

# OSELAS.BSP( )

## Phytec phyCORE-PXA270

**PHYTEC**



Quickstart Manual

<http://www.oselas.com>

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## **Part I**

# **OSELAS Quickstart for Phytec phyCORE-PXA270**

# 1 Getting a working Environment

## 1.1 Download Software Components

In order to follow this manual, some software archives are needed. There are several possibilities how to get these: either as part of an evaluation board package or by downloading them from the Pengutronix web site.

The central place for OSELAS related documentation is <http://www.oselas.com>. This website provides all required packages and documentation (at least for software components which are available to the public).

To build OSELAS.BSP-Phytec-phyCORE-10, the following archives have to be available on the development host:

- `ptxdist-1.99.12.tgz`
- `ptxdist-1.99.12-patches.tgz`
- `OSELAS.BSP-Phytec-phyCORE-10.tar.gz`
- `OSELAS.Toolchain-1.99.3.1.tar.bz2`

If they are not available on the development system yet, it is necessary to get them.

## 1.2 PTXdist Installation

The PTXdist build system can be used to create a root filesystem for embedded Linux devices. In order to start development with PTXdist it is necessary to install the software on the development system.

This chapter provides information about how to install and configure PTXdist on the development host.

### 1.2.1 Main parts of PTXdist

The most important software component which is necessary to build an OSELAS.BSP( ) board support package is the `ptxdist` tool. So before starting any work we'll have to install PTXdist on the development host.

PTXdist consists of the following parts:

**The `ptxdist` Program:** `ptxdist` is installed on the development host during the installation process. `ptxdist` is called to trigger any action, like building a software packet, cleaning up the tree etc. Usually the `ptxdist` program is used in a *workspace* directory, which contains all project relevant files.

**A Configuration System:** The config system is used to customize a *configuration*, which contains information about which packages have to be built and which options are selected.

**Patches:** Due to the fact that some upstream packages are not bug free – especially with regard to cross compilation – it is often necessary to patch the original software. PTXdist contains a mechanism to automatically apply patches to packages. The patches are bundled into a separate archive. Nevertheless, they are necessary to build a working system.

**Package Descriptions:** For each software component there is a "recipe" file, specifying which actions have to be done to prepare and compile the software. Additionally, packages contain their configuration snippet for the config system.

**Toolchains:** PTXdist does not come with a pre-built binary toolchain. Nevertheless, PTXdist itself is able to build toolchains, which are provided by the OSELAS.Toolchain() project. More in-deep information about the OSELAS.Toolchain() project can be found here: [http://www.pengutronix.de/oselas/toolchain/index\\_en.html](http://www.pengutronix.de/oselas/toolchain/index_en.html)

**Board Support Package** This is an optional component, mostly shipped aside with a piece of hardware. There are various BSP available, some are generic, some are intended for a specific hardware.

## 1.2.2 Extracting the Sources

To install PTXdist, at least two archives have to be extracted:

**ptxdist-1.99.12.tgz** The PTXdist software itself.

**ptxdist-1.99.12-patches.tgz** All patches against upstream software packets (known as the 'patch repository').

**ptxdist-1.99.12-projects.tgz** Generic projects (optional), can be used as a starting point for self-built projects.

The PTXdist and patches packets have to be extracted into some temporary directory in order to be built before the installation, for example the `local/` directory in the user's home. If this directory does not exist, we have to create it and change into it:

```
~# cd
~# mkdir local
~# cd local
```

Next steps are to extract the archives:

```
~/local# tar -zxf ptxdist-1.99.12.tgz
~/local# tar -zxf ptxdist-1.99.12-patches.tgz
```

and if required the generic projects:

```
~/local# tar -zxf ptxdist-1.99.12-projects.tgz
```

If everything goes well, we now have a `PTXdist-1.99.12` directory, so we can change into it:

```
~/local# cd ptxdist-1.99.12
~/local/ptxdist-1.99.12# ls -l
total 487
drwxr-xr-x 13 jb users 1024 Mar 23 13:25 ./
```

```
drwxr-xr-x 22 jb users 3072 Mar 23 13:25 ../
-rw-r--r-- 1 jb users 377 Feb 23 22:23 .gitignore
-rw-r--r-- 1 jb users 18361 Apr 24 2003 COPYING
-rw-r--r-- 1 jb users 3731 Mar 11 18:09 CREDITS
-rw-r--r-- 1 jb users 115540 Mar 7 15:25 ChangeLog
-rw-r--r-- 1 jb users 58 Apr 24 2003 INSTALL
-rw-r--r-- 1 jb users 2246 Feb 9 14:29 Makefile.in
-rw-r--r-- 1 jb users 4196 Jan 20 22:33 README
-rw-r--r-- 1 jb users 691 Apr 26 2007 REVISION_POLICY
-rw-r--r-- 1 jb users 54219 Mar 23 10:51 TODO
drwxr-xr-x 2 jb users 1024 Mar 23 11:27 autoconf/
-rwxr-xr-x 1 jb users 28 Jun 20 2006 autogen.sh*
drwxr-xr-x 2 jb users 1024 Mar 23 11:27 bin/
drwxr-xr-x 6 jb users 1024 Mar 23 11:27 config/
-rwxr-xr-x 1 jb users 226185 Mar 23 11:27 configure*
-rw-r--r-- 1 jb users 12390 Mar 23 11:16 configure.ac
drwxr-xr-x 2 jb users 1024 Mar 23 11:27 debian/
drwxr-xr-x 8 jb users 1024 Mar 23 11:27 generic/
drwxr-xr-x 164 jb users 4096 Mar 23 11:27 patches/
drwxr-xr-x 2 jb users 1024 Mar 23 11:27 platforms/
drwxr-xr-x 4 jb users 1024 Mar 23 11:27 plugins/
drwxr-xr-x 6 jb users 30720 Mar 23 11:27 rules/
drwxr-xr-x 7 jb users 1024 Mar 23 11:27 scripts/
drwxr-xr-x 2 jb users 1024 Mar 23 11:27 tests/
```

### 1.2.3 Prerequisites

Before PTXdist can be installed it has to be checked if all necessary programs are installed on the development host. The configure script will stop if it discovers that something is missing.

The PTXdist installation is based on GNU autotools, so the first thing to be done now is to configure the packet:

```
~/local/ptxdist-1.99.12# ./configure
```

This will check your system for required components PTXdist relies on. If all required components are found the output ends with:

```
[...]
checking whether /usr/bin/patch will work... yes

configure: creating ./config.status
config.status: creating Makefile
config.status: creating scripts/ptxdist_version.sh
config.status: creating rules/ptxdist-version.in

ptxdist version 1.99.12 configured.
Using '/usr/local' for installation prefix.
```

Report bugs to [ptxdist@pengutronix.de](mailto:ptxdist@pengutronix.de)

Without further arguments PTXdist is configured to be installed into `/usr/local`, which is the standard location for user installed programs. To change the installation path to anything non-standard, we use the `--prefix` argument to the `configure` script. The `--help` option offers more information about what else can be changed for the installation process.

The installation paths are configured in a way that several PTXdist versions can be installed in parallel. So if an old version of PTXdist is already installed there is no need to remove it.

One of the most important tasks for the `configure` script is to find out if all the programs PTXdist depends on are already present on the development host. The script will stop with an error message in case something is missing. If this happens, the missing tools have to be installed from the distribution before re-running the `configure` script.

When the `configure` script is finished successfully, we can now run

```
~/local/ptxdist-1.99.12# make
```

All program parts are being compiled, and if there are no errors we can now install PTXdist into its final location. In order to write to `/usr/local`, this step has to be performed as user `root`:

```
~/local/ptxdist-1.99.12# sudo make install
[enter root password]
[...]
```

If we don't have root access to the machine it is also possible to install into some other directory with the `--prefix` option. We need to take care that the `bin/` directory below the new installation dir is added to our `$PATH` environment variable (for example by exporting it in `~/ .bashrc`).

The installation is now done, so the temporary folder may now be removed:

```
~/local/ptxdist-1.99.12# cd
~# rm -fr local
```

### 1.2.4 Configuring PTXdist

When using PTXdist for the first time, some setup properties have to be configured. Two settings are the most important ones: Where to store the source packages and if a proxy must be used to gain access to the world wide web.

Run PTXdist's setup:

```
~# ptxdist setup
```

Due to PTXdist is working with sources only, it needs various source archives from the world wide web. If these archives are not present on our host, PTXdist starts the `wget` command to download them on demand.



#### 1.2.4.1 Proxy Setup

To do so, an internet access is required. If this access is managed by a proxy `wget` command must be advised to use it. PTXdist can be configured to advice the `wget` command automatically: Navigate to entry *Proxies* and enter the required addresses and ports to access the proxy in the form:

`<protocol>://<address>:<port>`

#### 1.2.4.2 Source Archive Location

Whenever PTXdist downloads source archives it stores these archives in a project local manner. If we are working with more than one project, every project would download its own required archives. To share all source archives between all projects PTXdist can be configured to use only one archive directory for all projects it handles: Navigate to menu entry *Source Directory* and enter the path to the directory where PTXdist should store archives to share between projects.

#### 1.2.4.3 Generic Project Location

If we already installed the generic projects we should also configure PTXdist to know this location. If we already did so, we can use the command `ptxdist projects` to get a list of available projects and `ptxdist clone` to get a local working copy of a shared generic project.

Navigate to menu entry *Project Searchpath* and enter the path to projects that can be used in such a way. Here we can configure more than one path, each part can be delimited by a colon. For example for PTXdist's generic projects and our own previous projects like this:

```
/usr/local/lib/ptxdist-1.99.12/projects:/office/my_projects/ptxdist
```

Leave the menu and store the configuration. PTXdist is now ready for use.

### 1.3 Toolchains

Before we can start building our first userland we need a cross toolchain. On Linux, toolchains are no monolithic beasts. Most parts of what we need to cross compile code for the embedded target comes from the *GNU Compiler Collection*, `gcc`. The `gcc` packet includes the compiler frontend, `gcc`, plus several backend tools (`cc1`, `g++`, `ld` etc.) which actually perform the different stages of the compile process. `gcc` does not contain the assembler, so we also need the *GNU Binutils package* which provides lowlevel stuff.

Cross compilers and tools are usually named like the corresponding host tool, but with a prefix – the *GNU target*. For example, the cross compilers for ARM and powerpc may look like

- `arm-softfloat-linux-gnu-gcc`
- `powerpc-unknown-linux-gnu-gcc`

With these compiler frontends we can convert e.g. a C program into binary code for specific machines. So for example if a C program is to be compiled natively, it works like this:

```
~# gcc test.c -o test
```

To build the same binary for the ARM architecture we have to use the cross compiler instead of the native one:

```
~# arm-softfloat-linux-gnu-gcc test.c -o test
```

Also part of what we consider to be the "toolchain" is the runtime library (libc, dynamic linker). All programs running on the embedded system are linked against the libc, which also offers the interface from user space functions to the kernel.

The compiler and libc are very tightly coupled components: the second stage compiler, which is used to build normal user space code, is being built against the libc itself. For example, if the target does not contain a hardware floating point unit, but the toolchain generates floating point code, it will fail. This is also the case when the toolchain builds code for i686 CPUs, whereas the target is i586.

So in order to make things working consistently it is necessary that the runtime libc is identical with the libc the compiler was built against.

PTXdist doesn't contain a pre-built binary toolchain. Remember that it's not a distribution but a development tool. But it can be used to build a toolchain for our target. Building the toolchain usually has only to be done once. It may be a good idea to do that over night, because it may take several hours, depending on the target architecture and development host power.

### 1.3.1 Using Existing Toolchains

If a toolchain is already installed which is known to be working, the toolchain building step with PTXdist may be omitted.



The OSELAS.BoardSupport() Packages shipped for PTXdist have been tested with the OSELAS.Toolchains() built with the same PTXdist version. So if an external toolchain is being used which isn't known to be stable, a target may fail. Note that not all compiler versions and combinations work properly in a cross environment.

---

Every OSELAS.BoardSupport() Package checks for its OSELAS.Toolchain it's tested against, so using a different toolchain vendor requires an additional step:

Open the OSELAS.BoardSupport() Package menu with:

```
~# ptxdist platformconfig
```

and navigate to architecture --> toolchain and check for specific toolchain vendor. Clear this entry to disable the toolchain vendor check.

### 1.3.2 Building a Toolchain

PTXdist handles toolchain building as a simple project, like all other projects, too. So we can download the OSELAS.Toolchain bundle and build the required toolchain for the OSELAS.BoardSupport() Package.

A PTXdist project generally allows to build into some project defined directory; all OSELAS.Toolchain projects that come with PTXdist are configured to use the standard installation paths mentioned below.

All OSELAS.Toolchain projects install their result into `/opt/OSELAS.Toolchain-1.99.3.1/`.



---

Usually the `/opt` directory is not world writeable. So in order to build our OSELAS.Toolchain into that directory we need to use a root account to change the permissions. PTXdist detects this case and asks if we want to run `sudo` to do the job for us. Alternatively we can enter:

```
mkdir /opt/OSELAS.Toolchain-1.99.3.1
chown <username> /opt/OSELAS.Toolchain-1.99.3.1
chmod a+rw /opt/OSELAS.Toolchain-1.99.3.1.
```

---

We recommend to keep this installation path as PTXdist expects the toolchains at `/opt`. Whenever we go to select a platform in a project, PTXdist tries to find the right toolchain from data read from the platform configuration settings and a toolchain at `/opt` that matches to these settings. But that's for our convenience only. If we decide to install the toolchains at a different location, we still can use the *toolchain* parameter to define the toolchain to be used on a per project base.

#### 1.3.2.1 Building the OSELAS.Toolchain for OSELAS.BSP-Phytec-phyCORE-10

To compile and install an OSELAS.Toolchain we have to extract the OSELAS.Toolchain archive, change into the new folder, configure the compiler in question and start the build.

The required compiler to build the OSELAS.BSP-Phytec-phyCORE-10 board support package is

```
arm-iwmmx-linux-gnueabi_gcc-4.3.2_glibc-2.8_binutils-2.18_kernel-2.6.27-sanitized
```

So the steps to build this toolchain are:

```
~# tar xf OSELAS.Toolchain-1.99.3.1.tar.bz2
~# cd OSELAS.Toolchain-1.99.3.1
~/OSELAS.Toolchain-1.99.3.1# ptxdist select ptxconfigs/\ 
> arm-iwmmx-linux-gnueabi_gcc-4.3.2_glibc-2.8_binutils-2.18_kernel-2.6.27-sanitized.ptxconfig
~/OSELAS.Toolchain-1.99.3.1# ptxdist go
```

At this stage we have to go to our boss and tell him that it's probably time to go home for the day. Even on reasonably fast machines the time to build an OSELAS.Toolchain is something like around 30 minutes up to a few hours.

Measured times on different machines:

- Single Pentium 2.5 GHz, 2 GiB RAM: about 2 hours
- Turion ML-34, 2 GiB RAM: about 1 hour 30 minutes
- Dual Athlon 2.1 GHz, 2 GiB RAM: about 1 hour 20 minutes
- Dual Quad-Core-Pentium 1.8 GHz, 8 GiB RAM: about 25 minutes

Another possibility is to read the next chapters of this manual, to find out how to start a new project.

When the OSELAS.Toolchain project build is finished, PTXdist is ready for prime time and we can continue with our first project.

### 1.3.3 Freezing the Toolchain

As we build and install this toolchain with regular user permissions we should modify the permissions as a last step to avoid any later manipulation. To do so we could set all toolchain files to read only or change recursively the owner of the whole installation to user root.

This is an important step for reliability. Do not omit it!

#### 1.3.3.1 Building additional Toolchains

The OSELAS.Toolchain-1.99.3.1 bundle comes with various predefined toolchains. Refer the `ptxconfigs/` folder for other definitions. To build additional toolchains we only have to clean our current toolchain project, removing the current `selected_ptxconfig` link and creating a new one.

```
~/OSELAS.Toolchain-1.99.3.1# ptxdist clean
~/OSELAS.Toolchain-1.99.3.1# rm selected_ptxconfig
~/OSELAS.Toolchain-1.99.3.1# ptxdist select \ 
> ptxconfigs/any_other_toolchain_def.ptxconfig
~/OSELAS.Toolchain-1.99.3.1# ptxdist go
```

All toolchains will be installed side by side architecture dependent into directory

`/opt/OSELAS.Toolchain-1.99.3.1/architecture_part.`

Different toolchains for the same architecture will be installed side by side version dependent into directory

`/opt/OSELAS.Toolchain-1.99.3.1/architecture_part/version_part.`

## 2 Building phyCORE-PXA270's root filesystem

### 2.1 Extracting

In order to work with a PTXdist based project we have to extract the archive first.

```
~# tar -zxf OSELAS.BSP-Phytec-phyCORE-10.tar.gz
~# cd OSELAS.BSP-Phytec-phyCORE-10
```

PTXdist is project centric, so now after changing into the new directory we have access to all valid components.

```
~/OSELAS.BSP-Phytec-phyCORE-10# ls -l
```

```
total 44
-rw-r--r--  1 jb users 4078 Dec  3 18:10 ChangeLog
-rw-r--r--  1 jb users 1313 Nov  1 13:31 Kconfig
-rw-r--r--  1 jb users 1101 Nov  4 21:05 TODO
drwxr-xr-x 10 jb users 4096 Jan 14 17:33 configs/
drwxr-xr-x  3 jb users 4096 Jan 14 15:08 documentation/
drwxr-xr-x  5 jb users 4096 Nov 13 12:30 local_src/
drwxr-xr-x  5 jb users 4096 Dec 15 10:19 patches/
drwxr-xr-x  6 jb users 4096 Jun  8 2008 projectroot/
drwxr-xr-x  3 jb users 4096 Nov  1 14:18 protocols/
drwxr-xr-x  4 jb users 4096 Jan  8 16:28 rules/
drwxr-xr-x  3 jb users 4096 Jan  7 08:55 tests/
```

Notes about some of the files and directories listed above:

**ChangeLog** Here you can read what has changed in this release. Note: This file does not always exist.

**documentation** If this BSP is one of our OSELAS BSPs, this directory contains the Quickstart you are currently reading in.

**configs** A multiplatform BSP contains configurations for more than one target. This directory contains the platform configuration files.

**projectroot** Contains files and configuration for the target's runtime. A running GNU/Linux system uses many text files for runtime configuration. Most of the time the generic files from the PTXdist installation will fit the needs. But if not, customized files are located in this directory.

**rules** If something special is required to build the BSP for the target it is intended for, then this directory contains these additional rules.

**patches** If some special patches are required to build the BSP for this target, then this directory contains these patches on a per package basis.

**tests** Contains test scripts for automated target setup.

## 2.2 Selecting a Software Platform

First of all we have to select a software platform for the userland configuration. This step defines what kind of applications will be built for the hardware platform. The OSELAS.BSP-Phytec-phyCORE-10 comes with a predefined configuration we select in the following step:

```
~/OSELAS.BSP-Phytec-phyCORE-10# ptxdist select \   
> configs/ptxconfig  
info: selected ptxconfig:  
      'configs/ptxconfig'
```

## 2.3 Selecting a Hardware Platform

Before we can build this BSP, we need to select one of the possible targets to build for. In this case we want to build for the phyCORE-PXA270:

```
~/OSELAS.BSP-Phytec-phyCORE-10# ptxdist platform \   
> configs/phyCORE-PXA270-1.99.12-1/platformconfig.pcm990  
info: selected platformconfig:  
      'configs/phyCORE-PXA270-1.99.12-1/platformconfig.pcm990'
```

Note: If you have installed the OSELAS.Toolchain() at its default location, PTXdist should already have detected the proper toolchain while selecting the platform. In this case it will output:

```
found and using toolchain:  
'/opt/OSELAS.Toolchain-1.99.3.1/arm-iwmmx-linux-gnueabi/  
  gcc-4.3.2-glibc-2.8-binutils-2.18-kernel-2.6.27-sanitized/bin'
```

If it fails you can continue to select the toolchain manually as mentioned in the next section. If this autodetection was successful, we can omit the steps of the section and continue to build the BSP.

## 2.4 Selecting a Toolchain

If not automatically detected, the last step in selecting various configurations is to select the toolchain to be used to build everything for the target.

```
~/OSELAS.BSP-Phytec-phyCORE-10# ptxdist toolchain \   
> /opt/OSELAS.Toolchain-1.99.3.1/arm-iwmmx-linux-gnueabi/\   
> gcc-4.3.2-glibc-2.8-binutils-2.18-kernel-2.6.27-sanitized/bin
```

## 2.5 Building the Root Filesystem

Now everything is prepared for PTXdist to compile the BSP. Starting the engines is simply done with:

```
~/OSELAS.BSP-Phytec-phyCORE-10# ptxdist go
```

PTXdist does now automatically find out from the `selected_ptxconfig` and `selected_platformconfig` files which packages belong to the project and starts compiling their *targetinstall* stages (that one that actually puts the compiled binaries into the root filesystem). While doing this, PTXdist finds out about all the dependencies between the packets and brings them into the correct order.

While the command `ptxdist go` is running we can watch it building all the different stages of a packet. In the end the final root filesystem for the target board can be found in the `platform-phyCORE-PXA270.PCM990/root/` directory and a bunch of *\*.ipk* packets in the `platform-phyCORE-PXA270.PCM990/packages/` directory, containing the single applications the root filesystem consists of.

Now that there is a root filesystem in our workspace we'll have to make it visible to the phyCORE-PXA270. There are two possibilities to do this:

1. Making the root filesystem persistent in the onboard media.
2. Booting from the development host, via network.

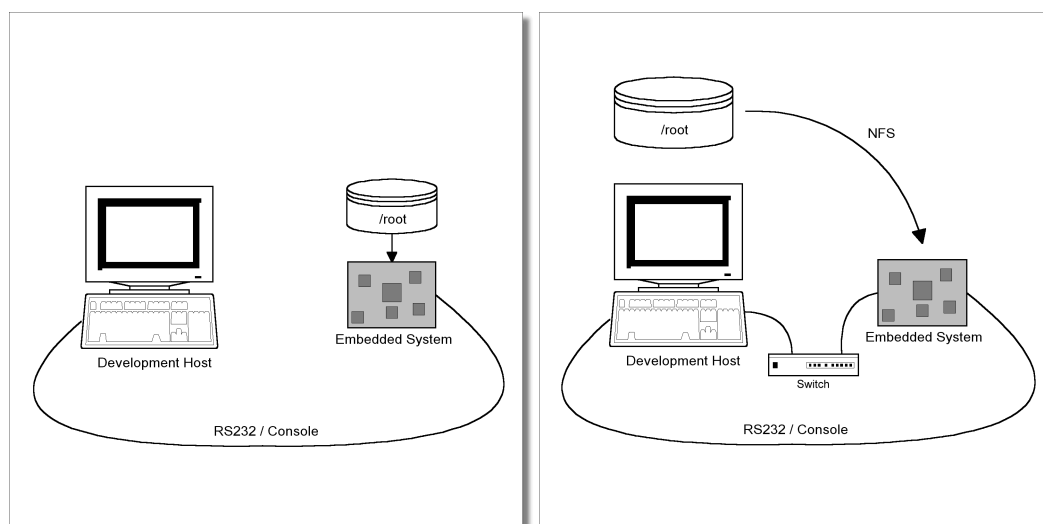


Figure 2.1: Booting the root filesystem, built with PTXdist, from the host via network and from flash.

Figure 2.1 shows both methods. The main method used in the OSELAS.BSP-Phytec-phyCORE-10 BSP is to provide all needed components to run on the target itself. The Linux kernel and the root filesystem is persistent in the media the target features. This means the only connection needed is the nullmodem cable to see what is happening on our target. We call this method *standalone*.

The other method is to provide all needed components via network. In this case the development host is connected to the phyCORE-PXA270 with a serial nullmodem cable and via ethernet; the embedded board boots into the bootloader, then issues a TFTP request on the network and boots the kernel from the TFTP server on the

host. Then, after decompressing the kernel into the RAM and starting it, the kernel mounts its root filesystem via NFS (Network File System) from the original location of the `platform-phyCORE-PXA270.PCM990/root/` directory in our PTXdist workspace.

The OSELAS.BSP-Phytec-phyCORE-10 provides both methods. The latter one is especially for development purposes, as it provides a very quick turnaround while testing the kernel and the root filesystem.

This chapter describes how to set up our target with features supported by PTXdist to simplify this challenge.

## 2.6 Target Side Preparation

The phyCORE-PXA270 uses U-Boot as its bootloader. U-Boot can be customized with environment variables and scripts to support any boot constellation. OSELAS.BSP-Phytec-phyCORE-10 comes with a predefined environment setup to easily bring up the phyCORE-PXA270.

Usually the environment doesn't have to be set manually on our target. PTXdist comes with an automated setup procedure to achieve a correct environment on the target.

Due to the fact that some of the values of these U-Boot environment variables must meet our local network environment and development host settings we have to define them prior to running the automated setup procedure.

Note: At this point of time it makes sense to check if the serial connection is already working, because it is essential for any further step we will do.

We can try to connect to the target with our favorite terminal application (`minicom` or `kermit` for example). With a powered target we identify the correct physical serial port and ensure that the communication is working. Make sure to leave this terminal application to unlock the serial port prior to the next steps.

To set up development host and target specific value settings, we run the command

```
~/OSELAS.BSP-Phytec-phyCORE-10# ptxdist boardsetup
```

We navigate to "Network Configuration" and replace the default settings with our local network settings. In the next step we also should check if the "Host's Serial Configuration" entries meet our local development host settings. Especially the "serial port" must correspond to our real physical connection.

When everything is set up, we can "Exit" the dialog and save our new settings.

Now the command

```
~/OSELAS.BSP-Phytec-phyCORE-10# ptxdist test setenv
```

will automatically set up a correct default environment on our phyCORE-PXA270. We have to powercycle our target to make this step happen.

It should output lines like these when it was successful:

```
=====
Please power on your board now!
=====
```

```
Logging into U-Boot.....OK
Setting new environment.....OK
Test finished successfully.
```



Note: If it fails, reading `platform-phyCORE-PXA270.PCM990/test.log` will give further information about why it has failed. Also extending the command line shown above by a `--debug` can help to see what's going wrong.



Users reported this step could fail if the Linux system running PTXdist is a virtual machine as guest in an operating system from Redmont. In this case it seems at least one of the two OSes is eating up characters sent to the serial line. Pengutronix recommends running PTXdist on a real Linux system.

---

## 2.7 Stand-Alone Booting Linux

To use the target standalone, the rootfs has to be made persistent in one of the onboard supported media of the phyCORE-PXA270. The following sections describe the steps necessary to bring the rootfs into the onboard NOR type flash.

Only for preparation we need a network connection to the embedded board and a network aware bootloader which can fetch any data from a TFTP server.

After preparation is done, the phyCORE-PXA270 can work independently from the development host. We can "cut" the network (and serial cable) and the phyCORE-PXA270 will continue to work.

### 2.7.1 Development Host Preparations

On the development host a TFTP server has to be installed and configured. The exact method to do so is distribution specific; as the TFTP server is usually started by one of the `inetd` servers, the manual sections describing `inetd` or `xinetd` should be consulted.

Usually TFTP servers are using the `/tftpboot` directory to fetch files from, so if we want to push kernel images into this directory we have to make sure we are able to write there. As the access permissions are normally configured in a way to let only user `root` write to `/tftpboot` we have to change it. The boardsetup scripts coming with this BSP expect write permission in TFTP directory!

We can run a simple:

```
~# touch /tftpboot/my_file
```

to test if we have permissions to create files in this directory. If it fails we have to ask the administrator to grant these permissions.

Note: We must `/tftpboot` part of the command above with our local settings.

## 2.7.2 Preparations on the Embedded Board

To boot phyCORE-PXA270 stand-alone, anything needed to run a Linux system must be locally accessible. So at this point of time we must replace any current content in phyCORE-PXA270's flash memory.

But first we must create the new root filesystem image prepared for its usage on the phyCORE-PXA270:

```
~/OSELAS.BSP-Phytec-phyCORE-10# ptxdist images
```

To simplify this step, OSELAS.BSP-Phytec-phyCORE-10 comes with an automated setup procedure for this step. To use this procedure we run the command:

```
~/OSELAS.BSP-Phytec-phyCORE-10# ptxdist test flash
```

Note: This command requires a serial and a network connection. The network connection can be cut after this step.

This command will automatically write a root filesystem to the correct flash partition on the phyCORE-PXA270. It only works if we previously have set up the environment variables successfully (described at page 16).

The command should output lines like this when it was successful:

```
=====
Please power on your board now!
=====

Logging into U-Boot.....OK
Flashing kernel.....OK
Flashing rootfs.....OK
Flashing oftree.....OK
Test finished successfully.
```

Note: If it fails, reading `platform-phyCORE-PXA270.PCM990/test.log` will give further information about why it has failed.

## 2.7.3 Booting the Embedded Board

To check that everything went successfully up to here, we can run the *boot* test.

```
~/OSELAS.BSP-Phytec-phyCORE-10# ptxdist test boot
```

```
=====
Please power on your board now!
=====

Checking for U-Boot.....OK
Checking for Kernel.....OK
Checking for init.....OK
Checking for login.....OK
Test finished successfully.
```

This will check if the environment settings and flash partitioning are working as expected, so the target comes up in stand-alone mode up to the login prompt.

Note: If it fails, reading `platform-phyCORE-PXA270.PCM990/test.log` will give further information about why it has failed.

After the next reset or powercycle of the board, it should boot the kernel from the flash, start it and mount the root filesystem also from flash.

Note: The default login account is `root` with an empty password.

## 2.8 Remote-Booting Linux

The next method we want to try after building a root filesystem is the network-remote boot variant. This method is especially intended for development as everything related to the root filesystem happens on the host only. It's the fastest way in a phase of a project, where things are changing frequently. Any change made in the local `platform-phyCORE-PXA270.PCM990/root/` directory simply "appears" on the embedded device immediately.

All we need is a network interface on the embedded board and a network aware bootloader which can fetch the kernel from a TFTP server.

### 2.8.1 Development Host Preparations

If we already have booted the phyCORE-PXA270 locally (as described in the previous section), all of the development host preparations are done.

If not, then a TFTP server has to be installed and configured on the development host. The exact method of doing this is distribution specific; as the TFTP server is usually started by one of the `inetd` servers, the manual sections describing `inetd` or `xinetd` should be consulted.

Usually TFTP servers are using the `/tftpboot` directory to fetch files from, so if we want to push data files to this directory, we have to make sure we are able to write there. As the access permissions are normally configured in a way to let only user `root` write to `/tftpboot` we have to change it. If we don't want to change the permission or if its disallowed to change anything, the `sudo` command may help.

```
~/OSELAS.BSP-Phytec-phyCORE-10# sudo cp platform-phyCORE-PXA270.PCM990/images/linuximage  
/tftpboot/uImage-pcm027
```

The NFS server is not restricted to a certain filesystem location, so all we have to do on most distributions is to modify the file `/etc/exports` and export our root filesystem to the embedded network. In this example file the whole work directory is exported, and the "lab network" between the development host is 192.168.23.0, so the IP addresses have to be adapted to the local needs:

```
/home/<user>/work 192.168.23.0/255.255.255.0(rw,no_root_squash,sync)
```

Note: Replace `<user>` with your home directory name.

## 2.8.2 Preparations on the Embedded Board

We already provided the phyCORE-PXA270 with the default environment at page 16. So there is no additional preparation required here.

## 2.8.3 Booting the Embedded Board

The default environment settings coming with the OSELAS.BSP-Phytec-phyCORE-10 has the possibility to boot from the internal flash or from the network. The definition what should happen after power on is made with the environment variable `boot_cmd`. The default setting is `run bcmd_flash` and will boot from flash.

To change this behavior we have to change the value of the `boot_cmd` environment variable to `run bcmd_net`.

```
uboot> setenv boot_cmd 'run bcmd_net'
uboot> saveenv
```

The next time the target will start it will use the network based booting mechanism.

## 3 Accessing Peripherals

The following sections provide an overview of the supported hardware components and their corresponding operating system drivers. Further changes can be ported on demand of the customer.

Phytec's phyCORE-PXA270 starter kit consists of the following individual boards:

1. The phyCORE-PXA270 module itself (PCM-027), containing the PXA270, RAM, flash, the GPIO expander chip and several other peripherals.
2. The starter kit baseboard (PCM990).
3. A GPIO breakout board (PCM-989).

To achieve maximum software re-use, the Linux kernel offers a sophisticated infrastructure, layering software components into board specific parts. The OSELAS.BSP( ) tries to modularize the kit features as far as possible; that means that when a customized baseboards or even customer specific module is developed, most of the software support can be re-used without error prone copy-and-paste. So the kernel code corresponding to the boards above can be found in

1. `arch/arm/mach-pxa/pcm027.c` for the CPU module
2. `arch/arm/mach-pxa/pcm969_990-baseboard.c` for the baseboard. With this file two common baseboards PCM969 and PCM990 are supported. The kernel commandline parameter can be used to select the board type during boot period. `board=pcm990` turns on board specific support for PCM990. The correct kernel command line should be set up in the u-boot environment. So mostly you don't have to change this.

In fact, software re-use is one of the most important features of the Linux kernel and especially of the ARM port, which always had to fight with an insane number of possibilities of the System-on-Chip CPUs.



Note that the huge variety of possibilities offered by the phyCORE modules makes it difficult to have a completely generic implementation on the operating system side. Nevertheless, the OSELAS.BSP( ) can easily be adapted to customer specific variants. In case of interest, contact the Pengutronix support ([support@pengutronix.de](mailto:support@pengutronix.de)) and ask for a dedicated offer.

---

The following sections provide an overview of the supported hardware components and their operating system drivers.

### 3.1 NOR Flash

Linux offers the Memory Technology Devices Interface (MTD) to access low level flash chips, directly connected to a SoC CPU.

Modern kernels offer a method to define flash partitions on the kernel command line, using the `mtddparts` command line argument:

```
mtddparts=physmap-flash.0:256k(u-boot)ro,4096k(system),-(root)
```

This line, for example, specifies several partitions with their size and name which can be used as `/dev/mtd0`, `/dev/mtd1` etc. from Linux. Additionally, this argument is also understood by reasonably new U-Boot bootloaders, so if there is any need to change the partitioning layout, the U-Boot environment is the only place where the layout has to be changed.

From userspace the NOR flash partitions can be accessed as

- `/dev/mtdblock0` (e.g. U-Boot partition)
- `/dev/mtdblock1` (e.g. U-Boot environment partition)
- `/dev/mtdblock2` (e.g. Kernel partition)
- `/dev/mtdblock3` (e.g. Linux rootfs partition)

Note: This is an example only. The partitioning on our phyCORE-PXA270 target can differ from this layout.

Only the `/dev/mtdblock3` on the phyCORE-PXA270 has a filesystem, so the other partitions cannot be mounted into the rootfs. The only way to access them is by pushing a prepared flash image into the corresponding `/dev/mtd` device node.

## 3.2 PWM Units

The PXA270 has four PWM units which can be programmed individually. However, as the phyCORE-PXA270 has some hardware restrictions, not all of them can be used under all circumstances:

- PWM#0 is used for LCD Backlight brightness (see section ??)
- PWM#1 is used to controll the motor speed on the GPIO expander board
- PWM#2 is not available
- PWM#3 is not available

The PWM units can be controlled with sysfs entries, with which we can acquire a PWM unit, setup the period and output. Due to optimisation issue the four PWM Units are registerd to two platformdevices, each of which represents two PWM units. You can find the sysfs directories for the platform devices under `/sys/bus/platform/devices/pxa27x-pwm.0` and `/sys/bus/platform/devices/pxa27x-pwm.1`, while the first one represents PWM#0 and PWM#2, the second one PWM#1 and PWM#3. The entries we can use to control the PWM units are located under the correpsonding platform device directories. For each PWM unit there are five entries:

- `.../acquire`

Before we can control a PWM unit, we must first acquire it to make sure that it is not used already by some one else. Just write the PWM unit number we want to acquire into this entrie. Note that we can only acquire a PWM unit the platform device actually represents. e.g. you can acquire PWM#0 and PWM#2 with `/sys/bus/platform/devices/pxa27x-pwm.0?/acquire`. If we wish to control PWM#3, you'd have to use the acauire entry in `/sys/bus/platform/devices/pxa27x-pwm.1`. Once we have acquired a PWM unit, we can use the entries listed below to control it.

- `.../release`

Write a non-zero value into this entrie to release our currently acquired PWM unit.

- .../period

This entry can be used to change the period of the PWM signal. The unit of the values being written here is Nanoseconds. Valid numbers are 100 ...10000000 (100 us ...10 ms). Default value is 78770.

- .../maxlevel

Use this entry to set the maximal level of our PWM output. Default value is 255.

- .../setlevel

Writing a value into this entry will set the pwm output level. The actual output of the PWM unit will be a percentage of the presetted maximal level.

Note: You can only control a PWM units directly only if it is not acquired by another driver already. As default all predefined PWM unit listed above are registered to a corresponding driver. On PCM990 PWM#0 is acquired and locked by the backlight driver. If you wish to access this element, please use the infrastructures provided by the individual drivers. Please consult section ??). If you wish to access the PWM unit manually, you have to unload the driver controlling the unit first before you acquire it through the user interface. We don't recommend this though.

### 3.3 GPIO Events

Some GPIOs are able to issue an interrupt. For example, on the breakout board the following pins offer this feature:

- GPIO14 is used as Key1 event input
- GPIO86 is used as Key2 event input
- GPIO87 is used as Key3 event input
- GPIO91 is used as light sensor event input

The interrupts generated by the gpios can be registered to the UIO(Userspace IO) Subsystem. As default GPIO91 is registered. The UIO Subsystem creates a device node in devfs for every registered uio device. To enable interrupt collecting write a non-zero value into /dev/uio0. Reading the device /dev/uio0 returns an int value which is the event count (number of interrupts) seen by the device or a read error if no changes have occurred since last read. If you open the devices in a blocking way, the read operation will block until an interrupt happens. The file descriptor can be passed to poll().

If you want to register events from other gpios to the uio subsystem. You can edit the board file in kernel. Look at the file arch/arm/mach-pxa/pcm969\_990-baseboard.c in the kernel tree and refer to the struct pcm990\_gpioevent\_uio\_info.



Note that this interface is a temporary one. The Open Source Automation Development Lab (OSADL) is working on an "Industrial I/O" driver framework which will probably supersede this interface in the future.

---

## 3.4 GPIO

Like most modern System-on-Chip CPUs, the PXA270 has numerous GPIO pins, some of which can be used for general purpose operations. If the generic GPIO kernel driver is loaded it offers a special sysfs entry that can be used to map a pin for userspace usage.

Refer `Documentation/gpio.txt` in-kernel documentation for further details how to use them. An usage example is given in section 4.2.

## 3.5 LCD Graphics

phyCORE-PXA270's LCD support uses the standard PXA2XX's framebuffer support and can be used as a regular console when also an USB keyboard is attached to the system. fb-tools can be used to manipulate the frame buffer (colour depth).

There're two types of LCD supported on the target: NEC n16448bc20 and Sharp lq084v1dg21. The LCD type must be selected with kernel command line during boot time. `lcd=lq084v1dg21` e.g. declares that the Sharp LCD is to be used. The default selection is Sharp lq084v1dg21. If we have any issues with our display, we can try to switch to `lcd=n16448bc20`. Changing the content of the variable `bargs_base` in u-boot Environment to do this (refer section ??).

For display definitions (resolution and frequency) see source file

```
arch/arm/mach-pxa/pcm969_990-baseboard.c
```

in the kernel tree.

The LCD's backlight can be controlled by using the backlight class driver. This driver offers a sysfs entry to control the brightness and a connection to the frame buffer console and to the X-server for power management.

We can find the sysfs entries in `/sys/class/backlight/pwm-backlight` and control them with plain ASCII numbers.

- `max_brightness`  
To read back the maximum value (hardware dependend). This value feeded into the brightness entry gives the maximum backlight brightness.
- `brightness`  
Set the current brightness value (0 ...max\_brightness).
- `bl_power`  
Set or read back backlight power. 0 means backlight is off, 1 means on.
- `actual_brightness`  
To read back the current brightness setting. Its the same as brightness.



On the development board, J23 must be in position 1-2 to make the PWM#0 control the inverter. See chapter "LCD interface" in the phyCORE-PXA270 manual for further details.

---



## 3.6 SPI Master

The phyCORE-PXA270 board supports an SPI bus, based on the PXA270's integrated SPI controller. It is connected to the onboard devices using the standard kernel method, so all methods described here are not special to the phyCORE-PXA270.

Connected device can be found in the sysfs at the path `/sys/bus/spi/devices`. It depends on the corresponding SPI slave device driver if it provides access to the SPI slave device through this way (sysfs), or any different kind of API.

On the phyCORE-PXA270, channel 1 of the SPI controller is connected to the MAX7301 GPIO expander chip. The BSP currently uses the "Chip Select" alternate function of GPIO 24 to select the MAX7301; This means the controller handles chip selection by its own in hardware. This SPI controller mode works fine if only one SPI slave device is connected (in the case of phyCORE-PXA270 it is the MAX7301).

If it's planned in a custom design to add more devices to this SPI channel 1 (to let it act like a bus) any chip selection has to be done in software. In this case also for the MAX7301, so GPIO 24 must be a regular GPIO without any alternate function enabled.

For a description of the SPI framework see [Documentation/spi/spi-summary](#) and for PXA2xx's SPI driver see [Documentation/spi/pxa2xx](#)

## 3.7 GPIO Expander MAX7301

This MAX7301 is a SPI bus based GPIO expander supporting 28 additional EGPIOs.

We can find the general information of the gpio expander chip in `/sys/class/gpio/gpiochip228/`.

To control the direction and level of each EGPIO we have to use the `gpiolib` sysfs entries as described in section 3.4.

Note: The GPIO base number of MAX7301 expander is 228. So we have to remember to add 228 to the single GPIO number on the expander when we want to control it. E.g. GPIO2 on the MAX7301 expander will be GPIO230 on the system.

## 3.8 MMC/SD Card

The phyCORE-PXA270 supports *Secure Digital Cards* and *Multi Media Cards* in conjunction with its PCMC990 to be used as general purpose blockdevices. These devices can be used in the same way as any other blockdevice.



These kind of devices are hot pluggable, so you must pay attention not to unplug the device while it's still mounted. This may result in data loss.

---

After inserting an MMC/SD card, the kernel will generate new device nodes in `dev/`. The full device can be reached via its `/dev/mmcblk0` device node, MMC/SD card partitions will occur in the following way:

`/dev/mmcblk0pY`

Y counts as the partition number starting from 1 to the max count of partitions on this device.

Note: These partition device nodes will only occur if the card contains a valid partition table ("harddisk" like handling). If it does not contain one, the whole device can be used for a filesystem ("floppy" like handling). In this case `/dev/mmcblk0` must be used for formatting and mounting.

The partitions can be formatted with any kind of filesystem and also handled in a standard manner, e.g. the `mount` and `umount` command work as expected.

## 3.9 AC97 Based Audio

The sound features can be used through standard PXA2xx AC97 ALSA support for the onboard Wolfson WM9712 device. See sources in `sound/arm/pxa2xx.c` in the kernel source tree for further information.

### 3.9.1 Sound Output

To play a sound, copy our favorite mp3 file to the phyCORE-PXA270, pop up the volume and play the file.

```
~# amixer sset PCM,0 20,20 unmute
~# amixer sset Headphone,0 20,20 unmute
~# amixer sset Master,0 20,20 unmute      # control the speaker
~# amixer sset 'Master Left Inv',0 on     # activate the speaker by phase reversal
~# madplay <mp3file_name>
```

If external loudspeakers are connected it is possible to mute the built-in speaker with `amixer sset 'Master Left Inv',0 off`.

Note: We also can use the command "alsamixer" to handle mixer's settings.

### 3.9.2 Sound Record

Note: When the Wolfson WM9712 chip comes up after power on, every sound source is muted as default. To record any sound the desired audio source must be unmuted first.

To activate sound capturing the internal ADCs have to be powered up and unmuted first:

```
~# amixer sset ADC,0 on
~# amixer sset Capture 15,15 unmute
```

Now its time to select the desired audio source for capturing. The following commands select the stereo line in as the source:

```
~# amixer sset Line 30,30 unmute
~# amixer sset 'Capture Select',0 Line
```

To select the microphone instead of the stereo line in, these commands are required:

```
~# amixer sset 'Mic 1',0 30
~# amixer sset Capture Select,0 'Mic 1'
```

Maybe the recorded sound level will be very low. To improve the volume we can enable a 20dB boost with the following command:

```
~# amixer sset 'Capture 20dB Boost',0 on
```

To record any sound the command `arecord` is the recommended way to do it. This example records about 20 seconds from the desired source:

```
~# arecord -f dat -d 20 -D hw:0,0 test.wav
```

See `arecord`'s manual for further meaning of the command line parameters.

### 3.9.3 Advanced Sound Handling

Note: The Wolfson WM9712 is a complex beast with many features. Sometimes it's hard to understand why it works or why it fails. Armed with its datasheet, the AC'97 specification and the kernel's powerful AC97 debug feature it is much easier to use WM9712 features in the manner we like or the way the chip supports it. Not all WM9712 features are supported by the ALSA utils out of the box. Some of these features need kernel driver patches to make the ALSA utils aware of it.

To see the current WM9712 register settings simply enter:

```
~# cat /proc/asound/card0/codec97#0/ac97#0-0+regs
```

This is an easy way to check the results of the `amixer` command and if it supports this feature out of the box.

To change any register's value manually (without `amixer` command for test purposes only) simply enter:

```
~# echo "1a 0404" > /proc/asound/card0/codec97#0/ac97#0-0+regs
```

This example updates WM9712's register `0x1A` to the new value `0x0404`. You will also need the datasheet here to know the registers, their offset and meaning.

Note: Give all values in hex but without leading `0x`.

## 3.10 AC97 Based Touchscreen

This device is supported through PXA2xx's standard AC97 support for the onboard Wolfson WM9712 device driver for touchscreen. In userspace this device is supported through the `tslib`, so it can be used by an X server as a pointing device. See sources in `driver/input/touchscreen/wm97xx.c` in the kernel source tree for further information.

Modul parameters to control the driver:

- **cont\_rate** Sample rate in continuous mode (Hz).  
Default is 200 samples per second.
- **pen\_int** Pen down detection (1 = interrupt, 0 = polling).  
This driver can either poll or use an interrupt to indicate a pen down event. If the IRQ request fails, then it will fall back to polling mode. Default is interrupt.
- **pressure** Pressure readback (1 = pressure, 0 = no pressure).
- **ac97\_touch\_slot** Touch screen data slot AC97 number.  
enable/disable AUX ADC sysfs, default is enabled
- **aux\_sys** disable AUX ADC sysfs entries.
- **status\_sys** disable codec status sysfs entries.  
enable/disable codec status sysfs, default is enabled
- These parameters are used to help the input layer discard out of range readings and reduce jitter etc.
  - min, max: indicate the min and max values our touch screen returns
  - fuzz: use a higher number to reduce jitter

The default values correspond to Mainstone II in QVGA mode Please read Documentation/input/input-programming.txt for more details.

- **abs\_x** Touchscreen absolute X min, max, fuzz.
- **abs\_y** Touchscreen absolute Y min, max, fuzz.
- **abs\_p** Touchscreen absolute Pressure min, max, fuzz.
- **rpu** Set internal pull up resistor for pen detect.  
Pull up is in the range 1.02k (least sensitive) to 64k (most sensitive) i.e. pull up resistance = 64k Ohms / rpu.  
We adjust this value if we are having problems with pen detect not detecting any down event.
- **pil** Set current used for pressure measurement.  
Set
  - pil = 2 to use 400µA
  - pil = 1 to use 200µA and
  - pil = 0 to disable pressure measurement.

This is used to increase the range of values returned by the ADC when measuring touchpanel pressure.

- **pressure** Set threshold for pressure measurement.  
Pen down pressure below threshold is ignored.
- **delay** Set ADC sample delay.  
For accurate touchpanel measurements, some settling time may be required between the switch matrix applying a voltage across the touchpanel plate and the ADC sampling the signal.  
This delay can be set by setting delay = n. Valid values of n can be looked up in the 'delay\_table' in the driver source. Long delays >1ms are supported for completeness, but are not recommended.
- **five\_wire** Set to '1' to use 5-wire touchscreen.  
NOTE: Five wire mode does not allow for readback of pressure.
- **mask** Set ADC mask function.  
Sources of glitch noise, such as signals driving an LCD display, may feed through to the touch screen plates

and affect measurement accuracy. In order to minimise this, a signal may be applied to the MASK pin to delay or synchronise the sampling.

- 0 = No delay or sync
- 1 = High on pin stops conversions
- 2 = Edge triggered, edge on pin delays conversion by delay param (above)
- 3 = Edge triggered, edge on pin starts conversion after delay param

Using the touchscreen requires a calibration. This has to be done the first time a newly built OSELAS.BSP-Phytec-phyCORE-10 runs on the target to create the calibration information before we can use the X server.

To do so run the command:

```
~# ts_calibrate
```

The command uses the environment variable TSLIB\_TSDEVICE (defined in /etc/profile) and the so called ts-lib, configured in /etc/ts.conf.

Note: When we intend to calibrate the touchpanel, stop an already running X server prior to starting `ts_calibrate`. They can't share the framebuffer, so the X server gets killed and the `ts_calibrate` command might hang forever.

## 3.11 USB host controller unit

The phyCORE-PXA270 supports a standard OHCI Rev. 1.0a compliant host controller onboard for low and full speed connections.

Up to two ports are supported by this CPU.

Only channel 1 is supported, channel 2 and 3 are not available.

Make sure the required USB device module for the device to be attached is already loaded. The OSELAS.BSP-Phytec-phyCORE-10 supports USB mice and USB Mass Storage devices (MemorySticks aso.) as default.

## 3.12 Network

The phyCORE-PXA270 module has an SMSC 91C111 ethernet chip onboard, which is being used to provide the `eth0` network interface. The interface offers a standard Linux network port which can be programmed using the BSD socket interface.

## 3.13 I<sup>2</sup>C Master

The PXA270 processor based phyCORE-PXA270 supports a dedicated I<sup>2</sup>C controller onchip. The kernel supports this controller as a master controller.

Additional I<sup>2</sup>C device drivers can use the standard I<sup>2</sup>C device API to gain access to their devices through this master controller.

For further information about the I<sup>2</sup>C framework see `Documentation/i2c` in the kernel source tree.

### 3.13.1 I<sup>2</sup>C Realtime Clock RTC8564

Due to the kernel's Real Time Clock framework the RTC8564 clock chip can be accessed using the same tools as for any other real time clocks.

Date and time can be manipulated with the `hwclock` tool, using the `-w` (`systohc`) and `-s` (`hctosys`) options. For more information about this tool refer to `hwclock`'s manpage.

OSELAS.BSP-Phytec-phyCORE-10 tries to set up the date at system startup. If there was a powerfail `hwclock` will state:

```
pcf8564 1-0051 path: low voltage detected, date/time is not reliable.  
pcf8564 1-0051 path: retrieved date/time is not valid.
```

In this case set the date manually (see `man date`) and run `hwclock -w -u` to store the new date into the RTC8564.

### 3.13.2 I<sup>2</sup>C device 24W32

This device is a 4 kiB non-volatile memory for general purpose usage.

This type of memory is accessible through the `sysfs` filesystem. To read the EEPROM content simply `open()` the entry `/sys/bus/i2c/devices/1-0052/eeprom` and use `fseek()` and `read()` to get the values.

## 3.14 Status LEDs

These LEDs are supported to display CPU activity and heart beat. They occupy the two processor GPIOs 90 and 91 for this purpose.

Note: These GPIOs are also used with the breakout board. So activity and heart beat function are disabled as default.

## 3.15 Socket CAN

The phyCORE-PXA270 has one SJA1000 based CAN controller, which is supported by drivers using the CAN framework "Socket-CAN". Using this framework, CAN interfaces can be programmed with the BSD socket API.

### 3.15.1 About Socket-CAN

The CAN (Controller Area Network<sup>1</sup>) bus offers a low-bandwidth, prioritised message fieldbus for communication between microcontrollers. Unfortunately, CAN was not designed with the ISO/OSI layer model in mind, so most CAN APIs available throughout the industry don't support a clean separation between the different logical protocol layers, like for example known from ethernet.

The *Socket-CAN* framework for Linux extends the BSD socket API concept towards CAN bus. It consists of

---

<sup>1</sup>ISO 11898/11519

- a core part (candev.ko)
- chip drivers (e. g. mscan, sja1000 etc.)

So in order to start working with CAN interfaces we'll have to make sure all necessary drivers are loaded.

### 3.15.1.1 Starting and Configuring Interfaces from the Command Line

If all drivers are present in the kernel, "ifconfig -a" shows which network interfaces are available; as Socket-CAN chip interfaces are normal Linux network devices (with some additional features special to CAN), not only the ethernet devices can be observed but also CAN ports.

For this example, we are only interested in the first CAN port, so the information for can0 looks like

```
~# ifconfig can0
can0 Link encap:UNSPEC HWaddr 00-00-00-00-00-00-00-00-00-00-00-00-00-00-00
      inet addr:127.42.23.180 Mask:255.255.255.0
      UP RUNNING NOARP MTU:16 Metric:1
      RX packets:35948 errors:0 dropped:0 overruns:0 frame:0
      TX packets:1 errors:0 dropped:0 overruns:0 carrier:0
      collisions:0 txqueuelen:10000
      RX bytes:243744 (238.0 KiB) TX bytes:2 (2.0 B)
      Interrupt:145 Base address:0x900
```

The output contains the usual parameters also shown for ethernet interfaces, so not all of these are necessarily relevant for CAN (for example the MAC address). These parameters contain useful information:

Field	Description
cano	Interface Name
NOARP	CAN cannot use ARP protocol
MTU	Maximum Transfer Unit, always 8
RX packets	Number of Received Packets
TX packets	Number of Transmitted Packets
RX bytes	Number of Received Bytes
TX bytes	Number of Transmitted Bytes
errors...	Bus Error Statistics

Table 3.1: CAN interface information

Interfaces shown by the "ifconfig -a" command can be configured with `canconfig`. This command adds CAN specific configuration possibilities for network interfaces, similar to for example `iwconfig` for wireless ethernet cards.

The baudrate for cano can now be changed:

```
~# canconfig can0 bitrate 250000
```

and the interface is started with

```
~# ifconfig can0 up
```

### 3.15.1.2 Using the CAN Interfaces from the Command Line

After successfully configuring the local CAN interface and attaching some kind of CAN devices to this physical bus, we can test this connection with command line tools.

The tools `cansend` and `candump` are dedicated to this purpose.

To send a simple CAN message with ID `0x20` and one data byte of value `0xAA` just enter:

```
~# cansend can0 --identifier=0x20 0xAA
```

To receive CAN messages run the `candump` command:

```
~# candump can0
interface = can0, family = 29, type = 3, proto = 0
<0x020> [1] aa
```

The output of `candump` shown in this example was the result of running the `cansend` example above on a different machine.

See `cansend`'s and `candump`'s manual pages for further information about using and options.



## 4 Special Notes

### 4.1 Analysing the CAN Bus Data Transfer

The OSELAS.BSP-Phytec-phyCORE-10 BSP comes with the standard *pcap* library and *tcpdump* tool. Both are capable of analyzing CAN data transfer which includes time stamping.

We set up the CAN interface(s) as usual and use it in our application. With *tcpdump* we can sniff at any point of time the data transferred on the CAN line.

To do so, we simply start *tcpdump*:

```
~# tcpdump -i can0
tcpdump: verbose output suppressed, use -v or -vv for full protocol decode
listening on can0, link-type LINUX_CAN (Linux CAN), capture size 68 bytes
```

Whenever there is any traffic on the line, *tcpdump* will log it to stdout. We will generate some traffic by using the *cansend* command:

```
~# cansend can0 -i 0x12 0x0f 0xf0 0x10 0x01
```

For this data, *tcpdump* will output:

```
00:15:52.482066 CAN Out ID:00000012 PL_LEN:4 PAYLOAD: 0x0f 0xf0 0x10 0x01
```

The log *tcpdump* generates consist of six fields:

1. 00:15:52.482066 is the timestamp this data was on the line. Its format is HH:MM:SS:TTTTTT, with TTTTTT as second's fraction
2. CAN interface type
3. Out message's data direction on this interface
4. ID:00000012 CAN message ID
5. PL\_LEN:4 byte count of message data
6. PAYLOAD: 0x0f 0xf0 0x10 0x01 the payload data

Some notes:

- The data direction field could be Out or In
- The CAN message ID encodes some additional info into higher bit values:

- Bit 31 encodes an extended frame. If this bit is set, an extended message frame was on the line
- Bit 30 encodes an RTR frame. If this bit is set, a remote transmission message frame was on the line

The message ID resides in the lower bits of this field

- The PAYLOAD field could be empty, when there were no data elements in the message

## 4.2 GPIO Usage Example

When the generic architecture GPIO support is enabled in the running kernel, some new entries are occurring in the sysfs. Everything is controlled via files that can be written and read to generate some action on the digital lines.

We can find all The control files are all contained in `/sys/class/gpio`

```
~# ls /sys/class/gpio/
export      gpiochip129  gpiochip64   unexport
gpiochip0   gpiochip32   gpiochip96
```

Note: The output of our current phyCORE-PXA270 BSP implementation can vary from the listing shown above.

The `gpiochip0` folder provides information about single gpio controller registered on the phyCORE-PXA270 board:

```
~# ls /sys/class/gpio/gpiochip0
base      label      ngpio      subsystem  uevent
```

The entry `base` contains information about the base GPIO number and `ngpio` contains the whole amount of GPIOs provided by this GPIO controller.

We use GPIO19 as an example to show the usage of single GPIOs.

```
~# echo 19 > /sys/class/gpio/export
```

This way we export `gpio19` for userspace usage. If the export was successful, we will find a new directory named `/sys/class/gpio/gpio19` afterwards. Within this directory we will be able to find the entries to access the functions of this gpio.

If we wish to set the direction and initial level of the GPIO, we can use the command:

```
~# echo "high" > /sys/class/gpio19/direction
```

This way we export GPIO19 for userspace usage and define our GPIO's direction attribute to an output with initially high level. We can change the value or direction of this GPIO by using the entries `direction` or `value`.

Note: This method is not very fast, so for quickly changing GPIOs it is still necessary to write a kernel driver. The shown method works fine for example to influence an LED directly from userspace.

To unexport an already exported GPIO, write the corresponding pinnumber into the `/sys/class/gpio/export`.

```
~# echo 19 > /sys/class/gpio/unexport
```

Now the directory `/sys/class/gpio/gpio19` will disappear.

## 5 Getting help

Below is a list of locations where you can get help in case of trouble. For questions how to do something special with PTXdist or general questions about Linux in the embedded world, try these.

### 5.1 Mailing Lists

#### About PTXdist in particular

This is an English language public mailing list for questions about PTXdist. See

[http://www.pengutronix.de/maillinglists/index\\_en.html](http://www.pengutronix.de/maillinglists/index_en.html)

how to subscribe to this list. If you want to search through the mailing list archive, visit

<http://www.mail-archive.com/>

and search for the list *ptxdist*.

#### About embedded Linux in general

This is a German language public mailing list for general questions about Linux in embedded environments. See

[http://www.pengutronix.de/maillinglists/index\\_de.html](http://www.pengutronix.de/maillinglists/index_de.html)

how to subscribe to this list. Note: You also can send mails in English.

### 5.2 News Groups

#### About Linux in embedded environments

This is an English newsgroup for general questions about Linux in embedded environments.

**comp.os.linux.embedded**

#### About general Unix/Linux questions

This is a German newsgroup for general questions about Unix/Linux programming.

**de.comp.os.unix.programming**

## 5.3 Chat/IRC

About PTXdist in particular

**irc.freenode.net:6667**

Create a connection to the **irc.freenode.net:6667** server and enter the chatroom **#ptxdist**. This is an English room to answer questions about PTXdist. Best time to meet somebody there is at European daytime.

## 5.4 Miscellaneous

**Online Linux Kernel Cross Reference**

A powerful online cross reference.

<http://lxr.linux.no/>

**U-Boot manual (partially)**

Manual how to survive in an embedded environment and how to use the U-Boot on target's side

<http://www.denx.de/wiki/DULG>

## 5.5 phyCORE-PXA270 Support Maillist

**OSELAS.Phytec@pengutronix.de**

This is an english language public maillist for all BSP related questions specific to Phytex's hardware. See web site

[http://www.pengutronix.de/maillinglists/index\\_en.html](http://www.pengutronix.de/maillinglists/index_en.html)

## 5.6 Commercial Support

You can order immediate support through customer specific mailing lists, by telephone or also on site. Ask our sales representative for a price quotation for your special requirements.

Contact us at:

**Pengutronix**  
**Peiner Str. 6-8**  
**31137 Hildesheim**  
**Germany**  
**Phone: +49 - 51 21 / 20 69 17 - 0**  
**Fax: +49 - 51 21 / 20 69 17 - 55 55**

or by electronic mail:

**sales@pengutronix.de**