_8_7	UWord16 portion of the mask value (only lower byte)	Set 8bit acceptance mask 7 for the case when using 8-bit mask.	✓	
MSCAN_SET_ACC_MODE	MSCAN_ACC_MODE_xxx (xxx=2X32/4X16/8X8/CLOSED)	Set the receive acceptance filter configuration. The ID acceptance filtering is applied any time a new message is received.	✓	
MSCAN_SET_CLOCK_SOURCE	MSCAN_IPBUS/MSCAN_XTAL	Select the MSCAN clock source.	✓	
MSCAN_SET_PRESCALER	UWord16 value 1-64	Set the ratio between the CANCLK signal frequency and the time quanta clock frequency of the MSCAN module.	✓	

Table 5-44. MSCAN Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
MSCAN_SET_SAMPLING	MSCAN_1SAMP_PER_BIT/ MSCAN_3SAMPS_PER_BIT	Select number of times the line is sampled to get the bit value.	✓	
MSCAN_SET_SJW	UWord16 value 1-4	Set the Synchronization Jump Width (SJW) parameter of the CAN bit timing machine. The SJW is specified in the time-quanta units and is always at least 1 tq. See the CAN standard document for more information.	✓	
MSCAN_SET_TSEG1	UWord16 value 4-16	The Time Segment 1 parameter of the CAN bit timing machine. The Time Segment 1 is specified in time-quanta units and is always at least 1 tq. See the CAN standard document for more information.	✓	
MSCAN_SET_TSEG2	UWord16 value 2-8	Set the Time Segment 2 parameter of the CAN bit timing machine. The Time Segment 2 is specified in time-quanta units and is always at least 1 tq. See the CAN standard document for more information.	✓	
MSCAN_SLEEP	MSCAN_ON/MSCAN_OFF	Enter (ON) or leave (OFF) the sleep state of the MSCAN module.	✓	
MSCAN_SOFT_RESET	MSCAN_ON/MSCAN_OFF	Enter/leave the internal soft-reset state of the MSCAN module. In case of entering the reset state, any ongoing transmission or reception is quit and synchronization to the bus is lost.	✓	
MSCAN_STOP_IN_WAIT	MSCAN_ENABLE/MSCAN_ DISABLE	Enable/disable the low-power sleep mode of the MSCAN module in the CPU wait mode.	✓	
MSCAN_TEST_BUSOFF_HOLD	NULL	Return a non-zero value when the MSCAN module is stuck in the bus-off state. This may happen if manual bus-off recovery mode was configured for the MSCAN module. The bus-off state may be recovered using the MSCAN_RECOVER_BUSOFF_STATE ioctl command.	✓	
MSCAN_TEST_RXACT	NULL	Return a non-zero value if the MSCAN module is just receiving the CAN message.	✓	

Table 5-44. MSCAN Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
MSCAN_TEST_RXFRM	NULL	Return a non-zero value if a CAN frame was received since the MSCAN_CLEAR_RXFRM ioctl command was called last time. The RXFRM flag can not be used to generate the CPU interrupt. Do not confuse the RXFRM flag with the RXFULL interrupt flag.	✓	
MSCAN_TEST_SYNCH	NULL	Return a non-zero value if the MSCAN module is synchronized to the CAN bus. When synchronized, it is able to participate in the communication process.	✓	
MSCAN_TIMESTAMP_TIMER	MSCAN_ENABLE/MSCAN_DISABLE	Enable/disable the timestamp timer.	✓	
MSCAN_TINT_DISABLE	combination of MSCAN_xxx_INT (xxx=TXEMPTY0|TXEMPTY1|TXEMPTY2|TXEMPTY_ALL)	Disable the selected transmitter buffer empty interrupts.	✓	
MSCAN_TINT_ENABLE	combination of MSCAN_xxx_INT (xxx=TXEMPTY0|TXEMPTY1|TXEMPTY2|TXEMPTY_ALL)	Enable the selected transmitter buffer empty interrupts.	✓	
MSCAN_TRANSMIT	combination of MSCAN_TXBUFFERxxx (xxx=0|1|2)	Submit the transmit buffer(s) selected by the parameter value for a transmission onto the CAN bus. Once submitted, the buffers are marked as full and should not be accessed by CPU. Submitted buffer(s) go empty either if transmission is aborted or successfully completed.	✓	
MSCAN_WAIT_SLEEP	NULL	Wait until sleep mode is entered.	✓	
MSCAN_WAKEUP_FILTER	MSCAN_ENABLE/MSCAN_DISABLE	Enable/disable the low-pass filter on the wake-up condition.	✓	

Table 5-45. Identifiers for MSCAN Driver

Module identifier	56F82xxx	56F84xxx
MSCAN_RB	✓	
MSCAN_TB	✓	

The following ioctl commands operate on top of the receive or transmit Message Buffer structures. Use the MSCAN_RB or MSCAN_TB module identifiers as the first parameter to all ioctl calls when executing any of these commands.

Table 5-46. MSCANMB Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
MSCANMB_GET_DATAPTR	NULL	Return the UWord16 pointer to the data part of the message currently stored in the message buffer.	✓	
MSCANMB_GET_ID	NULL	Return the CAN frame identifier of the message currently stored in the Message Buffer as UWord32. The returned Message Identifier is converted from a raw form of the MB structure so that it can be treated as a standard 32-bit number. The most significant bit (MSB) of the return value is set for the extended 29-bit identifiers. The MSB is cleared for the standard 11-bit identifiers.	✓	
MSCANMB_GET_ID_RAW	NULL	Return the four IDR registers of MB as UWord32. The returned value is in the raw format as it is stored in the MB registers so further conversions are needed to obtain a numeric representation of the message identifier.	✓	
MSCANMB_GET_LEN	NULL	Return the length of the frame data part currently stored in the message buffer as UWord16 value 0-8.	✓	
MSCANMB_GET_RTR	NULL	Return a non-zero value as UWord16; if the RTR flag is set in the Message Buffer.	✓	

Table 5-46. MSCANMB Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
MSCANMB_GET_TIMESTAMP	NULL	Return the time-stamp value as UWord16; which was assigned to this message buffer. The time-stamp is a value of the free-running timer/counter captured at the time the message was received or transmitted from/to the CAN bus. The time-stamp timer must be enabled in order to generate valid time-stamp values.	✓	
MSCANMB_SET_ID	32bit Identifier value (constant). Use an OR-combination of the ID numeric value and the following constants MSCAN_ID_xxx (xxx=EXT|RTR)	Assign the CAN message identifier to the specified Message Buffer, and clears or sets the Remote Transmit Request flag in the MB. The identifier value passed to this ioctl command should contain information about whether it is specified in the standard 11-bit format or extended 29-bit format. The most significant bit (MSB) is reserved for this purpose. You can use the predefined MSCAN_ID_EXT constant OR-ed with the ID value being passed to the ioctl to set the MSB.	✓	
MSCANMB_SET_ID_RAW	UWord32 ID raw value.	Assign the CAN message identifier to the specified Message Buffer. This command behaves in a similar manner as the MSCANMB_SET_ID ioctl command, except that the passed identifier value must already be in the raw format suitable for writing into the IDR registers of the Message Buffer structure.	✓	
MSCANMB_SET_ID_V	32bit Identifier value (variable). Use an OR-combination of the ID numeric value and the following constants MSCAN_ID_xxx (xxx=EXT|RTR)	Assign the CAN message identifier to the specified Message Buffer. This command operates in the same way as the MSCANMB_SET_ID command, except that the MSCANMB_SET_ID_V ioctl command is implemented as a function call and it is thus more suitable for passing the 32-bit identifier stored in the caller's variable.	✓	

Table 5-46. MSCANMB Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
MSCANMB_SET_LEN	UWord16 value 0-8	Set the message length field of the specified message buffer structure. Typically the length is set before the message is to be transmitted onto the CAN bus.	✓	
MSCANMB_SET_RTR	MSCAN_ON/MSCAN_OFF	Set/clear the Remote Transmit Request (RTR) bit in the message identifier value of the specified Message Buffer.	✓	
MSCANMB_SET_TBP	UWord16 value 0-255	Set the local priority of the associated message buffer structure. The local priority is used for the internal prioritization process of the CAN and is defined to be highest for the smallest binary number.	✓	

5.1.21 On-Chip Clock Synthesis (OCCS) Driver

This section describes the DSP56800EX_Quick_Start API for the MC56F2xxx and MC56F84xxx OCCS on-chip module. The functionality of the OCCS module itself is described in the 56F82XXX Reference Manual (MC56F82XXXRM) or 56F84XXX Reference Manual (MC56F84XXXRM).

This module provides the 2X system clock frequency to the System Integration Module (SIM), which generates the various derivative system and peripheral clocks for the chip. The on-chip clock synthesis module allows product design using several user selectable clock sources, including an 8 MHz / 400 kHz internal relaxation oscillator, a 32 kHz internal RC oscillator (56F84xxx) or a 200 kHz internal RC oscillator (56F82xxx), an external clock input, a 4 MHz to 16 MHz external crystal oscillator, and a PLL to run up to a 100 MHz system bus frequency.

The Table 5-47 shows module identifiers for OCCS Driver.

Table 5-47. Identifiers for OCCS Driver

Module identifier	56F82xxx	56F84xxx
OCCS	✓	✓

The Table 5-48 shows all commands dedicated for OCCS Driver.

Table 5-48. OCCS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
OCCS_200KHZ_RC_OSCILATOR_OPERATION	OCCS_ENABLE/OCCS_DISABLE	Enable/disable the power down of the 200 kHz internal RC oscillator. Note: To prevent a loss of clock to the core or the PLL, this bit should never be asserted while this clock source is selected by the PRECS field in the control register.	✓	
OCCS_32KHZ_RC_OSCILATOR_OPERATION	OCCS_ENABLE/OCCS_DISABLE	Enable/disable the power down of the 32 kHz internal RC oscillator. Note: To prevent a loss of clock to the core or the PLL, this bit should never be asserted while this clock source is selected by the PRECS field in the control register.		✓
OCCS_ADJUST_RELAX_OSC_FREQ	UWord16 value 0-1023	Adjust the internal Relaxation Oscillator frequency by changing the size of the internal capacitor. The reset value is in the middle of the range.	✓	✓

Table 5-48. OCCS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
OCCS_CLEAR_FLAG	combination of OCCS_STATUS_xxx (xxx=LOCK_LOST_INT1|LOCK_LOST_INT0|CLOCK_LOST)	Clear the selected flags (bits) in the PLL Status register.	✓	✓
OCCS_CLOCK_MONITOR_ENABLE	OCCS_ENABLE/OCCS_DISABLE	Enable/disable the clock monitor functionality of the XOSC.	✓	✓
OCCS_CLOCK_SOURCE_TOPWM_NANO_EDGE	OCCS_RAW_PLL/OCCS_PLL_DIV2	Set the 200MHz clock source to PWM nano edge. The recommended setting is (OCCS_PLL_DIV2), when the PLL output frequency is 400 MHz, then the PLL DIV2 Clock is selected as PWM 2X clock.	✓	
OCCS_CRYSTAL_CLOCK_DIV2	OCCS_ENABLE/OCCS_DISABLE	Enable/disable the external oscillator output divider by 2 before use as MSTR_OSC. Note: The [OCCS_CTRL_PRECS] bit field should not be selecting the external clock source while changing the value of OSC_DIV2 to avoid glitches on the system clock.		✓
OCCS_CRYSTAL_OSCILLATOR_POWER_DOWN	OCCS_ENABLE/OCCS_DISABLE	Enable/disable the power down of the external crystal oscillator. Note: To prevent a loss of clock to the core or the PLL, this bit should never be asserted while this clock source is selected.	✓	✓
OCCS_DIRECT_CLOCK_MODE	OCCS_ENABLE/OCCS_DISABLE	Enable/disable the direct clock input on the XTAL pin. Use OCCS_ENABLE when the clock source is connected on the XTAL pin. Use OCCS_DISABLE when the crystal or the resonator is connected on the EXTAL and XTAL pins. Note that the OCCS_SELECT_EXT_CLOCK_SOURCE command needs to be used first to switch clock input to OCCS_CLKIN_OSC.	✓	✓
OCCS_GET_IPBUS_FREQ	UWord32 oscillator frequency [Hz]	Return the IPBus Clock frequency value in Hz as UWord32.	✓	✓

Table 5-48. OCCS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
OCCS_GET_ZCLOCK_SOURCE	NULL	Return the same values as OCCS_SET_ZCLOCK_SOURCE parameters, any other value means synchronizing is in progress.	✓	✓
OCCS_INIT	NULL	Initialize the OCCS peripheral registers using the appconfig.h _INIT values.	✓	✓
OCCS_INIT	NULL	Initialize the OCCS peripheral registers using the appcongig.h _INIT values.	✓	✓
OCCS_INT_DISABLE	combination of (OCCS_LOL1_INT|OCCS_LOL0_INT|OCCS_LOSS_OF_CLOCK_INT)	Disable the selected OCCS interrupts.	✓	✓
OCCS_INT_ENABLE	combination of OCCS_LOL0_INT_xxx | OCCS_LOL1_INT_xxx | OCCS_LOSS_OF_CLOCK_INT (xxx=ANY_EDGE/FALLING_EDGE/RISING_EDGE)	Enable the selected OCCS interrupts. Note: the PLL Interrupt 1 and PLL Interrupt 0 can be enabled in a selected mode only if they were disabled before. It is not possible to change the mode of the PLL Interrupt 1 or 0 once it is enabled (for example change from any edge to falling edge).	✓	✓
OCCS_INTERNAL_RELAX_OSC_OPERATION	OCCS_ENABLE/OCCS_DISABLE/OCCS_STANDBY (80xx only)	Enable/disable the Relaxation Oscillator. Power-down the relaxation oscillator if the crystal oscillator is being used. To prevent loss of clock to the core or the PLL, set this bit only if the prescaler clock source has been changed to the crystal oscillator.	✓	✓
OCCS_LOCK_DETECTOR	OCCS_ENABLE/OCCS_DISABLE	Enable/disable the lock detector.	✓	✓
OCCS_POWER_MODE	OCCS_HIGH_POWER/OCCS_LOW_POWER	Set the resonator or crystal power mode.	✓	✓
OCCS_READ_CLOCK_CHECK_REFERENCE	NULL	Read and return the result of clock checking function for internal reference clock as UWord16.	✓	✓
OCCS_READ_CLOCK_CHECK_TARGET	NULL	Read and return the result of clock checking function for external clock as UWord16.	✓	✓
OCCS_READ_CONTROL_REG	NULL	Read and return the content of the PLL Control register as UWord16.	✓	✓

Table 5-48. OCCS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
OCCS_READ_DIVIDE_BY_REG	NULL	Read and return the content of the PLL Divide-by register as UWord16.	✓	✓
OCCS_READ_FLAG	combination of OCCS_STATUS_xxx (xxx=LOCK_LOST_INT1|LOCK_LOST_INT0|CLOCK_LOST|LOCK_1|LOCK_0|POWER_DOWN|ZCLOCK|CRYSTAL_READY)	Return zero if flag is cleared, non-zero if flag is set.	✓	✓
OCCS_READ_OSC_CONTROL_REG	NULL	Read and return the content of the Oscillator Control register as UWord16.	✓	✓
OCCS_READ_OSC_CONTROL2_REG	NULL	Read and return the content of the Oscillator Control 2 register as UWord16.	✓	✓
OCCS_READ_OSC_OK_FLAG	NULL	Return a non-zero value after the crystal oscillator has started up (the XOSC OK indicator). This command returns zero when the oscillator clock is not stable or if XOSC is disabled.	✓	✓
OCCS_READ_STATUS_REG	NULL	Read and return the content of the PLL Status register as UWord16.	✓	✓
OCCS_RETRIM_OSC_200K	UWord16 value 0-511	Adjust the 200 kHz Internal RC Oscillator frequency by the parameter value.	✓	
OCCS_RETRIM_OSC_32K	UWord16 value 0-511	Adjust the 32 kHz Internal RC Oscillator frequency by the parameter value.		✓
OCCS_SELECT_EXT_CLOCK_SOURCE	OCCS_CLKIN_CLKIN/OCCS_CLKIN_EXTAL	Select the external clock source. There are only two clock sources to be chosen from. One is direct clock input and second is crystal/resonator input. The second input can be configured as a standard EXTAL/XTAL input or as a direct clock input on the XTAL pin. The external clock source selected by OCCS_SELECT_EXT_CLOCK_SOURCE may then become an official MSTR_OSC clock by using the OCCS_SET_PRESCALER_CLOCK command.	✓	✓

Table 5-48. OCCS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
OCCS_SELECT_EXT_CLOCK_SOURCE	OCCS_CLKIN_PRI/OCCS_CLKIN_ALT/OCCS_CLKIN_OSC.	Select the source of external clock signal.		
OCCS_SET_CLOCK_CHECK	OCCS_ENABLE/OCCS_DISABLE	Enable/disable the clock checking function. This command enables clock checking function and resets counters REF_COUNT and TARGET_CNT, when parameter is OCCS_ENABLE. When clock checking function finished, bit CHK_ENA is cleared and in counters REF_COUNT and TARGET_CNT are valid values. The parameter OCCS_DISABLE stops the clock checking function.	✓	✓
OCCS_SET_CORE_CLOCK	combination UWord16 value 1-64 and OCCS_CLOCK_IN_DIVIDE_BY_xxx (xxx= 1/2/4/8/16/32/64/128/256)	Configure the OCCS module to the most frequently used mode, when the PLL block provides clock to the DSC core (ZCLOCK Source is set to Postscaler output). First the command sets the ZCLOCK Source to Prescaler output and turns the lock detector on. Then it writes the "param" value to the PLL Divide by Register and it waits until the PLL is locked. Finally it switches the ZCLOCK Source to the Postscaler output.	✓	✓
OCCS_SET_DIVIDE_BY	UWord16 value 0-63	Set the PLL Divide-by value. This command writes the parameter to the PLL Divide-by register. Use this command only when ZCLOCK Source is set to MSTR clock.	✓	✓
OCCS_SET_LORTP	UWord16 value 1-15	Set the loss-of-reference clock trip point. The parameter controls the amount of time required for the loss of reference clock interrupt to be generated. It's recommended to keep the value of LORTP >= 2.	✓	✓
OCCS_SET_POSTSCALER	OCCS_CLOCK_OUT_DIVIDE_BY_x (x=1,2,4,8,16,32,64,128,256)	Set the post scaler factor.	✓	✓
OCCS_SET_POSTSCALER	OCCS_CLOCK_OUT_DIVIDE_BY_xxx (xxx=1/2/4/8/16/32/64/128/256)	Set the postscaler.	✓	✓

Table 5-48. OCCS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
OCCS_SET_PRESCALER_CLOCK	OCCS_INTERNAL_RELAX_OSC/OCCS_CRYSTAL_OSC	Set the prescaler clock source. OCCS_CRYSTAL_OSC should only be set if XTAL and EXTAL pin functions are enabled in the appropriate GPIO control register.	✓	✓
OCCS_SET_ZCLOCK_SOURCE	OCCS_POSTSCALER_OUTPUT/OCCS_PRESCALER_OUTPUT(83xx only) /OCCS_MSTR_OSC_OUTPUT(80xx only) /OCCS_xxx_OSC_OUTPUT (xxx=PLL/MSTR) (800x & 84xxx & 827xxx)	Set the sys_clk_x2 source to the SIM, which generates divided-down versions of this signal for use by memories and the IP Bus. If PLLPD is set, ZSRC is automatically set to 0 to prevent a loss of the reference clock to the core. NOTE: Before switching to a new clock source, you must enable the new source. The PLL should be on, configured, and locked before switching to it. For extra assurance in cases where the PLL may be stressed, confirm that the PLL remains locked for a period of time before switching to it.	✓	✓
OCCS_TEMP_TRIM_OSC_8MHZ	UWord16 value 0-15	Set the temperature trim value.	✓	✓
OCCS_TEST_CLOCK_CHECK	NULL	Test if clock checking function has finished.	✓	✓
OCCS_TRIM_OSC_200K	NULL	Set the factory frequency trim value of the 200 kHz Internal RC Oscillator.	✓	
OCCS_TRIM_OSC_32K	NULL	Set the factory frequency trim value of the 32 kHz Internal RC Oscillator.		✓
OCCS_TRIM_RELAX_OSC_8MHZ	NULL	Adjust the Relaxation Oscillator frequency to 8MHz using the factory settings. This command reads the factory TRIM value from the internal flash and modifies the TRIM bits in the Oscillator Control register. The standard startup code of the applications created with DSC56800EX_Quick_Start is capable of setting the required frequency and trimming value automatically, when this is enabled in the Graphical Configuration Tool.	✓	✓

Table 5-48. OCCS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
OCCS_WPROTECT_CLK_SETTINGS	OCCS_ENABLE(_PERMANENT)/OCCS_DISABLE(_PERMANENT)	Set the write-protection of the Clock-related configuration bits. Depending on the (PERMANENT) parameter value, the protection may be activated/deactivated permanently (until next reset) or might be changed later.	✓	✓
OCCS_WPROTECT_OSC_SETTINGS	OCCS_ENABLE(_PERMANENT)/OCCS_DISABLE(_PERMANENT)	Set the write-protection of the Oscillator -related configuration bits. Depending on the (PERMANENT) parameter value, the protection may be activated/deactivated permanently (until next reset) or might be changed later.	✓	✓
OCCS_WPROTECT_PLL_SETTINGS	OCCS_ENABLE(_PERMANENT)/OCCS_DISABLE(_PERMANENT)	Set the write-protection of the PLL-related configuration bits. Depending on the (PERMANENT) parameter value, the protection may be activated/deactivated permanently (until next reset) or might be changed later.	✓	✓
OCCS_WRITE_CONTROL_REG	UWord16	Write the parameter value to the PLL Control register.	✓	✓
OCCS_WRITE_DIVIDE_BY_REG	UWord16	Write the parameter value to the PLL Divide-by register.	✓	✓
OCCS_WRITE_OSC_CONTROL_REG	UWord16	Write the parameter value to the Oscillator Control register.	✓	✓
OCCS_WRITE_OSC_CONTROL2_REG	UWord16	Write the parameter value to the Oscillator Control 2 register.	✓	✓

5.1.22 Periodic Interrupt Timer (PIT) Driver

The programmable interval timer module (PIT) contains clock select logic, a 16-bit up counter, a modulo register, and a control register. The modulo and control registers are read/writable. The counter is read only.

The modulo register is loaded with a value to count to and the prescaler is set to determine the counting rate. When enabled, the counter counts up to the modulo value and set a flag (and an interrupt request if enabled), reset to 0x0000, and resume counting.

The Table 5-49 shows module identifiers for PIT Driver.

Table 5-49. Identifiers for PIT Driver

Module identifier	56F82xxx	56F84xxx
PIT_0	✓	✓
PIT_1	✓	✓

The Table 5-50 shows all commands dedicated for PIT Driver.

Table 5-50. PIT Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
PIT_CLEAR_ROLLOVER_INT	NULL	Clear the PIT rollover interrupt flag. Typically, this command is used in the PIT interrupt service routine to acknowledge the interrupt event.	✓	✓
PIT_COUNTER	PIT_ENABLE/PIT_DISABLE	Enable/disable the PIT module counter. This command has no effect on PIT_1 or PIT_2 modules if these operate in "slave mode". In the slave mode the PIT module counter is enabled or disabled simultaneously with PIT_0 counter. See the PIT_SLAVE_MODE command for more details.	✓	✓
PIT_INIT	NULL	Initialize the PIT peripheral registers using the appconfig.h _INIT values.	✓	✓
PIT_INIT	NULL	Initialize the PIT peripheral registers using the appconfig.h _INIT values.	✓	✓
PIT_READ_COUNTER_REG	NULL	Read and return the PIT counter register value as UWord16.	✓	✓

Table 5-50. PIT Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
PIT_READ_MODULO_REG	NULL	Read and return the PIT modulo register value as UWord16.	✓	✓
PIT_ROLLOVER_INT	PIT_ENABLE/PIT_DISABLE	Enable/disable the PIT interrupt to be generated. The PIT interrupt is generated when PIT counter value wraps to zero after reaching the modulo value.	✓	✓
PIT_SET_CLOCK	PIT_IPBUS_CLOCK/PIT_CLOCKxxx (xxx=1/2/3)	Select the source of the clocking for the PIT counter. This field should not be changed when CNT_EN is set.	✓	✓
PIT_SET_PRESCALER	PIT_PRESCALER_xxx (xxx=1/2/4/8/16/32/64/128/256/512/1024/2048/4096/8192/16384/32768)	Set the counter prescaler. The PIT count clock is derived directly from the IP Bus clock, divided by the prescaler value.	✓	✓
PIT_SLAVE_MODE	PIT_ENABLE/PIT_DISABLE	Enable/disable the PIT "slave mode". It is applicable to PIT_1 and PIT_2 only. When slave mode is enabled on PIT, enabling or disabling PIT_0 counter also enables or disables this PIT. Slave mode can be used for simultaneous count-enabling or disabling of multiple PIT modules.	✓	✓
PIT_WRITE_MODULO_REG	UWord16	Set the PIT modulo register, which is the terminal value of the PIT counter. When the counter reaches the modulo value, it is wrapped to zero at the next counter clock and the PIT interrupt event is raised (if enabled). The modulo value of zero causes the PIT counter to remain zero and to generate the PIT interrupts at each counter clock (IP Bus clock divided by prescaler value).	✓	✓

5.1.23 Power Management Controller (PMC) Driver

This specification details the on-chip power management controller module. This module contains the core voltage regulators and power monitoring circuitry. Its function is to ensure that the chip is operated only within legal voltage ranges and to assist in the orderly shutdown of the chip in the event that the power supply is interrupted. It also regulates the internal voltage rails for the core digital and analog logic.

The Table 5-51 shows module identifiers for PMC Driver.

Table 5-51. Identifiers for PMC Driver

Module identifier	56F82xxx	56F84xxx
PMC	✓	✓

The Table 5-52 shows all commands dedicated for PMC Driver.

Table 5-52. PMC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
PMC_CLEAR_LOW_VOLTAGE_INT	combination of PMC_xxx (xxx=LVI|27V_LEVEL|22V_LEVEL)	Clear the selected low voltage interrupt flags. This command can be used for example in the LVI interrupt service routine to clear low voltage interrupt flags.	✓	✓
PMC_CLEAR_STICKY_FLAG	combination of PMC_STICKY_xxx_FLAG (xxx=LV22|LV27)	Clear the selected sticky low voltage flags. The flags indicate that supply voltage dropped below the 2.7V/2.2V level. Once set, those bits remain set until a 1 is written to those bit positions or until a reset occurs.	✓	✓
PMC_GET_BANDGAP_TRIM	NULL	Return the trim value (0-15) of the bandgap reference in the regulator as UWord16.	✓	✓
PMC_GET_LOW_VOLTAGE	combination of PMC_xxx_LEVEL (xxx=22V|27V)	Get the low voltage sticky interrupt flags.	✓	✓
PMC_GET_NONSTICKY_INT_SOURCE	combination of PMC_xxx_LEVEL (xxx=22V|27V)	Get the low voltage nonsticky interrupts flags.	✓	✓

Table 5-52. PMC Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
PMC_GET_SMALL_27V_REGULATOR_STATUS	NULL	Return the small regulator 2.7V active flag. The small regulator supplies the power to the crystal oscillator, relaxation oscillator, PLL and duty cycle corrector. It can be power down using the SIM's PWR [SR27PDN] bits.	✓	✓
PMC_INIT	NULL	Initialize the PMC peripheral registers using the appconfig.h _INIT values.	✓	✓
PMC_INT_DISABLE	combination of PMC_xxx_LEVEL (xxx=HVI_27V|HVI_22V|LVI_27V|LVI_22V)	Disable the low/high voltage interrupt.	✓	✓
PMC_INT_ENABLE	combination of PMC_xxx_LEVEL (xxx=HVI_27V|HVI_22V|LVI_27V|LVI_22V)	Enable the low/high voltage interrupt.	✓	✓
PMC_INT_SELECT	combination of PMC_xxx_LEVEL (xxx=HVI_27V|HVI_22V|LVI_27V|LVI_22V)	Enable the selected low voltage interrupts.	✓	✓
PMC_READ_CTRL_REG	NULL	Read and return the value of PMC Control register as UWord16.	✓	✓
PMC_READ_STATUS_REG	NULL	Read and return the PMC Status register as UWord16.	✓	✓
PMC_SET_ADC_VOLTAGE_REF_BUFFER	PMC_ENABLE/PMC_DISABLE	Enable/disable the voltage reference buffer that drives the 1.2V bandgap reference to the ADC.	✓	✓
PMC_SET_BANDGAP_TRIM	UWord16 value 0-15	Set the trim value of the bandgap reference in the regulator. Its reset state is the mid-range.	✓	✓
PMC_TEST_FLAG	combination of PMC_xxx_FLAG (xxx=STICKY_LV27|STICKY_LV22|LV_27V|LV_22V)	Test the selected flags.	✓	✓
PMC_WRITE_CTRL_REG	UWord16	Write to the PMC Control register.	✓	✓
PMC_WRITE_STATUS_REG	UWord16	Write to the PMC Status register. Note: An inappropriate write to register might clear Write-1-to-Clear (LVI/SLV27F/SLV22F) flags.	✓	✓

5.1.24 Programmable Delay Block (PDB)

The primary function of the programmable delay block (PDB) is simply to provide a controllable delay from the PWM SYNC output to the sample trigger input of the programmable gain amplifiers and ADCs as well as a controllable window that is synchronized with PWM pulses for analog comparators to compare the analog signals in a defined window.

The PDB provides the following features:

- 16-bit resolution with prescaler
- Positive transition of trigger_in will initiate the counter
- Supports two trigger_out signals. Each has an independently controlled delay from sync_in
- Trigger outputs can be ORed together to schedule two conversions from one input trigger event
- Trigger outputs can be used to schedule precise edge placement for a pulsed output. This feature is used to generate the control signal for the HSCMP windowing feature (see description of High Speed Comparator module) and output to a package pin if needed
- Continuous trigger or single shot mode supported
- Bypass mode supported
- Each trigger output is independently enabled

The Table 5-53 shows module identifiers for PDB Driver.

Table 5-53. Identifiers for PDB Driver

Module identifier	56F82xxx	56F84xxx
PDB_0		✓
PDB_1		✓

The Table 5-54 shows all commands dedicated for PDB Driver.

Table 5-54. PDB Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
PDB_CLEAR_DELAY_A_FLAG	NULL	Clear the delay A flag.		✓
PDB_CLEAR_DELAY_B_FLAG	NULL	Clear the delay B flag.		✓
PDB_CLEAR_DELAY_C_FLAG	NULL	Clear the delay C flag.		✓
PDB_CLEAR_DELAY_D_FLAG	NULL	Clear the delay D flag.		✓

Table 5-54. PDB Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
PDB_CLEAR_OVERFLOW	NULL	Clear the counter overflow interrupt flag.		✓
PDB_CNT_OVERFLOW_INT	PDB_ENABLE/PDB_DISABLE	Enable/disable the counter overflow interrupt.		✓
PDB_GET_OVERFLOW	NULL	Get the counter overflow interrupt flag.		✓
PDB_INIT	NULL	Initialize the PDB peripheral registers using the appconfig.h _INIT values.		✓
PDB_MODULE	PDB_ENABLE/PDB_DISABLE	Enable/disable the PDB module. When the module is disabled all Trigger and PreTrigger outputs are low.		✓
PDB_READ_COUNT	NULL	Read and return the PDB Counter register value as UWord16.		✓
PDB_READ_CTRLA_REG	NULL	Read and return the value of the Control A register as UWord16.		✓
PDB_READ_CTRLC_REG	NULL	Read and return the value of the Control C register as UWord16.		✓
PDB_READ_MCTRL_REG	NULL	Read and return the value of the Master Control register as UWord16.		✓
PDB_SELECT_LOAD_MODE	PDB_LOAD_IMMEDIATELY/ PDB_LOAD_AFTER_ROLL_OVER	Select the behavior of the PDB_SET_LDOK command. Use PDB_LOAD_IMMEDIATELY to enable the DELAY* and MOD registers to be loaded immediately after PDB_SET_LDOK command. Use PDB_LOAD_AFTER_ROLL_OVER to load registers after calling the PDB_SET_LDOK command when the counter rolls over in continuous mode or when a trigger signal is received in one-shot mode.		✓
PDB_SET_CONTINUOUS_MODE	PDB_ENABLE/PDB_DISABLE	Set continuous or one-shot mode.		✓
PDB_SET_DELAY_A_INTERRUPT	PDB_ENABLE/PDB_DISABLE	Enable/disable the interrupt on the DELAYA successful compare request.		✓
PDB_SET_DELAY_B_INTERRUPT	PDB_ENABLE/PDB_DISABLE	Enable/disable the interrupt on the DELAYB successful compare request.		✓
PDB_SET_DELAY_C_INTERRUPT	PDB_ENABLE/PDB_DISABLE	Enable/disable the interrupt on the DELAYC successful compare request.		✓

Table 5-54. PDB Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
PDB_SET_DELAY_D_INTERRUPT	PDB_ENABLE/PDB_DISABLE	Enable/disable the interrupt on the DELAYD successful compare request.		✓
PDB_SET_FAULT_A	PDB_ENABLE/PDB_DISABLE	Enable/disable the Fault A. A logic 1 on the Fault A input forces TriggerA output to initial value set by PDB_SET_INIT_A_VALUE command until a counter reload occurs.		✓
PDB_SET_FAULT_A_LENGTH	PDB_xxx (xxx=2_IPBUS_CYCLES/4_IPBUS_CYCLES)	Select the minimum width (number of IP bus clock cycles) of the input fault when it is recognized as a valid fault condition.		✓
PDB_SET_FAULT_A_POLARITY	PDB_xxx (xxx=TRUE_INDICATE_FAULT/FALSE_INDICATE_FAULT)	Select the Fault A polarity.		✓
PDB_SET_FAULT_C	PDB_ENABLE/PDB_DISABLE	Enable/disable the Fault C. A logic 1 on the Fault C input forces TriggerC output to initial value set by PDB_SET_INIT_C_VALUE command until a counter reload occurs.		✓
PDB_SET_FAULT_C_LENGTH	PDB_xxx (xxx=2_IPBUS_CYCLES/4_IPBUS_CYCLES)	Select the minimum width (number of IP bus clock cycles) of the input fault when it is recognized as a valid fault condition.		✓
PDB_SET_FAULT_C_POLARITY	PDB_xxx (xxx=TRUE_INDICATE_FAULT/FALSE_INDICATE_FAULT)	Select the Fault C polarity.		✓
PDB_SET_INIT_A_VALUE	PDB_xxx (xxx=INIT_FALSE/INIT_TRUE)	Set the Trigger A output value which is forced when Fault A is active and enabled by PDB_SET_FAULT_A command. In COMBINED_DELAY_AB output mode, the specified Trigger A output value is also forced whenever the counter is reloaded.		✓

Table 5-54. PDB Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
PDB_SET_INIT_C_VALUE	PDB_xxx (xxx=INIT_FALSE/INIT_TRUE)	Set the Trigger C output value which is forced when Fault C is active and enabled by PDB_SET_FAULT_C command. In COMBINED_DELAY_CD output mode, the specified Trigger C output value is also forced whenever the counter is reloaded.		✓
PDB_SET_INPUT_TRIGGER	PDB_TRIG_xxx (xxx=SEL0/SEL1/SEL2/SEL3/SEL4/SEL5/SEL6/SW_TRIG)	Select the PDB Input trigger source. Select one of seven input signals as a trigger. The PDB module can also be triggered by software when SW_TRIG mode is selected. Use the PDB_SET_SW_TRIGGER command to trigger.		✓
PDB_SET_LDOK	NULL	Load the DELAY and MOD registers. The effect of this LDOK settings also depends on the LDMOD bit controlled by PDB_SELECT_LOAD_MODE command.		✓
PDB_SET_PRESCALER	PDB_CLOCK_DIVIDER_xxx (xxx=1/2/4/8/16/32/64/128)	Set the PDB clock prescaler.		✓
PDB_SET_SW_TRIGGER	NULL	Activate the software trigger which triggers a reset and restarts the counter. The trigger mode should be first set to SW_TRIG with the PDB_SET_INPUT_TRIGGER command. Alternatively, if TriggerA or TriggerB is bypassed the SW trigger it will propagate immediately.		✓
PDB_SET_TRIGGER_A_BYPASS	PDB_ENABLE/PDB_DISABLE	Bypass the Trigger A Output of the PDB module.		✓
PDB_SET_TRIGGER_A_DISABLE	NULL	Disable the PDB Trigger A output.		✓
PDB_SET_TRIGGER_A_ENABLE	NULL	Enable the PDB Trigger A output. The PDB Trigger A is generated when PDB counter value reaches the DELAY A value.		✓

Table 5-54. PDB Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
PDB_SET_TRIGGER_A_OUTSEL	PDB_xxx (xxx=SEPARATED_DELAY_A_B/COMBINED_DELAY_AB)	Select the triggers A and B output mode. In SEPARATED mode, the Trigger A is a function of DELAYA only and Trigger B is a function of DELAYB only. In COMBINED mode, the Trigger A and Trigger B outputs are a function of combined DELAYA and DELAYB.		✓
PDB_SET_TRIGGER_B_BYPASS	PDB_ENABLE/PDB_DISABLE	Bypass the Trigger B Output of the PDB module.		✓
PDB_SET_TRIGGER_B_DISABLE	NULL	Disable the PDB Trigger B output.		✓
PDB_SET_TRIGGER_B_ENABLE	NULL	Enable the PDB Trigger B output. The PDB Trigger B is generated when PDB counter value reaches the DELAY B value.		✓
PDB_SET_TRIGGER_C_BYPASS	PDB_ENABLE/PDB_DISABLE	Bypass the Trigger C Output of the PDB module.		✓
PDB_SET_TRIGGER_C_DISABLE	NULL	Disable the PDB Trigger C output.		✓
PDB_SET_TRIGGER_C_ENABLE	NULL	Enable the PDB Trigger C output. The PDB Trigger C is generated when PDB counter value reaches the DELAY C value.		✓
PDB_SET_TRIGGER_C_OUTSEL	PDB_xxx (xxx=SEPARATED_DELAY_C_D/COMBINED_DELAY_CD)	Select the triggers C and D output mode. In SEPARATED mode, the Trigger C is a function of DELAYC only and Trigger D is a function of DELAYD only. In COMBINED mode, the Trigger C and Trigger D outputs are a function of combined DELAYC and DELAYD.		✓
PDB_SET_TRIGGER_D_BYPASS	PDB_ENABLE/PDB_DISABLE	Bypass the Trigger D Output of the PDB module.		✓
PDB_SET_TRIGGER_D_DISABLE	NULL	Disable the PDB Trigger D output.		✓
PDB_SET_TRIGGER_D_ENABLE	NULL	Enable the PDB Trigger D output. The PDB Trigger D is generated when PDB counter value reaches the DELAY D value.		✓

Table 5-54. PDB Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
PDB_TEST_DELAY_A_FLAG	NULL	Return a non-zero value when a successful compare of the values of counter and DELAYA occurred.		✓
PDB_TEST_DELAY_B_FLAG	NULL	Return a non-zero value when a successful compare of the values of counter and DELAYB occured.		✓
PDB_TEST_DELAY_C_FLAG	NULL	Return a non-zero value when a successful compare of the values of counter and DELAYC occured.		✓
PDB_TEST_DELAY_D_FLAG	NULL	Return a non-zero value when a successful compare of the values of counter and DELAYD occured.		✓
PDB_TEST_FAULT_A_STATUS	NULL	Return a non-zero value when Fault A input is set.		✓
PDB_TEST_FAULT_C_STATUS	NULL	Return a non-zero value when Fault C input is set.		✓
PDB_TEST_LDOK	NULL	Return the non-zero value when the LDOK bit is set. Use this command to determine if the values in the DELAY* and MOD registers are pending in buffers (non-zero) or if the write has already taken effect (zero).		✓
PDB_WRITE_CTRLA_REG	UWord16	Write the parameter value to the Control A register. Note: an inappropriate write to register can clear Write-1-to-Clear (DAF/DBF) flags.		✓
PDB_WRITE_CTRLC_REG	UWord16	Write the parameter value to the Control C register. Note: an inappropriate write to register can clear Write-1-to-Clear (DCF/DDF) flags.		✓
PDB_WRITE_DELAYA	UWord16	Write the parameter value to the DelayA register, which represents the delay between the input PDB trigger and trigger A output. Note: The write is buffered. Writing to this register writes the data into a buffer, where it is held depending on the value of LDOK and LDMOD bits. The bits are controlled by PDB_SELECT_LOAD_MODE and PDB_SET_LDOK commands.		✓

Table 5-54. PDB Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
PDB_WRITE_DELAYB	UWord16	Write the parameter value to the DelayB register, which represents the delay between the input PDB trigger and trigger B output. Note: The write is buffered. Writing to this register writes the data into a buffer, where it is held depending on the value of LDOK and LDMOD bits. The bits are controlled by PDB_SELECT_LOAD_MODE and PDB_SET_LDOK commands.		✓
PDB_WRITE_DELAYC	UWord16	Write the parameter value to the DelayC register, which represents the delay between the input PDB trigger and trigger C output. Note: The write is buffered. Writing to this register writes the data into a buffer, where it is held depending on the value of LDOK and LDMOD bits. The bits are controlled by PDB_SELECT_LOAD_MODE and PDB_SET_LDOK commands.		✓
PDB_WRITE_DELAYD	UWord16	Write the parameter value to the DelayD register, which represents the delay between the input PDB trigger and trigger D output. Note: The write is buffered. Writing to this register writes the data into a buffer, where it is held depending on the value of LDOK and LDMOD bits. The bits are controlled by PDB_SELECT_LOAD_MODE and PDB_SET_LDOK commands.		✓
PDB_WRITE_MCTRL_REG	UWord16	Write to the Master Control register the parameter value. Note: an inappropriate write to register may cause accidental clear of Write-1-to-Clear flag (COF) and accidental set of the LDOK bit.		✓

Table 5-54. PDB Driver Command

Cmd	pParam	Description	56F82xxx	56F84xxx
PDB_WRITE_MOD	UWord16	Write the parameter value to the counter modulo register, which presents the terminal value of the PDB counter. When counter reaches the modulo value, it resets to 0x0001. Note: The write is buffered. Writing to this register writes the data into a buffer, where it is held depending on the value of LDOK and LDMOD bits. The bits are controlled by PDB_SELECT_LOAD_MODE and PDB_SET_LDOK commands.		✓

5.1.25 Quad Timer (QT) Driver

Each timer module (QT) contains four identical counter/timer groups. Each 16-bit counter/timer group contains a prescaler, a counter, a load register, a hold register, a capture register, two compare registers, two status and control registers, and one control register. All of the registers except the prescaler are read/writable.

The load register provides the initialization value to the counter when the counter's terminal value has been reached.

The hold register captures the counter's value when other counters are being read. This feature supports the reading of cascaded counters.

The capture register enables an external signal to take a "snap shot" of the counter's current value.

The COMP1 and COMP2 registers provide the values to which the counter is compared. If a match occurs, the OFLAG (TMR Output signal) can be set, cleared, or toggled. At match time, an interrupt is generated if enabled, and the new compare value is loaded into the COMP1 or COMP2 registers from CMPLD1 and CMPLD2 if enabled.

The prescaler provides different time bases useful for clocking the counter/timer. The counter provides the ability to count internal or external events.

Within a timer module (set of four timer/counters), the input pins are shareable.

The Table 5-55 shows module identifiers for QTIMER Driver.

Table 5-55. Identifiers for QTIMER Driver

Module identifier	56F82xxx	56F84xxx
QTIMER_A0	✓	✓
QTIMER_A1	✓	✓
QTIMER_A2	✓	✓
QTIMER_A3	✓	✓
QTIMER_B0	✓	
QTIMER_B1	✓	
QTIMER_B2	✓	
QTIMER_B3	✓	

The Table 5-56 shows all commands dedicated for QT Driver.

Table 5-56. QT Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
QT_CLEAR_COMPARE_FLAG	combination of QT_COMPARE1_FLAG|QT_COMPARE2_FLAG	Clear the selected timer/counter compare flags.	✓	✓
QT_CLEAR_FLAG	combination of QT_xxx_FLAG (xxx=COMPARE|OVERFLOW|INPUT_EDGE|VAL)	Clear the selected timer/counter flags. Specify combination of Timer Compare Flag (TCF), Timer Overflow Flag (TOF), Input Edge Flag (IEF) and Forced OFLAG Value flag (VAL).	✓	✓
QT_CO_CHANNEL_INIT	QT_ENABLE/QT_DISABLE	Enable/disable another timer/counter in the same Quad Timer module to force the re-initialization of this timer/counter, when it has encountered an active compare event (co-channel initialization).	✓	✓
QT_DMA_READ_REQ_CMPLD1	QT_ENABLE/QT_DISABLE	Enable/disable DMA write requests for CMPLD1 whenever data is transferred out of the CMPLD1 register into the COMP1 register.	✓	✓
QT_DMA_READ_REQ_CMPLD2	QT_ENABLE/QT_DISABLE	Enable DMA write requests for CMPLD2 whenever data is transferred out of the CMPLD2 register into the CNTR or COMP2 registers.	✓	✓
QT_DMA_WRITE_REQ	QT_ENABLE/QT_DISABLE	Enables DMA read requests for CAPT when Input Edge Flag gets set.	✓	✓
QT_EXT_OFLAG_FORCE	QT_ENABLE/QT_DISABLE	Enable/disable the external OFLAG force. This means that the timers/counters from the same QT module set as a master can force the state of this timer/counter OFLAG output.	✓	✓
QT_FORCE_OFLAG	QT_ONE/QT_ZERO	Set/clear the OFLAG output using the software triggered FORCE command. First this command writes the passed 1-bit value to the [VAL] bit. Then it writes 1 to the [FORCE] bit, what causes that the current value of the VAL bit is written to the OFLAG output. Note: Use this command only if timer is disabled.	✓	✓
QT_INIT	NULL	Initialize the QT peripheral registers using the appconfig.h _INIT values.	✓	✓

Table 5-56. QT Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
QT_INT_DISABLE	QT_xxx_INT (xxx=COMPARE|COMPARE1|COMPARE2|OVERFLOW|INPUT_EDGE)	Disables selected interrupts.	✓	✓
QT_INT_ENABLE	QT_xxx_INT (xxx=COMPARE|COMPARE1|COMPARE2|OVERFLOW|INPUT_EDGE)	Enable selected interrupts.	✓	✓
QT_OUTPUT_ON_EXT_PIN	QT_ENABLE/QT_DISABLE	Enable/disable the OFLAG output signal to be put on the external pin. This command sets/clears the Output Enable [OEN] bit in the timer/counter Status and Control register.	✓	✓
QT_READ_CAPTURE_REG	NULL	Read and return the value of the timer/counter Capture register as UWord16.	✓	✓
QT_READ_CMP_STATUS_CONTROL_REG	NULL	Read and return the value of the timer/counter Comparator Status/Control register as UWord16.	✓	✓
QT_READ_COMPARE_FLAG	QT_COMPARE1_FLAG|QT_COMPARE2_FLAG	Return the status of selected timer/counter compare flags.	✓	✓
QT_READ_COMPARE_REG1	NULL	Read and return the value of the timer/counter Compare register 1 as UWord16.	✓	✓
QT_READ_COMPARE_REG2	NULL	Read and return the value of the timer/counter Compare register 2 as UWord16.	✓	✓
QT_READ_CONTROL_REG	NULL	Read and return the value of the timer/counter Control register as UWord16.	✓	✓
QT_READ_COUNTER_REG	NULL	Read and return the value of the timer/counter Counter register as UWord16.	✓	✓
QT_READ_EXT_INPUT_PIN	NULL	Read the current state of the external input pin after application of the Input Polarity Select (IPS) bit, return 0x0000 (input pin is 0) or 0x0100 (input pin is 1).	✓	✓
QT_READ_FILT_REG	NULL	Read and return the value of fiter Fegister.	✓	✓

Table 5-56. QT Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
QT_READ_FLAG	QT_COMPARE_FLAG|QT_OVERFLOW_FLAG|QT_INPUT_EDGE_FLAG|QT_VAL_FLAG	Read and return the status of selected timer/counter flags.	✓	✓
QT_READ_HOLD_REG	NULL	Read and return the value of the timer/counter Hold register as UWord16.	✓	✓
QT_READ_LOAD_REG	NULL	Read and return the value of the timer/counter Load register as UWord16.	✓	✓
QT_READ_STATUS_CONTROL_REG	NULL	Read and return the value of the timer/counter Status and Control register as UWord16.	✓	✓
QT_SET_ALTERNATIVE_LOAD	QT_ENABLE/QT_DISABLE	Enable/disable re-initializing of the counter from alternative CMPLD2 register.	✓	✓
QT_SET_CAPTURE_MODE	QT_CAPTURE_DISABLED/QT_RISING_EDGE/QT_FALLING_EDGE/QT_BOTH_EDGES	Set Input Capture Mode.	✓	✓
QT_SET_COUNT_DIRECTION	QT_COUNT_UP/QT_COUNT_DOWN	Select if timer/counter counts up or down.	✓	✓
QT_SET_COUNT_LENGTH	QT_ROLL_OVER/QT_UNTIL_COMPARE_AND_REINIT	Select if timer/counter counts up to the compare value and then re-initializes itself to the value specified in the load register (QT_UNTIL_COMPARE_AND_REINIT); or the counter continues counting past the compare value up to the binary roll over (QT_ROLL_OVER).	✓	✓

Table 5-56. QT Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
QT_SET_COUNT_MODE	QT_NO_OPERATION / QT_COUNT_RISING_EDGES_MODE / QT_COUNT_BOTH_EDGES_MODE / QT_GATED_COUNT_MODE / QT_QUADRATURE_COUNT_MODE / QT_SIGNED_COUNT_MODE / QT_TRIGGERED_COUNT_MODE / QT_CASCADE_COUNT_MODE / QT_ONE_SHOT_MODE / QT_PULSE_OUTPUT_MODE / QT_FIXED_FREQ_PWM_MODE / QT_VARIABLE_FREQ_PWM_MODE	Set timer/counter count mode.	✓	✓
QT_SET_COUNT_ONCE	QT_COUNT_REPEATEDLY/ QT_UNTIL_COMPARE_AND_STOP	Select if timer/counter counts repeatedly or until the compare event and then it stops.	✓	✓
QT_SET_COUNTING_UPON_SEC_TRIG	QT_ENABLE/QT_DISABLE	Enable/disable counting timer upon receiving a second trigger.	✓	✓
QT_SET_DEBUG_ACTION	QT_DEBUG_xxx (CONTINUE/HALT_TMR/FORCE_OUT_0/HALT_TMR_FORCE_OUT_0)	Set certain actions in response to the chip entering the debug mode.	✓	✓
QT_SET_FAULT_FUNCTION	QT_ENABLE/QT_DISABLE	Enable/disable the fault function.	✓	✓
QT_SET_INPUT_POLARITY	QT_NORMAL_POLARITY/QT_INVERTED_POLARITY	Set the polarity of the timer/counter input signal.	✓	✓
QT_SET_LOAD_CONTROL1	QT_NEVER_PRELOAD/QT_LOAD_ON_CMP1/QT_LOAD_ON_CMP2	Specify the preload event for the Compare Register 1.	✓	✓
QT_SET_LOAD_CONTROL2	QT_NEVER_PRELOAD/QT_LOAD_ON_CMP1/QT_LOAD_ON_CMP2	Specify the preload event for the Compare Register 2.	✓	✓

Table 5-56. QT Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
QT_SET_OUTPUT_MODE	QT_SET_WHILE_ACTIVE / QT_CLEAR_ON_COMPARE / QT_SET_ON_COMPARE / QT_TOGGLE_ON_COMPARE / QT_TOGGLE_USING_ALT_COMPARE / QT_CLEAR_ON_SECONDARY / QT_CLEAR_ON_COUNTER_ROLLOVER / QT_GATED_CLOCK_WHILE_ACTIVE	Set timer/counter output mode (i.e. the mode of operation for the OFLAG output signal).	✓	✓
QT_SET_OUTPUT_POLARITY	QT_NORMAL_POLARITY/QT_INVERTED_POLARITY	Set the timer/counter output signal polarity.	✓	✓
QT_SET_PRIMARY_SOURCE	QT_COUNTER0_INPUT / QT_COUNTER1_INPUT / QT_COUNTER2_INPUT / QT_COUNTER3_INPUT / QT_COUNTER0_OUTPUT / QT_COUNTER1_OUTPUT / QT_COUNTER2_OUTPUT / QT_COUNTER3_OUTPUT / QT_IPBUS_DIV_1 / QT_IPBUS_DIV_2 / QT_IPBUS_DIV_4 / QT_IPBUS_DIV_8 / QT_IPBUS_DIV_16 / QT_IPBUS_DIV_32 / QT_IPBUS_DIV_64 / QT_IPBUS_DIV_128	Set primary count source of timer/counter.	✓	✓
QT_SET_RELOAD_ON_CAPTURE	QT_ENABLE/QT_DISABLE	Enable/disable reload of the counter on a capture event.	✓	✓
QT_SET_SECONDARY_SOURCE	QT_COUNTER0_INPUT / QT_COUNTER1_INPUT / QT_COUNTER2_INPUT / QT_COUNTER3_INPUT	Set secondary count source of timer/counter.	✓	✓
QT_TEST_LAST_COUNT_DIRECTION	NULL	Return the direction of the last count.	✓	✓
QT_WRITE_CMP_STATUS_CONTROL_REG	UWord16	Write the parameter value into the timer/counter Comparator Status/Control register.	✓	✓
QT_WRITE_COMPARE_REG1	UWord16	Write the parameter value into the timer/counter Compare register 1.	✓	✓

Table 5-56. QT Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
QT_WRITE_COMPARE_REG2	UWord16	Write the parameter value into the timer/counter Compare register 2.	✓	✓
QT_WRITE_CONTROL_REG	UWord16	Write the parameter value into the timer/counter Control register.	✓	✓
QT_WRITE_COUNTER_REG	UWord16	Write the parameter value into the timer/counter Counter register.	✓	✓
QT_WRITE_FILT_REG	UWord16	Write the Filter register.	✓	✓
QT_WRITE_LOAD_REG	UWord16	Write the parameter value into the timer/counter Load register.	✓	✓
QT_WRITE_PRELOAD_COMPARE_REG1	UWord16	Write the parameter value into the timer/counter Comparator Load register 1.	✓	✓
QT_WRITE_PRELOAD_COMPARE_REG2	UWord16	Write the parameter value into the timer/counter Comparator Load register 2.	✓	✓
QT_WRITE_STATUS_CONTROL_REG	UWord16	Write the parameter value into the timer/counter Status and Control register.	✓	✓
QT0_MASS_DISABLE	combination of QT_CH0|QT_CH1|QT_CH2|QT_CH3	Mass disable selected timer channels.	✓	✓
QT0_MASS_ENABLE	combination of QT_CH0|QT_CH1|QT_CH2|QT_CH3	Mass enable selected timer channels.	✓	✓

5.1.26 Queued Serial Communication Interface (SCI) Driver

The SCI allows asynchronous serial communications with peripheral devices.

The SCI provides the following feautures :

- Full-duplex or single-wire operation
- Standard mark/space non-return-to-zero (NRZ) format
- 16-bit integer and 3-bit fractional baud rate selection
- Programmable 8-bit or 9-bit data format
- Separately enabled transmitter and receiver
- Separate receiver and transmitter DSC core interrupt requests
- Programmable polarity for transmitter and receiver
- Two receiver wake-up methods: idle line or address mark
- Clockless receiver wake-up on active input edge
- Interrupt-driven operation with multiple flags:Transmitter empty, Transmitter idle, Receiver full, Receiver overrun, Receiver idle, Receiver input edge, Noise error, Framing error, Parity error
- Receiver framing error detection
- Hardware parity checking
- 1/16 bit-time noise detection

The Table 5-57 shows module identifiers for SCI Driver.

Table 5-57. Identifiers for SCI Driver

Module identifier	56F82xxx	56F84xxx
SCI_0	✓	✓
SCI_1	✓	✓
SCI_2		✓

The Table 5-58 shows all commands dedicated for SCI Driver.

Table 5-58. SCI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SCI_BUFFERED_RX	SCI_ENABLE / SCI_DISABLE	Enable/disable the read operations if the SCI operates in a BUFFERED mode. The buffer pointers are initialized and interrupts enabled.	✓	✓

Table 5-58. SCI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SCI_BUFFERED_TX	SCI_ENABLE / SCI_DISABLE	Enable/disable the write operations if the SCI operates in a BUFFERED mode. The buffer pointers are initialized and interrupts enabled.	✓	✓
SCI_CLEAR_EXCEPTION	NULL	Clear the read/write functions exception if exists.	✓	✓
SCI_CLEAR_STATUS_REG	NULL	Clear the SCI Status Register.	✓	✓
SCI_DATA_FORMAT	SCI_WORD_9BIT / SCI_WORD_8BIT	Set SCI word length.	✓	✓
SCI_DATA_POLARITY	SCI_INVERTED / SCI_NOT_INVERTED	Set polarity of transmitted and received data.	✓	✓
SCI_DMA_RECEIVER	SCI_ENABLE / SCI_DISABLE	Enable/disable the DMA Receiver.	✓	✓
SCI_DMA_TRANSMITTER	SCI_ENABLE / SCI_DISABLE	Enable/disable the DMA Transmitter.	✓	✓
SCI_GET_ERROR	NULL	Test any of Error flags in the SCI Status Register. Return non-zero if any error bit is set.	✓	✓
SCI_GET_LIN_SYNC_ERROR	NULL	Test the LIN Sync Error flag in the SCI Status Register. Return non-zero if the bit is set.	✓	✓
SCI_GET_RX_ACTIVE	NULL	Test the Receiver Active flag in the SCI Status Register. Return non-zero if the bit is set.	✓	✓
SCI_GET_RX_BUFFER_FREESPACE	NULL	Return the free space in the receive buffer during the BUFFERED operation.	✓	✓
SCI_GET_RX_CHARS_READY	NULL	Number of characters pending in the receive buffer during the BUFFERED operation.	✓	✓
SCI_GET_RX_FRAMING_ERROR	NULL	Test the Framing Error flag in the SCI Status Register. Return non-zero if the bit is set.	✓	✓
SCI_GET_RX_FULL	NULL	Test the Receiver Full flag in the SCI Status Register. Return non-zero if the bit is set.	✓	✓

Table 5-58. SCI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SCI_GET_RX_IDLE	NULL	Test the Receiver Idle flag in the SCI Status Register. Return non-zero if the bit is set.	✓	✓
SCI_GET_RX_NOISE_ERROR	NULL	Test the Noise Error flag in the SCI Status Register. Return non-zero if the bit is set.	✓	✓
SCI_GET_RX_OVERRUN	NULL	Test the Receiver Overrun flag in the SCI Status Register. Return non-zero if the bit is set.	✓	✓
SCI_GET_RX_PARITY_ERROR	NULL	Test the Parity Error flag in the SCI Status Register. Return non-zero if the bit is set.	✓	✓
SCI_GET_STATUS	NULL	Return SCI0 or SCI1 read/write status register according to module used.	✓	✓
SCI_GET_STATUS_REG	NULL	Read and return the value of SCI Status Register.	✓	✓
SCI_GET_TX_BUFFER_FREESPACE	NULL	Return the free space in the transmit buffer during the BUFFERED operation.	✓	✓
SCI_GET_TX_EMPTY	NULL	Test the Transmitter Empty flag in the SCI Status Register. Return non-zero if the bit is set.	✓	✓
SCI_GET_TX_IDLE	NULL	Test the Transmitter Idle flag in the SCI Status Register. Return non-zero if the bit is set.	✓	✓
SCI_INIT	NULL	Initialize the SCI periheral registers using the appcongig.h _INIT values.	✓	✓
SCI_INT_DISABLE	SCI_TX_EMPTY | SCI_TX_IDLE | SCI_RX_FULL | SCI_RX_ERROR	Disable selected interrupt sources.	✓	✓
SCI_INT_ENABLE	SCI_TX_EMPTY | SCI_TX_IDLE | SCI_RX_FULL | SCI_RX_ERROR	Enable selected interrupt sources.	✓	✓
SCI_LIN_MODE	SCI_ENABLE / SCI_DISABLE	Enable/disable the LIN slave operation mode.	✓	✓

Table 5-58. SCI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SCI_OPERATING_MODE	SCI_NORMAL_MODE | SCI_INTERNAL_LOOP_MODE | SCI_SINGLE_WIRE_MODE	Set SCI loop mode operation.	✓	✓
SCI_PARITY	SCI_PARITY_ODD / SCI_PARITY_EVEN / SCI_PARITY_NONE	Set SCI parity mode.	✓	✓
SCI_READ_CANCEL	NULL	Clear RIEF flag; clear RxCounter and disable interrupts in SCI0 or SCI1 module used.	✓	✓
SCI_READ_CONTROL_REG	NULL	Read and return the value of SCI Control Register.	✓	✓
SCI_READ_DATA	NULL	Read and return the value of the SCI Data Register.	✓	✓
SCI_RECEIVE_DMA_REQ	NULL	Test the RDMA bit if the SCI is currently requesting a DMA data transfer for received data.	✓	✓
SCI_RECEIVER	SCI_ENABLE / SCI_DISABLE	Enable/disables the SCI Receiver.	✓	✓
SCI_RECEIVER_IDLE_INT	SCI_ENABLE / SCI_DISABLE	Enable/disable the Receiver Idle Interrupt.	✓	✓
SCI_RECEIVER_INPUT_EDGE_FLAG	NULL	Test the Receiver Input Edge Flag if an active edge was seen on the RXD input pin.	✓	✓
SCI_RECEIVER_INPUT_EDGE_INT	SCI_ENABLE / SCI_DISABLE	Enable/disable the Input Edge Interrupt.	✓	✓
SCI_RX_ERROR_INT	SCI_ENABLE / SCI_DISABLE	Enable/disable Receive Error Interrupt.	✓	✓
SCI_RX_FULL_INT	SCI_ENABLE / SCI_DISABLE	Enable/disable Receiver Full Interrupt.	✓	✓
SCI_SEND_BREAK	NULL	Send a single break character.	✓	✓
SCI_SEND_XOFF	NULL	Send the XOFF priority character.	✓	✓
SCI_SEND_XON	NULL	Send the XON priority character.	✓	✓

Table 5-58. SCI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SCI_SET_BAUDRATE	One of the SCI_BAUDxx constants (or UWord16 divisor value)	Configure the SCI Baud Rate Register. The SCI_BAUD_xx (xx = baud rate) values are defined for the most common clock frequencies.	✓	✓
SCI_SET_FRACTIONAL_BAUDRATE	UWord16 value 0-7	Configure the SCI Fractional Baud Rate divider. Provide a value from 0 to 7 that is divided by 8.	✓	✓
SCI_STOP_IN_WAIT	SCI_ENABLE / SCI_DISABLE	Enable/disable the low-power STOP mode during the CPU WAIT mode.	✓	✓
SCI_TEST_STATUS_REG	SCI_TX_EMPTY_FLAG | SCI_TX_IDLE_FLAG | SCI_RX_FULL_FLAG | SCI_RX_IDLE_LINE_FLAG | SCI_OVERRUN_FLAG | SCI_NOISE_FLAG | SCI_FRAMING_ERROR_FLAG | SCI_PARITY_ERROR_FLAG | SCI_RX_ACTIVE_FLAG | SCI_LIN_SYNC_ERROR_FLAG	Test the selected bits in SCI Status Register.	✓	✓
SCI_TRANSMIT_DMA_REQ	NULL	Test the TDMA bit if the SCI is currently requesting a DMA data transfer for transmit data.	✓	✓
SCI_TRANSMITTER	SCI_ENABLE / SCI_DISABLE	Enable/disable the SCI Transmitter.	✓	✓
SCI_TX_EMPTY_INT	SCI_ENABLE / SCI_DISABLE	Enable/disable Transmitter Empty Interrupt.	✓	✓
SCI_TX_IDLE_INT	SCI_ENABLE / SCI_DISABLE	Enable/disable Transmitter Idle Interrupt.	✓	✓
SCI_WAIT	NULL	Put SCI receiver in sleep mode.	✓	✓
SCI_WAKEUP	NULL	Wake up the SCI receiver.	✓	✓
SCI_WAKEUP_CONDITION	SCI_WAKE_BY_ADDRESS / SCI_WAKE_BY_IDLE	Set SCI wake up mode.	✓	✓
SCI_WRITE_CANCEL	NULL	Clear RIEF flag; clear TxCounter and disable interrupts in SCI0 or SCI1 module used.	✓	✓
SCI_WRITE_CONTROL_REG	UWord16	Write to SCI Control Register.	✓	✓

Table 5-58. SCI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SCI_WRITE_DATA	UWord16	Write to SCI Data Register.	✓	✓

5.1.27 Serial Peripheral Interface (SPI) Driver

The serial peripheral interface (SPI) module enables full-duplex, synchronous, serial communication between the chip and peripheral devices, including other chips. Software can poll the SPI status flags or SPI operation can be interrupt driven. The block contains six 16-bit memory mapped registers for control parameters, status, and data transfer.

The Table 5-59 shows module identifiers for SPI Driver.

Table 5-59. Identifiers for SPI Driver

Module identifier	56F82xxx	56F84xxx
SPI_0	✓	✓
SPI_1	✓	✓
SPI_2		✓

The Table 5-60 shows all commands dedicated for SPI Driver.

Table 5-60. SPI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SPI_CAN_READ_DATA	NULL	Return non-zero if valid data are waiting in receive FIFO.	✓	✓
SPI_CAN_WRITE_DATA	NULL	Return non-zero if free space in TX FIFO enables data write.	✓	✓
SPI_CLEAR_EXCEPTION	NULL	Clear read/write functions exception if it exists.	✓	✓
SPI_CLEAR_MODE_FAULT	NULL	Clear Status and Control Register MODF bit (Mode Fault bit).	✓	✓
SPI_DEVICE	SPI_ENABLE / SPI_DISABLE	Enable/disable SPI device.	✓	✓
SPI_DMA_RX	SPI_ENABLE / SPI_DISABLE	Enable SPI RX DMA.	✓	✓
SPI_DMA_TX	SPI_ENABLE / SPI_DISABLE	Enable SPI TX DMA.	✓	✓
SPI_ERROR_INT	SPI_ENABLE / SPI_DISABLE	Interrupt enable or disable for ERRIE.	✓	✓

Table 5-60. SPI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SPI_GET_ERROR	NULL	Test is any error is reported in the the Status and Control Register (test OVRF and MODF bits).	✓	✓
SPI_GET_MODE_FAULT	NULL	Test mode fault MODF bit.	✓	✓
SPI_GET_RX_FULL	NULL	Test receiver full SPRF bit.	✓	✓
SPI_GET_RX_OVERFLOW	NULL	Test overflow OVRF bit.	✓	✓
SPI_GET_STATUS	NULL	Get the status of read/write functions, returns UWord16.	✓	✓
SPI_GET_TX_EMPTY	NULL	Test the transmitter empty SPTE bit.	✓	✓
SPI_INIT	NULL	Initialization of the SPI periheral registers using appconfig.h _INIT values.	✓	✓
SPI_INT_DISABLE	SPI_TX_EMPTY | SPI_RX_FULL | SPI_ERROR	Disable the selected SPI interrupts.	✓	✓
SPI_INT_ENABLE	SPI_TX_EMPTY | SPI_RX_FULL | SPI_ERROR	Enable the selected SPI interrupts.	✓	✓
SPI_MULT_BAUD_DIV	SPI_MULT_DIV_1x / SPI_MULT_DIV_2x	Set multiplication factor of the baudrate divisor value.	✓	✓
SPI_OVERRIDE_SS_INPUT	SPI_ENABLE / SPI_DISABLE	Override the internal SS input with value of SPMSTR bit.	✓	✓
SPI_QUEUED_MODE	SPI_ENABLE / SPI_DISABLE	Enable SPI FIFOs.	✓	✓
SPI_READ_CANCEL	NULL	Cancel non-blocking read operation.	✓	✓
SPI_READ_CONTROL_REG	NULL	Read and return the value of SPI Control Register.	✓	✓
SPI_READ_DATA	NULL	Read SPI Data Receive Register. It contains previously received data.	✓	✓
SPI_RX_FULL_INT	SPI_ENABLE / SPI_DISABLE	Interrupt enable or disable for SPRIE.	✓	✓
SPI_SET_BAUD_DIV	SPI_DIVx(2/4/8/16/32/64/128 /256)	Set SPI baud rate (clock) divisor.	✓	✓

Table 5-60. SPI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SPI_SET_CLOCK_PHASE	SPI_SCLK_EDGE / SPI_SS_EDGE	Determine the condition which starts data shift out of SLAVE device. Transmission is started by first SCLK edge or falling edge on /SS pin (which edge starts slave transmission).	✓	✓
SPI_SET_CLOCK_POLARITY	SPI_RISING_EDGE / SPI_FALLING_EDGE	Set SPI clock edge which shifts out data - either falling edge or rising edge.	✓	✓
SPI_SET_MODE	SPI_MASTER / SPI_SLAVE	Set SPI to MASTER or SLAVE mode.	✓	✓
SPI_SET_MODE_FAULT	SPI_ENABLE / SPI_DISABLE	Configure SPI device to use mode fault detection logic or to disable mode fault checking (ena/dis mode fault).	✓	✓
SPI_SET_ORDER	SPI_LSB_FIRST / SPI_MSB_FIRST	Select SPI data shift bit ordering - MSB bit first or LSB bit.	✓	✓
SPI_SET_RXFULL_CONDITION	SPI_RXFULL_WHEN_xxx or value 0..3	Set how many words (plus 1) in RX FIFO causes the RXFULL condition.	✓	✓
SPI_SET_SS_MODE	one of SPI_SS_xxx (the two SPI_SS_AUTO_xxx may be combined)	Set the SS signal mode during SPI-Master operation.	✓	✓
SPI_SET_SS_OUTPUT	boolean	Set the SS pin value in SPI_SS_MANUAL_OUT mode.	✓	✓
SPI_SET_SS_WIRED_OR_MODE	SPI_OPEN_DRAIN/SPI_NORMAL	Set the SS pin mode.	✓	✓
SPI_SET_TX_DATA_SIZE	data size (2..16)	Set length of the data word in bits. Possible value is 2-16.	✓	✓
SPI_SET_TXEMPTY_CONDITION	SPI_TXEMPTY_WHEN_xxx or value 0..3	Set how many words in TX FIFO causes the TXEMPTY condition.	✓	✓
SPI_SET_WIRED_OR_MODE	SPI_NORMAL / SPI_OPEN_DRAIN	Set normal or wired-OR mode of the SPI pins.	✓	✓
SPI_STOP_MODE_HOLDOFF	SPI_ENABLE / SPI_DISABLE	Enable Stop Mode Holdoff.	✓	✓
SPI_TEST_SS_INPUT	NULL	Return immediate state of the SS input pin.	✓	✓
SPI_TX_EMPTY_INT	SPI_ENABLE / SPI_DISABLE	Interrupt enable or disable for SPTIE.	✓	✓

Table 5-60. SPI Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SPI_WRITE_CANCEL	NULL	Cancel non-blocking write operation.	✓	✓
SPI_WRITE_CONTROL_REG	UWord16	Write to SPI Control Register.	✓	✓
SPI_WRITE_DATA	UWord16	Write data to SPI Data Transmit Register. When in MASTER mode it initiates transmission.	✓	✓
SPI_WRITE_DATA_DELAY	UWord16 (0..0x1fff)	Set inter-word delay in the IPbus clocks.	✓	✓

5.1.28 System (SYS) Driver

This section describes the API for on-chip system support functions - system integration module, low voltage detection and external bus interface.

The Table 5-61 shows module identifiers for SYS Driver.

Table 5-61. Identifiers for SYS Driver

Module identifier	56F82xxx	56F84xxx
SYS | SIM	✓	✓

The Table 5-62 shows all commands dedicated for SYS Driver.

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_ADC_REORDERING	SYS_ENABLE/SYS_DISABLE	Enable the re-ordering of scan control bits of Cyclic ADC for test channels..		✓
SYS_CLEAR_RESET_SOURCE	any of SYS_xxx_RESET (SW/COP/COP_TOR/COP_LOR/EXTERN/POWER_ON/ANY/EZPORT/COP_WINDOW)	Acknowledge reset sources and clear selected bits in the Reset Staus Register.	✓	✓
SYS_CLKODIV_SELECT	one of SYS_xxx (DIV1/DIV2/DIV4/DIV8/DIV16/DIV32/DIV128)	Select CLKOUT divide factor.	✓	✓
SYS_CLKOUT	SYS_ENABLE/SYS_DISABLE	Enable/disable CLKOUT pin.	✓	✓
SYS_CLKOUT_1	SYS_ENABLE/SYS_DISABLE	Enable/disable CLKOUT1 pin.	✓	✓
SYS_CLKOUT_1_SELECT	one of SYS_CLKOUT_1_xxx (BUSCLK/2X_BUSCLK/DIV4_BUSCLK/MSTR_OSC/ROSC_8M/ROSC_200K)	Select CLSKOUT_1 source.		✓
SYS_CLKOUT_1_SELECT	one of SYS_CLKOUT_1_xxx (BUSCLK/2X_BUSCLK/DIV4_BUSCLK/MSTR_OSC/ROSC_8M/ROSC_32K)	Select CLSKOUT_1 source.	✓	

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_CLKOUT_SELECT	one of SYS_CLKOUT_xxx (SYSCLK/IPB-CLK/HSCLK/MSTRCLK)	Select CLSKOUT source.	✓	✓
SYS_DISABLE_IN_STOP_REG2	combination of SYS_xxx_MOD2	Disable modules in STOP mode.	✓	✓
SYS_DMA_ENABLE	DMAEBL_RUN_MODE/DMAEBL_RUN_WAIT_MODES/DMAEBL_ALL_MODES/DMAEBL_DISABLE_AND_WP/DMAEBL_RUN_MODE_AND_WP/DMAEBL_RUN_WAIT_MODES_AND_WP/DMAEBL_ALL_MODES_AND_WP	Selelct if DMA is enabled in RUN, WAIT, RUN and WAIT, or all modes. If the WP (Write protected) command is used, seting canot be changed until the next reset.	✓	✓
SYS_ENABLE_IN_STOP_REG2	combination of SYS_xxx_MOD2	Enable modules in STOP mode.	✓	✓
SYS_FAST_MODE	SYS_ENABLE/SYS_DISABLE	Decide if the system will boot in fast mode(core:bus :: 2:1) or normal mode..		✓
SYS_GET_12_POWER_MODE	NULL	Return Regulator Control as UWord16 value.	✓	✓
SYS_GET_27_POWER_MODE	NULL	Return Regulator Control as UWord16 value.	✓	✓
SYS_GET_27_POWERDOWN	NULL	Return Regulator Control as UWord16 value.	✓	✓
SYS_GET_FAST_MODE	NULL	Return UWord16 TRUE-Fast mode, False-Normal mode.		✓
SYS_GET_LOW_POWER_MODE	NULL	Return non-zero if device is in LPMODE mode.	✓	✓
SYS_GET_LOW_POWER_MODE	NULL	Return non-zero if device is in VLP-MODE mode.	✓	✓
SYS_GET_POWER_MODE	NULL	Get current power mode. Returned UWord16 value can be tested for presence of the SYS_REDUCED_POWER and SYS_POWER_MODE_PERMANENT flags.	✓	✓
SYS_HS_CLOCK_DISABLE	combination of SYS_HS_xxx (IIC/PWM/TMR/SCI0/SCI1)	Enable high-speed clock.		✓

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_HS_CLOCK_DISABLE	combination of SYS_HS_xxx (SCI0/SCI1)	Enable high-speed clock.	✓	
SYS_HS_CLOCK_ENABLE	combination of SYS_HS_xxx (IIC/PWM/TMR/SCI0/SCI1)	Enable high-speed clock.		✓
SYS_HS_CLOCK_ENABLE	combination of SYS_HS_xxx (SCI0/SCI1)	Enable high-speed clock.	✓	
SYS_INIT	NULL	Initialize SIM and LVI periheral registers using the appconfig.h _INIT values.	✓	✓
SYS_ONCE	SYS_ENABLE/SYS_DISABLE	OnCE module enable.	✓	✓
SYS_PERIPH_CLK_DISABLE	combination of SYS_xxx_MOD	Disable peripheral clock.	✓	✓
SYS_PERIPH_CLK_ENABLE	combination of SYS_xxx_MOD	Enable peripheral clock.	✓	✓
SYS_PERIPH_CLK_REG2_DISABLE	combination of SYS_xxx_MOD2	Disable peripheral clock.	✓	✓
SYS_PERIPH_CLK_REG2_ENABLE	combination of SYS_xxx_MOD2	Enable peripheral clock.	✓	✓
SYS_PERIPH_SW_RESET	combination of SYS_xxx_PSWR (GPIO;TA;MSCAN;IIC0;QSPI1;QSPI0;SCI1;SCI0;DACA;DACB;PIT1;PIT0;CRC;CYCADC;CMP;EWM;PWMA)	Issue software reset of peripheral.		✓
SYS_PERIPH_SW_RESET	combination of SYS_xxx_PSWR (GPIO;TB;TA;FLEXCAN;IIC1;IIC0;QSPI1;QSPI0;SCI1;SCI0;DAC;PDB1;PDB0;PIT1;PIT0;QDC;CRC;CYCADC;SARADC;CMP;EWM;PWMA)	Issue software reset of peripheral.	✓	
SYS_READ_IO_SHORT_ADDR_LOCATION_REG	NULL	Get I/O short address mode base address as UWord32.	✓	✓
SYS_READ_LSH_JTAG_ID	NULL	Return JTAG ID as UWord16.	✓	✓
SYS_READ_MSH_JTAG_ID	NULL	Return JTAG ID as UWord16.	✓	✓

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_READ_SW_CONTROL_REG0	NULL	Read and return SIM software control register 0 as UWord16.	✓	✓
SYS_READ_SW_CONTROL_REG1	NULL	Read and return SIM software control register 1 as UWord16.	✓	✓
SYS_READ_SW_CONTROL_REG2	NULL	Read and return SIM software control register 2 as UWord16.	✓	✓
SYS_READ_SW_CONTROL_REG3	NULL	Read and return SIM software control register 3 as UWord16.	✓	✓
SYS_READ_SW_CONTROL_REG4	NULL	Read and return SIM software control register 4 as UWord16.		✓
SYS_READ_SW_CONTROL_REG5	NULL	Read and return SIM software control register 5 as UWord16.		✓
SYS_READ_SW_CONTROL_REG6	NULL	Read and return SIM software control register 6 as UWord16.		✓
SYS_READ_SW_CONTROL_REG7	NULL	Read and return SIM software control register 7 as UWord16.		✓
SYS_RST_FLT	SYS_ENABLE/SYS_DISABLE	External Reset Padcell Input Filter Enable.	✓	✓
SYS_SELECT_CLKIN	SYS_CLKIN0/SYS_CLKIN1	Determine the GPIO port used for the CLKIN input to the OCCS, CLKIN0 -(GPIOC0 alt1) , CLKIN1 -(GPIOC3 alt3).	✓	✓
SYS_SELECT_MASTER_PIT	SYS_PIT1/SYS_PIT0	Select Master Programmable Interval Timer.	✓	✓
SYS_SET_12_POWER_MODE	SYS_NORMAL_POWER/SYS_REDUCED_POWER | SYS_POWER_MODE_PERMANENT	Set Small Regulator 1.2 V Supply Powerdown Control.	✓	✓
SYS_SET_27_POWER_MODE	SYS_NORMAL_POWER/SYS_REDUCED_POWER | SYS_POWER_MODE_PERMANENT	Set Small Regulator 2.7 V Supply Standby Control.	✓	✓
SYS_SET_27_POWERDOWN	SYS_NORMAL_POWER/SYS_POWERDOWN_MODE | SYS_POWER_MODE_PERMANENT	Set Small Regulator 2.7 V Supply Standby Control.	✓	✓

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_SET_A0PAD_FUNCTION	one of SYS_A0PAD_xxx (ANA0_CMPA3/CMPC_O)	Package pin function selection.	✓	
SYS_SET_A0PAD_FUNCTION	one of SYS_A0PAD_xxx (ANA0_CMPA3/CMPC_O)	Package pin function selection.		✓
SYS_SET_B10PAD_FUNCTION	one of SYS_B10PAD_xxx (ANC14/XB_IN8)	Package pin function selection.	✓	
SYS_SET_B11PAD_FUNCTION	one of SYS_B11PAD_xxx (ANC15/XB_IN7)	Package pin function selection.	✓	
SYS_SET_B1PAD_FUNCTION	one of SYS__B1PAD_xxx (ANB1_CMPB_IN0/DACB)	Package pin function selection.		✓
SYS_SET_B9PAD_FUNCTION	one of SYS_B9PAD_xxx (ANC13/PADXB_IN9)	Package pin function selection.	✓	
SYS_SET_C0PAD_FUNCTION	one of SYS_C0PAD_xxx (EXTAL/CLKIN)	Package pin function selection.	✓	
SYS_SET_C0PAD_FUNCTION	one of SYS_C0PAD_xxx (EXTAL/CLKIN)	Package pin function selection.		✓
SYS_SET_C10PAD_FUNCTION	one of SYS_C10PAD_xxx (MASK/MOSI0/XB_IN5/MISO0)	Package pin function selection.	✓	
SYS_SET_C10PAD_FUNCTION	one of SYS_C10PAD_xxx (XB_OUT9/MOSI0/XB_IN5/MISO0)	Package pin function selection.		✓
SYS_SET_C11PAD_FUNCTION	one of SYS_C11PAD_xxx (SCL1/TXD1/CANTX)	Package pin function selection.	✓	
SYS_SET_C11PAD_FUNCTION	one of SYS_C11PAD_xxx (TXD1/SCL0)	Package pin function selection.		✓
SYS_SET_C12PAD_FUNCTION	one of SYS_C12PAD_xxx (CANRX/SDA1/RXD1)	Package pin function selection.	✓	
SYS_SET_C12PAD_FUNCTION	one of SYS_C12PAD_xxx (SDA0/RXD1)	Package pin function selection.		✓
SYS_SET_C13PAD_FUNCTION	one of SYS_C13PAD_xxx (TA3/XB_IN6)	Package pin function selection.		✓
SYS_SET_C13PAD_FUNCTION	one of SYS_C13PAD_xxx (TA3/XB_IN6/EWM_OUTB)	Package pin function selection.	✓	

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_SET_C14PAD_FUNCTION	one of SYS_C14PAD_xxx (SDA0/XB_OUT4)	Package pin function selection.	✓	
SYS_SET_C14PAD_FUNCTION	one of SYS_C14PAD_xxx (SDA0/XB_OUT4/PWM_FAULT4)	Package pin function selection.		✓
SYS_SET_C15PAD_FUNCTION	one of SYS_C15PAD_xxx (SCL0/XB_OUT5)	Package pin function selection.		✓
SYS_SET_C15PAD_FUNCTION	one of SYS_C15PAD_xxx (XB_OUT5/PWM_SCL0)	Package pin function selection.	✓	
SYS_SET_C2PAD_FUNCTION	one of SYS_C2PAD_xxx (TXD0/TB0/XB_IN2/CLKOUT0)	Package pin function selection.	✓	
SYS_SET_C2PAD_FUNCTION	one of SYS_C2PAD_xxx (TXD0/XB_OUT11/XB_IN2/CLKOUT0)	Package pin function selection.		✓
SYS_SET_C3PAD_FUNCTION	one of SYS_C3PAD_xxx (TA0/CMPA_O/RXD0/CLKIN1)	Package pin function selection.	✓	
SYS_SET_C3PAD_FUNCTION	one of SYS_C3PAD_xxx (TA0/CMPA_O/RXD0/CLKIN1)	Package pin function selection.		✓
SYS_SET_C4PAD_FUNCTION	one of SYS_C4PAD_xxx (TA1/CMPB_O/XB_IN6/EWM_OUT_B)	Package pin function selection.		✓
SYS_SET_C4PAD_FUNCTION	one of SYS_C4PAD_xxx (TA1/CMPB_O/XB_IN8/EWM_OUT_B)	Package pin function selection.	✓	
SYS_SET_C5PAD_FUNCTION	one of SYS_C5PAD_xxx (DAC0/XB_IN7)	Package pin function selection.	✓	
SYS_SET_C5PAD_FUNCTION	one of SYS_C5PAD_xxx (DACA/XB_IN7)	Package pin function selection.		✓
SYS_SET_C6PAD_FUNCTION	one of SYS_C6PAD_xxx (TA2/XB_IN3/CMPREF)	Package pin function selection.	✓	
SYS_SET_C6PAD_FUNCTION	one of SYS_C6PAD_xxx (TA2/XB_IN3/CMPREF/SS0_B)	Package pin function selection.		✓

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_SET_C7PAD_FUNCTION	one of SYS_C7PAD_xxx (SSB0_B/TXD0)	Package pin function selection.	✓	
SYS_SET_C7PAD_FUNCTION	one of SYS_C7PAD_xxx (SSB0_B/TXD0/XB_IN8)	Package pin function selection.		✓
SYS_SET_C8PAD_FUNCTION	one of SYS_C8PAD_xxx (MISO0/RXD0/XB_IN9)	Package pin function selection.	✓	
SYS_SET_C8PAD_FUNCTION	one of SYS_C8PAD_xxx (XB_OUT6/RXD0/MISO0/XB_IN9)	Package pin function selection.		✓
SYS_SET_C9PAD_FUNCTION	one of SYS_C9PAD_xxx (SCLK0/XB_IN4/XB_OUT8/TXD0)	Package pin function selection.		✓
SYS_SET_C9PAD_FUNCTION	one of SYS_C9PAD_xxx (XB_IN4/SCLK0)	Package pin function selection.	✓	
SYS_SET_D5PAD_FUNCTION	one of SYS_D5PAD_xxx (MASK/XB_IN5/XB_OUT9)	Package pin function selection.	✓	
SYS_SET_D6PAD_FUNCTION	one of SYS_D6PAD_xxx (TXD2/XB_IN4/XB_OUT8)	Package pin function selection.	✓	
SYS_SET_D7PAD_FUNCTION	one of SYS_D7PAD_xxx (XB_OUT11/XB_IN_7/XB_MISO1)	Package pin function selection.	✓	
SYS_SET_E4PAD_FUNCTION	one of SYS_E4PAD_xxx (PWMB2/XB_IN2)	Package pin function selection.		✓
SYS_SET_E4PAD_FUNCTION	one of SYS_E4PAD_xxx (PWMB2B/XB_IN2)	Package pin function selection.	✓	
SYS_SET_E5PAD_FUNCTION	one of SYS_E5PAD_xxx (PWMA2/XB_IN3)	Package pin function selection.		✓
SYS_SET_E5PAD_FUNCTION	one of SYS_E5PAD_xxx (PWMA2A/XB_IN3)	Package pin function selection.	✓	
SYS_SET_E6PAD_FUNCTION	one of SYS_E6PAD_xxx (PWMB3/XB_IN4)	Package pin function selection.		✓
SYS_SET_E6PAD_FUNCTION	one of SYS_E6PAD_xxx (PWMB3B/XB_IN4)	Package pin function selection.	✓	
SYS_SET_E7PAD_FUNCTION	one of SYS_E7PAD_xxx (PWMA3/XB_IN5)	Package pin function selection.		✓

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_SET_E7PAD_FUNCTION	one of SYS_E7PAD_xxx (PWMA3A/XB_IN5)	Package pin function selection.	✓	
SYS_SET_E8PAD_FUNCTION	one of SYS_E8PAD_xxx (PWMA_FAULT0)	Package pin function selection.	✓	
SYS_SET_E9PAD_FUNCTION	one of SYS_E9PAD_xxx (PWMA_FAULT1)	Package pin function selection.	✓	
SYS_SET_F0PAD_FUNCTION	one of SYS_F0PAD_xxx (SCLK1/XB_IN6)	Package pin function selection.		✓
SYS_SET_F0PAD_FUNCTION	one of SYS_F0PAD_xxx (XB_IN6/TB2/SCLK1)	Package pin function selection.	✓	
SYS_SET_F10PAD_FUNCTION	one of SYS_F10PAD_xxx (PWMA_FAULT6/XB_OUT10)	Package pin function selection.	✓	
SYS_SET_F11PAD_FUNCTION	one of SYS_F11PAD_xxx (TXD0/XB_IN11)	Package pin function selection.	✓	
SYS_SET_F12PAD_FUNCTION	one of SYS_F12PAD_xxx (MISO1)	Package pin function selection.	✓	
SYS_SET_F13PAD_FUNCTION	one of SYS_F13PAD_xxx (MOSI1)	Package pin function selection.	✓	
SYS_SET_F14PAD_FUNCTION	one of SYS_F14PAD_xxx (SCLK1)	Package pin function selection.	✓	
SYS_SET_F15PAD_FUNCTION	one of SYS_F15PAD_xxx (RXD0/XB_IN10)	Package pin function selection.	✓	
SYS_SET_F1PAD_FUNCTION	one of SYS_F1PAD_xxx (CLKOUT1 /XB_IN7 /CMPD_O)	Package pin function selection.	✓	
SYS_SET_F1PAD_FUNCTION	one of SYS_F1PAD_xxx (CLKOUT1/XB_IN7/CMPD_O)	Package pin function selection.		✓
SYS_SET_F2PAD_FUNCTION	one of SYS_F2PAD_xxx (SCL0/XB_OUT6/MISO1)	Package pin function selection.		✓
SYS_SET_F2PAD_FUNCTION	one of SYS_F2PAD_xxx (SCL1/XB_OUT6)	Package pin function selection.	✓	
SYS_SET_F3PAD_FUNCTION	one of SYS_F3PAD_xxx (SDA0/XB_OUT7/MOSI1)	Package pin function selection.		✓

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_SET_F3PAD_FUNCTION	one of SYS_F3PAD_xxx (SDA1/XB_OUT7)	Package pin function selection.	✓	
SYS_SET_F4PAD_FUNCTION	one of SYS_F4PAD_xxx (TXD1/XB_OUT8)	Package pin function selection.	✓	
SYS_SET_F4PAD_FUNCTION	one of SYS_F4PAD_xxx (XB_OUT8/TXD1/PWMA_0X /PWMA_FAULT6)	Package pin function selection.		✓
SYS_SET_F5PAD_FUNCTION	one of SYS_F5PAD_xxx (RXD1/XB_OUT9)	Package pin function selection.	✓	
SYS_SET_F5PAD_FUNCTION	one of SYS_F5PAD_xxx (RXD1/XB_OUT9/PWMA_1X /PWMA_FAULT7)	Package pin function selection.		✓
SYS_SET_F6PAD_FUNCTION	one of SYS_F6PAD_xxx (TB2/PWMA_3X/XB_IN2)	Package pin function selection.	✓	
SYS_SET_F6PAD_FUNCTION	one of SYS_F6PAD_xxx (XB_IN2/PWMA_3X)	Package pin function selection.		✓
SYS_SET_F7PAD_FUNCTION	one of SYS_F7PAD_xxx (CMPC_0/SS1_B/XB_IN3/TB 3)	Package pin function selection.	✓	
SYS_SET_F7PAD_FUNCTION	one of SYS_F7PAD_xxx (XB_IN3/CMPC_O/SS1_B)	Package pin function selection.		✓
SYS_SET_F8PAD_FUNCTION	one of SYS_F8PAD_xxx (RXD0/TB1/CMPD_O)	Package pin function selection.	✓	
SYS_SET_F8PAD_FUNCTION	one of SYS_F8PAD_xxx (RXD0/XB_OUT10/CMPDO/ PWMA_2X)	Package pin function selection.		✓
SYS_SET_F9PAD_FUNCTION	one of SYS_F9PAD_xxx (FAULT7/XB_OUT11)	Package pin function selection.	✓	
SYS_SET_G0PAD_FUNCTION	one of SYS_G0PAD_xxx (XB_OUT6)	Package pin function selection.	✓	
SYS_SET_G10PAD_FUNCTION	one of SYS_G10PAD_xxx (PWMA_2X/XB_IN8)	Package pin function selection.	✓	
SYS_SET_G11PAD_FUNCTION	one of SYS_G11PAD_xxx (TB3/CLKOUT0/MOSI1)	Package pin function selection.	✓	
SYS_SET_G1PAD_FUNCTION	one of SYS_G1PAD_xxx (XB_OUT7)	Package pin function selection.	✓	

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_SET_G2PAD_FUNCTION	one of SYS_G2PAD_xxx (XB_OUT4)	Package pin function selection.	✓	
SYS_SET_G3PAD_FUNCTION	one of SYS_G3PAD_xxx (XB_OUT5)	Package pin function selection.	✓	
SYS_SET_G4PAD_FUNCTION	one of SYS_G4PAD_xxx (PWMA_FAULT2)	Package pin function selection.	✓	
SYS_SET_G5PAD_FUNCTION	one of SYS_G5PAD_xxx (PWMA_FAULT3)	Package pin function selection.	✓	
SYS_SET_G6PAD_FUNCTION	one of SYS_G6PAD_xxx (PWMA_FAULT4/TB2/XB_OUT8)	Package pin function selection.	✓	
SYS_SET_G7PAD_FUNCTION	one of SYS_G7PAD_xxx (PWMA_FAULT5/XB_OUT9)	Package pin function selection.	✓	
SYS_SET_G8PAD_FUNCTION	one of SYS_G8PAD_xxx (PWMA_0X/TA2/XB_OUT10)	Package pin function selection.	✓	
SYS_SET_G9PAD_FUNCTION	one of SYS_G9PAD_xxx (PWMA_1X/TA3/XB_OUT11)	Package pin function selection.	✓	
SYS_SET_LOW_POWER_MODE	SYS_ENABLE/SYS_DISABLE	Cause the device to enter/exit LPMODE.	✓	✓
SYS_SET_POWER_MODE	SYS_NORMAL_POWER/SYS_REDUCED_POWER | SYS_POWER_MODE_PERMANENT	Control the operation mode of the device.	✓	✓
SYS_SET_PWMAF0_INPUT	one of SYS_PWMAF0_xxx (GPIO_E8/XB_OUT29)	SCI0 input selection.	✓	
SYS_SET_PWMAF1_INPUT	one of SYS_PWMAF1_xxx (GPIO_E9/XB_OUT30)	SCI0 input selection.	✓	
SYS_SET_PWMAF2_INPUT	one of SYS_PWMAF2_xxx (GPIO_G4/XB_OUT31)	SCI0 input selection.	✓	
SYS_SET_PWMAF3_INPUT	one of SYS_PWMAF3_xxx (GPIO_G5/XB_OUT32)	SCI0 input selection.	✓	
SYS_SET_SCI0_INPUT	one of SYS_SCI0_xxx (GPIOC3/XB_OUT38)	SCI0 input selection.		✓
SYS_SET_SCI1_INPUT	one of SYS_SCI1_xxx (GPIOC12/XB_OUT39)	SCI1 input selection.		✓

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_SET_TMRA0_INPUT	one of SYS_TMRA0_xxx (GPIO_C3/XB_OUT49)	TMRB0 input selection.	✓	
SYS_SET_TMRA0_INPUT	one of SYS_TMRA0_xxx (GPIOC3/XB_OUT34)	TMRA0 input selection.		✓
SYS_SET_TMRA1_INPUT	one of SYS_TMRA1_xxx (GPIO_C4/XB_OUT50)	TMRB1 input selection.	✓	
SYS_SET_TMRA1_INPUT	one of SYS_TMRA1_xxx (GPIOC4/XB_OUT35)	TMRA1 input selection.		✓
SYS_SET_TMRA2_INPUT	one of SYS_TMRA2_xxx (GPIO_C6_G8/TMRA2_XB_OUT51)	TMRB2 input selection.	✓	
SYS_SET_TMRA2_INPUT	one of SYS_TMRA2_xxx (GPIOC6/XB_OUT36)	TMRA2 input selection.		✓
SYS_SET_TMRA3_INPUT	one of SYS_TMRA3_xxx (GPIO_C13_G9/XB_OUT52)	TMRB3 input selection.	✓	
SYS_SET_TMRA3_INPUT	one of SYS_TMRA3_xxx (GPIOC13/XB_OUT37)	TMRA3 input selection.		✓
SYS_SET_TMRB0_INPUT	one of SYS_TMRB0_xxx (GPIO_C2/XB_OUT34)	TMRB0 input selection.	✓	
SYS_SET_TMRB1_INPUT	one of SYS_TMRB1_xxx (GPIO_F8/XB_OUT35)	TMRB1 input selection.	✓	
SYS_SET_TMRB2_INPUT	one of SYS_TMRB2_xxx (GPIO_F6_F0_G6/XB_OUT36)	TMRB2 input selection.	✓	
SYS_SET_TMRB3_INPUT	one of SYS_TMRB3_xxx (GPIO_F7_G11/XB_OUT37)	TMRB3 input selection.	✓	
SYS_SET_VERY_LOW_POWER_MODE	SYS_ENABLE/SYS_DISABLE	Causes the device to enter/exit VLP-MODE.	✓	✓
SYS_SOFTWARE_RESET	NULL	Issue software reset.	✓	✓
SYS_STOP	SYS_ENABLE(_PERMANENT)/SYS_DISABLE(_PERMANENT)	Enable/disable the STOP instruction.	✓	✓

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_TEST_RESET_SOURCE	any of SYS_xxx_RESET (SW/COP/COP_TOR/COP_LOR/EXTERN/POWER_ON/ANY/EZPORT/COP_WINDOW)	Get and test source of the previous RESET.	✓	✓
SYS_WAIT	SYS_ENABLE(_PERMANENT)/SYS_DISABLE(_PERMANENT)	Enable/disable the WAIT instruction.	✓	✓
SYS_WPROTECT_CLOCK_SETTINGS	SYS_ENABLE(_PERMANENT)/SYS_DISABLE(_PERMANENT)	Write protect PCE, SD and PCR.	✓	✓
SYS_WPROTECT_GPIOD	SYS_ENABLE(_PERMANENT)/SYS_DISABLE(_PERMANENT)	Write protect GPIO_D_PER, GPIO_D_PPMODE, and GPIO_D_DRIVE.	✓	✓
SYS_WPROTECT_POWER_MODE	SYS_ENABLE(_PERMANENT)/SYS_DISABLE(_PERMANENT)	Write protect Power Mode Control.	✓	✓
SYS_WPROTECT_SIGNALS_ROUTING	SYS_ENABLE(_PERMANENT)/SYS_DISABLE(_PERMANENT)	Write protect GPSx, XBAR, GPIO_X_PER, GPIO_X_PPMODE, GPIO_X_DRIVE and GIO_X_IFE registers}.	✓	✓
SYS_WRITE_IO_SHORT_ADDR_LOCATION_REG	UWord32	Set I/O short address mode base address.	✓	✓
SYS_WRITE_SW_CONTROL_REG0	UWord16	Write SIM software control register 0.	✓	✓
SYS_WRITE_SW_CONTROL_REG1	UWord16	Write SIM software control register 1.	✓	✓
SYS_WRITE_SW_CONTROL_REG2	UWord16	Write SIM software control register 2.	✓	✓
SYS_WRITE_SW_CONTROL_REG3	UWord16	Write SIM software control register 3.	✓	✓
SYS_WRITE_SW_CONTROL_REG4	UWord16	Write SIM software control register 4.		✓
SYS_WRITE_SW_CONTROL_REG5	UWord16	Write SIM software control register 5.		✓
SYS_WRITE_SW_CONTROL_REG6	UWord16	Write SIM software control register 6.		✓

Table 5-62. SYS Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
SYS_WRITE_SW_CONTROL_REG 7	UWord16	Write SIM software control register 7.		✓

5.1.29 Inter-Peripheral Crossbar Switch (XBAR) Driver

This module implements an array of M N-input combinational muxes. All muxes share the same N inputs in the same order, but each mux has its own independent select field. The intended application of this module is to provide a flexible crossbar switch function that allows any input (typically from external GPIO or internal module outputs) to be connected to any output (typically to external GPIO or internal module inputs) under user control. This is used to allow user configuration of data paths between internal modules and between internal modules and GPIO.

The Table 5-63 shows module identifiers for XBAR Driver.

Table 5-63. Identifiers for XBAR Driver

Module identifier	56F82xxx	56F84xxx
XBAR_A	✓	✓
XBAR_B	✓	✓

The Table 5-64 shows all commands dedicated for XBAR Driver.

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_A_INIT	NULL	Initialize XBAR_A periheral registers using the appconfig.h _INIT values.	✓	✓
XBAR_A_READ_CROSSBAR_CTRL_0	NULL	Read and return the value of the Crossbar A Control Register 0.	✓	✓
XBAR_A_READ_CROSSBAR_CTRL_1	NULL	Read and return the value of the Crossbar A Control Register 1.	✓	✓
XBAR_A_READ_CROSSBAR_REG_0	NULL	Read and return the value of the Crossbar A Select Register 0.	✓	✓
XBAR_A_READ_CROSSBAR_REG_1	NULL	Read and return the value of the Crossbar A Select Register 1.	✓	✓
XBAR_A_READ_CROSSBAR_REG_10	NULL	Read and return the value of the Crossbar A Select Register 10.	✓	✓
XBAR_A_READ_CROSSBAR_REG_11	NULL	Read and return the value of the Crossbar A Select Register 11.	✓	✓
XBAR_A_READ_CROSSBAR_REG_12	NULL	Read and return the value of the Crossbar A Select Register 12.	✓	✓
XBAR_A_READ_CROSSBAR_REG_13	NULL	Read and return the value of the Crossbar A Select Register 13.	✓	✓

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_A_READ_CROSSBAR_REG_14	NULL	Read and return the value of the Crossbar A Select Register 14.	✓	✓
XBAR_A_READ_CROSSBAR_REG_15	NULL	Read and return the value of the Crossbar A Select Register 15.	✓	✓
XBAR_A_READ_CROSSBAR_REG_16	NULL	Read and return the value of the Crossbar A Select Register 16.	✓	✓
XBAR_A_READ_CROSSBAR_REG_17	NULL	Read and return the value of the Crossbar A Select Register 17.	✓	✓
XBAR_A_READ_CROSSBAR_REG_18	NULL	Read and return the value of the Crossbar A Select Register 18.	✓	✓
XBAR_A_READ_CROSSBAR_REG_19	NULL	Read and return the value of the Crossbar A Select Register 19.	✓	✓
XBAR_A_READ_CROSSBAR_REG_2	NULL	Read and return the value of the Crossbar A Select Register 2.	✓	✓
XBAR_A_READ_CROSSBAR_REG_20	NULL	Read and return the value of the Crossbar A Select Register 20.	✓	✓
XBAR_A_READ_CROSSBAR_REG_21	NULL	Read and return the value of the Crossbar A Select Register 21.		✓
XBAR_A_READ_CROSSBAR_REG_22	NULL	Read and return the value of the Crossbar A Select Register 22.		✓
XBAR_A_READ_CROSSBAR_REG_23	NULL	Read and return the value of the Crossbar A Select Register 23.		✓
XBAR_A_READ_CROSSBAR_REG_24	NULL	Read and return the value of the Crossbar A Select Register 24.		✓
XBAR_A_READ_CROSSBAR_REG_25	NULL	Read and return the value of the Crossbar A Select Register 25.		✓
XBAR_A_READ_CROSSBAR_REG_26	NULL	Read and return the value of the Crossbar A Select Register 26.		✓
XBAR_A_READ_CROSSBAR_REG_27	NULL	Read and return the value of the Crossbar A Select Register 27.		✓
XBAR_A_READ_CROSSBAR_REG_28	NULL	Read and return the value of the Crossbar A Select Register 28.		✓
XBAR_A_READ_CROSSBAR_REG_29	NULL	Read and return the value of the Crossbar A Select Register 29.		✓

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_A_READ_CROSSBAR_REG_3	NULL	Read and return the value of the Crossbar A Select Register 3.	✓	✓
XBAR_A_READ_CROSSBAR_REG_4	NULL	Read and return the value of the Crossbar A Select Register 4.	✓	✓
XBAR_A_READ_CROSSBAR_REG_5	NULL	Read and return the value of the Crossbar A Select Register 5.	✓	✓
XBAR_A_READ_CROSSBAR_REG_6	NULL	Read and return the value of the Crossbar A Select Register 6.	✓	✓
XBAR_A_READ_CROSSBAR_REG_7	NULL	Read and return the value of the Crossbar A Select Register 7.	✓	✓
XBAR_A_READ_CROSSBAR_REG_8	NULL	Read and return the value of the Crossbar A Select Register 8.	✓	✓
XBAR_A_READ_CROSSBAR_REG_9	NULL	Read and return the value of the Crossbar A Select Register 9.	✓	✓
XBAR_A_SET_OUT_ADCA_TRIGGER	XBAR_A_INPUT_xxx	Set XBAR_A_OUT12 input.		✓
XBAR_A_SET_OUT_ADCA_TRIGGER	XBAR_A_INPUT_xxx	Set XBAR_A_OUT12 input.	✓	
XBAR_A_SET_OUT_ADCB_TRIGGER	XBAR_A_INPUT_xxx	Set XBAR_A_OUT13 input.		✓
XBAR_A_SET_OUT_ADCB_TRIGGER	XBAR_A_INPUT_xxx	Set XBAR_A_OUT13 input.	✓	
XBAR_A_SET_OUT_ADCC_TRIGGER	XBAR_A_INPUT_xxx	Set XBAR_A_OUT14 input.		✓
XBAR_A_SET_OUT_CMPA_SAMPLE	XBAR_A_INPUT_xxx	Set XBAR_A_OUT16 input.		✓
XBAR_A_SET_OUT_CMPA_SAMPLE	XBAR_A_INPUT_xxx	Set XBAR_A_OUT16 input.	✓	
XBAR_A_SET_OUT_CMPB_SAMPLE	XBAR_A_INPUT_xxx	Set XBAR_A_OUT17 input.		✓
XBAR_A_SET_OUT_CMPB_SAMPLE	XBAR_A_INPUT_xxx	Set XBAR_A_OUT17 input.	✓	
XBAR_A_SET_OUT_CMPC_SAMPLE	XBAR_A_INPUT_xxx	Set XBAR_A_OUT18 input.		✓

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_A_SET_OUT_CMPC_SAMPLE	XBAR_A_INPUT_xxx	Set XBAR_A_OUT18 input.	✓	
XBAR_A_SET_OUT_CMPD_SAMPLE	XBAR_A_INPUT_xxx	Set XBAR_A_OUT19 input.		✓
XBAR_A_SET_OUT_CMPD_SAMPLE	XBAR_A_INPUT_xxx	Set XBAR_A_OUT19 input.	✓	
XBAR_A_SET_OUT_DAC_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT15 input.		✓
XBAR_A_SET_OUT_DACA_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT15 input.	✓	
XBAR_A_SET_OUT_DACB_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT14 input.	✓	
XBAR_A_SET_OUT_DMA_REQ0	XBAR_A_INPUT_xxx	Set XBAR_A_OUT0 input.		✓
XBAR_A_SET_OUT_DMA_REQ0	XBAR_A_INPUT_xxx	Set XBAR_A_OUT0 input.	✓	
XBAR_A_SET_OUT_DMA_REQ1	XBAR_A_INPUT_xxx	Set XBAR_A_OUT1 input.		✓
XBAR_A_SET_OUT_DMA_REQ1	XBAR_A_INPUT_xxx	Set XBAR_A_OUT1 input.	✓	
XBAR_A_SET_OUT_DMA_REQ2	XBAR_A_INPUT_xxx	Set XBAR_A_OUT2 input.		✓
XBAR_A_SET_OUT_DMA_REQ2	XBAR_A_INPUT_xxx	Set XBAR_A_OUT2 input.	✓	
XBAR_A_SET_OUT_DMA_REQ3	XBAR_A_INPUT_xxx	Set XBAR_A_OUT3 input.		✓
XBAR_A_SET_OUT_DMA_REQ3	XBAR_A_INPUT_xxx	Set XBAR_A_OUT3 input.	✓	
XBAR_A_SET_OUT_EWM_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT58 input.		✓
XBAR_A_SET_OUT_EWM_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT40 input.	✓	
XBAR_A_SET_OUT_GPIO_C_14	XBAR_A_INPUT_xxx	Set XBAR_A_OUT4 input.		✓
XBAR_A_SET_OUT_GPIO_C_14	XBAR_A_INPUT_xxx	Set XBAR_A_OUT4 input.	✓	
XBAR_A_SET_OUT_GPIO_C_15	XBAR_A_INPUT_xxx	Set XBAR_A_OUT5 input.		✓
XBAR_A_SET_OUT_GPIO_C_15	XBAR_A_INPUT_xxx	Set XBAR_A_OUT5 input.	✓	
XBAR_A_SET_OUT_GPIO_C_2	XBAR_A_INPUT_xxx	Set XBAR_A_OUT11 input.	✓	

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_A_SET_OUT_GPIO_C10_F5	XBAR_A_INPUT_xxx	Set XBAR_A_OUT9 input.	✓	
XBAR_A_SET_OUT_GPIO_C8_F2	XBAR_A_INPUT_xxx	Set XBAR_A_OUT6 input.	✓	
XBAR_A_SET_OUT_GPIO_C9_F4	XBAR_A_INPUT_xxx	Set XBAR_A_OUT8 input.	✓	
XBAR_A_SET_OUT_GPIO_F_10	XBAR_A_INPUT_xxx	Set XBAR_A_OUT10 input.		✓
XBAR_A_SET_OUT_GPIO_F_2	XBAR_A_INPUT_xxx	Set XBAR_A_OUT6 input.		✓
XBAR_A_SET_OUT_GPIO_F_3	XBAR_A_INPUT_xxx	Set XBAR_A_OUT7 input.		✓
XBAR_A_SET_OUT_GPIO_F_3	XBAR_A_INPUT_xxx	Set XBAR_A_OUT7 input.	✓	
XBAR_A_SET_OUT_GPIO_F_4	XBAR_A_INPUT_xxx	Set XBAR_A_OUT8 input.		✓
XBAR_A_SET_OUT_GPIO_F_5	XBAR_A_INPUT_xxx	Set XBAR_A_OUT9 input.		✓
XBAR_A_SET_OUT_GPIO_F_8	XBAR_A_INPUT_xxx	Set XBAR_A_OUT10 input.	✓	
XBAR_A_SET_OUT_GPIO_F_9	XBAR_A_INPUT_xxx	Set XBAR_A_OUT11 input.		✓
XBAR_A_SET_OUT_GPIO_F10_G8	XBAR_A_INPUT_xxx	Set XBAR_A_OUT10 input.		✓
XBAR_A_SET_OUT_GPIO_F9_G9	XBAR_A_INPUT_xxx	Set XBAR_A_OUT11 input.		✓
XBAR_A_SET_OUT_GPIO_G_8	XBAR_A_INPUT_xxx	Set XBAR_A_OUT10 input.		✓
XBAR_A_SET_OUT_GPIO_G_9	XBAR_A_INPUT_xxx	Set XBAR_A_OUT11 input.		✓
XBAR_A_SET_OUT_PDB0_FAULTA	XBAR_A_INPUT_xxx	Set XBAR_A_OUT39 input.		✓
XBAR_A_SET_OUT_PDB0_FAULTC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT40 input.		✓
XBAR_A_SET_OUT_PDB0_TRIG0	XBAR_A_INPUT_xxx	Set XBAR_A_OUT38 input.		✓
XBAR_A_SET_OUT_PDB1_FAULTA	XBAR_A_INPUT_xxx	Set XBAR_A_OUT42 input.		✓
XBAR_A_SET_OUT_PDB1_FAULTC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT43 input.		✓

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_A_SET_OUT_PWMA_EXT_CLK	XBAR_A_INPUT_xxx	Set XBAR_A_OUT28 input.	✓	
XBAR_A_SET_OUT_PWMA_FAULT0	XBAR_A_INPUT_xxx	Set XBAR_A_OUT29 input.	✓	
XBAR_A_SET_OUT_PWMA_FAULT1	XBAR_A_INPUT_xxx	Set XBAR_A_OUT30 input.	✓	
XBAR_A_SET_OUT_PWMA_FAULT2	XBAR_A_INPUT_xxx	Set XBAR_A_OUT31 input.	✓	
XBAR_A_SET_OUT_PWMA_FAULT3	XBAR_A_INPUT_xxx	Set XBAR_A_OUT32 input.	✓	
XBAR_A_SET_OUT_PWMA_FORCE	XBAR_A_INPUT_xxx	Set XBAR_A_OUT33 input.		✓
XBAR_A_SET_OUT_PWMA_FORCE	XBAR_A_INPUT_xxx	Set XBAR_A_OUT33 input.	✓	
XBAR_A_SET_OUT_PWMA0_EXT_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT24 input.		✓
XBAR_A_SET_OUT_PWMA0_EXT_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT24 input.	✓	
XBAR_A_SET_OUT_PWMA0_EXTA	XBAR_A_INPUT_xxx	Set XBAR_A_OUT20 input.		✓
XBAR_A_SET_OUT_PWMA0_EXTA	XBAR_A_INPUT_xxx	Set XBAR_A_OUT20 input.	✓	
XBAR_A_SET_OUT_PWMA1_EXT_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT25 input.		✓
XBAR_A_SET_OUT_PWMA1_EXT_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT25 input.	✓	
XBAR_A_SET_OUT_PWMA1_EXTA	XBAR_A_INPUT_xxx	Set XBAR_A_OUT21 input.		✓
XBAR_A_SET_OUT_PWMA1_EXTA	XBAR_A_INPUT_xxx	Set XBAR_A_OUT21 input.	✓	
XBAR_A_SET_OUT_PWMA2_EXT_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT26 input.		✓
XBAR_A_SET_OUT_PWMA2_EXT_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT26 input.	✓	

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_A_SET_OUT_PWMA2_EXTA	XBAR_A_INPUT_xxx	Set XBAR_A_OUT22 input.		✓
XBAR_A_SET_OUT_PWMA2_EXTA	XBAR_A_INPUT_xxx	Set XBAR_A_OUT22 input.	✓	
XBAR_A_SET_OUT_PWMA3_EXT_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT27 input.		✓
XBAR_A_SET_OUT_PWMA3_EXT_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT27 input.	✓	
XBAR_A_SET_OUT_PWMA3_EXTA	XBAR_A_INPUT_xxx	Set XBAR_A_OUT23 input.		✓
XBAR_A_SET_OUT_PWMA3_EXTA	XBAR_A_INPUT_xxx	Set XBAR_A_OUT23 input.	✓	
XBAR_A_SET_OUT_PWMAB_EXT_CLK	XBAR_A_INPUT_xxx	Set XBAR_A_OUT28 input.		✓
XBAR_A_SET_OUT_PWMAB_FAULT0	XBAR_A_INPUT_xxx	Set XBAR_A_OUT29 input.		✓
XBAR_A_SET_OUT_PWMAB_FAULT1	XBAR_A_INPUT_xxx	Set XBAR_A_OUT30 input.		✓
XBAR_A_SET_OUT_PWMAB_FAULT2	XBAR_A_INPUT_xxx	Set XBAR_A_OUT31 input.		✓
XBAR_A_SET_OUT_PWMAB_FAULT3	XBAR_A_INPUT_xxx	Set XBAR_A_OUT32 input.		✓
XBAR_A_SET_OUT_PWMB_FORCE	XBAR_A_INPUT_xxx	Set XBAR_A_OUT57 input.		✓
XBAR_A_SET_OUT_PWMB0_EXT_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT53 input.		✓
XBAR_A_SET_OUT_PWMB1_EXT_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT54 input.		✓
XBAR_A_SET_OUT_PWMB2_EXT_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT55 input.		✓
XBAR_A_SET_OUT_PWMB3_EXT_SYNC	XBAR_A_INPUT_xxx	Set XBAR_A_OUT56 input.		✓
XBAR_A_SET_OUT_QD_CAP	XBAR_A_INPUT_xxx	Set XBAR_A_OUT48 input.		✓
XBAR_A_SET_OUT_QD_HOME	XBAR_A_INPUT_xxx	Set XBAR_A_OUT47 input.		✓

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_A_SET_OUT_QD_INDEX	XBAR_A_INPUT_xxx	Set XBAR_A_OUT46 input.		✓
XBAR_A_SET_OUT_QD_PHA	XBAR_A_INPUT_xxx	Set XBAR_A_OUT44 input.		✓
XBAR_A_SET_OUT_QD_PHB	XBAR_A_INPUT_xxx	Set XBAR_A_OUT45 input.		✓
XBAR_A_SET_OUT_QT_A0_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT49 input.		✓
XBAR_A_SET_OUT_QT_A0_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT34 input.	✓	
XBAR_A_SET_OUT_QT_A1_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT50 input.		✓
XBAR_A_SET_OUT_QT_A1_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT35 input.	✓	
XBAR_A_SET_OUT_QT_A2_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT51 input.		✓
XBAR_A_SET_OUT_QT_A2_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT36 input.	✓	
XBAR_A_SET_OUT_QT_A3_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT52 input.		✓
XBAR_A_SET_OUT_QT_A3_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT37 input.	✓	
XBAR_A_SET_OUT_QT_B0_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT34 input.		✓
XBAR_A_SET_OUT_QT_B1_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT35 input.		✓
XBAR_A_SET_OUT_QT_B2_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT36 input.		✓
XBAR_A_SET_OUT_QT_B3_IN	XBAR_A_INPUT_xxx	Set XBAR_A_OUT37 input.		✓
XBAR_A_SET_OUT_SCI0_RXD	XBAR_A_INPUT_xxx	Set XBAR_A_OUT38 input.	✓	
XBAR_A_SET_OUT_SCI1_RXD	XBAR_A_INPUT_xxx	Set XBAR_A_OUT39 input.	✓	
XBAR_A_SET_PDB1_TRIG0	XBAR_A_INPUT_xxx	Set XBAR_A_OUT41 input.		✓
XBAR_A_WRITE_CROSSBAR_CTRL_0	UWord16	Write the Crossbar A Control Register 0.	✓	✓
XBAR_A_WRITE_CROSSBAR_CTRL_1	UWord16	Write the Crossbar A Control Register 1.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_0	UWord16	Write the Crossbar A Select Register 0.	✓	✓

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_A_WRITE_CROSSBAR_REG_1	UWord16	Write the Crossbar A Select Register 1.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_10	UWord16	Write the Crossbar A Select Register 10.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_11	UWord16	Write the Crossbar A Select Register 11.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_12	UWord16	Write the Crossbar A Select Register 12.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_13	UWord16	Write the Crossbar A Select Register 13.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_14	UWord16	Write the Crossbar A Select Register 14.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_15	UWord16	Write the Crossbar A Select Register 15.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_16	UWord16	Write the Crossbar A Select Register 16.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_17	UWord16	Write the Crossbar A Select Register 17.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_18	UWord16	Write the Crossbar A Select Register 18.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_19	UWord16	Write the Crossbar A Select Register 19.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_2	UWord16	Write the Crossbar A Select Register 2.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_20	UWord16	Write the Crossbar A Select Register 20.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_21	UWord16	Write the Crossbar A Select Register 21.		✓
XBAR_A_WRITE_CROSSBAR_REG_22	UWord16	Write the Crossbar A Select Register 22.		✓
XBAR_A_WRITE_CROSSBAR_REG_23	UWord16	Write the Crossbar A Select Register 23.		✓
XBAR_A_WRITE_CROSSBAR_REG_24	UWord16	Write the Crossbar A Select Register 24.		✓

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_A_WRITE_CROSSBAR_REG_25	UWord16	Write the Crossbar A Select Register 25.		✓
XBAR_A_WRITE_CROSSBAR_REG_26	UWord16	Write the Crossbar A Select Register 26.		✓
XBAR_A_WRITE_CROSSBAR_REG_27	UWord16	Write the Crossbar A Select Register 27.		✓
XBAR_A_WRITE_CROSSBAR_REG_28	UWord16	Write the Crossbar A Select Register 28.		✓
XBAR_A_WRITE_CROSSBAR_REG_29	UWord16	Write the Crossbar A Select Register 29.		✓
XBAR_A_WRITE_CROSSBAR_REG_3	UWord16	Write the Crossbar A Select Register 3.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_4	UWord16	Write the Crossbar A Select Register 4.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_5	UWord16	Write the Crossbar A Select Register 5.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_6	UWord16	Write the Crossbar A Select Register 6.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_7	UWord16	Write the Crossbar A Select Register 7.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_8	UWord16	Write the Crossbar A Select Register 8.	✓	✓
XBAR_A_WRITE_CROSSBAR_REG_9	UWord16	Write the Crossbar A Select Register 9.	✓	✓
XBAR_B_INIT	NULL	Initialize XBAR_B periheral registers using the appconfig.h _INIT values.		
XBAR_B_READ_CROSSBAR_REG_0	NULL	Read and return the value of the Crossbar B Select Register 0.	✓	✓
XBAR_B_READ_CROSSBAR_REG_1	NULL	Read and return the value of the Crossbar B Select Register 1.	✓	✓
XBAR_B_READ_CROSSBAR_REG_2	NULL	Read and return the value of the Crossbar B Select Register 2.	✓	✓
XBAR_B_READ_CROSSBAR_REG_3	NULL	Read and return the value of the Crossbar B Select Register 3.	✓	✓

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_B_READ_CROSSBAR_REG_4	NULL	Read and return the value of the Crossbar B Select Register 4.	✓	✓
XBAR_B_READ_CROSSBAR_REG_5	NULL	Read and return the value of the Crossbar B Select Register 5.	✓	✓
XBAR_B_READ_CROSSBAR_REG_6	NULL	Read and return the value of the Crossbar B Select Register 6.	✓	✓
XBAR_B_READ_CROSSBAR_REG_7	NULL	Read and return the value of the Crossbar B Select Register 7.	✓	✓
XBAR_B_SET_OUT_AOI_1_A	XBAR_B_INPUT_xxx	Set XBAR_B_OUT4 input.		✓
XBAR_B_SET_OUT_AOI_1_A	XBAR_B_INPUT_xxx	Set XBAR_B_OUT4 input.	✓	
XBAR_B_SET_OUT_AOI_1_B	XBAR_B_INPUT_xxx	Set XBAR_B_OUT5 input.		✓
XBAR_B_SET_OUT_AOI_1_B	XBAR_B_INPUT_xxx	Set XBAR_B_OUT5 input.	✓	
XBAR_B_SET_OUT_AOI_1_C	XBAR_B_INPUT_xxx	Set XBAR_B_OUT6 input.		✓
XBAR_B_SET_OUT_AOI_1_C	XBAR_B_INPUT_xxx	Set XBAR_B_OUT6 input.	✓	
XBAR_B_SET_OUT_AOI_1_D	XBAR_B_INPUT_xxx	Set XBAR_B_OUT7 input.		✓
XBAR_B_SET_OUT_AOI_1_D	XBAR_B_INPUT_xxx	Set XBAR_B_OUT7 input.	✓	
XBAR_B_SET_OUT_AOI_2_A	XBAR_B_INPUT_xxx	Set XBAR_B_OUT8 input.		✓
XBAR_B_SET_OUT_AOI_2_A	XBAR_B_INPUT_xxx	Set XBAR_B_OUT8 input.	✓	
XBAR_B_SET_OUT_AOI_2_B	XBAR_B_INPUT_xxx	Set XBAR_B_OUT9 input.		✓
XBAR_B_SET_OUT_AOI_2_B	XBAR_B_INPUT_xxx	Set XBAR_B_OUT9 input.	✓	
XBAR_B_SET_OUT_AOI_2_C	XBAR_B_INPUT_xxx	Set XBAR_B_OUT10 input.		✓
XBAR_B_SET_OUT_AOI_2_C	XBAR_B_INPUT_xxx	Set XBAR_B_OUT10 input.	✓	
XBAR_B_SET_OUT_AOI_2_D	XBAR_B_INPUT_xxx	Set XBAR_B_OUT11 input.		✓
XBAR_B_SET_OUT_AOI_2_D	XBAR_B_INPUT_xxx	Set XBAR_B_OUT11 input.	✓	
XBAR_B_SET_OUT_AOI_3_A	XBAR_B_INPUT_xxx	Set XBAR_B_OUT12 input.		✓

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_B_SET_OUT_AOI_3_A	XBAR_B_INPUT_xxx	Set XBAR_B_OUT12 input.	✓	
XBAR_B_SET_OUT_AOI_3_B	XBAR_B_INPUT_xxx	Set XBAR_B_OUT13 input.		✓
XBAR_B_SET_OUT_AOI_3_B	XBAR_B_INPUT_xxx	Set XBAR_B_OUT13 input.	✓	
XBAR_B_SET_OUT_AOI_3_C	XBAR_B_INPUT_xxx	Set XBAR_B_OUT14 input.		✓
XBAR_B_SET_OUT_AOI_3_C	XBAR_B_INPUT_xxx	Set XBAR_B_OUT14 input.	✓	
XBAR_B_SET_OUT_AOI_3_D	XBAR_B_INPUT_xxx	Set XBAR_B_OUT15 input.		✓
XBAR_B_SET_OUT_AOI_3_D	XBAR_B_INPUT_xxx	Set XBAR_B_OUT15 input.	✓	
XBAR_B_SET_OUT_AOI_O_A	XBAR_B_INPUT_xxx	Set XBAR_B_OUT0 input.		✓
XBAR_B_SET_OUT_AOI_O_A	XBAR_B_INPUT_xxx	Set XBAR_B_OUT0 input.	✓	
XBAR_B_SET_OUT_AOI_O_B	XBAR_B_INPUT_xxx	Set XBAR_B_OUT1 input.		✓
XBAR_B_SET_OUT_AOI_O_B	XBAR_B_INPUT_xxx	Set XBAR_B_OUT1 input.	✓	
XBAR_B_SET_OUT_AOI_O_C	XBAR_B_INPUT_xxx	Set XBAR_B_OUT2 input.		✓
XBAR_B_SET_OUT_AOI_O_C	XBAR_B_INPUT_xxx	Set XBAR_B_OUT2 input.	✓	
XBAR_B_SET_OUT_AOI_O_D	XBAR_B_INPUT_xxx	Set XBAR_B_OUT3 input.		✓
XBAR_B_SET_OUT_AOI_O_D	XBAR_B_INPUT_xxx	Set XBAR_B_OUT3 input.	✓	
XBAR_B_WRITE_CROSSBAR_REG_0	UWord16	Write the Crossbar the Crossbar B Select Register 0.	✓	✓
XBAR_B_WRITE_CROSSBAR_REG_1	UWord16	Write the Crossbar the Crossbar B Select Register 1.	✓	✓
XBAR_B_WRITE_CROSSBAR_REG_2	UWord16	Write the Crossbar the Crossbar B Select Register 2.	✓	✓
XBAR_B_WRITE_CROSSBAR_REG_3	UWord16	Write the Crossbar the Crossbar B Select Register 3.	✓	✓
XBAR_B_WRITE_CROSSBAR_REG_4	UWord16	Write the Crossbar the Crossbar B Select Register 4.	✓	✓

Table 5-64. XBAR Driver Commands

Cmd	pParam	Description	56F82xxx	56F84xxx
XBAR_B_WRITE_CROSSBAR_REG_5	UWord16	Write the Crossbar the Crossbar B Select Register 5.	✓	✓
XBAR_B_WRITE_CROSSBAR_REG_6	UWord16	Write the Crossbar the Crossbar B Select Register 6.	✓	✓
XBAR_B_WRITE_CROSSBAR_REG_7	UWord16	Write the Crossbar the Crossbar B Select Register 7.	✓	✓

Chapter 6
FreeMASTER Driver

6.1 Introduction

The FreeMASTER driver handles a communication between embedded application and the PC running the FreeMASTER tool. A communication protocol and the FreeMASTER tool enables real-time access to target resources, especially C-language variables and memory in general.

FreeMASTER protocol features:

- Read/Write Access to any memory location on the target.
- Atomic bit manipulation on target memory (bit-wise write access).
- Oscilloscope access - optimized real time access to variables (up to 8 variables). Sample rate depends on communication speed.
- Recorder - access to fast transient recorder running on-board as a part of FreeMASTER driver. Sample rate is limited by microcontroller CPU speed only. The length of data recorded depends on amount of available memory, 64kB maximum.
- Application commands - high level message delivery from PC to the application.

FreeMASTER driver features:

- Full FreeMASTER protocol implementation.
- SCI or JTAG as a native communication interface.
- Ability to write-protect memory regions or individual variables.
- Ability to deny access to unsafe memory.
- Two ways of how to handle Application Commands
  - — Classic: the application polls the App.Command status to determine any command is pending.
  - — Callback: the application registers a callback function which is automatically invoked upon reception of given command.
  - — The two approaches may be mixed in the application. Callback commands do not appear in the polling mechanism.

In previous DSP56800E_Quick_Start r2.1, the FreeMASTER driver was completely re-written to enable better code portability and memory protection features. The former Quick Start versions included similar driver named “pc_master”, which is still available for backward compatibility.

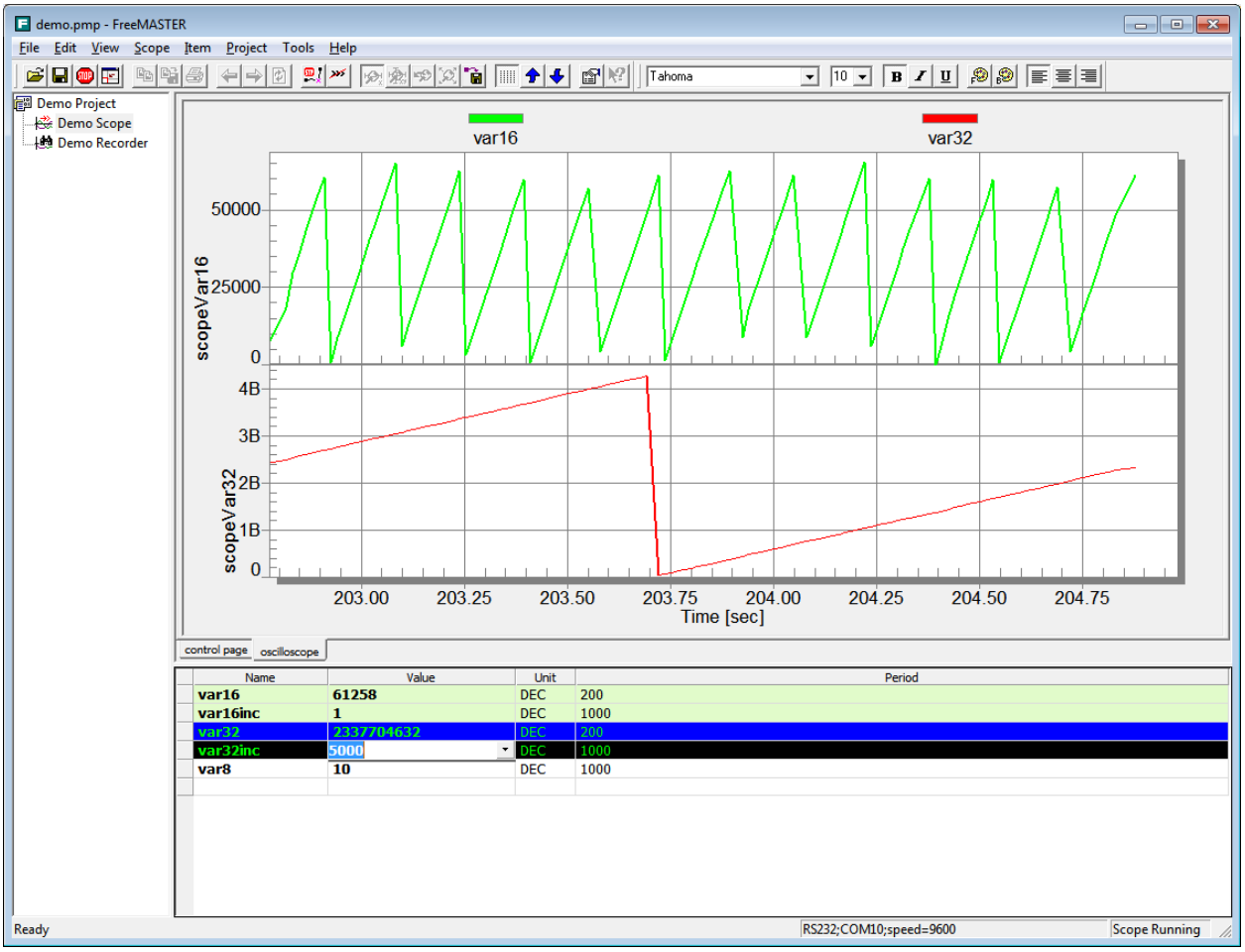


Figure 6-1. FreeMASTER Application Window

6.2 Driver Files

The driver code can be found in the `src/support/freemaster` subdirectory of the main install directory. The driver is highly configurable and not all of the .c files are needed to be compiled in all configurations. However, *all* the files may be added to the project as there are conditional compilation statements in the code, which assure only the required code gets actually compiled.

The driver is configured by macro constants defined in the *freemaster_cfg.h* file. This file is included by all FreeMASTER driver source files and should contain configuration constants which affect how the driver is compiled. With the DSP56800EX_Quick_Start, the *freemaster_cfg.h* file is rather simple and is not to be modified. The actual configuration should be done in the Quick Start's *appconfig.h* file which is included by *freemaster_cfg.h*. This scenario enables the FreeMASTER driver to be configured graphically, using the Graphical Configuration Tool.

The FreeMASTER driver may also be used without the DSP56800EX_Quick_Start and thus also without the *appconfig.h* file. In this case, all the configuration constants should be placed directly to the freemaster_cfg.h.

The following files are located in the `src/support/freemaster` directory:

- **freemaster.h** - The main driver header file. This is the only file which needs to be included by the application code.
- freemaster_cfg.h - The minimal driver configuration file which further includes the appconfig.h file and enables the driver to be configured in Graphical Configuration Tool.
- **freemaster_cfg.h.template** - An example of the full driver configuration file. Such a file needs to be used (and renamed to *freemaster_cfg.h*) in case the FreeMASTER driver is extracted and used outside the DSP56F800EX_Quick_Start environment.
- **freemaster_private.h** - Internal header file used by all driver source code. The compile-time verification of the configuration macros is done in this file. Also the default values of undefined configuration values are defined here.
- **freemaster_56F8xxx.c** - 56F82xxx and 56F84xxx hardware-specific functions are implemented in this file.
- **freemaster_56F8xxx.h** - 56F82xxx and 56F84xxx hardware-specific macros and inline functions are in this file.
- **freemaster_protocol.c** - Implements the FreeMASTER protocol decoder, which is independent on the communication interface used.
- **freemaster_protocol.h** - Internal header file which contains the FreeMASTER protocol constants.
- **freemaster_serial.c** - Physical SCI and JTAG interface is handled in this file. The protocol decoder is invoked from this file when a valid FreeMASTER message is received. This file also handles the response transmission back to the PC.
- **freemaster_appcmd.c** - Implementation of the FreeMASTER Application Commands.
- **freemaster_rec.c** - FreeMASTER Recorder implementation.
- **freemaster_scope.c** - FreeMASTER Oscilloscope implementation.
- **freemaster_tsa.c** - Target-side Addressing (TSA) implementation.
- **freemaster_tsa.h** - TSA header file which is indirectly included in the user application code too. This file defines the macros which are used to build the TSA tables in the user code.

6.3 Interrupt Handling

The FreeMASTER driver must be configured for one of the three modes of operation, differing in the way how the peripheral interrupts are used by the driver.

Table 6-1. FreeMASTER Driver Interrupt Mode

Mode	Description
Long Interrupt Mode	Both the communication interface and the protocol decoder are processed in the SCI or JTAG interrupt. The time spent in the interrupt routine depends on the what protocol command is being handled. Such a non-deterministic behavior may require the application interrupt levels to be balanced with care.

Table 6-1. FreeMASTER Driver Interrupt Mode (Continued)

Mode	Description
Short Interrupt Mode	The communication is handled in the interrupt while the protocol is decoded and handled only when the “poll” function is called. The time spent in the interrupt service routine is rather short as the characters are just fetched to or from the buffer. One additional communication buffer (receiver queue) is required to store received characters before they are handled by the protocol state machine.
Poll-driven Mode	No-interrupt operation. Both the communication interface and the protocol are handled only when the “poll” function is called. Typically, this function is called from the application main loop.

6.4 New Features

In addition to the JTAG communication support, there are two other important new features in the FreeMASTER driver.

6.4.1 Target-side Addressing

One of the new features in the FreeMASTER driver if comparing it with the old “pc_master” driver is the Target-side Addressing capability (TSA). With this feature, the user is able to describe the variables and structure data types directly in the application source code and make this information available for the FreeMASTER tool. The tool may then use this information instead of reading it from the application’s ELF/Dwarf executable file.

Once the variables are described in TSA tables in the application source code (see Section 6.6.1, “Driver API.” below), the FreeMASTER driver can also use this information to protect other memory from being accessed by the PC.

6.4.2 Application Command Callbacks

Another new feature of the FreeMASTER driver is a capability of invoking the user-defined callback functions when the Application Command is received. The callback function obtains the Application Command number and data as a parameters. Callback’s return value is used as a Application Command result code.

In the old driver, the Application Command status needed to be periodically tested, for example in the application main loop. This approach is still possible with the FreeMASTER driver.

6.5 Driver Configuration

This section describes the FreeMASTER driver configuration constants which can be placed in the *appconfig.h* file (or *freemaster_cfg.h* file).

Table 6-2. FreeMASTER Communication Configuration Items for appconfig.h

SYMBOL	TYPE	DESCRIPTION
FMSTR_LONG_INTR FMSTR_SHORT_INTR FMSTR_POLL_DRIVEN	numeric (zero / non-zero)	Exactly one of the three constants must be set to a non-zero value. Such a macro then affects how the FreeMASTER driver uses interrupts. See table Table 6-1 above.
FMSTR_SCI_BASE	address (numeric)	In case the SCI is to be used as a communication interface, this constant must be defined as a base address of SCI peripheral register space. With DSP56800EX_Quick_Start, you can find these constants in the processor-specific “arch.h” file (SCI0_BASE, SCI1_BASE or SCI_BASE).
FMSTR_USE_JTAG	numeric (zero / non-zero)	When defined as a non-zero value, the JTAG will be used for communication instead of the SCI. **Default: 0 (false)**
FMSTR_USE_JTAG_TXFIX	numeric (zero / non-zero)	When non-zero, the driver implements software workaround of the JTAG TDF status bit problem. See more information in the JTAG communication plug-in for the FreeMASTER tool. **Default: 0 (false)**
FMSTR_JTAG_BASE	address (numeric)	In case the JTAG is to be used as a communication interface, this constant may be defined as a base address of JTAG register space. As the JTAG registers are located at the same address on all 56F82xxx and 56F84xxx processors, this value needs not to be defined and its **default** value is **0xFFFF00**.
FMSTR_COMM_BUFFER_SIZE	integer	Defines the size of the FreeMASTER communication buffer. This buffer is used to store the frames being received or frames to be sent over the SCI or JTAG. If this constant is undefined or is defined as zero, a sufficient memory buffer is allocated by the driver. **Default: 0 (automatic)**
FMSTR_COMM_RQUEUE_SIZE	integer	The size of additional receive queue for short interrupt processing. Needed only in FMSTR_SHORT_INTR mode. **Default: 32**
Application Commands		

Table 6-2. FreeMASTER Communication Configuration Items for appconfig.h (Continued)

SYMBOL	TYPE	DESCRIPTION
FMSTR_USE_APPCMD	numeric (zero / non-zero)	When defined non-zero, this constant enables a support for FreeMASTER Application Commands. **Default: 0 (false)**
FMSTR_APPCMD_BUFF_SIZE	integer	A size of buffer which will receive the Application Command parameters. The parameters are stored in the buffer until the application code processes and acknowledges the application command. **Default: 16**
FMSTR_MAX_APPCMD_CALLS	integer	A number of different Application Commands for which the callback functions are to be registered. If this constant is not defined or is zero, the support for Application Command callbacks is not compiled in. **Default: 0**
Oscilloscope		
FMSTR_USE_SCOPE	numeric (zero / non-zero)	When defined non-zero, this constant enables a support for the FreeMASTER Oscilloscope. Oscilloscope enables a faster (simultaneous) access to up to 8 variables and is used when the variables are to be displayed in the real-time graph. If this feature is not enabled, the FreeMASTER uses standard memory access commands to access variables in graph sequentially. **Default: 0 (false)**
FMSTR_MAX_SCOPE_VARS	integer	This constant defines how many variables will it be possible to display in the FreeMASTER Oscilloscope. The **default** value is **8**. It makes sense to set this value in the range of 2...8. Values lower than 8 may save some data RAM allocated by the driver (6bytes per variable). The current version of the FreeMASTER tool does not support more than 8 variables to be displayed in graph.
Recorder		

Table 6-2. FreeMASTER Communication Configuration Items for appconfig.h (Continued)

SYMBOL	TYPE	DESCRIPTION
FMSTR_USE_RECORDER	numeric (zero / non-zero)	When defined non-zero, this constant enables a support for the FreeMASTER Recorder. Recorder is an advanced feature which enables up to 8 variables to be internally sampled to the on-board memory. The sampling can be stopped manually or automatically based on a threshold crossing condition. Sampled data buffer is downloaded to the FreeMASTER as a block and data values are displayed in the graph. Disabling the recorder feature may save significant amount of code and data memory. **Default: 0 (false)**
FMSTR_MAX_REC_VARS	integer	This constant defines how many variables will it be possible to display in the FreeMASTER Recorder. The **default** value is **8**. It makes sense to set this value in the range of 2...8. Values lower than 8 may save some data RAM allocated by the driver (6bytes per variable). The current version of the FreeMASTER tool does not support more than 8 variables to be displayed in graph.
FMSTR_REC_OWNBUFF	numeric (zero / non-zero)	When defined non-zero, the user may (must) supply his own memory to be used as a recorder buffer. The recorder buffer is the memory dedicated to the recorder feature and is used to hold sampled variable values. As the buffer may be up to 64kB long, it may sometimes be desirable the user allocates the memory himself and do not let the driver to allocate it statically. When undefined or set to zero, the FreeMASTER driver statically allocates the recorder buffer (FMSTR_REC_BUFF_SIZE bytes). **Default: 0 (false)**
FMSTR_REC_BUFF_SIZE	integer UWord16	This constant is used when FMSTR_REC_OWNBUFF is undefined or set to zero. It defines the size of the recorder buffer which is to be allocated by the FreeMASTER driver. **Default: 256**

Table 6-2. FreeMASTER Communication Configuration Items for appconfig.h (Continued)

SYMBOL	TYPE	DESCRIPTION
FMSTR_REC_FARBUFF	numeric (zero / non-zero)	When defined non-zero, the recorder buffer allocated by the FreeMASTER driver is put in the ".fardata" memory segment, which is typically put to the external memory after the address 0x10000 by the linker. **Default: 0 (false)**
FMSTR_REC_TIMEBASE	UWord16 constant	This constant is used to describe the recorder sampling rate as it is implemented in the application. The time base value specified by this constant is used as the base X-axis unit in the recorder graph. You can use one of the following macros to build the value (providing a 14bit 'x" value): - FMSTR_REC_BASE_NANOSEC(x) - FMSTR_REC_BASE_MICROSEC(x) - FMSTR_REC_BASE_MILLISEC(x) - FMSTR_REC_BASE_SECONDS(x) The (**default**) value of **zero** can be used as "unknown", which forces the FreeMASTER recorder to display the X-axis values as indexes instead of time.
Target-side Addressing		
FMSTR_USE_TSA	numeric (zero / non-zero)	When defined non-zero, this constant enables a support for so-called Target-side Addressing (TSA). This is a new feature in the FreeMASTER protocol, which enables the FreeMASTER tool to obtain variable information directly from the embedded application. With this feature, it is no more necessary for the FreeMASTER tool to load and parse the application ELF file. It also enables the TSA-safety feature. **Default: 0 (false)**
FMSTR_USE_TSA_SAFETY	numeric (zero / non-zero)	When defined non-zero and TSA is enabled, this constant activates the FreeMASTER memory protection. In this mode, the driver actively denies any access to memory areas which are not described by any TSA table in the application. Also with this feature, the variables described by a TSA entries can be declared as Read/Write or Read-Only for the FreeMASTER tool. **Default: 0 (false)**

Table 6-2. FreeMASTER Communication Configuration Items for appconfig.h (Continued)

SYMBOL	TYPE	DESCRIPTION
FMSTR_USE_TSA_INROM	numeric (zero / non-zero)	With this constant defined as a non-zero value, all TSA tables are declared as “const”, i.e they are put to “.const.data” segment. This segment is typically put to Flash memory in DSP56F800EX_Quick_Start applications. **Default: 0 (false)**
Memory Access		
FMSTR_USE_READMEM	numeric (zero / non-zero)	When this constant is defined as a non-zero value, the support for Read-Memory feature is implemented. It is recommended to enable this feature. **Default: 1 (true)**
FMSTR_USE_WRITEMEM	numeric (zero / non-zero)	When this constant is defined as a non-zero value, the support for Write-Memory feature is implemented. It is recommended to enable this feature. **Default: 1 (true)**
FMSTR_USE_WRITEMEMMASK	numeric (zero / non-zero)	When this constant is defined as a non-zero value, the support for Masked (bit-wise) Memory Write feature is implemented. It is recommended to this feature. **Default: 1 (true)**
Variable Access *(subset of Memory Access features, implemented for backward compatibility only)*		
FMSTR_USE_READVAR	numeric (zero / non-zero)	When this constant is defined as a non-zero value, the support for Read-Variable feature is implemented. This command enables a read access to 1, 2 or 4 byte variables. This functionality is a subset of the Read-Memory feature. Comparing it with the Read-Memory feature, there is one byte saved on the communication line. **Default: 0 (false)**
FMSTR_USE_WRITEVAR	numeric (zero / non-zero)	When this constant is defined as a non-zero value, the support for Write-Variable feature is implemented. This command enables a write access to 1, 2 or 4 byte variables. This functionality is a subset of the Write-Memory feature. Comparing it with the Write-Memory feature, there is one byte saved on the communication line. **Default: 0 (false)**

Table 6-2. FreeMASTER Communication Configuration Items for appconfig.h (Continued)

SYMBOL	TYPE	DESCRIPTION
FMSTR_USE_WRITEVARMASK	numeric (zero / non-zero)	When this constant is defined as a non-zero value, the support for Masked Write-Variable feature is implemented. This command enables a write access to 1 and 2 byte variables only. This functionality is a subset of the Masked Write-Memory feature. Comparing it with the Masked Write-Memory feature, there is one byte saved on the communication line. **Default: 0 (false)**

6.6 Driver Usage

The FreeMASTER driver was designed to be easily used in any DSP56F800EX_Quick_Start application and also in custom user code. With DSP56F800EX_Quick_Start, the following steps are necessary to enable a basic FreeMASTER connectivity in the application:

- The FreeMASTER driver needs to be configured in the **Graphical Configuration Tool** or in the *appconfig.h* file directly.
- The **freemaster.h** file needs to be included in any application source file which makes FreeMASTER API calls.
- The **FMSTR_Init()** function has to be called before any other FreeMASTER driver API calls.
- For FMSTR_LONG_INTR or FMSTR_SHORT_INTR modes, the **SCI or JTAG interrupts** need to be directed to **FMSTR_Isr()** function. This is done automatically when the FreeMASTER driver is configured using the Graphical Configuration Tool.

  The **interrupt priority levels** need to be set (in GCT) and the interrupts have to be enabled in the processor core (**archEnableInt()**).
- For FMSTR_SHORT_INTR or FMSTR_POLL_DRIVEN modes, the **FMSTR_Poll()** API function needs to be called periodically in the application. For example in the application main loop.

See Driver API description in the next section for more detail on how to use advanced FreeMASTER features like Application Commands, Recorder or TSA.

6.6.1 Driver API

This section describes the FreeMASTER driver API. It can be expected the same API will be used with the new FreeMASTER driver on other Freescale platforms as well.

The following header files are needed in order to use the FreeMASTER driver:

Required Header File(s):

```
#include “qs.h”
#include “freemaster.h”
```

The next sections describe each driver API function in detail. Function arguments for each routine are described as *in* or *out*

1. *in* argument means that the parameter value is an input only to the function.
2. *out* argument means that the parameter value is an output only from the function.

6.6.1.1 FMSTR_Init() - Initializes the FreeMASTER Communication

Call:

```
void FMSTR_Init(void);
```

Arguments: None.

Description: This function initializes internal variables of the FreeMASTER driver and enables the communication interface (SCI or JTAG). This function does not change the configuration of communication module, the module must be initialized before the *FMSTR_Init* function is called.

For the SCI communication, the SCI module has to be configured either dynamically in run-time or using the GCT and the *SCI_INIT* ioctl call. See for more details. It is not necessary to set the transmitter and receiver enable bits in the SCI control register (SCICR).

In case the interrupt-driven SCI communication is to be used either in *FMSTR_SHORT_INTR* or *FMSTR_LONG_INTR* mode, the SCI interrupt vectors need to be routed to *FMSTR_Isr* function and interrupt priority levels should be set to Level 0, 1, or 2. It is not necessary to set any of the interrupt enable bits in the SCI control register (SCICR). The SCI TX Idle interrupt is not used at all.

For the JTAG communication (as there is no settings for the JTAG module) the only what needs to be done is routing the JTAG interrupt vectors to *FMSTR_Isr* function and setting proper interrupt priority levels. For JTAG polling mode (*FMSTR_POLL_DRIVEN*), no setup operations are required at all.

Returns: None.

Range Issues: None.

Special Issues: None.

Design/Implementation: None.

Example 6-1. FMSTR_Init

```
...
ioctl(SCI_0, SCI_INIT, NULL);
...
...
FMSTR_Init();
...
```

This code initializes the SCI module and then it initializes the FreeMASTER driver

6.6.1.2 FMSTR_Poll() - The FreeMASTER polling method

Call:

```
void FMSTR_Poll(void);
```

Arguments: None.

Description: Except when the driver is configured for the *FMSTR_LONG_INTR* mode, the *FMSTR_Poll* function must be called periodically in the application. Typically, such a call is placed to the application main loop, while the application critical tasks are handled in the interrupts.

In the *FMSTR_SHORT_INTR* interrupt mode, the *FMSTR_Poll* function fetches all bytes which were received by the SCI or JTAG interrupt service routine and were put in the temporary receive queue. The fetched bytes are then all fed to the protocol state machine. If the state machine determines the protocol message is received without error, the protocol message decoder is invoked. If, in-turn, the message is evaluated as a valid and supported message, the protocol message handler function is invoked to process the message.

To prevent receive data overflow in *FMSTR_SHORT_INTR* mode, the *FMSTR_Poll* function must be called at least once per: *FMSTR_COMM_RQUEUE_SIZE * Tchar* time, where *Tchar* is the time it takes to receive one byte.

In the *FMSTR_POLL_DRIVEN* mode, there is no receive queue and no interrupt service routine which would handle character reception. In this mode, the *FMSTR_Poll* function accesses the SCI or JTAG peripheral status registers to detect any character was received. To prevent receive data overflow, the *FMSTR_Poll* function must be called at least once per *Tchar* time.

In the *FMSTR_LONG_INTR* mode, the complete process described above is performed during the SCI or JTAG interrupt. There is no need to call the *FMSTR_Poll* function at all and it is actually compiled to an empty function. You can still have the function being called in the application main loop to make the code independent on interrupt mode selected.

Returns: None.

Range Issues: None.

Special Issues: None.

Design/Implementation: None.

Example 6-2. FMSTR_Poll

```
...
for(;;)
{
        ...
        FMSTR_Poll();
}
```

This code demonstrates the usage of the FMSTR_Poll API function

6.6.1.3 FMSTR_Isr() - The FreeMASTER interrupt dispatcher

Call:

```
#pragma interrupt
void FMSTR_Isr(void);
```

Arguments: None.

Description: Except when the driver is configured for the *FMSTR_POLL_DRIVEN* mode, the *FMSTR_Isr* function must be used as the SCI or JTAG interrupt service routine in the application.

This function handles the SCI or JTAG communication for the *FMSTR_SHORT_INTR* and *FMSTR_LONG_INTR* modes.

Returns: None.

Range Issues: None.

Special Issues: None.

Design/Implementation: None.

Example 6-3. FMSTR_Isr

```
#define INT_VECTOR_ADDR_47              FMSTR_Isr
#define INT_PRIORITY_LEVEL_47           INTC_LEVEL1
#define INT_VECTOR_ADDR_48              FMSTR_Isr
#define INT_PRIORITY_LEVEL_48           INTC_LEVEL1
#define INT_VECTOR_ADDR_50              FMSTR_Isr
#define INT_PRIORITY_LEVEL_50           INTC_LEVEL1
```

This (*appconfig.h*) code shows how the FMSTR_Isr is set as SCI_1 TX Empty, RX Full and RX Error interrupt service routine in the 56F82748 project.

6.6.1.4 FMSTR_Recorder() - The FreeMASTER recorder engine

Call:

```
#pragma interrupt called
void FMSTR_Recorder(void);
```

Arguments: None.

Description: This function takes one sample of variable values being recorded using the FreeMASTER recorder. In case the recorder is not active at the moment when *FMSTR_Recorder* is called, the function returns immediately. When the recorder is active, the values of variables being recorded are copied to the recorder buffer and the trigger condition is evaluated.

In case the trigger condition is satisfied, the recorder enters the post-trigger mode, in which it counts the follow-up samples (*FMSTR_Recorder* function calls) and de-activates the recorder when required post-trigger samples are sampled.

Typically, you call the *FMSTR_Recorder* function in the Timer or PWM interrupt service routine. For simple test purposes, this function can also be called in the application main loop.

Returns: None.

Range Issues: None.

Special Issues: None.

Design/Implementation: This function saves and restores all registers used, so it is possible to invoke this function from an interrupt service routine safely.

Example 6-4. FMSTR_Recorder

```
#pragma interrupt
void timer_isr()
{
...
FMSTR_Recorder();
...
}
```

This code shows how the FMSTR_Recorder function is invoked as a part of Timer interrupt service routine.

6.6.1.5 FMSTR_TriggerRec() - Force recorder trigger

Call:

```
void FMSTR_TriggerRec(void);
```

Arguments: None.

Description: This function forces the recorder trigger condition to happen, which causes the recorder to be automatically de-activated after a post-trigger samples are sampled. This function can be used in the application when it needs to have the trigger occurrence under its control.

Returns: None.

Range Issues: None.

Special Issues: None.

Design/Implementation: None.

Example 6-5. FMSTR_TriggerRec

```
FMSTR_TriggerRec();
```

This code shows how the FMSTR_TriggerRec function is invoked

6.6.1.6 FMSTR_SetUpRecBuff() - Set the recorder buffer

Call:

```
void FMSTR_SetUpRecBuff(
FMSTR_ADDR nBuffAddr,
FMSTR_SIZE nBuffSize);
```

Arguments:

nBuffAddr - a pointer to the memory which is to be used as a recorder buffer

nBuffSize - a size of the memory buffer

Description: This function can only be used when the *FMSTR_REC_OWNBUFF* configuration constant is set to a non-zero value. The user calls this function to “give” the data buffer he allocated to the FreeMASTER driver, which will use it as a recorder buffer.

Up to 64kB buffer may be used as a recorder buffer.

Returns: None.

Range Issues: None.

Special Issues: None.

Design/Implementation: None.

Example 6-6. FMSTR_SetUpRecBuff

```
UWord16 my_rec_buff[0x1000];

...
...

FMSTR_SetUpRecBuff(my_rec_buff, 0x1000);
```

This code shows how the user-allocated buffer can be set as the recorder buffer.

6.6.1.7 FMSTR_GetAppCmd() - Get pending Application Command

Call:

```
FMSTR_APPCMD_CODE FMSTR_GetAppCmd(void);
```

Arguments: None.

Description: This function can be used to detect if any Application Command is waiting to be processed by the application. In case there is no command pending, this function returns *FMSTR_APPCMDRESULT_NOCMD* constant. Otherwise, this function returns a code of the Application Command which needs to be processed. Use the *FMSTR_AppCmdAck* API call to acknowledge the Application Command after it is processed and to return the appropriate result code to the FreeMASTER tool.

The *FMSTR_GetAppCmd* function does not report commands for which a callback handler function exists. In case the *FMSTR_GetAppCmd* function is called when a callback-registered Command is pending (and before it is actually processed by the callback function), this function returns *FMSTR_APPCMDRESULT_NOCMD.*

Returns: The code of an Application Command which needs to be processed.

Range Issues: None.

Special Issues: None.

Design/Implementation: None.

Example 6-7. FMSTR_GetAppCmd

```
...
// check if a new command has been received
nAppCmdCode = FMSTR_GetAppCmd();

// when a new command arrives, the nAppCmdCode contains command
// code. In other case, the "NOCMD" special value is returned
if (nAppCmdCode != FMSTR_APPCMDRESULT_NOCMD)
{
// each command may have different processing and different
// result code. The command processing is finished by
// calling FMSTR_AppCmdAck() with the result code value
switch(nAppCmdCode)
{
case 1:
        ...
        ...
        FMSTR_AppCmdAck(0x13);
        break;
case 2:
        ...
```

This code shows how to process the Application Commands, for example in the main loop.

6.6.1.8 FMSTR_GetAppCmdData() - Get Application Command data

Call:

```
FMSTR_APPCMD_PDATA FMSTR_GetAppCmdData(FMSTR_SIZE* pDataLen);
```

Arguments:

pDataLen (out) - pointer to a variable which receives the length of the data available in the buffer. May be NULL when this information is not needed.

Description: This function can be used to retrieve the Application Command data, once the application determines the Application Command is pending (see *FMTR_GetAppCmd* function above).

There is just a single buffer to hold the Application Command data (the buffer length is *FMSTR_APPCMD_BUFF_SIZE* bytes). In case the data are to be used in the application after the command is processed by the *FMSTR_AppCmdAck* call, the user needs to copy the data out to a private buffer.

Returns: Pointer to Application Command data.

Range Issues: None.

Special Issues: None.

Design/Implementation: None.

Example 6-8. FMSTR_GetAppCmdData

```
...
switch(nAppCmdCode)
{
case 1:
        ...
        pData = FMSTR_GetAppCmdData(NULL);
        ...
        FMSTR_AppCmdAck(0x13);
        break;
case 2:
        ...
```

This code shows how to get the Application Command data when processing the Command.

6.6.1.9 FMSTR_AppCmdAck() - Finish processing of the Application Command

Call:

```
void FMSTR_AppCmdAck(FMSTR_APPCMD_RESULT nResultCode);
```

Arguments:

nResultCode (in) - the result code which is to be returned to the FreeMASTER tool

Description: This function is used when Application Command processing is finished in the application. The *nResultCode* passed to this function is returned back to the FreeMASTER tool and the driver is re-initialized to expect other Application Commands.

After this function is called, and before the next Application Command arrives, the return value of the *FMSTR_GetAppCmd* function is *FMSTR_APPCMDRESULT_NOCMD*.

Returns: None.

Range Issues: None.

Special Issues: None.

Design/Implementation: None.

Example 6-9. FMSTR_AppCmdAck

```
...
switch(nAppCmdCode)
{
case 1:
         ...
         pData = FMSTR_GetAppCmdData(NULL);
         ...
         FMSTR_AppCmdAck(0x13);
         break;
case 2:
         ...
```

This code shows how to finish an Application Command processing.

6.6.1.10 FMSTR_AppCmdSetResponseData() - Set Application Command response data

Call:

```
void FMSTR_AppCmdSetResponseData(
FMSTR_ADDR nResultDataAddr,
FMSTR_SIZE nResultDataLen);
```

Arguments:

nResultDataAddr (in) - pointer to data buffer which is to be copied to the Application Command data buffer

nResultDataLen (in) - the length of a data to be copied. Must not exceed the *FMSTR_APPCMD_BUFF_SIZE* value.

Description: This function can be used *before* the Application Command processing is finished, when there are any data to be returned back to the PC. This function exists as such a feature is enabled by the FreeMASTER protocol. However, the current version of the FreeMASTER tool does not support the Application Command response data.

Returns: None.

Range Issues: None.

Special Issues: The response data buffer is copied to the Application Command data buffer, from where it is accessed in case the host requires it. Do not use the *FMSTR_GetAppCmdData* and the data buffer after the *FMSTR_AppCmdSetResponseData* is called.

Design/Implementation: None.

Example 6-10. FMSTR_GetAppCmdData

```
...
switch(nAppCmdCode)
{
case 1:
        ...
        FMSTR_AppCmdSetResponseData(“Hello”, 5);
        ...
        FMSTR_AppCmdAck(0x13);
        break;
case 2:
        ...
```

This code shows how to return a response data before the Application Command is finished.

6.6.1.11 FMSTR_RegisterAppCmdCall() - Register Application Command callback function

Call:

```
FMSTR_BOOL FMSTR_RegisterAppCmdCall(
FMSTR_APPCMD_CODE nAppCmdCode,
FMSTR_PAPPCMDFUNC pCallbackFunc);
```

Arguments:

nAppCmdCode (in) - an Application Command code for which the callback is to be registered

pCallbackFunc (in) - pointer to a callback function which is to be registered. Use NULL to un-register a callback registered previously with this Application Command.

Description: This function can be used to register a given function as a callback handler for an Application Command. The Application Command is identified using the single-byte code. The callback function is invoked automatically by the FreeMASTER driver, when the protocol decoder obtains a request to get the application command result code.

The prototype of the callback function should be:

FMSTR_APPCMD_RESULT HandlerFunction(

FMSTR_APPCMD_CODE nAppcmd,

FMSTR_APPCMD_PDATA pData,

FMSTR_SIZE nDataLen)

Where

nAppcmd - is the Application Command code

pData - points to Application Command data received (if any)

nDataLen - is the information about Application Command data length

The return value of the callback function is used as the Application Command result code and is returned to FreeMASTER tool.

Returns: Non-zero value when the callback function was successfully registered.

Range Issues: None.

Special Issues: None.

Design/Implementation: None.

Example 6-11. FMSTR_RegisterAppCmdCall

```
...
FMSTR_RegisterAppCmdCall(10, HandlerFunction);
```

This code shows how to register a callback function for Application Command with code 10.

6.6.1.12 Target-side Addressing API

When the Target-side Addressing (TSA) is enabled in the FreeMASTER driver configuration file (by setting the *FMSTR_USE_APPCMD* constant non-zero), the user should define so-called TSA tables in his application. This section describes macros which need to be used to define the TSA tables.

There can be any number of TSA tables spread across the application source files. There should be always one TSA Table List defined which informs the FreeMASTER driver about TSA tables.

When there is at least one TSA table and one TSA Table List defined in the application, the TSA information should automatically appear in the FreeMASTER symbols list. The FreeMASTER user is then able to create FreeMASTER variables based on these symbols. The TSA is supported in FreeMASTER version 1.2.37 and higher.

See the TSA example in the **freemaster_demo2 sample application** in DSP56800EX_Quick_Start installation. The application is also printed below on page -32.

6.6.1.12.1 TSA Table Definition

The TSA table describes the static or global variables, together with their address, size, type and access-protection information. In case the TSA-described variables are of a structure type, the TSA table may also describe this type and enable FreeMASTER user to access individual structure members of the variable.

The TSA table definition begins with FMSTR_TSA_TABLE_BEGIN macro:

```
FMSTR_TSA_TABLE_BEGIN(table_id)
```

Where the *table_id* is any valid C-language symbol identifying the table. There can be any number of TSA tables in the application, provided the table identifiers remain unique.

After this macro, the TSA table entries are placed using one of the macros below:

```
FMSTR_TSA_RW_VAR(name, type)                        // read/write variable entry
FMSTR_TSA_RO_VAR(name, type)                         // read-only variable entry
FMSTR_TSA_STRUCT(struct_name)                            // structure type entry
FMSTR_TSA_MEMBER(struct_name, member_name, type)
                                                       // structure member entry
```

The table is finished using the FMSTR_TSA_TABLE_END macro:

```
FMSTR_TSA_TABLE_END()
```

The TSA entry definition macros accept the following parameter:

- `name` - Variable name. The variable must be defined before the TSA table entry references it.
- `type` - Variable or member type. Only one of the pre-defined type constants may be used, as described below
- `struct_name` - Structure type name. The type must be defined (typedef) before the TSA table entry references it.
- `member_name` - Structure member name, without the dot at the beginning. The parent structure name is specified as a separate parameter in the FMSTR_TSA_MEMBER macro.

NOTE

Structure member entries (FMSTR_TSA_MEMBER) must immediately follow the parent structure entry (FMSTR_TSA_STRUCT).

In order to write-protect variables in the FreeMASTER driver (FMSTR_TSA_RO_VAR), the FMSTR_USE_TSA_SAFETY needs to be defined non-zero in the configuration file.

Despite of its name, the FMSTR_TSA_STRUCT macro may also be used to describe union data types.

Table 6-3. TSA Type Constants

CONSTANT	Description
FMSTR_TSA_UINT8 FMSTR_TSA_UINT16 FMSTR_TSA_UINT32 (FMSTR_TSA_UINT64)	1, 2, 4-byte unsigned integer type. Use it for both the standard C-language types like unsigned char, unsigned short or unsigned long and the user-defined types like UWord8, UWord16 or UWord32. 8-byte integer values are not used on 56F82xxx and 56F84xxx platform.
FMSTR_TSA_SINT8 FMSTR_TSA_SINT16 FMSTR_TSA_SINT32 (FMSTR_TSA_SINT64)	1, 2, 4-byte signed integer type. Use it for both the standard C-language types like char, short or long and the user-defined types like Word8, Word16 or Word32. 8-byte integer values are not used on 56F82xxx and 56F84xxx platform.
FMSTR_TSA_FRAC16 FMSTR_TSA_FRAC32	Fractional data types. Although these types are treated as integer types in C-language, it may be beneficial to describe them using these macro constants, so the FreeMASTER treats them properly.
FMSTR_TSA_UFRAC16 FMSTR_TSA_UFRAC32	Unsigned fractional data types. Although these types are treated as integer types in C-language, it may be beneficial to describe them using these macro constants, so the FreeMASTER treats them properly.
FMSTR_TSA_FLOAT	4-byte standard IEEE floating point type
FMSTR_TSA_DOUBLE	8-byte standard IEEE floating point type
FMSTR_TSA_USERTYPE(**name**)	Structure or union type. You must specify the type name as an argument.

6.6.1.12.2 TSA Table List

There **must** be exactly one TSA Table List in the application. The list contains one entry for each TSA table which is defined anywhere in the application.

The TSA Table List begins with the FMSTR_TSA_TABLE_LIST_BEGIN macro:

```
FMSTR_TSA_TABLE_LIST_BEGIN()
```

and continues with TSA table entries for each table:

```
FMSTR_TSA_TABLE(table_id)
FMSTR_TSA_TABLE(table_id2)
FMSTR_TSA_TABLE(table_id3)
...
```

The list is finished with the FMSTR_TSA_TABLE_LIST_END macro

```
FMSTR_TSA_TABLE_LIST_END()
```

6.6.2 Code Listing: freemaster_demo

```
/*****************************************************************************
*
* Freescale Semiconductor Inc.
* (c) Copyright 2013 Freescale Semiconductor, Inc.
* ALL RIGHTS RESERVED.
*
*****************************************************************************
*
* FILE NAME: main.c
*
* DESCRIPTION: Simple sample application demonstrating the functionality of
*              FreeMASTER software driver. Please see also the freemaster_demo2
*              application which demonstrates use of advanced FreeMASTER
*              features (Target-side Addressing, Memory Access security etc.)
*
*              The FreeMASTER driver and the SCI module are configured by GCT
*
* TARGET: MC56F82xxx device
*
*****************************************************************************/

/* required DSP56F800EX_Quick_Start header */
#include "qs.h"

/* low-level driver headers for each module used */
#include "intc.h"
#include "gpio.h"
#include "occs.h"
#include "sci.h"
#include "sys.h"
#include "cop.h"
#include "freemaster.h"

/* board-specific configuration */
#include "../board.h"

/* Test variables, will be displayed in the FreeMASTER application */
volatile UWord8  var8;
volatile UWord16 var16;
volatile UWord16 var16inc = 1;
volatile UWord32 var32;
volatile UWord32 var32inc = 100;

////////////////////////////////////////////////////////////////////////

void main (void)
{
          // Initialize SYS and GPIO modules
          ioctl(SYS, SYS_INIT, NULL);
          ioctl(COP, COP_INIT, NULL);

          ioctl(GPIO, GPIO_INIT_ALL, NULL);

          // initialize UART
          ioctl(SCI_RS232, SCI_INIT, NULL);


          // FreeMASTER initialization
          FMSTR_Init();

          // initialize & enable interrupts
```

```
            ioctl(INTC, INTC_INIT, NULL);
            archEnableInt();

            // other initializations
            var8 = 10;

            // main application loop
            while (1)
            {
                /* feed the dog */
                ioctl(COP, COP_CLEAR_COUNTER, NULL);

                // scope variables
                var16 += var16inc;
                var32 += var32inc;

                // This call should be placed in the timer interrupt or anywhere where
                // the recorder sampling should occur.
                FMSTR_Recorder();

                // The FreeMASTER polling call must be called periodically in the main
                // application loop to handle the communication interface and protocol.
                // Only in LONG_INTR FreeMASTER interrupt mode, all the processing is done
                // during the communication interrupt so the FMSTR_Poll() is not needed
                // (the function is compiled empty in this case).
                FMSTR_Poll();
            }
}
```

The FreeMASTER, GPIO, SCI_1, OCCS and SIM driver configuration extracted from the appconfig.h file:

```
/*.
    OCCS Configuration
-------------------------------------------
    Use Factory Trim Value: Yes
    Enable internal 32 kHz oscillator: No
    Power Down crystal oscillator: Yes
    Core frequency: 50 MHz
    VCO frequency: 200 MHz
    Loss of lock interrupt 0: Disable
    Loss of lock interrupt 1: Disable
    Loss of reference clock Interrupt: Disable
.*/
#define OCCS_CTRL_INIT                  0x0081U
#define OCCS_DIVBY_INIT                 0x2018U
#define OCCS_USE_FACTORY_TRIM           1
#define OCCS_USE_FACTORY_TRIM_TEMP      1

/*.
    SYS Configuration
-------------------------------------------
    SIM: Power Saving Modes: Stop enabled
    Wait enabled
         OnCE clock to processor core: Enabled when core TAP enabled
    DMA Enable in RUN and WAIT modes: DMA enabled in all power modes
    Enable External Reset Padcell Input Filter : No , SIM - Clock on GPIO: Enable CLKO_0: No
```

```
    SIM - Clock on GPIO: Enable CLKO_1: Yes
    Source: Continuous System Clock
    Divide by: 1
    SIM - HS_PERF Peripheral Clk: PWM
    SIM - Peripheral Clock Enable: GPIO F: Yes, GPIO E: No , GPIO D: No , GPIO C: No , GPIO
B: No , GPIO A: No , TMR A0: No
                                   TMR A1: No , TMR A2: No , TMR A3: No , SCI0: No , SCI1:
Yes, QSPI0: No , QSPI1: No , IIC: No , MSCAN: No
                                   CMP A: No , CMP B: No , CMP C: No , CMP D: No , CYC ADC:
No , CRC: No , QDC: No , PIT0: No , PIT1: No , DACA: No , DACB: No
                                  PWMCH0: No , PWMCH1: No , PWMCH2: No , PWMCH3: No , SIM -
Modules Enabled in Stop: GPIO F: No , SIM - Modules Enabled in Stop: GPIO E: No , SIM -
Modules Enabled in Stop: GPIO D: No , SIM - Modules Enabled in Stop: GPIO C: No , SIM -
Modules Enabled in Stop: GPIO B: No , SIM - Modules Enabled in Stop: GPIO A: No
    SIM - Modules Enabled in Stop: TMR A0: No , TMR A1: No , TMR A2: No , TMR A3: No ,
                                   SCI0: No , SCI1: No , QSPI0: No , QSPI1: No , IIC: No ,
MSCAN: No
                                   CMP A: No , CMP B: No , CMP C: No , CMP D: No , CYC ADC:
No , CRC: No , QDC: No , PIT0: No , PIT1: No , DACA: No , DACB: No
                                   PWMCH0: No , PWMCH1: No , PWMCH2: No , PWMCH3: No
    Protection of IPS and GPSxx  : Registers not protected
    Protection of PCE, SD and PCR: Registers not protected
    Protection of GPIO Port D: Registers not protected
    Protection of PWRMODE: Registers not protected
    GPIO Peripheral select registers (GPSn): ANA0/CMPA3
                                             ANB1/CMPB_IN0
                                             EXTAL
                                             TXD0
                                             TA0
                                             TA1
                                             DACA
                                             TA2
                                             SS0_B
                                             MOSI0
                                             SCLK0
                                             MOSI0
                                             Reserved
                                             Reserved
                                             TA3
                                             SDA0
                                             SCL0
                                             PWMA_2B
                                             PWMA_2A
                                             PWMA_3B
                                             PWMA_3A
                                             XB_IN6
                                             CLKOUT1
                                             SCL0
                                             SDA0
                                             TXD1
                                             RXD1
                                             Reserved
                                             CMPC_O
                                             RXD0
    Internal Peripheral Select Register 0 (IPS0): GPIOC3
                                                  GPIOC4
                                                  GPIOC6
                                                  GPIOC13
                                                  GPIOC3/GPIOC8/GPIOF8
                                                  GPIOC12/GPIOF5
    Miscellaneous Register 0 (SIM_MISC0): Disable
                                          Disable
                                          CLKIN0 (GPIOC0 alt1)
```

```
                                        PIT0 master, PIT1 slave
    SIM - Interrupts: Low voltage 2.2V: Disable
                      Low voltage 2.7V: Disable
                      High voltage 2.2V: Disable
                      High voltage 2.7V: Disable
    Enable Voltage Reference Buffer: No
    Bandgap trim: 7, Use Factory Trim Value: No
.*/
#define SIM_PCE0_INIT                   0x0002U
#define SIM_PCE1_INIT                   0x0802U
#define SIM_PCE2_INIT                   0x0000U
#define SIM_PCE3_INIT                   0x0000U

/*.
    INTC Configuration
-----------------------------------------
.*/
#define INTC_ICTL_INIT                  0x0000U
#define INT_VECTOR_ADDR_47              FMSTR_Isr
#define INT_PRIORITY_LEVEL_47           INTC_LEVEL1
#define INT_VECTOR_ADDR_48              FMSTR_Isr
#define INT_PRIORITY_LEVEL_48           INTC_LEVEL1
#define INT_VECTOR_ADDR_50              FMSTR_Isr
#define INT_PRIORITY_LEVEL_50           INTC_LEVEL1

/*.
    GPIO_F Configuration
-----------------------------------------
    Pin  0: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  1: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  2: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  3: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  4: Function: TXD1 , PullUp: Disable ,
    Pin  5: Function: RXD1 , PullUp: Disable ,
    Pin  6: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  7: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  8: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
.*/
#define GPIO_F_PER_INIT                 0x0030U

/*.
    SCI_1 Configuration
-----------------------------------------
    Baudrate: 9601 bps
    Enable Receiver: Enable
    Enable Transmitter: Enable
    Data word length: 8 bits
    Parity: None
    Polarity: True polarity
    Loop mode: Disable
    Function in Wait Mode: SCI module enabled in Wait Mode
    Interrupts: RX Full: Disable
                RX Error: Disable
                TX Empty: Disable
                TX Empty: Disable
    Enable RX and TX FIFO Queues: Disable
```

```
    RX Active Edge: Disable
    Enable TX DMA: Disable
    Enable RX DMA: Disable
    Hold off entry to stop mode: No
    Rx Idle Interrupt enabled: Disable
.*/
#define SCI_1_SCIBR_INIT                    0x0A2CU
#define SCI_1_SCICR_INIT                    0x000CU
#define SCI_1_SCICR2_INIT                   0x0000U
#define SCI_1_RX_BUFFER_OKLIMIT             0x000FU
#define SCI_1_RX_BUFFER_LOWLIMIT            0x000AU
#define SCI_1_SCICR3_INIT                   0x0000U

/*.
    FMSTR Configuration
-------------------------------------------
.*/
#define FMSTR_COMM_INTERFACE                2
#define FMSTR_LONG_INTR                     1
#define FMSTR_SHORT_INTR                    0
#define FMSTR_POLL_DRIVEN                   0
#define FMSTR_USE_SCOPE                     1
#define FMSTR_USE_RECORDER                  1
```

6.6.3 Code Listing: freemaster_demo2

The second FreeMASTER sample application demonstrates a usage of the TSA feature and both the callback and polled handling of the FreeMASTER Application Command.

```
/******************************************************************************
*
* Freescale Semiconductor Inc.
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* ALL RIGHTS RESERVED.
*
******************************************************************************
*
* FILE NAME: main.c
*
* DESCRIPTION: Advanced sample application demonstrating the functionality of
*              FreeMASTER software driver. See also the freemaster_demo
*              application, which demonstrates the key FreeMASTER features
*              only (without TSA, security and app.cmd callbacks)
*
*              The FreeMASTER driver and the SCI module are configured by GCT
*
* TARGET: MC56F82xxx device
*
******************************************************************************/

#include "qs.h"

#include "intc.h"
#include "gpio.h"
#include "occs.h"
#include "sci.h"
//#include "mscan.h"
#include "sys.h"
#include "cop.h"
#include "freemaster.h"

/* board-specific configuration */
#include "../board.h"

/*
 * Test structure types - demonstrates the "TSA" feature thanks to which the
 * FreeMASTER is able to load a variable and type information directly from
 * the embedded application.
 *
 */

typedef struct {

  UWord16 aa;
  UWord32 bb[2];
  Word16  cc;
  Word32  dd[3];
  UWord8  ee;
  Word8   ff[5];
} INNER_STRUCT;

typedef struct {

  UWord16 a;
  UWord32 b;
  INNER_STRUCT inA[4];
  INNER_STRUCT inB;
```

```
} OUTER_STRUCT;

/* Test variables, will be displayed in the FreeMASTER application */
volatile UWord8  var8;
volatile UWord16 var16;
volatile UWord16 var16inc = 1;
volatile UWord32 var32;
volatile UWord32 var32inc = 100;
volatile UWord8 nAppCmdCounter;

/* Structure type information will be available in the FreeMASTER application (TSA) */
OUTER_STRUCT so1, so2;
INNER_STRUCT si1, si2;

////////////////////////////////////////////////////////////////////////

/*
 * With TSA enabled, the user describes the global and static variables using
 * so-called TSA tables. There can be any number of tables defined in
 * the project files. Each table does have the identifier which should be
 * unique across the project.
 *
 * Note that you can declare variables as Read-Only or Read-Write.
 * The FreeMASTER driver denies any write access to the Read-Only variables
 * when TSA_SAFETY is enabled.
 */

FMSTR_TSA_TABLE_BEGIN(first_table)
    FMSTR_TSA_RO_VAR(var8,     FMSTR_TSA_UINT8)
    FMSTR_TSA_RO_VAR(var16,    FMSTR_TSA_UINT16)
    FMSTR_TSA_RO_VAR(var32,    FMSTR_TSA_UINT32)
    FMSTR_TSA_RW_VAR(var16inc, FMSTR_TSA_UINT16)
    FMSTR_TSA_RW_VAR(var32inc, FMSTR_TSA_UINT32)
    FMSTR_TSA_RW_VAR(so1,      FMSTR_TSA_USERTYPE(OUTER_STRUCT))
    FMSTR_TSA_RW_VAR(si1,      FMSTR_TSA_USERTYPE(INNER_STRUCT))

    FMSTR_TSA_STRUCT(OUTER_STRUCT)
    FMSTR_TSA_MEMBER(OUTER_STRUCT, a,   FMSTR_TSA_UINT16)
    FMSTR_TSA_MEMBER(OUTER_STRUCT, b,   FMSTR_TSA_UINT32)
    FMSTR_TSA_MEMBER(OUTER_STRUCT, inA, FMSTR_TSA_USERTYPE(INNER_STRUCT))
    FMSTR_TSA_MEMBER(OUTER_STRUCT, inB, FMSTR_TSA_USERTYPE(INNER_STRUCT))

    FMSTR_TSA_STRUCT(INNER_STRUCT)
    FMSTR_TSA_MEMBER(INNER_STRUCT, aa, FMSTR_TSA_UINT16)
    FMSTR_TSA_MEMBER(INNER_STRUCT, bb, FMSTR_TSA_UINT32)
    FMSTR_TSA_MEMBER(INNER_STRUCT, cc, FMSTR_TSA_SINT16)
    FMSTR_TSA_MEMBER(INNER_STRUCT, dd, FMSTR_TSA_SINT32)
    FMSTR_TSA_MEMBER(INNER_STRUCT, ee, FMSTR_TSA_UINT8)
    FMSTR_TSA_MEMBER(INNER_STRUCT, ff, FMSTR_TSA_SINT8)
FMSTR_TSA_TABLE_END()

/*
 * This is an example of another TSA table. Typically, you put one table
 * to each .c file where your global or static variables are instantiated.
 */

FMSTR_TSA_TABLE_BEGIN(next_table)
    FMSTR_TSA_RO_VAR(so2, FMSTR_TSA_USERTYPE(OUTER_STRUCT))
    FMSTR_TSA_RO_VAR(si2, FMSTR_TSA_USERTYPE(INNER_STRUCT))
FMSTR_TSA_TABLE_END()

////////////////////////////////////////////////////////////////////////
```

```
/*
 * This list describes all TSA tables which should be exported to the
 * FreeMASTER application.
 */

FMSTR_TSA_TABLE_LIST_BEGIN()
    FMSTR_TSA_TABLE(first_table)
    FMSTR_TSA_TABLE(next_table)
FMSTR_TSA_TABLE_LIST_END()

////////////////////////////////////////////////////////////////////////

/*
 * This function is registered as a application command handler (see
 * main() below. It gets automatically invoked when the PC FreeMASTER
 * application sends appropriate application command.
 *
 */

static FMSTR_APPCMD_RESULT myhandler(FMSTR_APPCMD_CODE nAppcmd, FMSTR_APPCMD_PDATA pData,
FMSTR_SIZE nDataLen)
{
    // the return value is used as the application command result code
    return (FMSTR_APPCMD_RESULT) 0x10;
}

////////////////////////////////////////////////////////////////////////

int main(void)
{
    UWord16 nAppCmdCode;

    // initialize SYS and GPIO modules
    ioctl(COP, COP_INIT, NULL);
    ioctl(SYS, SYS_INIT, NULL);
    ioctl(GPIO, GPIO_INIT_ALL, NULL);

    // initialize UART
    ioctl(SCI_RS232, SCI_INIT, NULL);

    // initialize MSCAN module - alternative FreeMASTER interface
//    ioctl(MSCAN, MSCAN_INIT, NULL);

    // FreeMASTER initialization
    FMSTR_Init();

    // registerring the App.Command handler
    FMSTR_RegisterAppCmdCall(10, myhandler);

    // initialize & enable interrupts
    ioctl(INTC, INTC_INIT, NULL);
    archEnableInt();

    // other initializations
    var8 = 10;

    // main application loop
    while (1)
    {
        /* feed the dog */
        ioctl(COP, COP_CLEAR_COUNTER, NULL);

        // scope variables
```

```
        var16 += var16inc;
        var32 += var32inc;

        // the application commands not registered with callback handlers
        // can be detected and processed using the API calls below

        // first, check if a new command has been received
        nAppCmdCode = FMSTR_GetAppCmd();

        // when a new command arrives, the nAppCmdCode contains the application
        // command code. In other case, the "NOCMD" special value is returned
        if (nAppCmdCode != FMSTR_APPCMDRESULT_NOCMD)
        {
            nAppCmdCounter++;

            // each command may have different processing and different
            // result code. The command processing is finished by
            // calling FMSTR_AppCmdAck() with the result code value
            switch(nAppCmdCode)
            {
                case 1: FMSTR_AppCmdAck((FMSTR_APPCMD_RESULT) var8); break;
                case 2: FMSTR_AppCmdAck((FMSTR_APPCMD_RESULT) ~var8); break;
                default: FMSTR_AppCmdAck(0); break;
            }
        }

        // This call should be placed in the timer interrupt or anywhere where
        // the recorder sampling should occur.
        FMSTR_Recorder();

        // The FreeMASTER poll call must be called in the main application loop
        // to handle the communication interface and protocol.
        // In LONG_INTR FreeMASTER interrupt mode, all the processing is done
        // during the communication interrupt routine and the FMSTR_Poll() is
        // compiled empty.
        FMSTR_Poll();
    }
}
```

The FreeMASTER, GPIO, SCI_1, OCCS and SIM driver configuration extracted from the appconfig.h file:

```
/*.
    OCCS Configuration
-----------------------------------------
    Use Factory Trim Value: Yes
    Enable internal 32 kHz oscillator: No
    Power Down crystal oscillator: Yes
    Core frequency: 50 MHz
    VCO frequency: 200 MHz
    Loss of lock interrupt 0: Disable
    Loss of lock interrupt 1: Disable
    Loss of reference clock Interrupt: Disable
.*/
#define OCCS_CTRL_INIT                  0x0081U
#define OCCS_DIVBY_INIT                 0x2018U
#define OCCS_USE_FACTORY_TRIM           1
#define OCCS_USE_FACTORY_TRIM_TEMP      1

/*.
```

```
    SYS Configuration
----------------------------------------
    SIM: Power Saving Modes: Stop enabled
    Wait enabled
         OnCE clock to processor core: Enabled when core TAP enabled
    DMA Enable in RUN and WAIT modes: DMA enabled in all power modes
    Enable External Reset Padcell Input Filter : No , SIM - Clock on GPIO: Enable CLKO_0: No
    SIM - Clock on GPIO: Enable CLKO_1: No
    SIM - Peripheral Clock Enable: GPIO F: Yes, GPIO E: No , GPIO D: No , GPIO C: Yes, GPIO
B: No , GPIO A: No , TMR A0: No
                                   TMR A1: No , TMR A2: No , TMR A3: No , SCI0: No , SCI1:
Yes, QSPI0: No , QSPI1: No , IIC0: No , FLEXCAN: No
                                   CMP A: No , CMP B: No , CMP C: No , CMP D: No , CYC ADC:
No , CRC: No , QDC: No , PIT0: No , PIT1: No , DACA: No , DACB: No
                                  PWMCH0: No , PWMCH1: No , PWMCH2: No , PWMCH3: No , SIM -
Modules Enabled in Stop: GPIO F: No , SIM - Modules Enabled in Stop: GPIO E: No , SIM -
Modules Enabled in Stop: GPIO D: No , SIM - Modules Enabled in Stop: GPIO C: No , SIM -
Modules Enabled in Stop: GPIO B: No , SIM - Modules Enabled in Stop: GPIO A: No
    SIM - Modules Enabled in Stop: TMR A0: No , TMR A1: No , TMR A2: No , TMR A3: No ,
                                   SCI0: No , SCI1: No , QSPI0: No , QSPI1: No , IIC0: No ,
FLEXCAN: No
                                   CMP A: No , CMP B: No , CMP C: No , CMP D: No , CYC ADC:
No , CRC: No , QDC: No , PIT0: No , PIT1: No , DACA: No , DACB: No
                                   PWMCH0: No , PWMCH1: No , PWMCH2: No , PWMCH3: No
    Protection of IPS and GPSxx  : Registers not protected
    Protection of PCE, SD and PCR: Registers not protected
    Protection of GPIO Port D: Registers not protected
    Protection of PWRMODE: Registers not protected
    GPIO Peripheral select registers (GPSn): ANA0/CMPA3
                                             ANB1/CMPB_IN0
                                             EXTAL
                                             TXD0
                                             TA0
                                             TA1
                                             DACA
                                             TA2
                                             SS0_B
                                             MOSI0
                                             SCLK0
                                             MOSI0
                                             Reserved
                                             Reserved
                                             TA3
                                             SDA0
                                             SCL0
                                             PWMA_2B
                                             PWMA_2A
                                             PWMA_3B
                                             PWMA_3A
                                             XB_IN6
                                             CLKOUT1
                                             SCL0
                                             SDA0
                                             TXD1
                                             RXD1
                                             Reserved
                                             CMPC_O
                                             RXD0
    Internal Peripheral Select Register 0 (IPS0): GPIOC3
                                                  GPIOC4
                                                  GPIOC6
                                                  GPIOC13
                                                  GPIOC3/GPIOC8/GPIOF8
```

```
                                                    GPIOC12/GPIOF5
    Miscellaneous Register 0 (SIM_MISC0): Disable
                                          Disable
                                          CLKIN0 (GPIOC0 alt1)
                                          PIT0 master, PIT1 slave
    SIM - Interrupts: Low voltage 2.2V: Disable
                      Low voltage 2.7V: Disable
                      High voltage 2.2V: Disable
                      High voltage 2.7V: Disable
    Enable Voltage Reference Buffer: No
    Bandgap trim: 7, Use Factory Trim Value: No
.*/
#define SIM_CLKOSR_INIT                  0x1020U
#define SIM_PCE0_INIT                    0x0012U
#define SIM_PCE1_INIT                    0x0802U
#define SIM_PCE2_INIT                    0x0000U
#define SIM_PCE3_INIT                    0x0000U

/*.
    GPIO_C Configuration
-----------------------------------------
    Pin  0: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  1: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  2: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  3: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  4: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  5: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  6: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  7: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  8: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  9: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin 10: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin 11: Function: CANTX , PullUp: Disable ,
    Pin 12: Function: CANRX , PullUp: Disable ,
    Pin 13: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin 14: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin 15: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
.*/
#define GPIO_C_PER_INIT                  0x1800U

/*.
    GPIO_F Configuration
-----------------------------------------
    Pin  0: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  1: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  2: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
```

```
    Pin  3: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  4: Function: TXD1 , PullUp: Disable ,
    Pin  5: Function: RXD1 , PullUp: Disable ,
    Pin  6: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  7: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
    Pin  8: Function: GPIO , Direction: Input , PullUp: Disable , Interrupt: Disable,
Int.Polarity: Active high ,
.*/
#define GPIO_F_PER_INIT                  0x0030U

/*.
    SCI_1 Configuration
-----------------------------------------
    Baudrate: 9601 bps
    Enable Receiver: Enable
    Enable Transmitter: Enable
    Data word length: 8 bits
    Parity: None
    Polarity: True polarity
    Loop mode: Disable
    Function in Wait Mode: SCI module enabled in Wait Mode
    Interrupts: RX Full: Disable
                RX Error: Disable
                TX Empty: Disable
                TX Empty: Disable
    Enable RX and TX FIFO Queues: Disable
    RX Active Edge: Disable
    Enable TX DMA: Disable
    Enable RX DMA: Disable
    Hold off entry to stop mode: No
    Rx Idle Interrupt enabled: Disable
.*/
#define SCI_1_SCIBR_INIT                 0x0A2CU
#define SCI_1_SCICR_INIT                 0x000CU
#define SCI_1_SCICR2_INIT                0x0000U
#define SCI_1_RX_BUFFER_OKLIMIT          0x000FU
#define SCI_1_RX_BUFFER_LOWLIMIT         0x000AU
#define SCI_1_SCICR3_INIT                0x0000U

/*.
    FMSTR Configuration
-----------------------------------------
.*/
#define FMSTR_COMM_INTERFACE             2
#define FMSTR_LONG_INTR                  0
#define FMSTR_SHORT_INTR                 0
#define FMSTR_POLL_DRIVEN                1
#define FMSTR_USE_APPCMD                 1
#define FMSTR_USE_SCOPE                  1
#define FMSTR_USE_RECORDER               1
#define FMSTR_USE_TSA                    1
#define FMSTR_USE_TSA_SAFETY             1
```

Chapter 7
Graphical Configuration Tool

7.1 Introduction

This section describes the functionality of the Graphical Configuration Tool (GCT) for the 56F82xxx and 56F84xxx family of Digital Signal Controllers. The Graphical User Interface (GUI), settings, file formats and the import/export rules will be described. The features and functionality of on-chip peripheral modules are described in the **MC56F8xxxx Reference Manual**.

GCT enables to create a static configuration of on-chip peripheral modules in an easy-to-use graphical environment. A graphical representation exists for all control bits or registers of each peripheral module. On the other hand, the status bits or bit-fields and other run-time-only registers are not covered by GCT. Typically, the run-time registers are accessed indirectly by the “ioctl” calls described in previous chapters.

7.1.1 Features

Main GCT features:

- Easy-to-use graphical environment
- Convenient navigation to individual peripheral modules
- Possibility to integrate GCT into CodeWarrior IDE 10.3 or higher version
- Immediate register values view
- Configuration warnings list

Supported peripheral modules:

- Processor block view, package pinout view
- On-chip Clock Synthesis (OCCS)
- Computer Operating Properly Watchdog (COP)
- System Integration Module (SIM, SYS)
- Interrupt controller (INTC)
- DMA Controller (DMA)
- Programmable Delay Block (PDB) - only 56F84xxx devices
- Quad Timer Module (QT)
- Periodic Interrupt Timer (PIT)
- General Purpose Input/Output (GPIO)
- Inter-Peripheral Crossbar Switch (XBAR)
- AOI - crosbarAND/OR/INVERT (AOI)
- Pulse Width Modulation A (PWMA)
- Pulse Width Modulation B (PWMB)
- Analog-to-Digital Converter (ADC)
- Digital-to-Analog Converter (DAC)

- High Speed Comparator (HSCMP)
- Queued Serial Communication Interface (QSCI)
- Queued Serial Peripheral Interface (QSPI)
- Inter-integrated Circuit Interface (IIC)
- FlexCAN Module (FCAN) - only 56F84xxx devices
- Modular/Scalable Controller Area Network (MSCAN) - only 56F82xxx devices
- Cyclic Redundancy Check (CRC) - only 56F84xxx devices
- Quadrature Encoder/Decoder (ENC)
- External Watchdog Monitor (EWM)
- Flash Memory Module (FTFA on 56F82xxx, FTFL on 56F84xxx)
- Flash Memory Controller (FMC)

7.1.2 How does it work?

The Graphical Configuration Tool (GCT) is a standard Microsoft Windows-based application used to graphically edit (read and write) project's *appconfig.h* file. The register initialization values edited by graphical controls can be immediately displayed and/or written back to the *appconfig.h* file.

The *appconfig.h* file is included by the application source code, and the register initialization values are used in the "init" functions to physically configure the peripheral module. An initialization function exists for each module and it is typically invoked using the "ioctl" INIT call (e.g. use the SCI1_INIT ioctl command to initialize the SCI module 1).

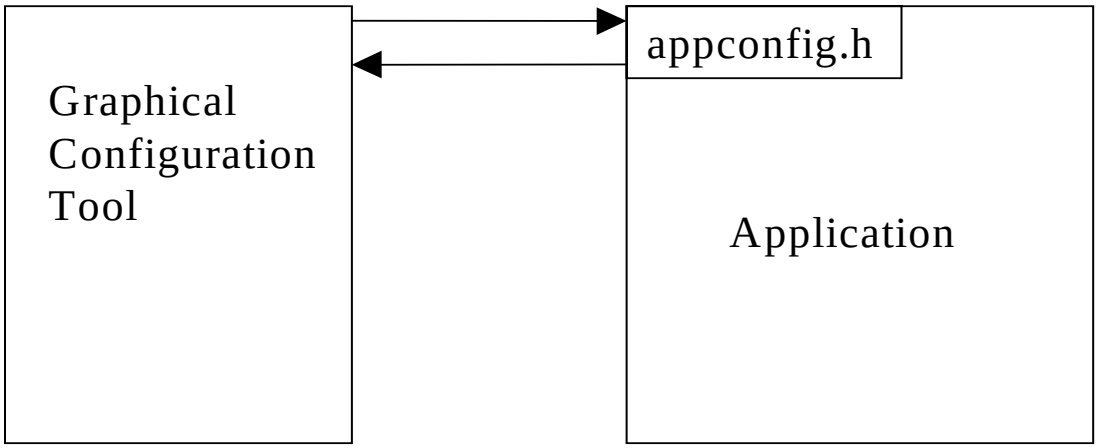

Figure 7-1. GCT Usage

The GCT is able to work as a stand-alone tool, however the integration with the CodeWarrior IDE 10.3 or higher version markedly increases the tool efficiency. The integration steps, as well as the installation, are described in detail in Section 1.2.2.1.

7.2 Program usage

This chapter contains a detailed description of the GCT user interface.

7.2.1 GUI Description

The GUI is organized as a common MS Windows application. The main window displays the following components (see Figure 7-2 below):

- **Peripheral Modules Tree** - The peripheral modules tree enables navigation through the structure of device modules. The user switches between different control pages by clicking on tree items.
- **Information Pane** - The upper left part of main application window displays the type of processor used, processor system clock and peripheral bus clock.
- **Module Settings Pane** - This pane displays the graphical controls which are used to configure the peripheral module.
- **Register Values View** - Displays immediate register values. This bar can be hidden if it is not needed.
- Warning List - This side bar displays a list of all configuration conflict warnings.

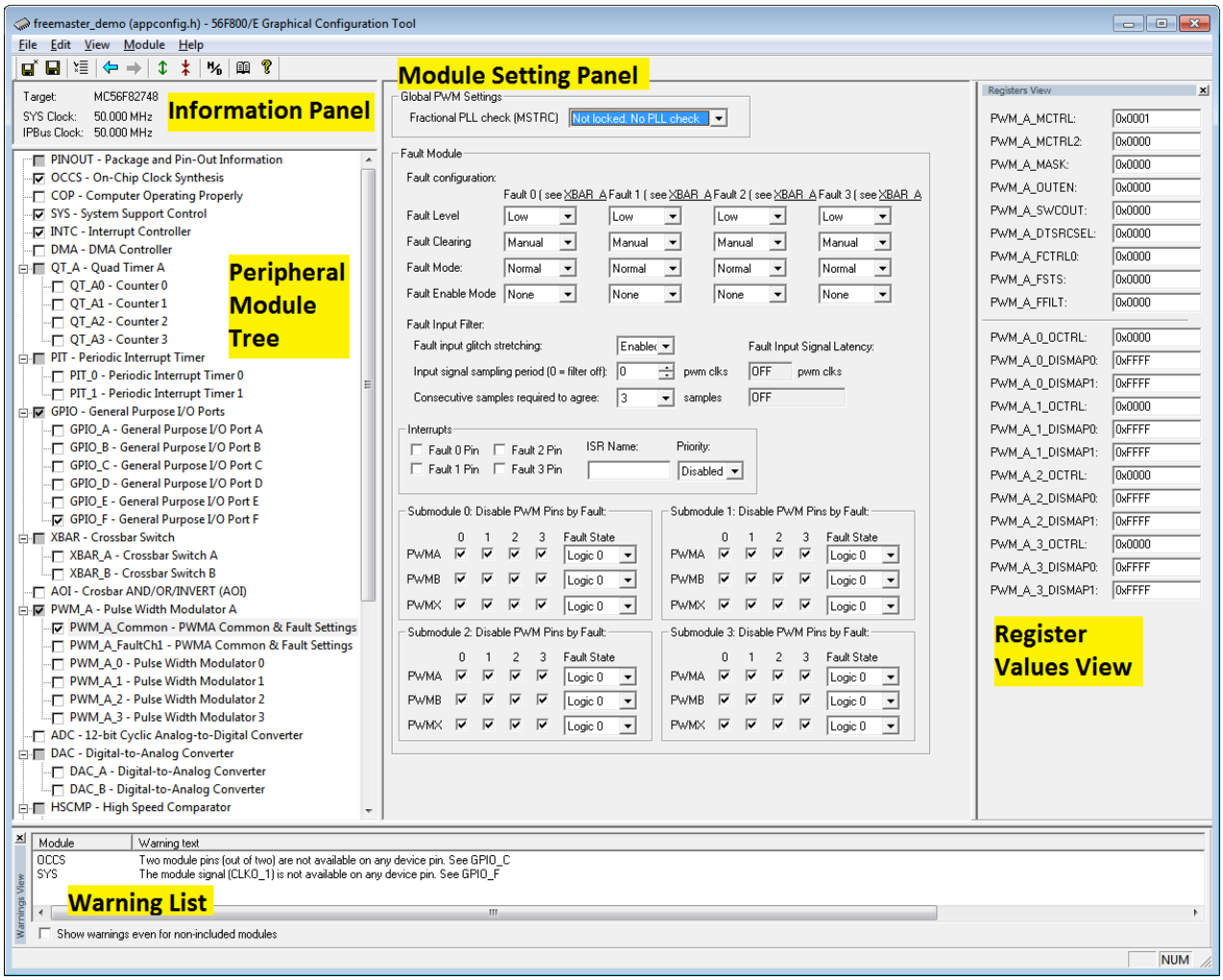

Figure 7-2. GCT Main Window

7.2.1.1 Peripheral Modules Tree

This part of the main application window contains a tree-like list of on-chip peripherals. There is a check-box control at each item, which can be used to enable or disable an *appconfig.h* output for a given module. When the box is unchecked, no module's register values are written to the output file. The GCT warns the user when there are changes made to a module configuration and the configuration is not selected to be saved.

7.2.1.2 Peripheral Module Settings Pane

This is the area where peripheral module control pages are displayed. Default configuration displayed in the GCT control page is a post-reset state of each peripheral module.

The graphical representation of peripheral module settings uses standard MS Windows control elements:

- **Edit Box** as numeric value or string input - numeric values are parsed as decimals by default. To specify hexadecimal number format use the standard “0x” prefix. The **H/D** toolbar button can be used to convert the value just being edited between these two formats.

  When using the Edit Box to specify an interrupt service routine (ISR) name in the GCT, use the valid C-language function name, without the types, parameters or even the brackets.
- **Drop-Down List Box** (Combo Box) - used as mode selectors, typically affecting a multiple-bits fields in a control register.
- **Check Box** - typically representing a single-bit configuration values

7.2.1.3 Pinout Page

The pinout page is a “welcome” page displayed initially when the GCT is started. This page shows a block diagram of the processor device as it is known from the data sheet.

The page content is actively generated by the GCT and displays several useful information about how the device is currently configured. For each peripheral module, the page displays a status icon which informs the user about what package pins are being used by the module and how they are configured.

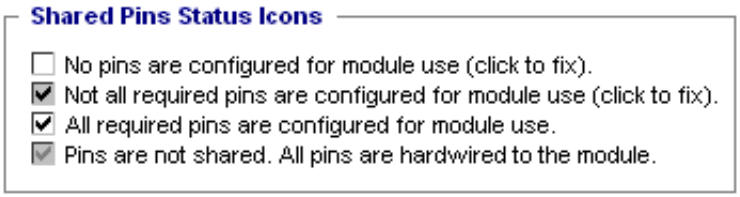

Figure 7-3. Pinout Page Status Icons

The page can also be switched to a “package view” where a top-view of the device package is displayed. Each package pin on this view is labeled by a function name assigned by pin multiplexer in a current project. Clicking on the pin label activates the GPIO control page where a pin multiplexer configuration can be changed.

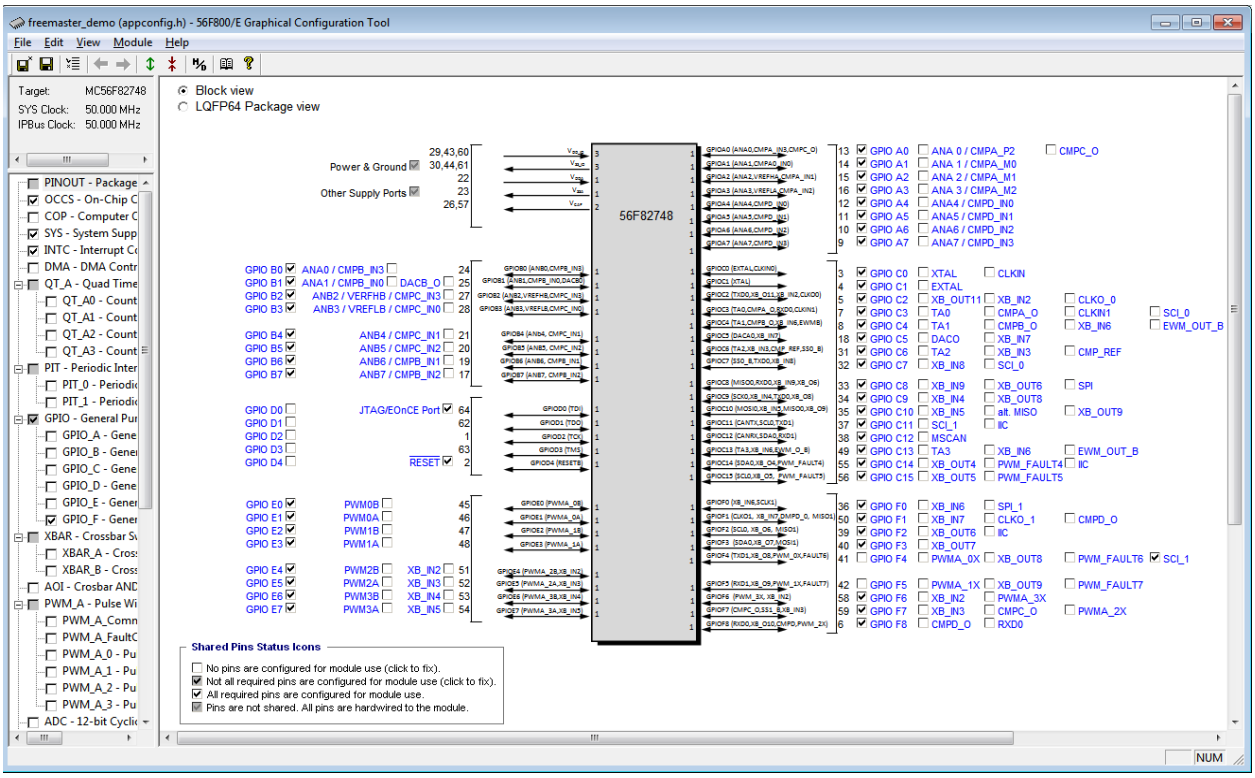

Figure 7-4. Pinout Page

7.2.1.4 Register View

On any of the GCT control pages, a **Register View** bar can be shown to display the immediate register values as they are to be written to the output file. For each module, all registers bound to graphical controls on the page are displayed. When a module configuration is modified, the affected registers values are red-highlighted in the Register View.

There is also a possibility to modify the register values directly in the Register View window (press “Enter” to accept a new value), causing the graphical controls to be redrawn accordingly. However, there are often other “run-time” bits in the control registers, which are not supposed to be set during an initialization. Modifying the register values without paying a high attention to each individual bit or bit-field of the register may cause the module settings to be invalid - even if the configuration looks good in the GCT.

The Register View bar can be activated or deactivated by a menu *“View / Register Summary”*.

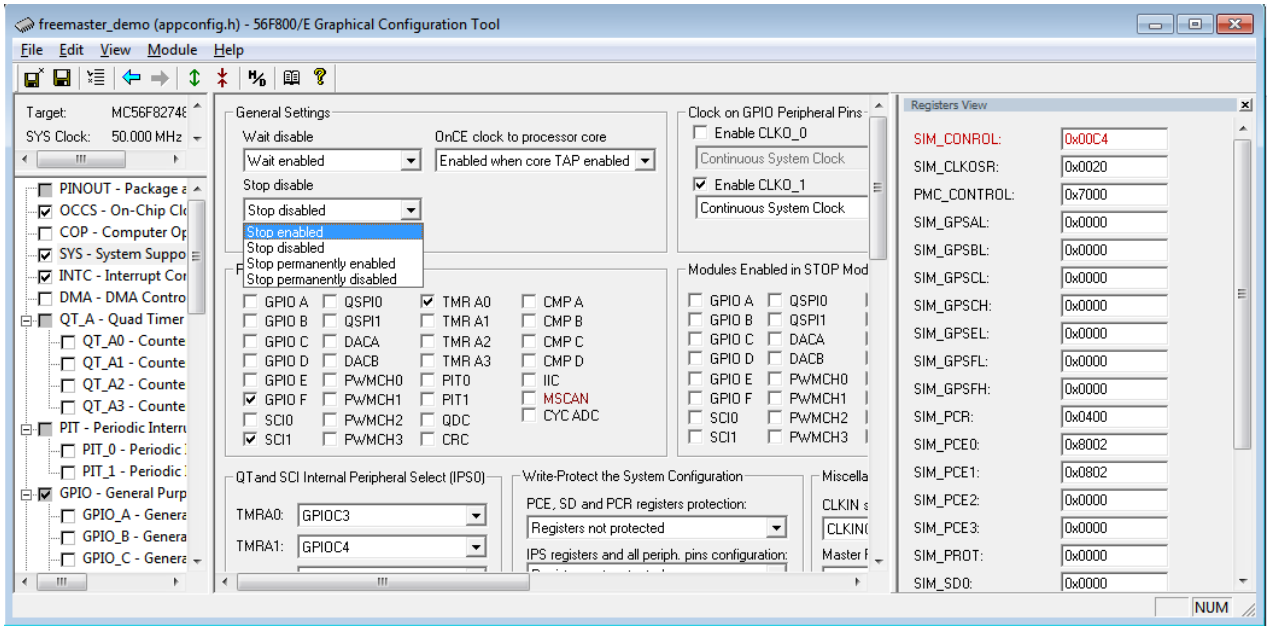

Figure 7-5. Register View

7.2.1.5 Warnings View

Similarly as the Registers View bar, the **Warnings View** bar can be shown or hidden any time when working with the GCT. Warnings View shows a list of warnings collected from across all control pages in the GCT. By default, the Warnings View displays only the warnings from modules selected to be saved to an output file (those with a “checkmark” sign in peripheral tree). All other warnings can be displayed in the list if required.

A double-click on a warning item in the list activates the control page where the potential conflict exists and a balloon-like hint is shown as a notification.

The Warnings View bar can be activated or deactivated by a menu *“View / Warnings Summary”*.

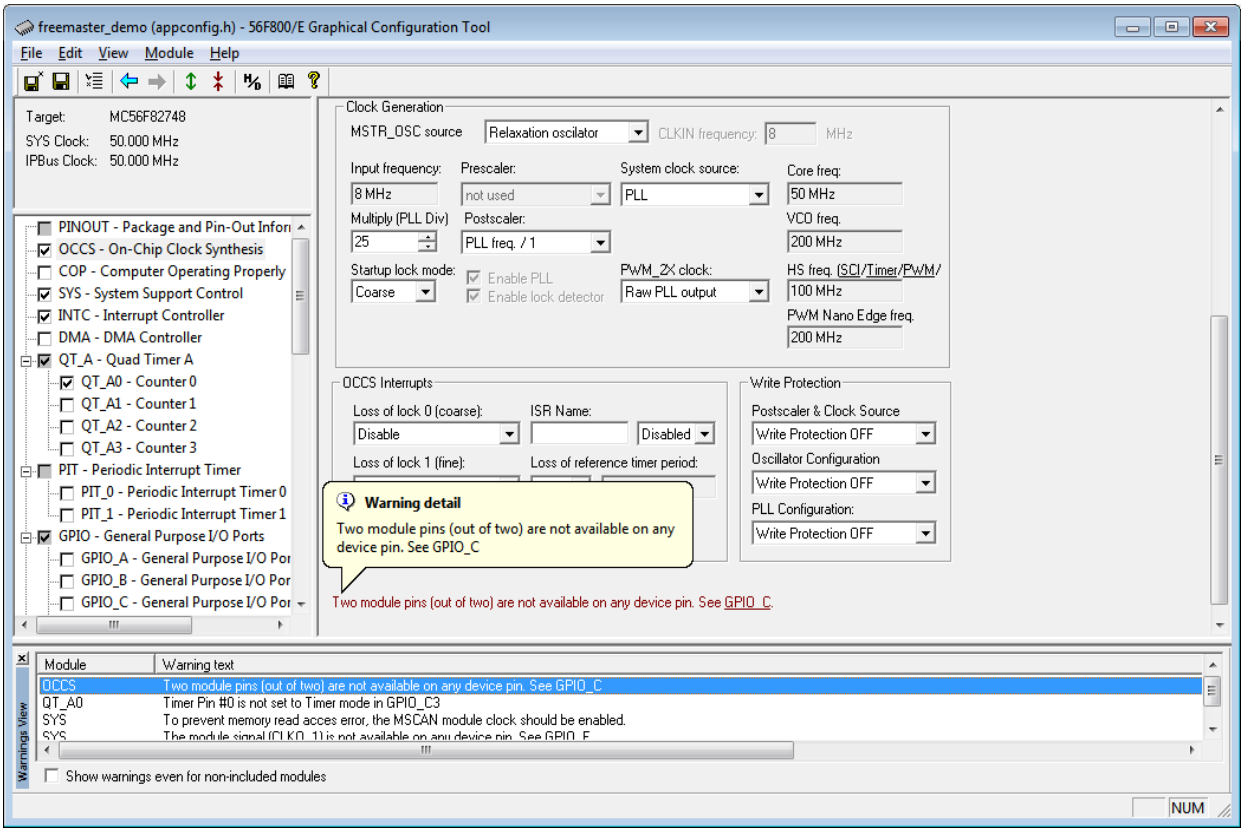

Figure 7-6. Warnings View

7.2.1.6 Options dialog

The Options dialog (Figure 7-7) can be invoked from a *"File / Options..."* menu. It contains the following settings for the overall GCT functionality:

- **Generate detailed comments** check-box enables saving of the "human-readable" commentary describing the configuration of each module.
- **Preserve user comments** check-box, when checked assures the user comments placed after the individual macro values are not lost when re-generating the *"appconfig.h"* file. This option is rarely used as there is typically no need for the user to manually edit any comments in the *"appconfig.h"* file.
- **Generate all register values** check-box enables saving of *all* register values of the selected peripheral modules into the *"appconfig.h"* file. When this option is not enabled (which is the default state), only the registers with non-reset values are saved. Omitting the reset-value registers in the *"appconfig.h"* file typically reduces a size of the module initialization code as those values not defined in the file are not written to the peripheral registers. On the other side, this approach requires **all the modules** being initialized to **be in post-reset state**, otherwise the result may be a most probably a mix of previous registers state and a GCT-defined configuration.

  This is a project-specific option, which is saved to the *"appconfig.h"* file as a macro constant named *APPCFG_DFLTS_OMITTED*. This constant is set to non-zero value when the **Generate all register values** option is turned off**.**

- **Set as default** check-box to save the selected options as default ones for the GCT and the current project.

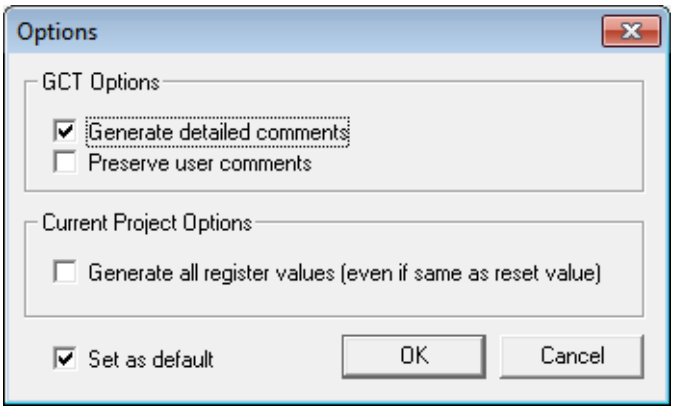

Figure 7-7. Options dialog

7.2.2 Application Configuration File Structure

The application configuration header file is a common ANSI C-language header file, which mostly contains register initialization values, but may contain other application global declarations or macros. The GCT parses and re-generates the register-values part of the file, while the other parts are ignored and left untouched.

In the Quick_Start projects, the application configuration file is named *"appconfig.h"* and resides in the *"ApplicationConfig"* project folder subdirectory. This file is included by all Quick_Start low-level driver source files where a configuration information is required.

However, the GCT can be used independently on the Quick_Start and its low-level drivers. The GCT is capable of loading and saving the configuration file under any name.

The configuration file can be logically divided into four parts:

- ***Heading*** is an arbitrary text before the first #define statement. Typically, the heading contains the application or user-specific file header or commentary. This part is not modified by the GCT. The first #define is typically a macro used to protect the file from multiple inclusion during compilation (i.e. standard #ifndef/#define sequence).
- ***General GCT Constants*** - *in which the processor type and external crystal clock frequency are specified as macros.*
- **Module Configuration Sections** - a block of configuration macro constants generated for each peripheral module. This part of the file is terminated with special comment ("/* end of auto-generated code ..*/).
- ***File Tail*** - *is anything what follows the configuration sections. The GCT keeps this section unchanged so the user may put his own global declarations and statements here. This feature enables a user to use the appconfig.h as a central application configuration file included also by his project source files and not only by "Quick_Start" driver files.*

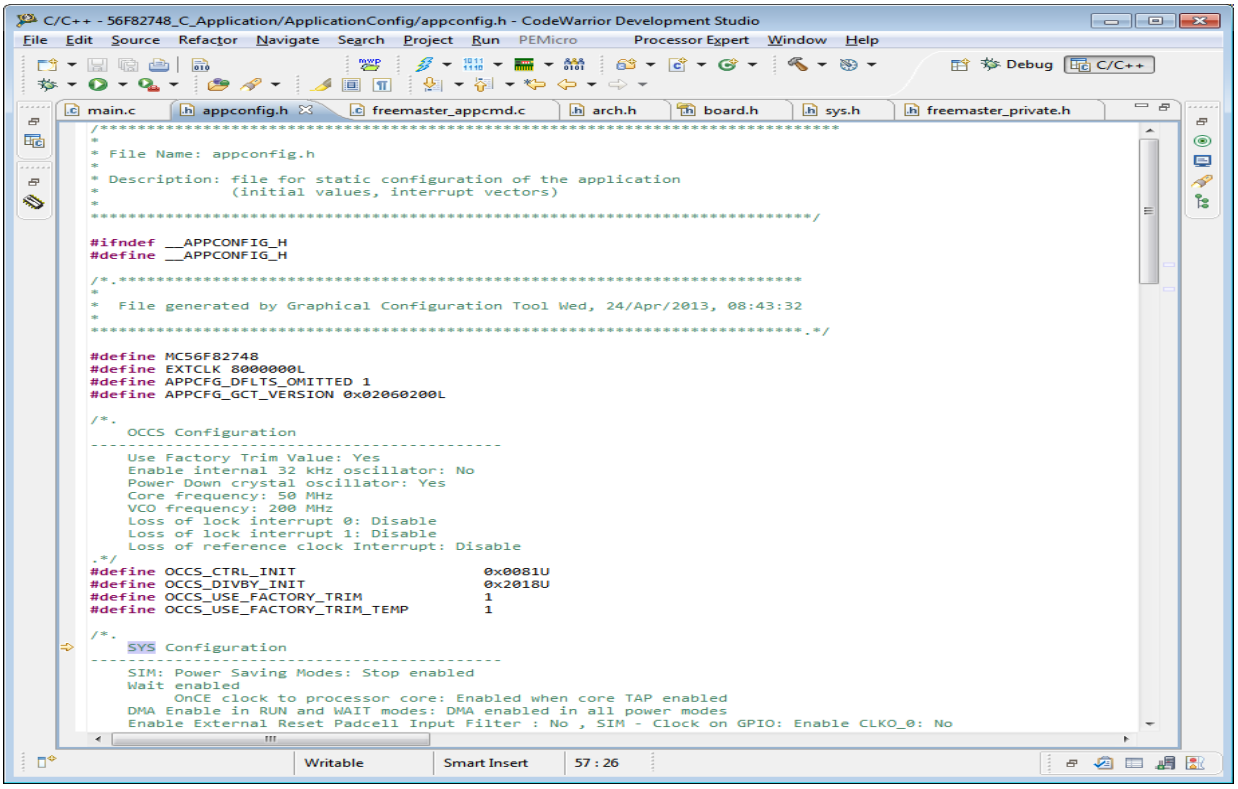

Figure 7-8. The *appconfig.h* File

Chapter 8
License

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Chapter 9
Revision history

Table 9-1. Revision history

Revision	Date	Substantial changes
0	04/2013	Initial release
1	05/2013	Updated Table 5-18
2	03/2015	Added the “Var” macro references to Chapter 2, “Core System Infrastructure”